

Parameter File

```
controller_manager:  
  ros_parameters:  
    :  
  joint_state_broadcaster:  
    ros_parameters:  
      joints:  
        - joint1  
        - joint2  
    :  
  forward_position_controller:  
    ros_parameters:  
      joints:  
        - joint1  
        - joint2
```

The same
"joints"
keyword, but
different
meaning



Load

Controllers

Forward command



Joint Trajectory



Broadcasters

Joint State Broadcaster



For **Joint State Broadcaster**, if you want to specify "joints", you also need and "interfaces". If either is not specified, it broadcasts **ALL** joints specified in URDF. See the [Doc](#).

ROS2 Control Framework

- [Controller Manager](#)
- [Resource manager](#)

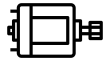
Controllers want to control the hardware.
All components are here to assist it.

Hardware Components

create your
own hardware
Interface if you
use existing
controllers



my_hardware



Load



```
<ros2_control>  
<hardware>  
  <pluginin>my_hardware</pluginin>  
  :  
</ros2_control>
```



URDF

URDF

```
<library path="my_package">  
<class name="my_hardware"  
  type="asdf::MyHardware"  
  base_class_type="hardware_interface::SystemInterface">  
  :  
</library path="my_package">
```



plugin.xml

Pluginlib

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