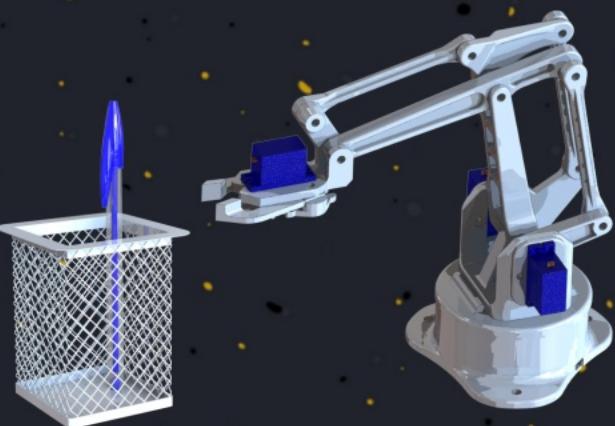
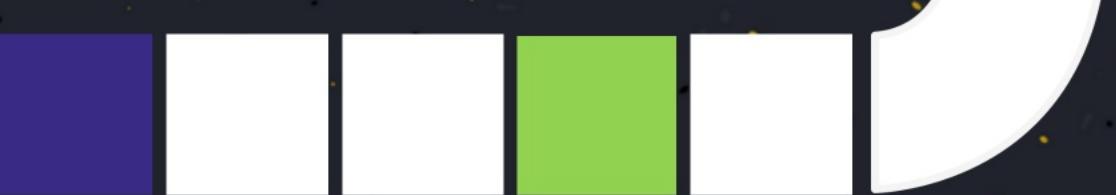
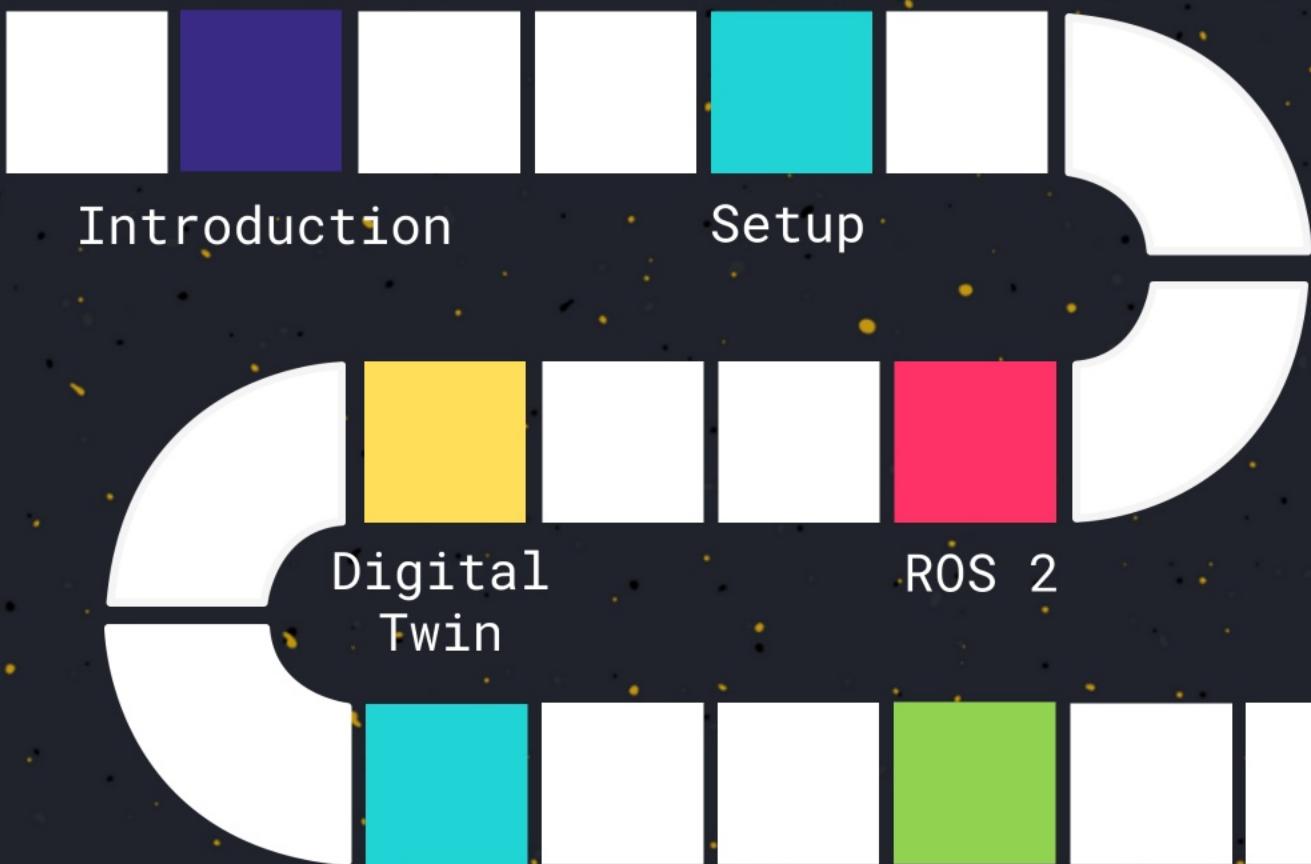
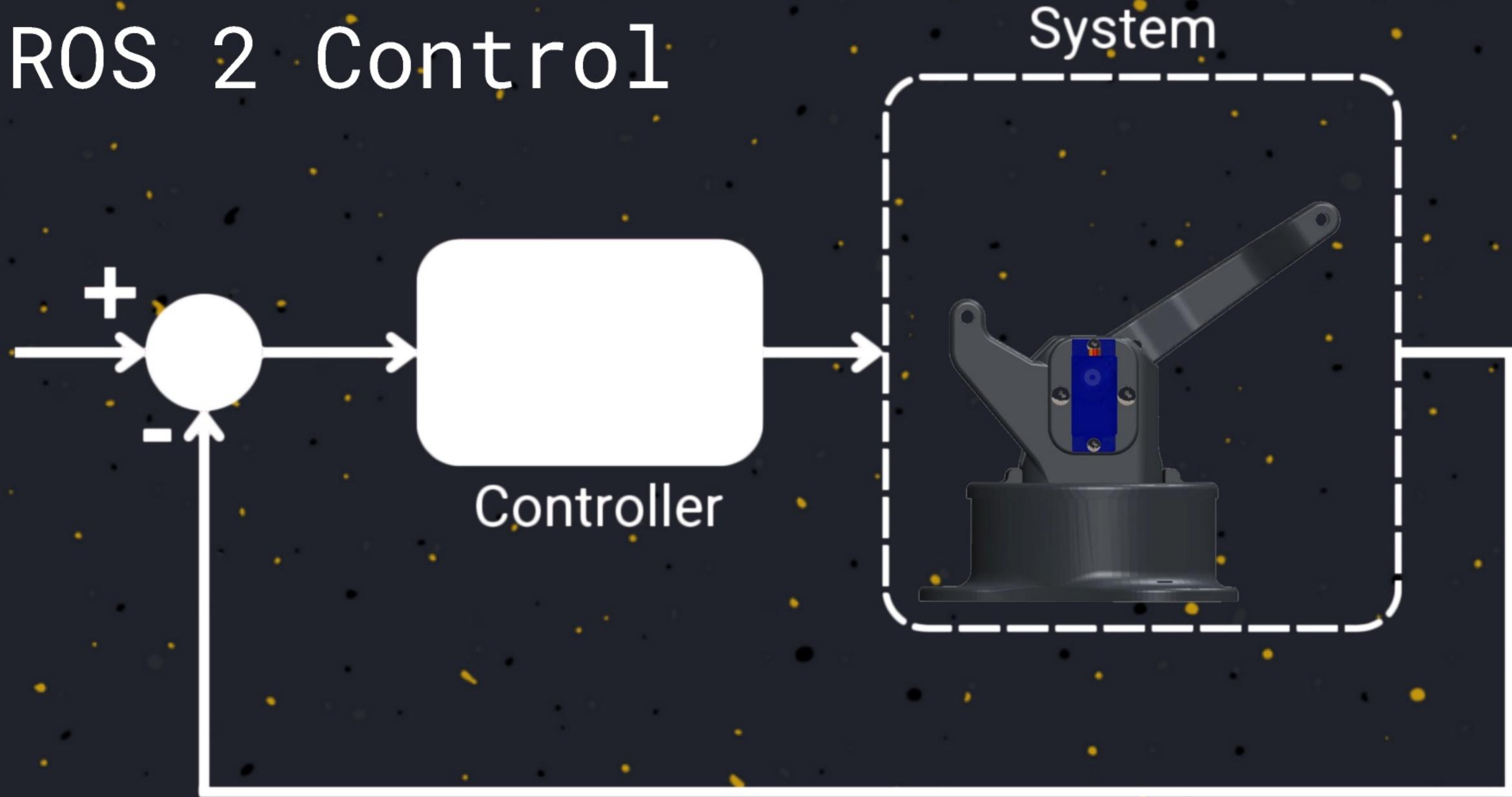


