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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_1.h"]
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smacc\_sm\_reference  
\_library/sm\_dance\_bot  
/include/sm\_dance\_bot  
/states/f\_pattern\_states  
/sti\_fpattern\_rotate\_1.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