

/home/ubuntu/ros2_ws
/src/CanRobotControl
/wm_motion_controller
/include/can/can_send.hpp

```
graph BT; A["/home/ubuntu/ros2_ws  
/src/CanRobotControl  
/wm_motion_controller  
/src/can/can_adaptor.cpp"] --> C["/home/ubuntu/ros2_ws  
/src/CanRobotControl  
/wm_motion_controller  
/include/can/can_send.hpp"]; B["/home/ubuntu/ros2_ws  
/src/CanRobotControl  
/wm_motion_controller  
/src/can/can_send.cpp"] --> C;
```

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