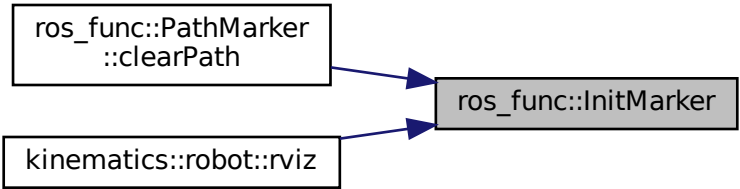


ros\_func::PathMarker  
::clearPath

kinematics::robot::rviz

ros\_func::InitMarker



```
graph LR; A[ros_func::PathMarker::clearPath] --> C[ros_func::InitMarker]; B[kinematics::robot::rviz] --> C;
```