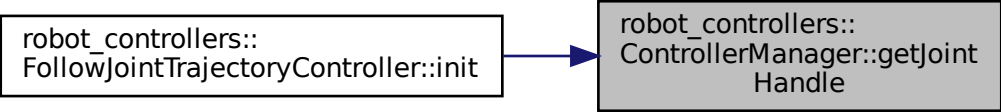


robot_controllers::
FollowJointTrajectoryController::init



```
graph LR; A["robot_controllers::  
FollowJointTrajectoryController::init"] --> B["robot_controllers::  
ControllerManager::getJoint  
Handle"]
```

robot_controllers::
ControllerManager::getJoint
Handle