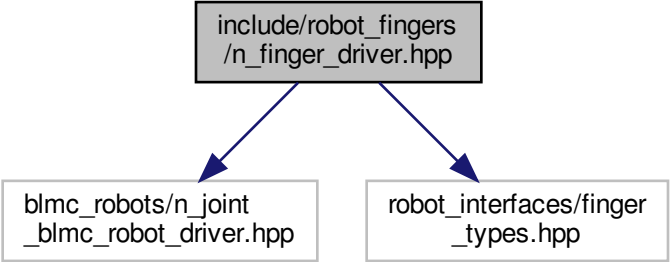


include/robot_fingers
/n_finger_driver.hpp



```
graph TD; A["include/robot_fingers  
/n_finger_driver.hpp"] --> B["blmc_robots/n_joint  
_blmc_robot_driver.hpp"]; A --> C["robot_interfaces/finger  
_types.hpp"]
```

blmc_robots/n_joint
_blmc_robot_driver.hpp

robot_interfaces/finger
_types.hpp