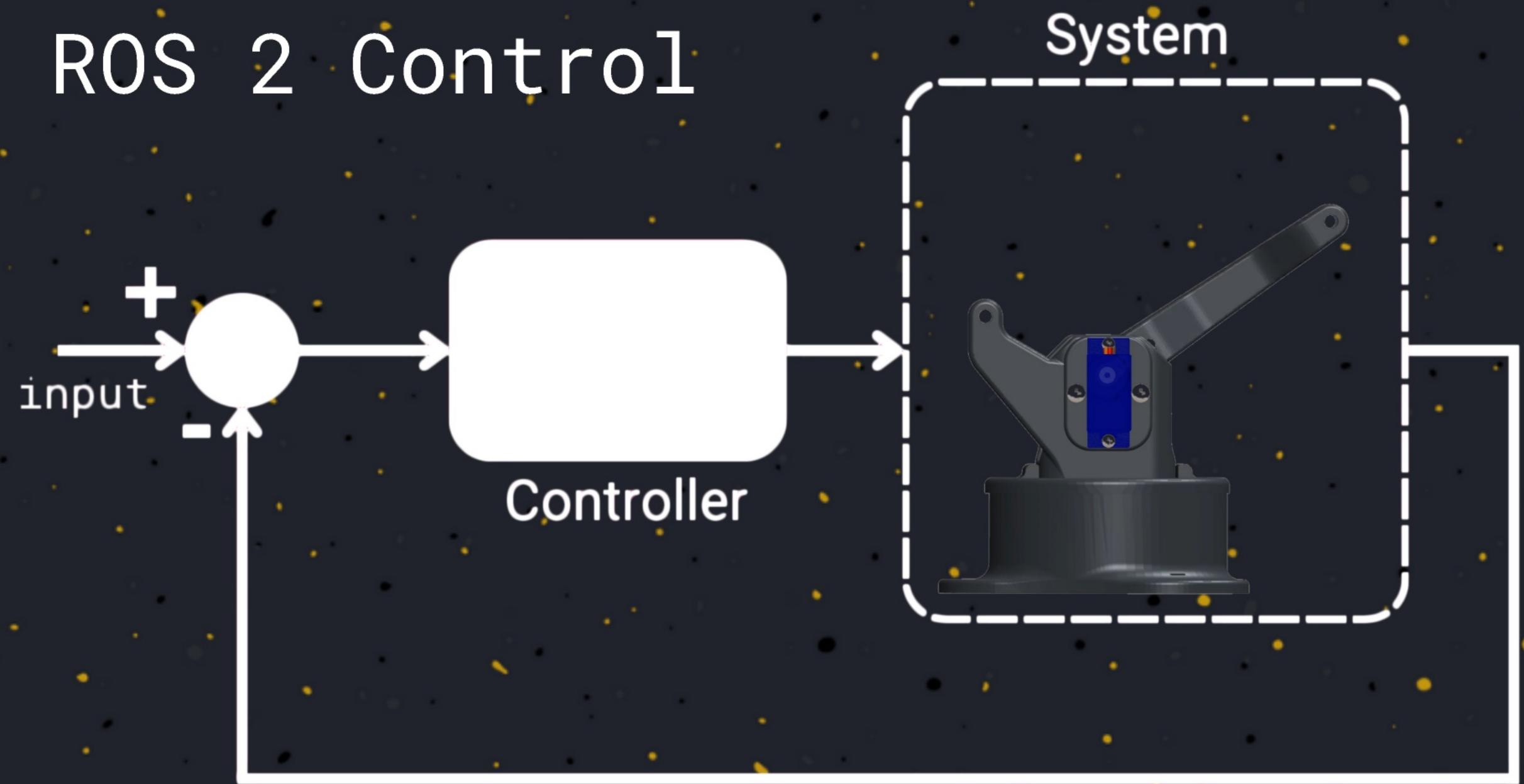
# Arduinobot



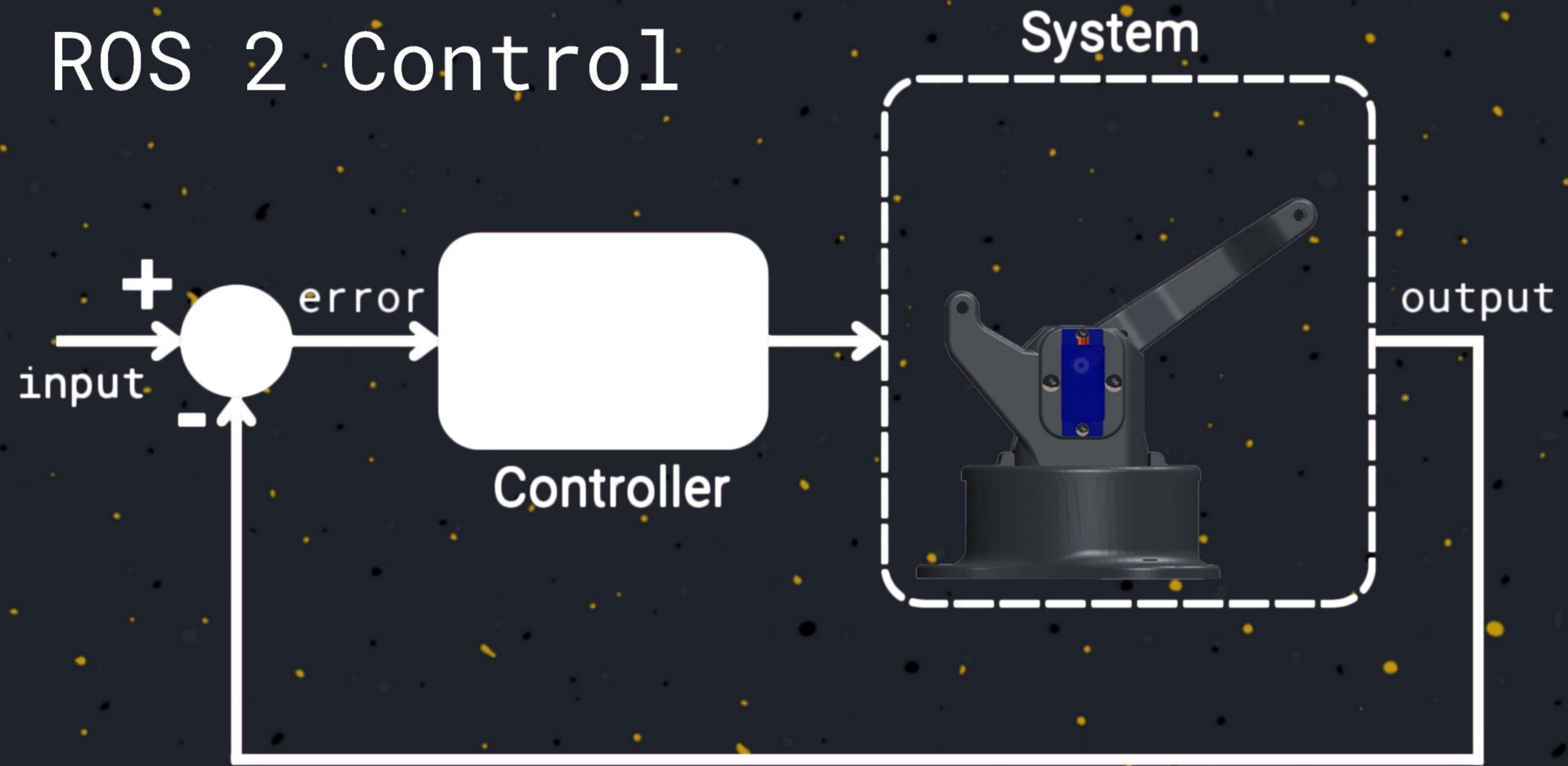
# ROS 2 Control



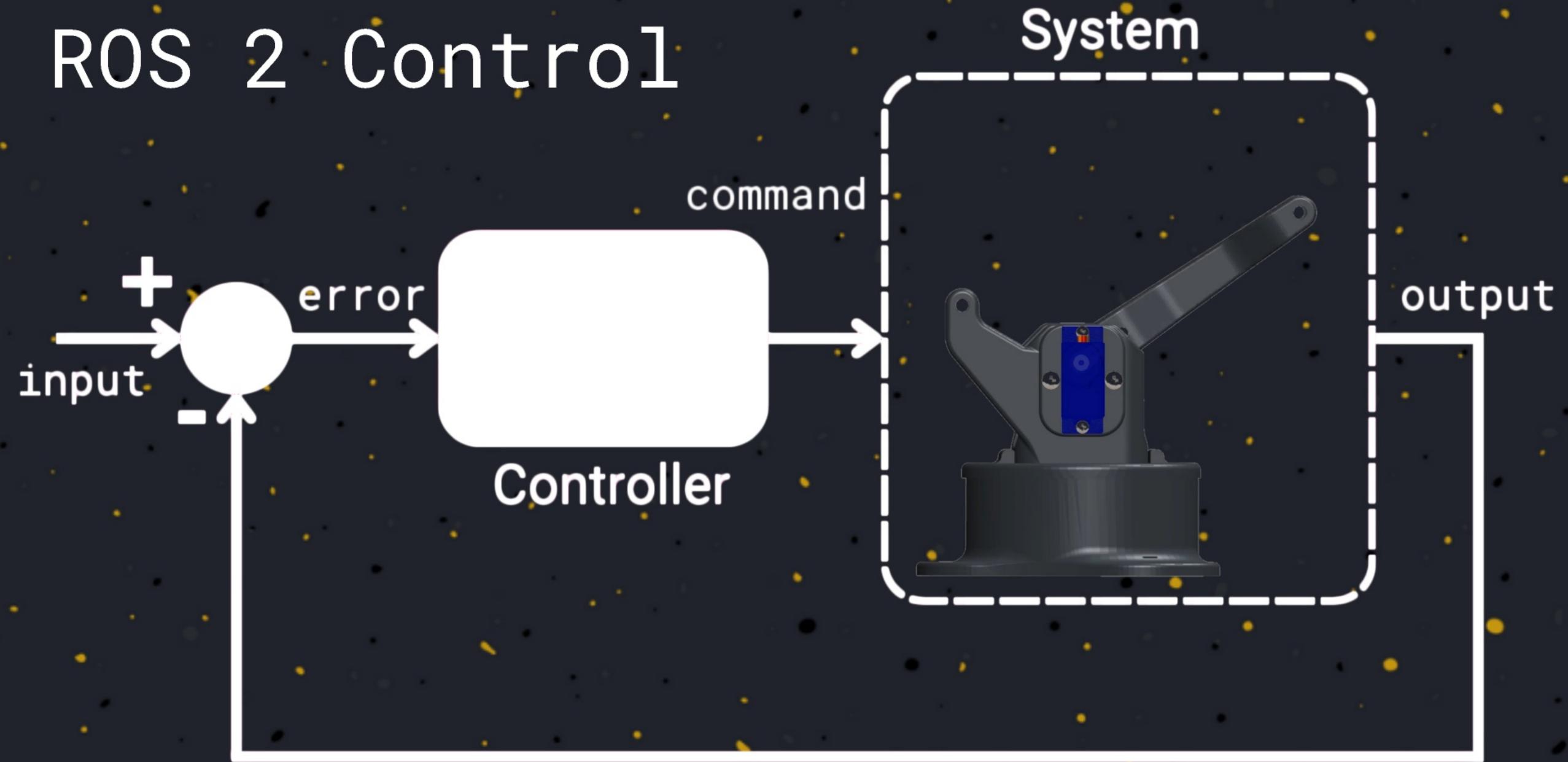
