Adding Custom Controllers

- Interface Decide   JTC
  - Yaml File
  - Urdf Ros2 Tags
  - Launching Control Manager

```
controller_manager:
  ros__parameters:
    update_rate: 100  # H

    joint_state_broadcaster:
      type: joint_state_broadcaster/JointStateBroadcaster
    joint_trajectory_controller:
      type: joint_trajectory_controller/JointTrajectoryController


joint_trajectory_controller:
  ros__parameters:
    joints:
      - joint_1
      - joint_2
      - joint_3
      - joint_4
      - joint_5
      - joint_6
      - left_gripper_finger_joint
      - right_gripper_finger_joint

    command_interfaces:
      - position

    state_interfaces:
      - position

    state_publish_rate: 50.0 # Defaults to 50
    action_monitor_rate: 20.0 # Defaults to 20
```

Joint position Trajectory controller