Example different ways to run the Atlas StandingEndEffectorController

Drake-only

End effectors
- Right Hand CTRL — r_ee_des
- Left Hand CTRL — l_ee_des
- Gaze CTRL — gaze_des
- …

COM CTRL — com_des
Support Bodies — supports
Nominal Pose — q_nom

Standing end effector controller — q_desired → PD → u → Atlas → x

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Gazebo + PD Control plugin

End effectors
- Right Hand CTRL — r_ee_des
- Left Hand CTRL — l_ee_des
- Head CTRL — gaze_des
- …

COM CTRL — com_des
Support Bodies — supports
Nominal Pose — q_nom

Standing end effector controller — JOINT_POSITION_CMDS → Gazebo

EST_ROBOT_STATE

LCM refrences

LCM-verse
- R_HAND_GOAL
- L_HAND_GOAL
- GAZE_GOAL
- COM_GOAL
- ACTIVE_SUPPORTS
- NOMINAL_POS_GOAL

Standing end effector controller — JOINT_POSITION_CMDS → Gazebo

EST_ROBOT_STATE