

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. 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 with state machines 'sm_dance_bot_warehouse', 'sm_dance_bot_warehouse_2', and 'sm_dance_bot_warehouse_3'. The target box is labeled 'cl_nav2z::Pose::getYaw'.