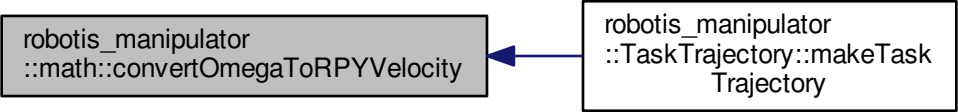


```
robotis_manipulator  
::math::convertOmegaToRPYVelocity
```



```
graph LR; A[robotis_manipulator::TaskTrajectory::makeTaskTrajectory] --> B[robotis_manipulator::math::convertOmegaToRPYVelocity];
```

```
robotis_manipulator  
::TaskTrajectory::makeTask  
Trajectory
```