

bot_common_ros.robo
_chisel_action_server.Robo
ChiselActionServer.MAIN

bot_common_ros.robo
_saw_action_server.RoboSaw
ActionServer.MAIN

bot_common_ros.actions.FSMAction
Server.fsm_loop

```
graph LR; A["bot_common_ros.robo_chisel_action_server.RoboChiselActionServer.MAIN"] --> C["bot_common_ros.actions.FSMActionServer.fsm_loop"]; B["bot_common_ros.robo_saw_action_server.RoboSawActionServer.MAIN"] --> C;
```

The diagram illustrates a system architecture where two separate action servers, 'RoboChiselActionServer.MAIN' and 'RoboSawActionServer.MAIN', both interact with a shared 'FSMActionServer.fsm_loop'. The nodes are represented as rectangular boxes. The two source nodes on the left are white with black borders, while the target node on the right is gray with a black border. Blue arrows indicate the direction of interaction from the source nodes to the target node.