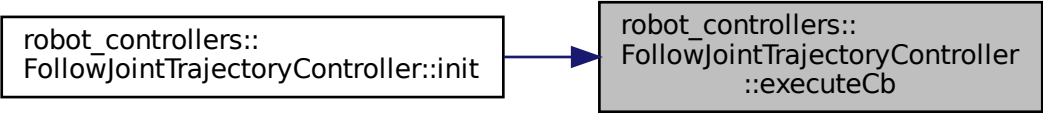


```
robot_controllers::  
FollowJointTrajectoryController::init
```



```
graph LR; A[robot_controllers::  
FollowJointTrajectoryController::init] --> B[robot_controllers::  
FollowJointTrajectoryController  
::executeCb];
```

```
robot_controllers::  
FollowJointTrajectoryController  
::executeCb
```