

smacc2\_sm\_reference  
\_library/sm\_dance\_bot  
\_warehouse\_2/include/sm  
\_dance\_bot\_warehouse\_2/orthogonals  
/or\_obstacle\_perception.hpp



```
graph BT; A["smacc2_sm_reference_library/sm_dance_bot_warehouse_2/src/sm_dance_bot_warehouse_2/sm_dance_bot_warehouse_2.cpp"] --> B["smacc2_sm_reference_library/sm_dance_bot_warehouse_2/include/sm_dance_bot_warehouse_2/sm_dance_bot_warehouse_2.hpp"]; B --> C["smacc2_sm_reference_library/sm_dance_bot_warehouse_2/include/sm_dance_bot_warehouse_2/orthogonals/or_obstacle_perception.hpp"];
```

The diagram illustrates the include chain for the file `sm_dance_bot_warehouse_2.cpp`. It starts at the bottom with the source file, moves up to the `sm_dance_bot_warehouse_2.hpp` header file, and then up to the `orthogonals/or_obstacle_perception.hpp` header file. Each step is indicated by a blue arrow pointing upwards.

smacc2\_sm\_reference  
\_library/sm\_dance\_bot  
\_warehouse\_2/include/sm  
\_dance\_bot\_warehouse\_2/sm  
\_dance\_bot\_warehouse\_2.hpp

smacc2\_sm\_reference  
\_library/sm\_dance\_bot  
\_warehouse\_2/src/sm\_dance  
\_bot\_warehouse\_2/sm\_dance  
\_bot\_warehouse\_2.cpp