

sm\_dance\_bot\_warehouse  
::cl\_lidar::CpForwardObstacle  
Detector::onInitialize



```
graph LR; A["sm_dance_bot_warehouse  
::cl_lidar::CpForwardObstacle  
Detector::onInitialize"] --> B["sm_dance_bot_warehouse  
::cl_lidar::CpForwardObstacle  
Detector::MessageCallbackStoreDistanceToWall"]
```

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::cl\_lidar::CpForwardObstacle  
Detector::MessageCallbackStoreDistanceToWall