# ROS 2 Control



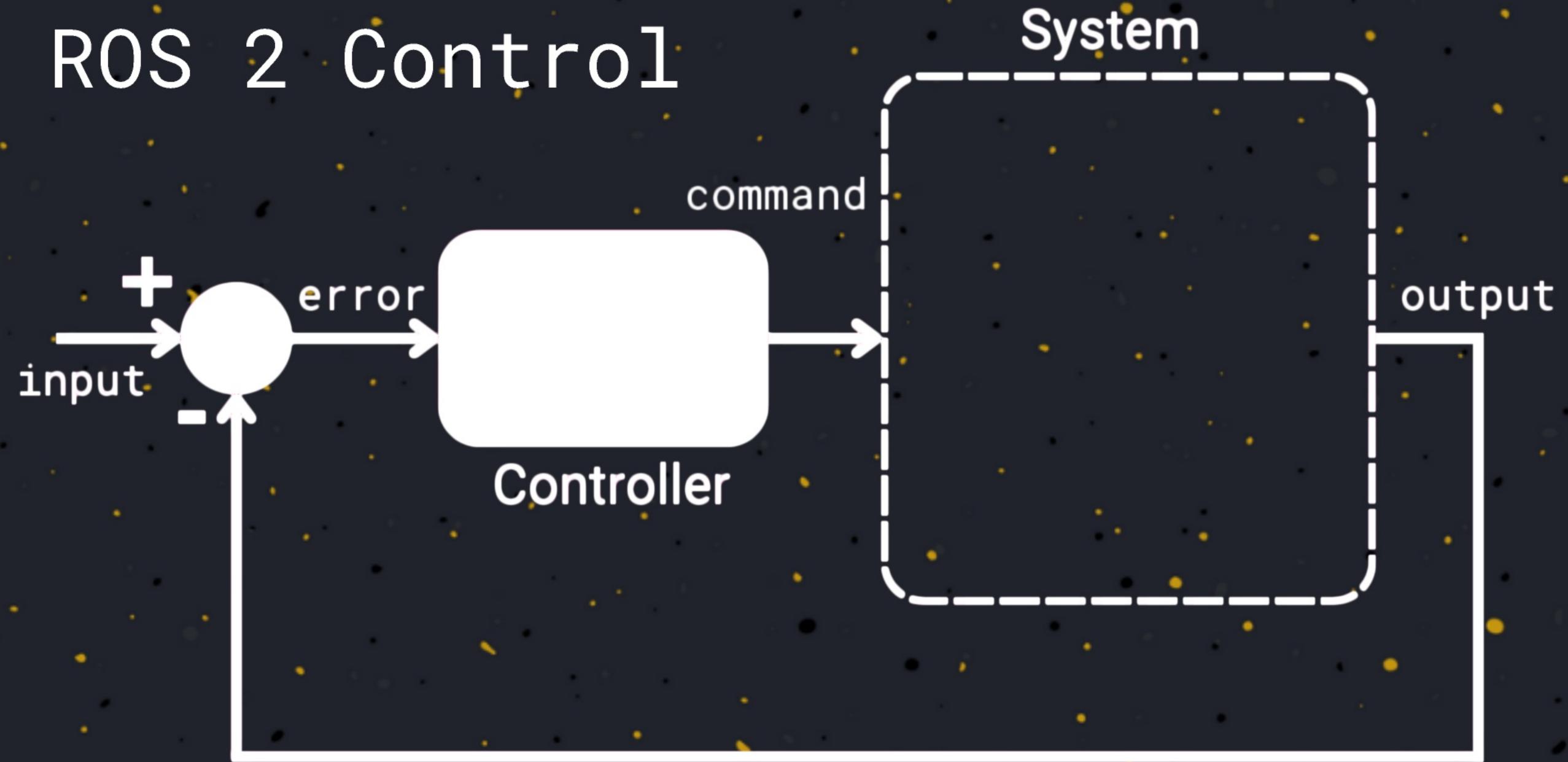
# ROS 2 Control



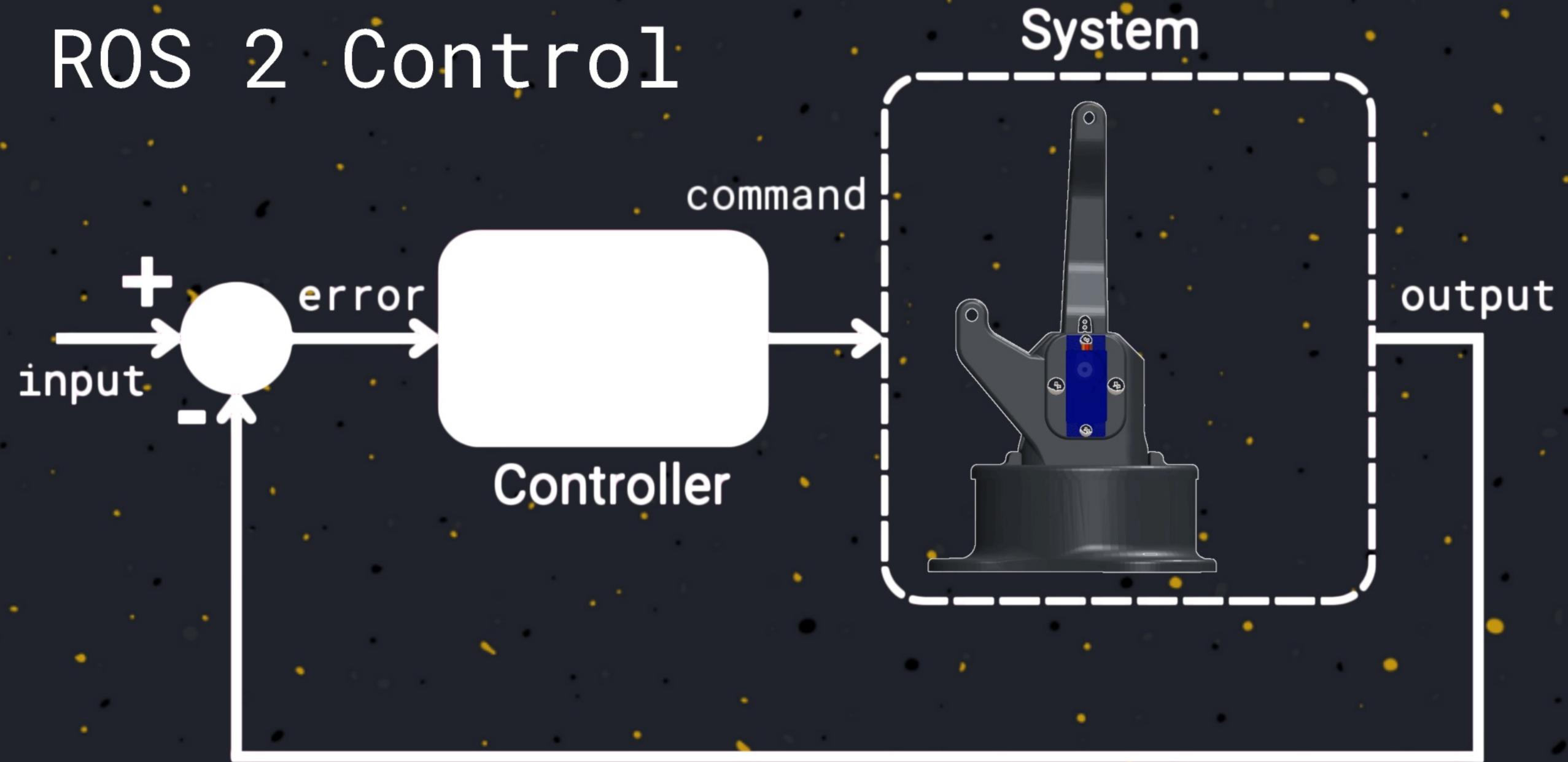
# ROS 2 Control



