

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

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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;
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The diagram illustrates a dependency or data flow. Three source boxes on the left, each containing a state machine name, a namespace, a class name, and a method name, have arrows pointing to a single target box on the right. The target box contains a namespace, a class name, and a method name. The source boxes are labeled 'sm_dance_bot_warehouse', 'sm_dance_bot_warehouse_2', and 'sm_dance_bot_warehouse_3'. The target box is labeled 'cl_nav2z::Pose::getYaw'.