```
robotis manipulator
        ··Minimum Jerk

    coefficient

     + MinimumJerk()
     + ~MinimumJerk()
     + calcCoefficient()
      + getCoefficient()
                -minimum jerk trajectory
                        generator
robotis manipulator
       ::JointTrajectory
- coefficient size
- minimum jerk coefficient
+ JointTrajectory()
```

+ ~JointTrajectory()+ makeJointTrajectory()+ getMinimumJerkCoefficient()

+ getJointWaypoint()