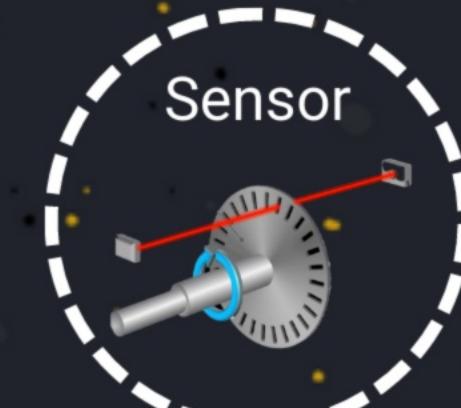
# ROS 2 Control



# ROS 2 Control



# Hardware Resources



Sensor

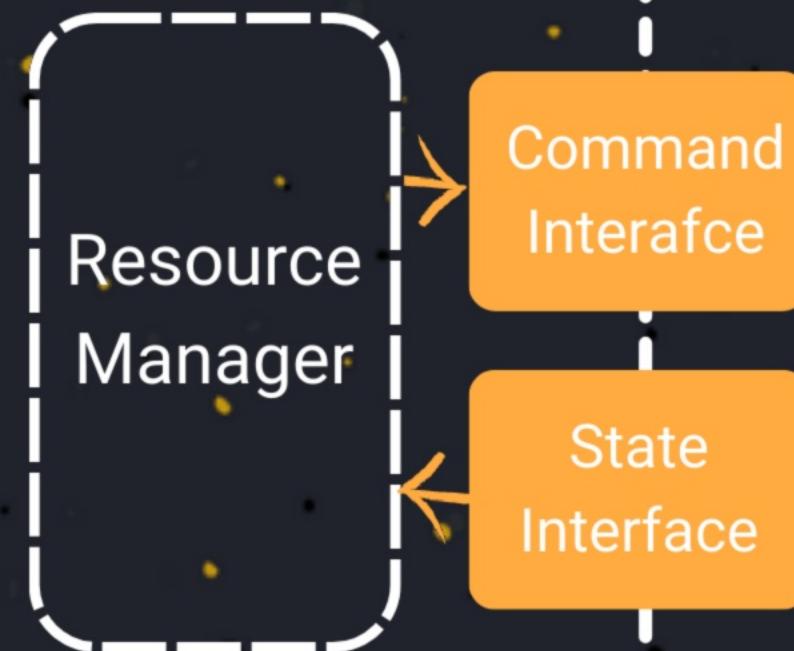


