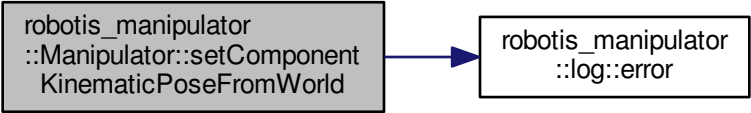


robotis\_manipulator  
::Manipulator::setComponent  
KinematicPoseFromWorld



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

robotis\_manipulator  
::log::error