

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 data flow or dependency. On the left, there are three rectangular boxes, each containing a string representing a state machine (sm_dance_bot_warehouse) and a method call (::getForwardDistance) on a specific boundary object (cl_nav2z::CpSquareShapeBoundary). Arrows from each of these three boxes point towards a single rectangular box on the right, which contains the string cl_nav2z::Pose::getYaw. This suggests that the yaw value is derived from or dependent on the forward distance information from these three different states or boundaries.