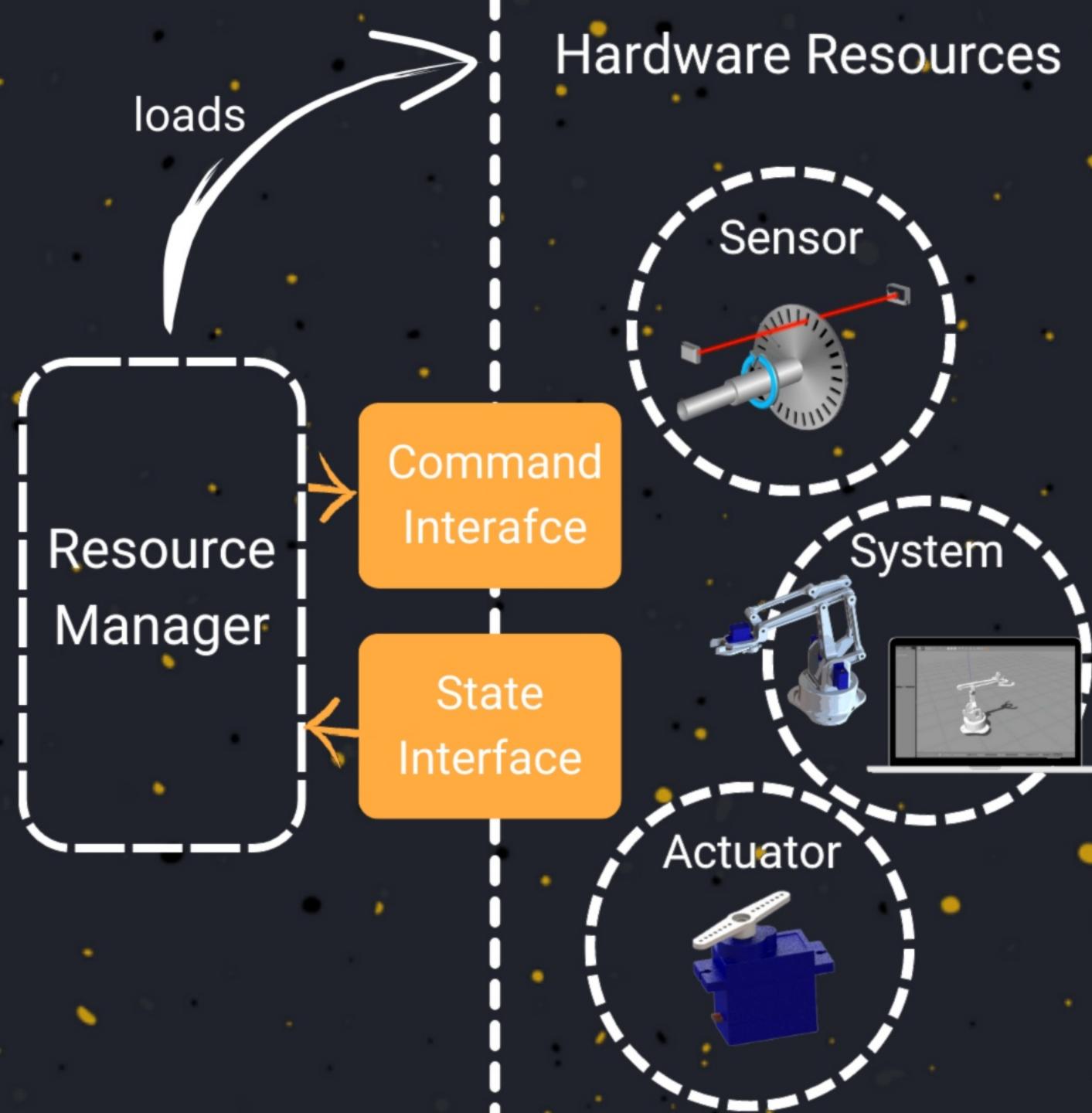
System

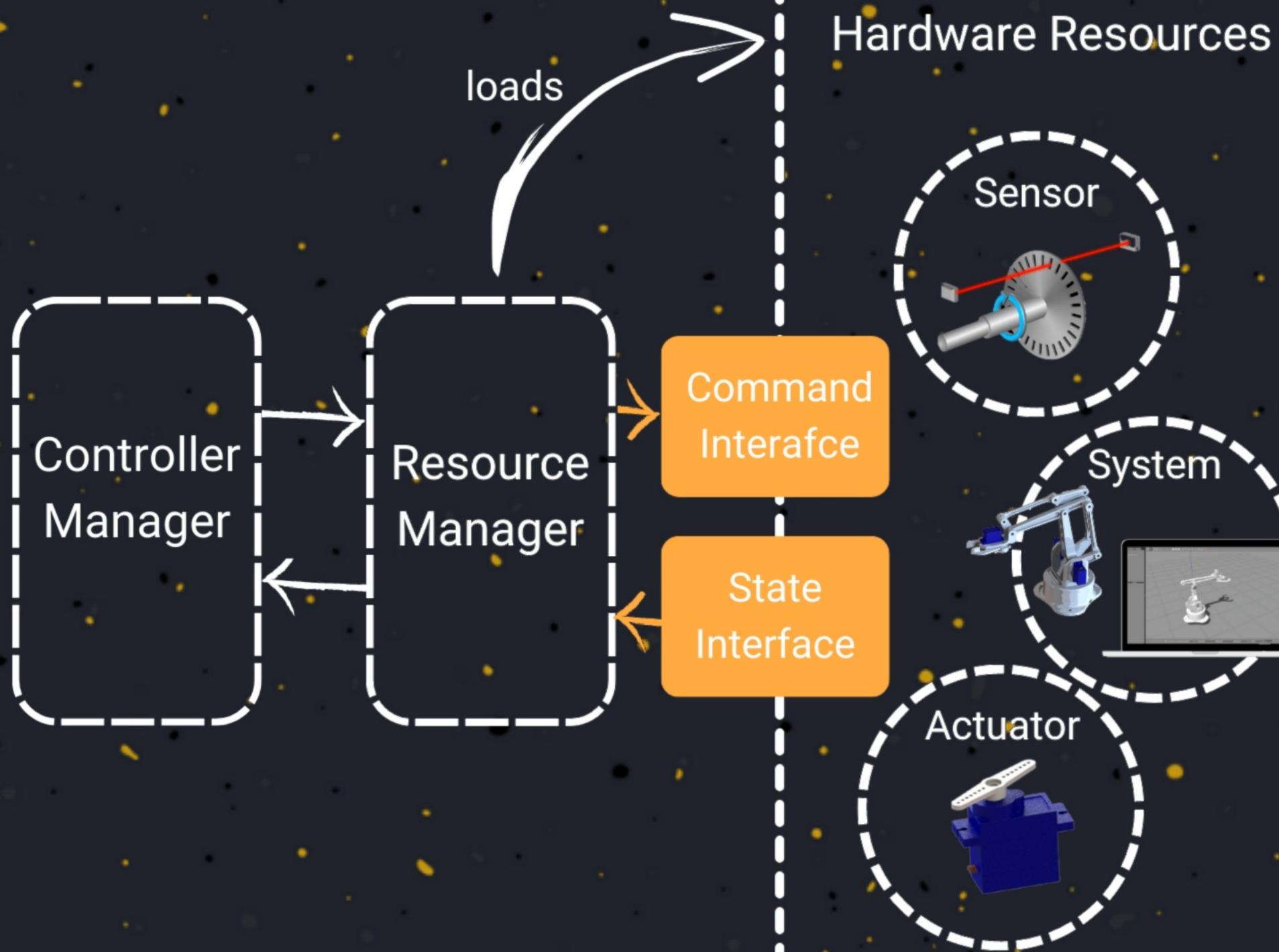


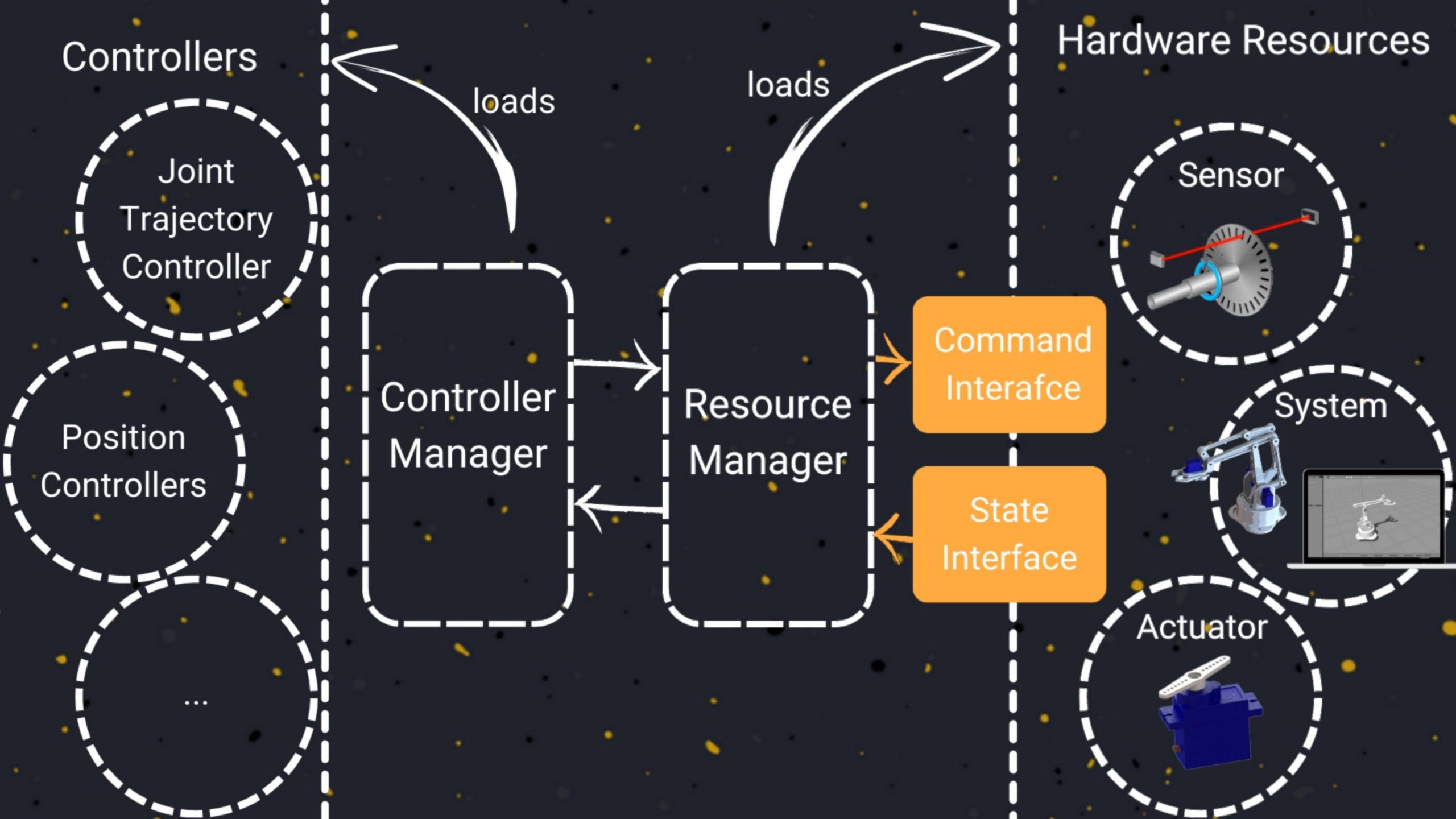
Actuator

