

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 machine names 'sm\_dance\_bot\_warehouse', 'sm\_dance\_bot\_warehouse\_2', and 'sm\_dance\_bot\_warehouse\_3'. The target box is labeled 'cl\_nav2z::Pose::getYaw'.