

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. On the left, there are three white rectangular boxes with black borders, each containing a text string. These strings represent a sequence of namespace and method calls: 'sm\_dance\_bot\_warehouse', followed by a specific instance identifier ('::cl\_nav2z::CpSquareShapeBoundary' with suffixes '\_2' and '\_3'), and finally a method call '::getForwardDistance'. Blue arrows originate from the right side of each of these three boxes and point towards a single gray rectangular box on the right. This gray box contains the text 'cl\_nav2z::Pose::getYaw', which represents the target of the dependency or the function being called.