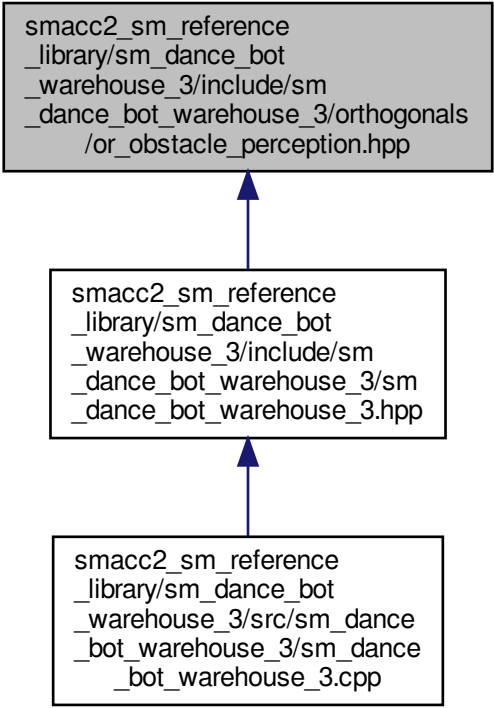


smacc2\_sm\_reference  
\_library/sm\_dance\_bot  
\_warehouse\_3/include/sm  
\_dance\_bot\_warehouse\_3/orthogonals  
/or\_obstacle\_perception.hpp



```
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