

```
graph BT; A["smacc_sm_reference  
_library/sm_dance_bot  
_strikes_back/include  
/sm_dance_bot_strikes_back  
/clients/cl_lidar/components  
/cp_lidar_data.hpp"] --> B["smacc_sm_reference  
_library/sm_dance_bot  
_strikes_back/include  
/sm_dance_bot_strikes_back  
/orthogonals/or_obstacle_perception.hpp"]; B --> C["smacc_sm_reference  
_library/sm_dance_bot  
_strikes_back/include  
/sm_dance_bot_strikes_back  
/sm_dance_bot_strikes_back.hpp"]; C --> D["smacc_sm_reference  
_library/sm_dance_bot  
_strikes_back/src/sm_dance  
_bot_strikes_back/sm_dance  
_bot_strikes_back.cpp"];
```

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_library/sm_dance_bot
_strikes_back/include
/sm_dance_bot_strikes_back
/clients/cl_lidar/components
/cp_lidar_data.hpp

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smacc_sm_reference
_library/sm_dance_bot
_strikes_back/src/sm_dance
_bot_strikes_back/sm_dance
_bot_strikes_back.cpp