

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

```
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. It receives three incoming calls from different state machines, represented by white boxes on the left. The first call is from `sm_dance_bot::cl_lidar::CbLidarSensor::onEntry`. The second call is from `sm_dance_bot_2::cl_lidar::CbLidarSensor::onEntry`. The third call is from `sm_dance_bot_strikes_back::cl_lidar::CbLidarSensor::onEntry`. Blue arrows indicate the direction of the calls from the state machines to the central sensor component.