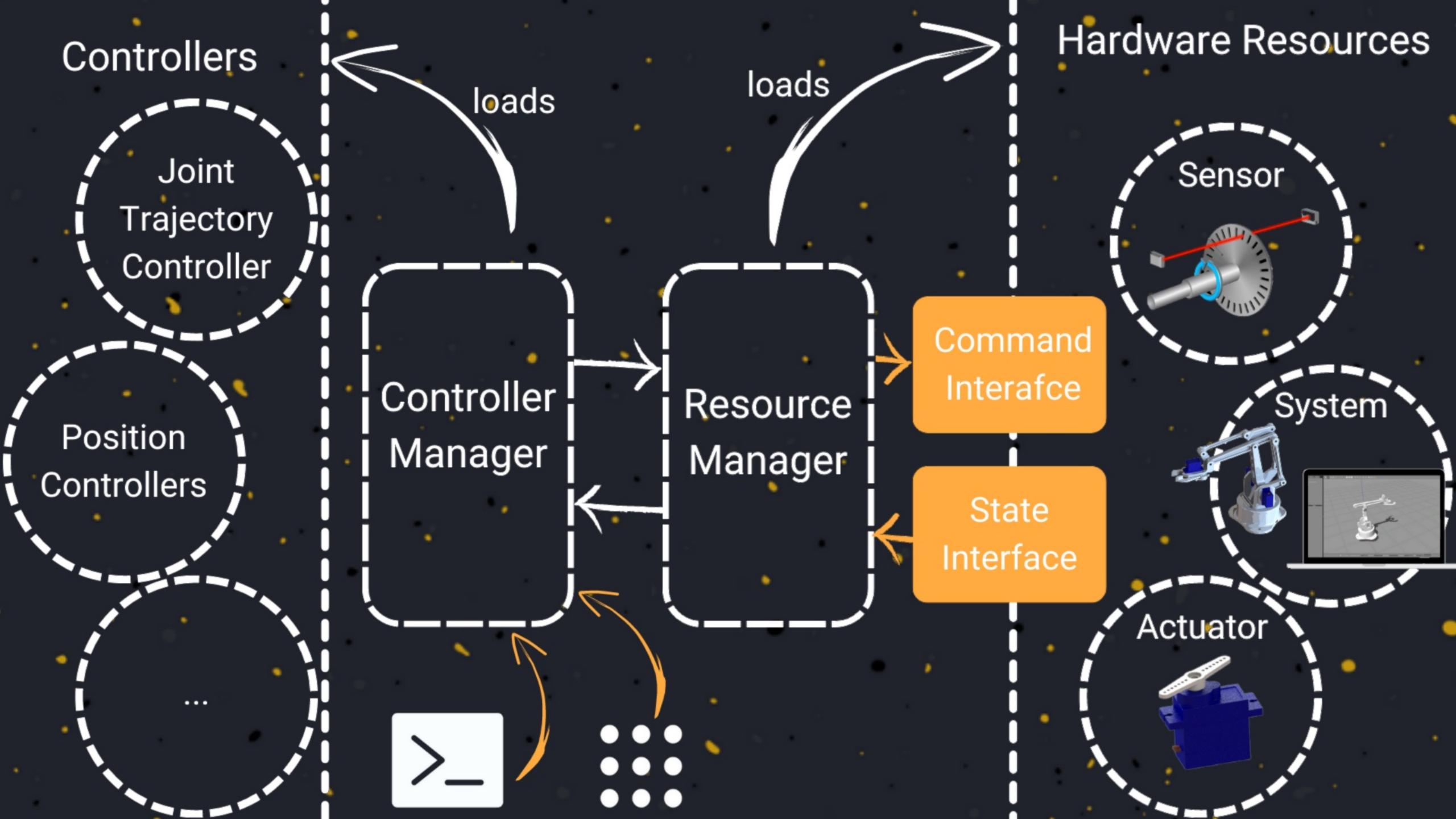
# Hardware Resources



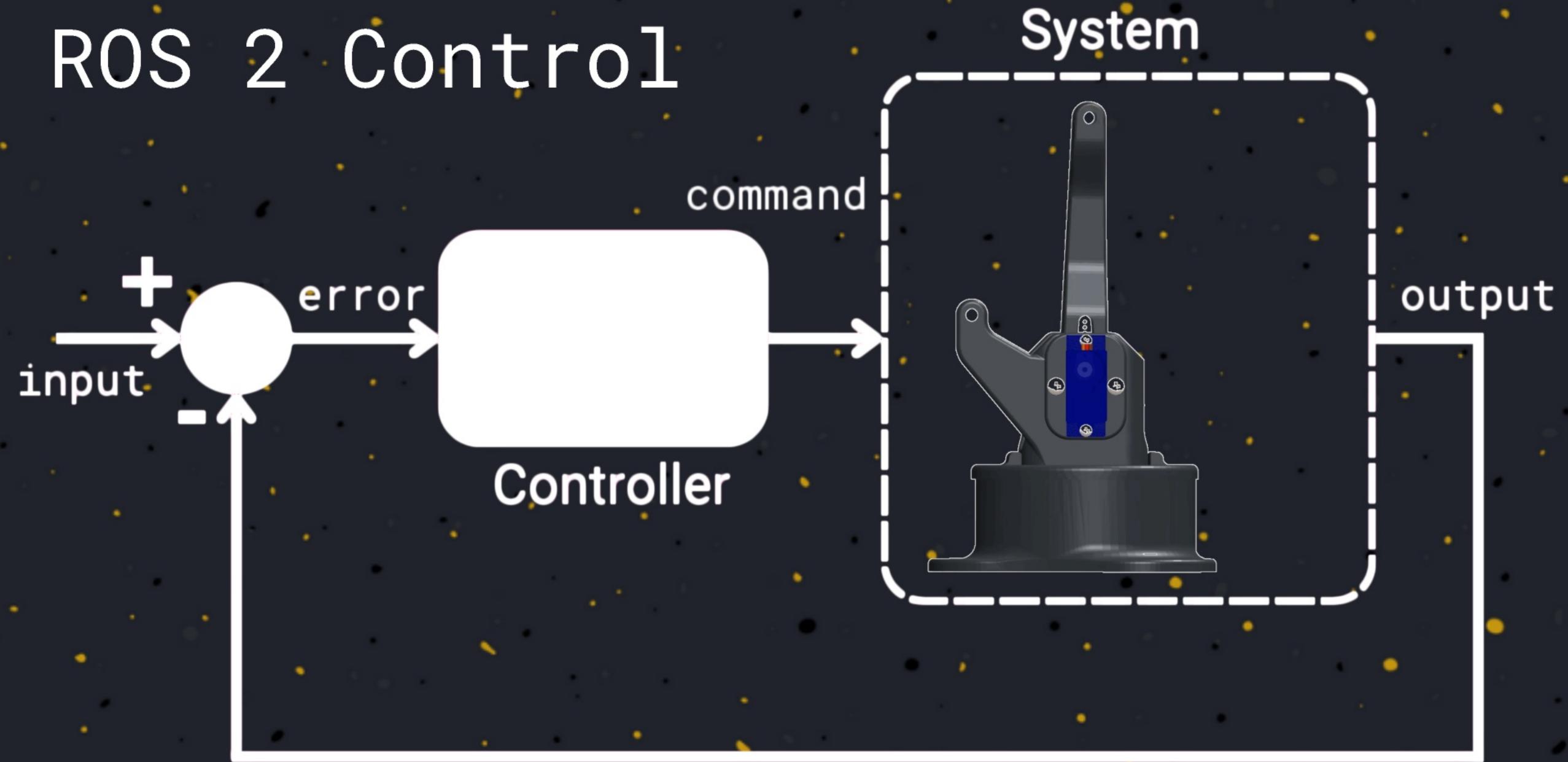






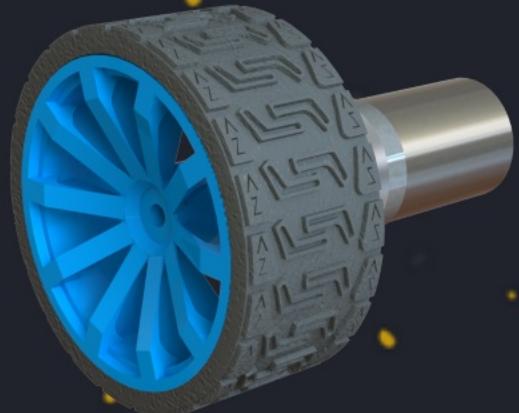


