

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). These boxes are arranged vertically. On the right, there is a single rectangular box with a gray background, containing the string cl_nav2z::Pose::getYaw. Three blue arrows originate from the right side of each of the three boxes on the left and point towards the left side of the gray box on the right, indicating that the three state machines provide input or data to the pose's yaw value.