

tesseract\_scene\_graph  
/include/tesseract\_scene  
\_graph/srdf/group\_rop\_kinematics.h

```
graph BT; A["tesseract_scene_graph  
/src/srdf_model.cpp"] --> C["tesseract_scene_graph  
/include/tesseract_scene_graph/srdf/group_rop_kinematics.h"]; B["tesseract_scene_graph  
/test/tesseract_scene_graph_srdf_unit.cpp"] --> C;
```

The diagram illustrates the inclusion relationships between three files in the tesseract\_scene\_graph project. At the top is a header file, 'tesseract\_scene\_graph/include/tesseract\_scene\_graph/srdf/group\_rop\_kinematics.h', which is shaded gray. Below it are two source files: 'tesseract\_scene\_graph/src/srdf\_model.cpp' on the left and 'tesseract\_scene\_graph/test/tesseract\_scene\_graph\_srdf\_unit.cpp' on the right. Blue arrows point from each source file to the header file, indicating that both source files include this header.

tesseract\_scene\_graph  
/src/srdf\_model.cpp

tesseract\_scene\_graph  
/test/tesseract\_scene  
\_graph\_srdf\_unit.cpp