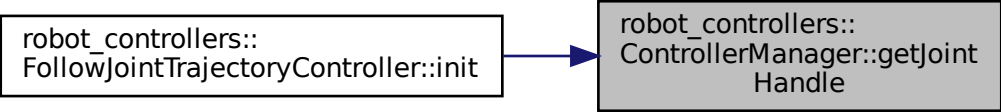


robot_controllers::
FollowJointTrajectoryController::init



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

robot_controllers::
ControllerManager::getJoint
Handle