

/home/bonnie/ros\_ws  
/src/progetto\_robotica  
/publisher\_pkg/include  
/publisher\_pkg/kinematics.h

```
graph TD; A["/home/bonnie/ros_ws  
/src/progetto_robotica  
/publisher_pkg/include  
/publisher_pkg/kinematics.h"] --> B[iostream]; A --> C[eigen3/Eigen/Core]; A --> D[eigen3/Eigen/Dense]; A --> E[math.h]; A --> F[vector];
```

iostream

eigen3/Eigen/Core

eigen3/Eigen/Dense

math.h

vector