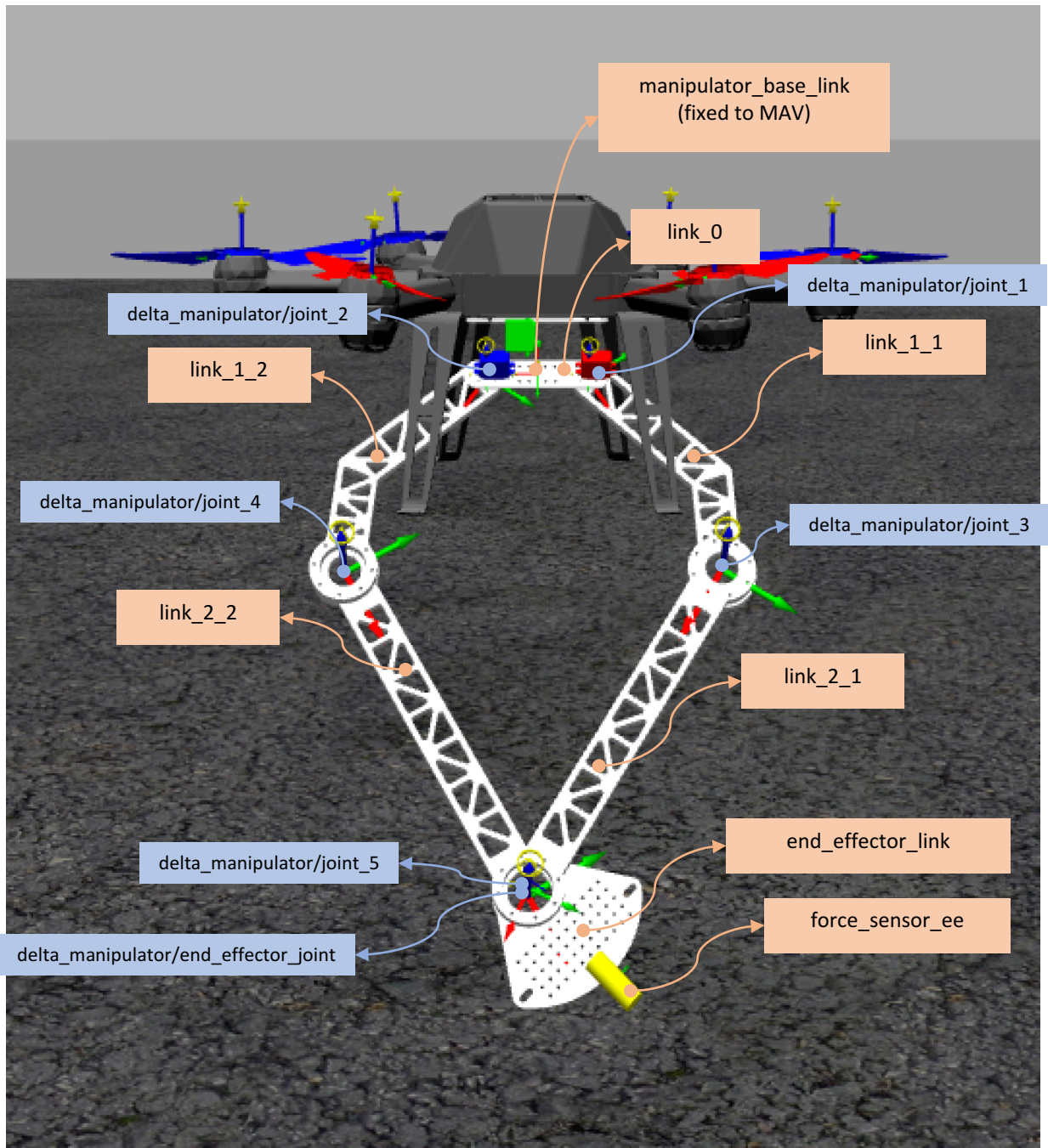# Simulation of delta_manipulator in RotorS

To launch this simulation:

```
roslaunch rotors_gazebo mav_with_delta_manipulator.launch
mav_name:=neo11
```

Simulation of delta_manipulator in RotorS

Topics:

The motor commands are sent to the topic
`${mav_name}/delta_manipulator/command/trajectory`. The message type is
`trajectory_msgs/JointTrajecotry`. The joint name field must match the joint name
defined in the xacro file.

The joint states are published on the topics
`${mav_name}/delta_manipulator/${motor_name}`.

The topic `${mav_name}/delta_manipulator/joint_states` combines the state of
all joints.