

```
graph BT; A["smacc_sm_reference_library/sm_moveit_3/src/sm_moveit_3_node.cpp"] --> B["smacc_sm_reference_library/sm_moveit_3/include/sm_moveit_3/sm_moveit_3.h"]; B --> C["smacc_sm_reference_library/sm_moveit_3/include/sm_moveit_3/superstates/ss_pick_object.h"]; C --> D["smacc_sm_reference_library/sm_moveit_3/include/sm_moveit_3/states/pick_states/st_grasp_approach.h"];
```

smacc_sm_reference
_library/sm_moveit_3
_include/sm_moveit_3
_states/pick_states/st
_grasp_approach.h

smacc_sm_reference
_library/sm_moveit_3
_include/sm_moveit_3
_superstates/ss_pick_object.h

smacc_sm_reference
_library/sm_moveit_3
_include/sm_moveit_3
_sm_moveit_3.h

smacc_sm_reference
_library/sm_moveit_3
_src/sm_moveit_3_node.cpp