

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). These boxes are labeled with subscripts 1, 2, and 3. Arrows from each of these three boxes point towards a single rectangular box on the right, which contains the string cl\_nav2z::Pose::getYaw. This suggests that the output of the three state machine actions is used to determine the yaw of the pose.