

cl_nav2z::backward
_global_planner::BackwardGlobal
Planner::createPlan

cl_nav2z::undo_path
_global_planner::UndoPathGlobal
Planner::createPlan

cl_nav2z::pure_spinning
_local_planner::publishGoalMarker

```
graph LR; A["cl_nav2z::backward  
_global_planner::BackwardGlobal  
Planner::createPlan"] --> C["cl_nav2z::pure_spinning  
_local_planner::publishGoalMarker"]; B["cl_nav2z::undo_path  
_global_planner::UndoPathGlobal  
Planner::createPlan"] --> C;
```