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graph BT; A["smacc_sm_reference  
_library/sm_dance_bot_2/src/sm_dance_bot_2.cpp"] --> B["smacc_sm_reference  
_library/sm_dance_bot_2/sm_dance_bot_2.h"]; B --> C["smacc_sm_reference  
_library/sm_dance_bot_2/states/ms_dance_bot_run_mode/s_pattern_states/ss_s_pattern_1.h"]; C --> D["smacc_sm_reference  
_library/sm_dance_bot_2/states/ms_dance_bot_run_mode/s_pattern_states/stipattern_rotate_1.h"]
```

smacc\_sm\_reference  
\_library/sm\_dance\_bot\_2/include/sm\_dance\_bot\_2/states/ms\_dance\_bot\_run\_mode/s\_pattern\_states/stipattern\_rotate\_1.h

smacc\_sm\_reference  
\_library/sm\_dance\_bot\_2/include/sm\_dance\_bot\_2/states/ms\_dance\_bot\_run\_mode/s\_pattern\_states/ss\_s\_pattern\_1.h

smacc\_sm\_reference  
\_library/sm\_dance\_bot\_2/include/sm\_dance\_bot\_2/sm\_dance\_bot\_2.h

smacc\_sm\_reference  
\_library/sm\_dance\_bot\_2/src/sm\_dance\_bot\_2.cpp