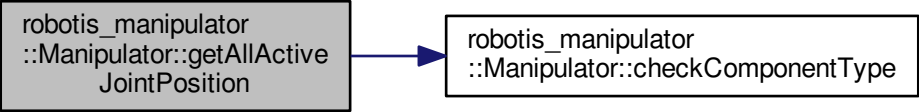


robotis_manipulator
::Manipulator::getAllActive
JointPosition



```
graph LR; A["robotis_manipulator::Manipulator::getAllActiveJointPosition"] --> B["robotis_manipulator::Manipulator::checkComponentType"]
```

A diagram showing a call from the `robotis_manipulator::Manipulator::getAllActiveJointPosition` method to the `robotis_manipulator::Manipulator::checkComponentType` method. The call is represented by a blue arrow pointing from the left box to the right box.

robotis_manipulator
::Manipulator::checkComponentType