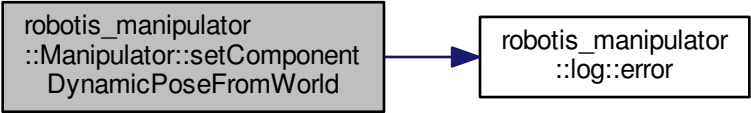


```
robotis_manipulator  
::Manipulator::setComponent  
DynamicPoseFromWorld
```



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

```
robotis_manipulator  
::log::error
```