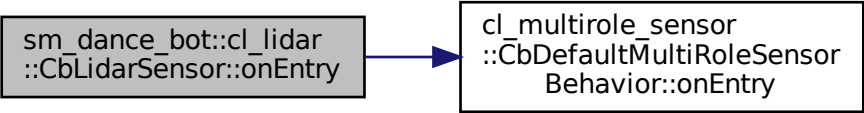


sm\_dance\_bot::cl\_lidar  
::CbLidarSensor::onEntry



```
graph LR; A["sm_dance_bot::cl_lidar::CbLidarSensor::onEntry"] --> B["cl_multirole_sensor::CbDefaultMultiRoleSensorBehavior::onEntry"]
```

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