

submodules/robot\_controllers  
/robot\_controllers/include  
/robot\_controllers/trajectory.h

```
graph TD; A["submodules/robot_controllers<br>/robot_controllers/include<br>/robot_controllers/trajectory.h"] --> B["ros/ros.h"]; A --> C["angles/angles.h"]; A --> D["trajectory_msgs/JointTrajectory.h"];
```

ros/ros.h

angles/angles.h

trajectory\_msgs/JointTrajectory.h