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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/include/sm_dance_bot/st_navigate_to_waypoints_x.h"]
```

smacc_sm_reference
_library/sm_dance_bot
_include/sm_dance_bot
/states/st_navigate_to
_waypoints_x.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