

dynamixel_controllers.joint
_position_controller_dual
_motor.JointPositionControllerDual.process_command



```
graph LR; A["dynamixel_controllers.joint_position_controller_dual_motor.JointPositionControllerDual.process_command"] --> B["dynamixel_controllers.joint_controller.JointController.rad_to_raw"]
```

dynamixel_controllers.joint
_controller.JointController.rad_to_raw