

```
graph BT; A["smacc_sm_reference  
_library/sm_fetch_robot  
_asynchronous_orthogonals  
/include/sm_fetch_robot_asynchronous  
_orthogonals/orthogonals/or_gripper.h"] --> B["smacc_sm_reference  
_library/sm_fetch_robot  
_asynchronous_orthogonals  
/include/sm_fetch_robot_asynchronous  
_orthogonals/sm_fetch_robot_asynchronous  
_orthogonals.h"]; B --> C["smacc_sm_reference  
_library/sm_fetch_robot  
_asynchronous_orthogonals  
/src/sm_fetch_robot_asynchronous  
_orthogonals_node.cpp"];
```

smacc\_sm\_reference  
\_library/sm\_fetch\_robot  
\_asynchronous\_orthogonals  
/include/sm\_fetch\_robot\_asynchronous  
\_orthogonals/orthogonals/or\_gripper.h

smacc\_sm\_reference  
\_library/sm\_fetch\_robot  
\_asynchronous\_orthogonals  
/include/sm\_fetch\_robot\_asynchronous  
\_orthogonals/sm\_fetch\_robot\_asynchronous  
\_orthogonals.h

smacc\_sm\_reference  
\_library/sm\_fetch\_robot  
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/src/sm\_fetch\_robot\_asynchronous  
\_orthogonals\_node.cpp