```
robotis manipulator
        ··Minimum.lerk

    coefficient

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

+ TaskTrajectory() + ~TaskTrajectory() + makeTaskTrajectory() + getMinimumJerkCoefficient()

+ getTaskWaypoint()