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graph BT; A["smacc_sm_reference_library/sm_dance_bot/src/sm_dance_bot.cpp"] --> B["smacc_sm_reference_library/sm_dance_bot/include/sm_dance_bot/sm_dance_bot.h"]; B --> C["smacc_sm_reference_library/sm_dance_bot/superstates/ss_f_pattern_1.h"]; C --> D["smacc_sm_reference_library/sm_dance_bot/include/sm_dance_bot/sti_fpattern_rotate_2.h"]
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smacc_sm_reference
_library/sm_dance_bot
/include/sm_dance_bot
/states/f_pattern_states
/sti_fpattern_rotate_2.h

smacc_sm_reference
_library/sm_dance_bot
/include/sm_dance_bot
/superstates/ss_f_pattern_1.h

smacc_sm_reference
_library/sm_dance_bot
/include/sm_dance_bot
/sm_dance_bot.h

smacc_sm_reference
_library/sm_dance_bot
/src/sm_dance_bot.cpp