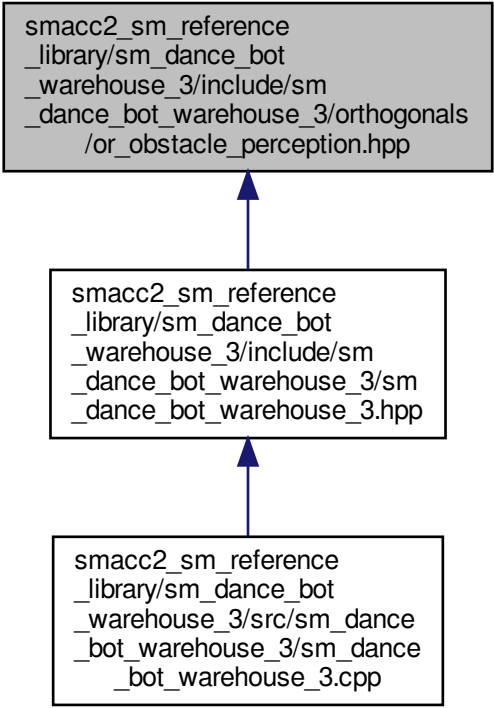


smacc2_sm_reference
_library/sm_dance_bot
_warehouse_3/include/sm
_dance_bot_warehouse_3/orthogonals
/or_obstacle_perception.hpp



```
graph BT; A["smacc2_sm_reference_library/sm_dance_bot_warehouse_3/src/sm_dance_bot_warehouse_3/sm_dance_bot_warehouse_3.cpp"] --> B["smacc2_sm_reference_library/sm_dance_bot_warehouse_3/include/sm_dance_bot_warehouse_3/sm_dance_bot_warehouse_3.hpp"]; B --> C["smacc2_sm_reference_library/sm_dance_bot_warehouse_3/include/sm_dance_bot_warehouse_3/orthogonals/or_obstacle_perception.hpp"];
```

smacc2_sm_reference
_library/sm_dance_bot
_warehouse_3/include/sm
_dance_bot_warehouse_3/sm
_dance_bot_warehouse_3.hpp

smacc2_sm_reference
_library/sm_dance_bot
_warehouse_3/src/sm_dance
_bot_warehouse_3/sm_dance
_bot_warehouse_3.cpp