

```
blmc_robots::NJointBlmcRobot  
Driver< robot_interfaces  
::NFingerObservation< N_FINGERS  
>, N_FINGERS *robot_interfaces  
::JOINTS_PER_FINGER, N_FINGERS  
*robot_interfaces::BOARDS_PER_FINGER >
```

```
robot_fingers::NFingerDriver< 1 >
```

```
robot_fingers::RealFinger  
Driver
```

