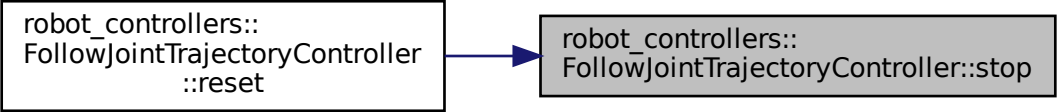


```
robot_controllers::  
FollowJointTrajectoryController  
::reset
```



```
robot_controllers::  
FollowJointTrajectoryController::stop
```