

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 dependency or call relationship. Three source boxes on the left point via blue arrows to a single target box on the right. The target box is shaded gray, while the source boxes are white with black borders. The text in the boxes represents function names and namespaces in a C++-like syntax.