

/home/ubuntu/ros2_ws
/src/CanRobotControl
/wm_motion_controller
/include/mediator/i_motion
_mediator.hpp

colleague/i_motion
_colleague.hpp

memory

```
graph TD; A["/home/ubuntu/ros2_ws  
/src/CanRobotControl  
/wm_motion_controller  
/include/mediator/i_motion  
_mediator.hpp"] --> B["colleague/i_motion  
_colleague.hpp"]; B --> A; B --> C[memory]; A --> C;
```