

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 a central component, `cl_multirole_sensor::CbDefaultMultiRoleSensorBehavior::onEntry`, which is the target of three different state machine entry points. The entry points are arranged vertically on the left: `sm_dance_bot::cl_lidar::CbLidarSensor::onEntry` at the top, `sm_dance_bot_2::cl_lidar::CbLidarSensor::onEntry` in the middle, and `sm_dance_bot_strikes_back::cl_lidar::CbLidarSensor::onEntry` at the bottom. Blue arrows point from each of these three boxes to the central box on the right, which has a gray background.