

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;
```

The diagram illustrates a central component, `cl_multirole_sensor::CbDefaultMultiRoleSensorBehavior::onEntry`, which is highlighted in a grey box. Three other components, each in a white box, have arrows pointing towards this central component. The first component is `sm_dance_bot::cl_lidar::CbLidarSensor::onEntry`, the second is `sm_dance_bot_2::cl_lidar::CbLidarSensor::onEntry`, and the third is `sm_dance_bot_strikes_back::cl_lidar::CbLidarSensor::onEntry`. The arrows indicate a flow or dependency from these three state machine entry points to the multirole sensor's entry point.