

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



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

The diagram consists of two rectangular boxes connected by a horizontal arrow pointing from left to right. The left box has a light gray background and a black border, containing three lines of text. The right box has a white background and a black border, also containing two lines of text. A solid blue arrow points from the right side of the left box to the left side of the right box.

cl_nav2z::pure_spinning
_local_planner::publishGoalMarker