# ROS 2 Control





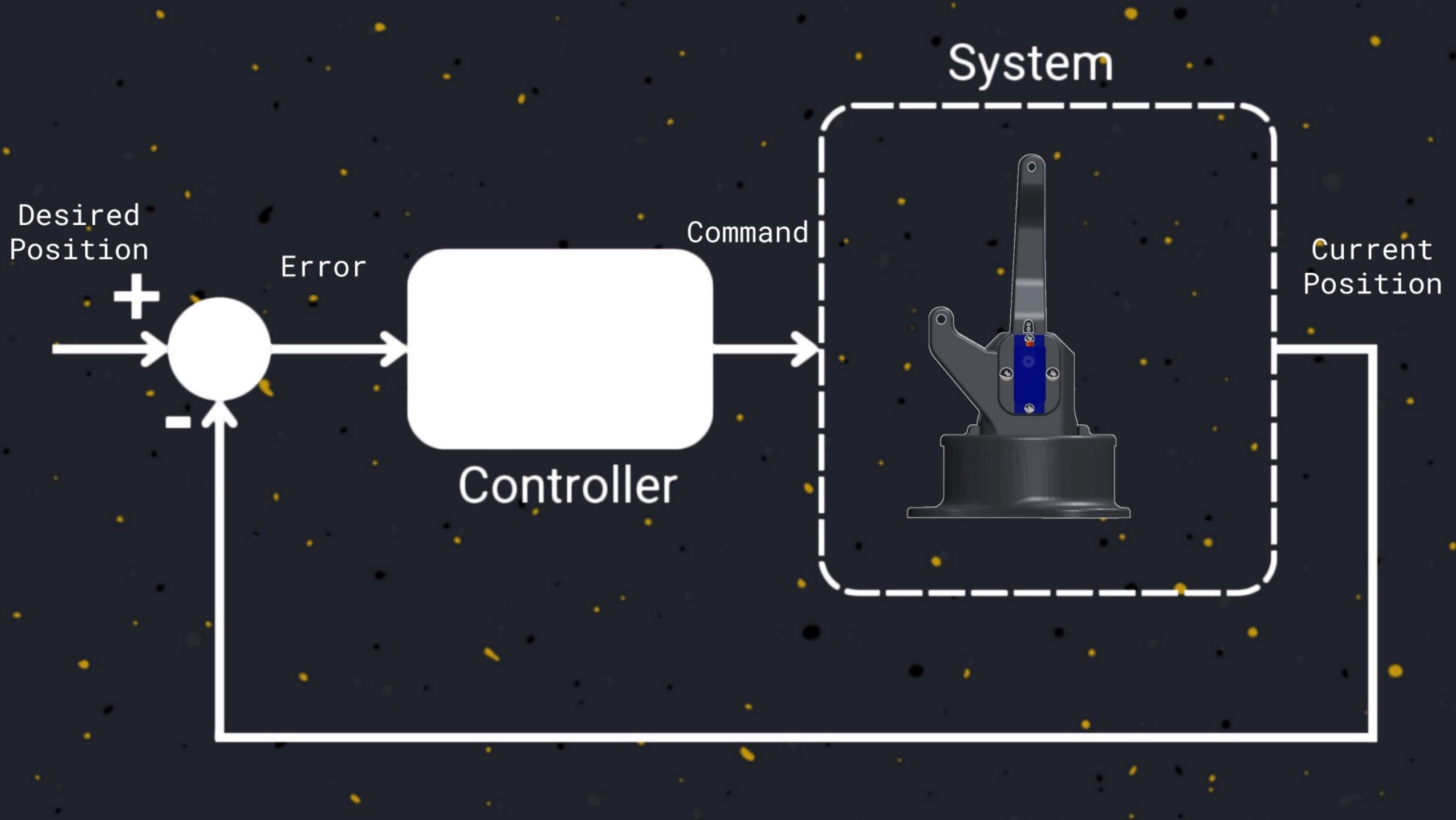
Position



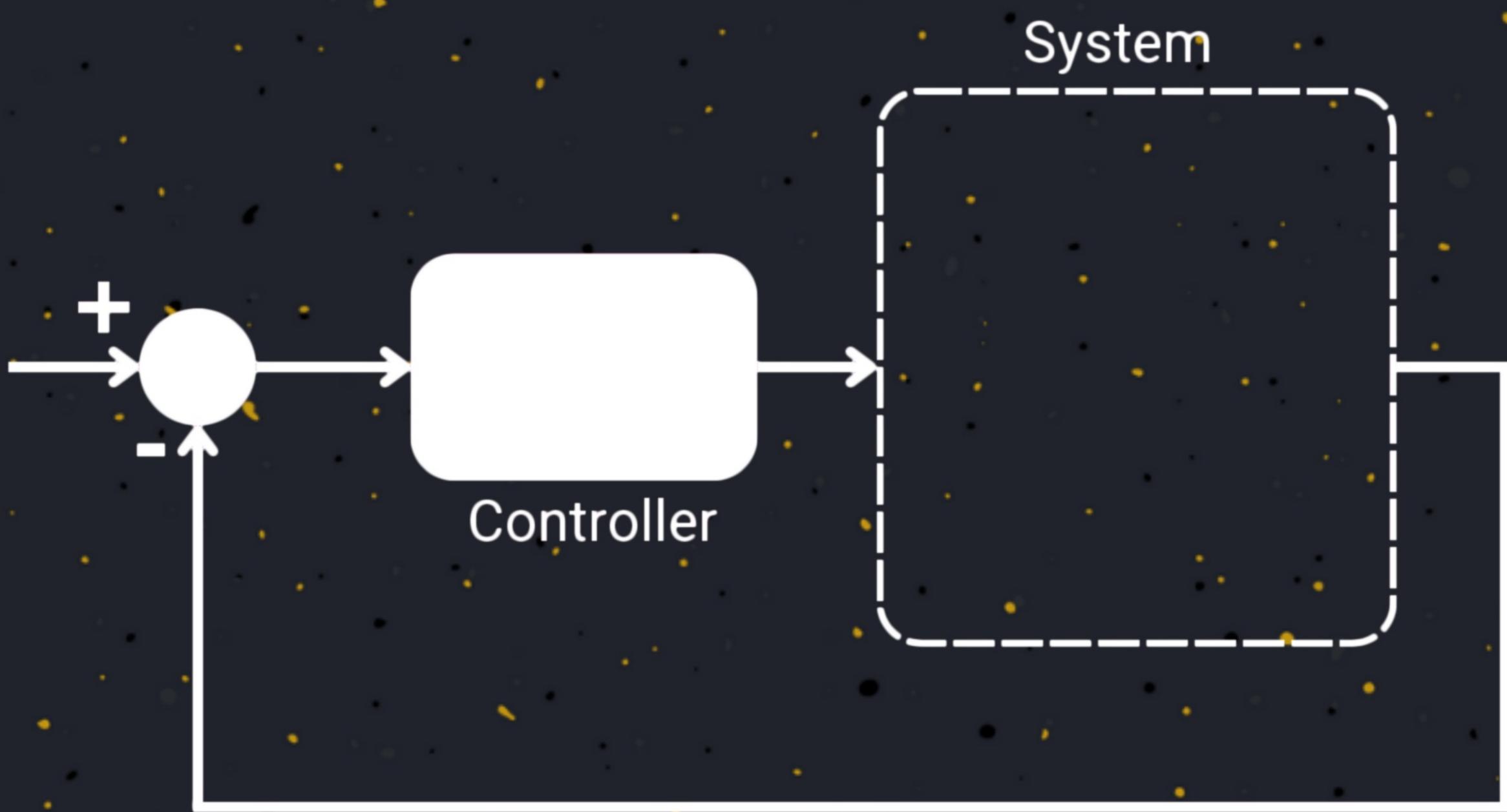
Velocity

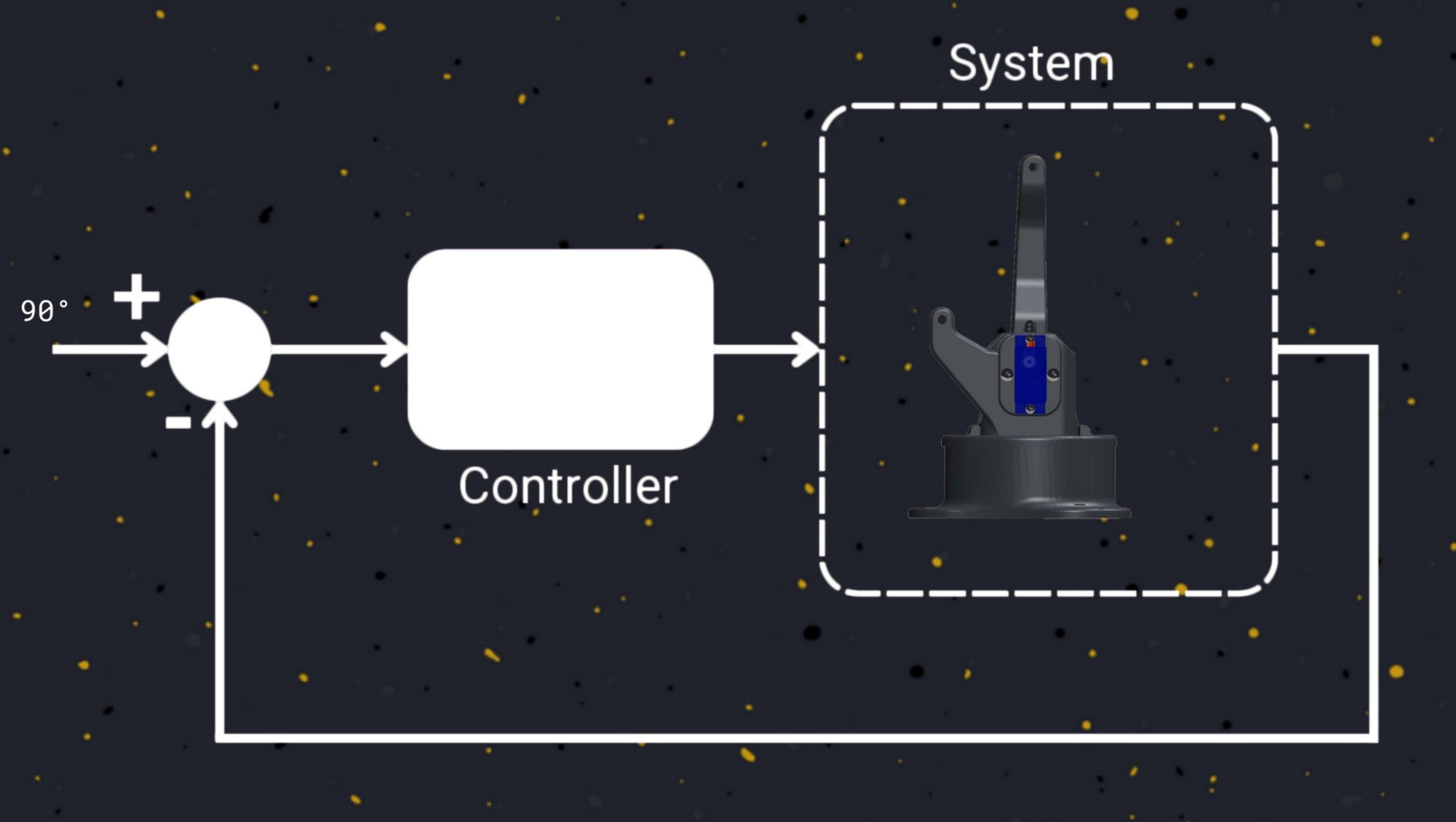


