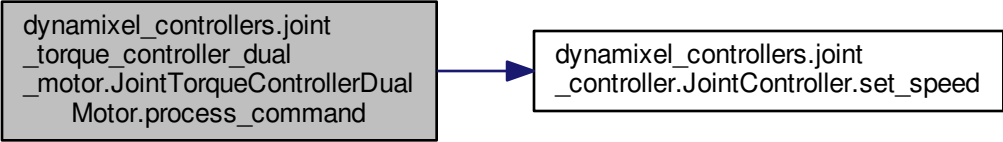


dynamixel_controllers.joint
_torque_controller_dual
_motor.JointTorqueControllerDual
Motor.process_command



```
graph LR; A["dynamixel_controllers.joint_torque_controller_dual_motor.JointTorqueControllerDual Motor.process_command"] --> B["dynamixel_controllers.joint_controller.JointController.set_speed"]
```

dynamixel_controllers.joint
_controller.JointController.set_speed