

```
graph BT; A["smacc_sm_reference_library/sm_moveit_2/src/sm_moveit_2_node.cpp"] --> B["smacc_sm_reference_library/sm_moveit_2/include/sm_moveit_2/sm_moveit_2.h"]; B --> C["smacc_sm_reference_library/sm_moveit_2/include/sm_moveit_2/superstates/ss_pick_object.h"]; C --> D["smacc_sm_reference_library/sm_moveit_2/include/sm_moveit_2/states/pick_states/st_grasp_approach.h"];
```

smacc_sm_reference
_library/sm_moveit_2
_include/sm_moveit_2
_states/pick_states/st
_grasp_approach.h

smacc_sm_reference
_library/sm_moveit_2
_include/sm_moveit_2
_superstates/ss_pick_object.h

smacc_sm_reference
_library/sm_moveit_2
_include/sm_moveit_2
_sm_moveit_2.h

smacc_sm_reference
_library/sm_moveit_2
_src/sm_moveit_2_node.cpp