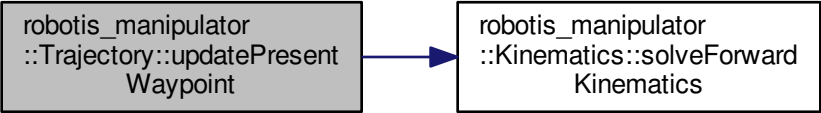


robotis_manipulator
::Trajectory::updatePresent
Waypoint



```
graph LR; A["robotis_manipulator::Trajectory::updatePresentWaypoint"] --> B["robotis_manipulator::Kinematics::solveForwardKinematics"]
```

robotis_manipulator
::Kinematics::solveForward
Kinematics