

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', 'cl\_nav2z::CpSquareShapeBoundary', and 'getForwardDistance'. The first box is at the top, the second in the middle, and the third at the bottom. On the right, there is a single gray rectangular box with a black border containing the text 'cl\_nav2z::Pose::getYaw'. Three blue arrows originate from the right side of each of the three white boxes and point towards the left side of the gray box, indicating that the three source elements contribute to or are used by the target element.