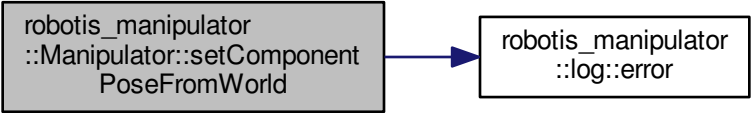


robotis_manipulator
::Manipulator::setComponent
PoseFromWorld



```
graph LR; A["robotis_manipulator  
::Manipulator::setComponent  
PoseFromWorld"] --> B["robotis_manipulator  
::log::error"]
```

robotis_manipulator
::log::error