

sm\_dance\_bot\_warehouse  
::cl\_nav2z::CpSquareShapeBoundary  
::getForwardDistance

sm\_dance\_bot\_warehouse  
\_2::cl\_nav2z::CpSquareShapeBoundary  
::getForwardDistance

sm\_dance\_bot\_warehouse  
\_3::cl\_nav2z::CpSquareShapeBoundary  
::getForwardDistance

cl\_nav2z::Pose::getYaw

```
graph LR; A["sm_dance_bot_warehouse  
::cl_nav2z::CpSquareShapeBoundary  
::getForwardDistance"] --> D["cl_nav2z::Pose::getYaw"]; B["sm_dance_bot_warehouse  
_2::cl_nav2z::CpSquareShapeBoundary  
::getForwardDistance"] --> D; C["sm_dance_bot_warehouse  
_3::cl_nav2z::CpSquareShapeBoundary  
::getForwardDistance"] --> D;
```

The diagram illustrates a dependency or data flow. Three source boxes on the left, each representing a state machine (sm\_dance\_bot\_warehouse) and a specific boundary type (CpSquareShapeBoundary) with a method (getForwardDistance), have arrows pointing to a single target box on the right. The target box represents a pose object (cl\_nav2z::Pose) and a method (getYaw). The boxes are arranged vertically, with the top box pointing to the target, the middle box pointing to the target, and the bottom box pointing to the target.