

sm\_dance\_bot::cl\_lidar  
::CbLidarSensor::onEntry

sm\_dance\_bot\_2::cl  
\_lidar::CbLidarSensor  
::onEntry

sm\_dance\_bot\_strikes  
\_back::cl\_lidar::CbLidarSensor  
::onEntry

cl\_multirole\_sensor  
::CbDefaultMultiRoleSensor  
Behavior::onEntry

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graph LR; A[sm_dance_bot::cl_lidar::CbLidarSensor::onEntry] --> D[cl_multirole_sensor::CbDefaultMultiRoleSensorBehavior::onEntry]; B[sm_dance_bot_2::cl_lidar::CbLidarSensor::onEntry] --> D; C[sm_dance_bot_strikes_back::cl_lidar::CbLidarSensor::onEntry] --> D;
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The diagram illustrates three source boxes on the left, each with a black border, pointing via blue arrows to a single target box on the right. The target box has a gray fill and a black border. The arrows originate from the bottom-right of the first box, the right side of the second box, and the top-right of the third box, all converging on the left side of the target box.