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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_waypoint_1.h"]
```

smacc\_sm\_reference  
\_library/sm\_dance\_bot  
\_include/sm\_dance\_bot  
/states/st\_navigate\_to  
\_waypoint\_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