

tesseract_motion_planners
/trajopt/include/tesseract
_motion_planners/trajopt/trajopt_utils.h

```
graph BT; A["tesseract_motion_planners  
/trajopt/src/profile/trajopt  
_default_composite_profile.cpp"] --> B["tesseract_motion_planners  
/trajopt/include/tesseract  
_motion_planners/trajopt/trajopt_utils.h"]; C["tesseract_motion_planners  
/trajopt/src/profile/trajopt  
_default_plan_profile.cpp"] --> B; D["tesseract_motion_planners  
/trajopt/src/trajopt_utils.cpp"] --> B;
```

The diagram illustrates the inclusion relationships between four files in the tesseract_motion_planners library. At the top is a header file, `trajopt_utils.h`, which is included by three source files located in the `src` directory. The source files are `_default_composite_profile.cpp`, `_default_plan_profile.cpp`, and `trajopt_utils.cpp`. Blue arrows point from each source file to the header file, indicating the direction of the include relationship.

tesseract_motion_planners
/trajopt/src/profile/trajopt
_default_composite_profile.cpp

tesseract_motion_planners
/trajopt/src/profile/trajopt
_default_plan_profile.cpp

tesseract_motion_planners
/trajopt/src/trajopt_utils.cpp