

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;
```

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 arrows indicate that the forward distance information from these three different states is used to determine the yaw of the pose.