

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 data flow or dependency. On the left, there are three rectangular boxes, each containing a string representing a state machine (sm_dance_bot_warehouse) and a method call (cl_nav2z::CpSquareShapeBoundary::getForwardDistance). The first box is labeled 'sm_dance_bot_warehouse', the second 'sm_dance_bot_warehouse_2', and the third 'sm_dance_bot_warehouse_3'. Arrows from each of these three boxes point towards a single rectangular box on the right, which is labeled 'cl_nav2z::Pose::getYaw'. This box is shaded gray and represents the target of the data flow.