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graph RL; S3["sm_dance_bot::move\n_base_z_client::CbNavigate\nGlobalPosition::onEntry"] --> S2["sm_dance_bot::move\n_base_z_client::CbNavigate\nGlobalPosition::goToRadialStart"]; S2 --> S1["sm_dance_bot::move\n_base_z_client::CbNavigate\nGlobalPosition::readStartPoseFromParameterServer"];
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sm_dance_bot::move
_base_z_client::CbNavigate
GlobalPosition::readStartPoseFromParameterServer

sm_dance_bot::move
_base_z_client::CbNavigate
GlobalPosition::goToRadialStart

sm_dance_bot::move
_base_z_client::CbNavigate
GlobalPosition::onEntry