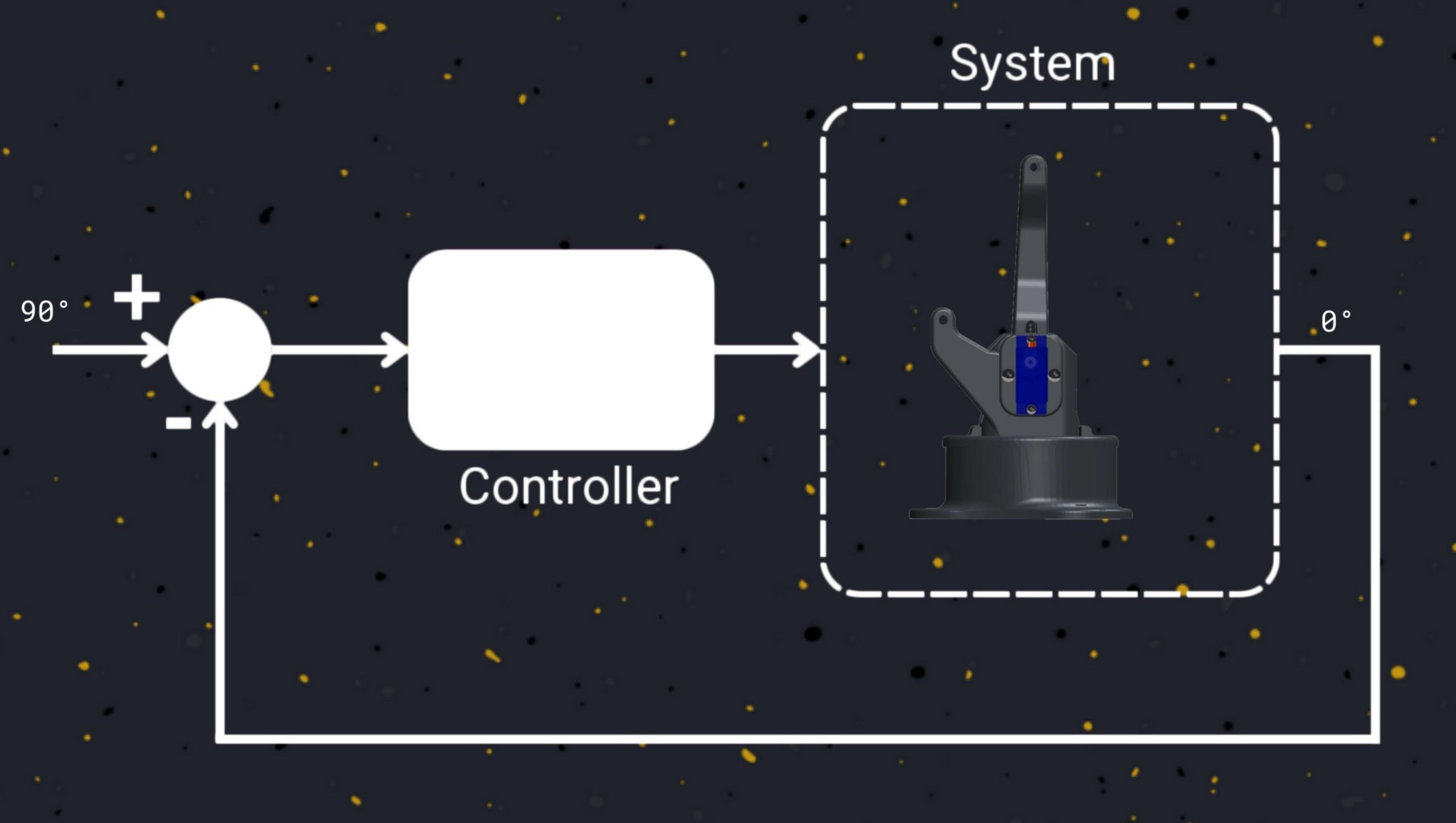
Effort

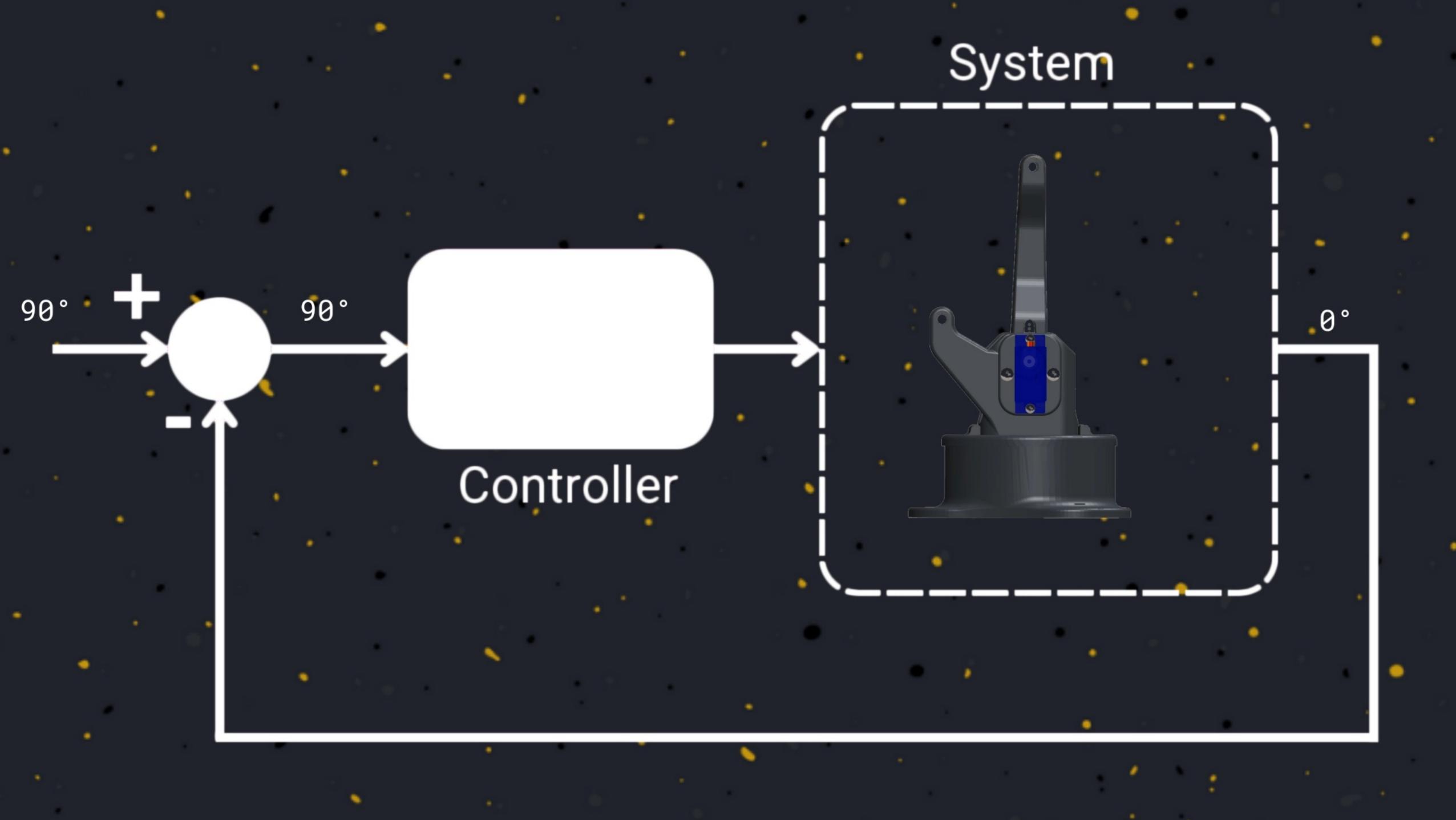


System

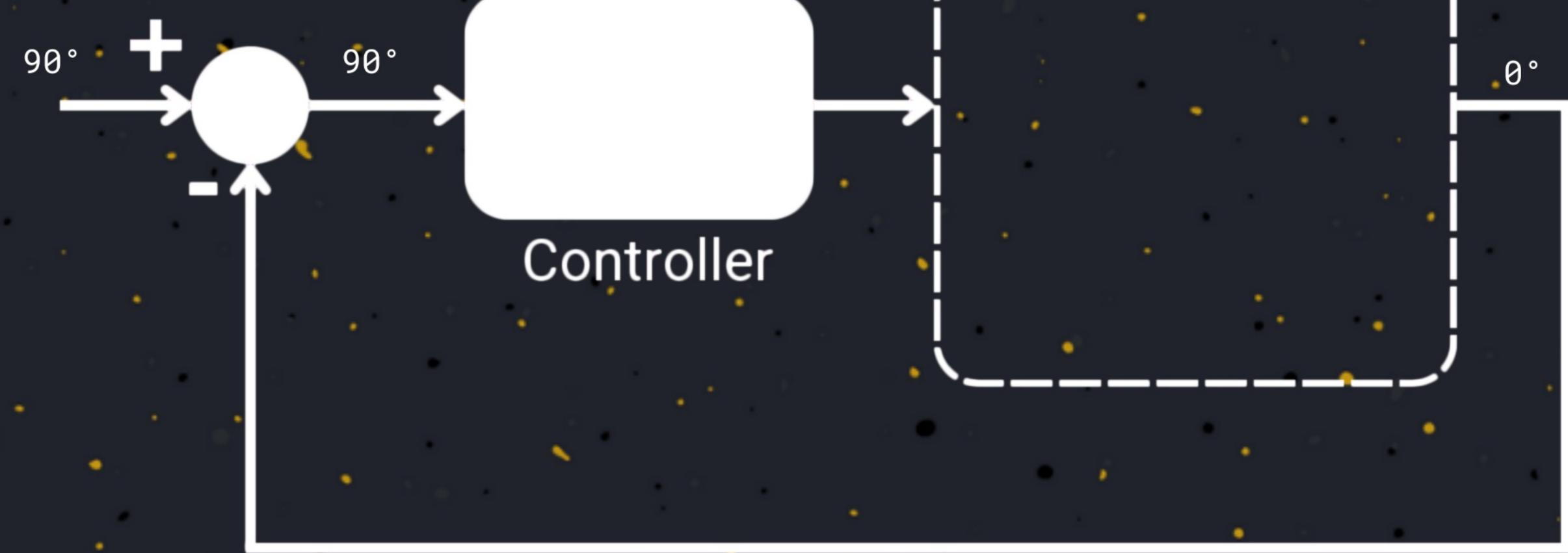




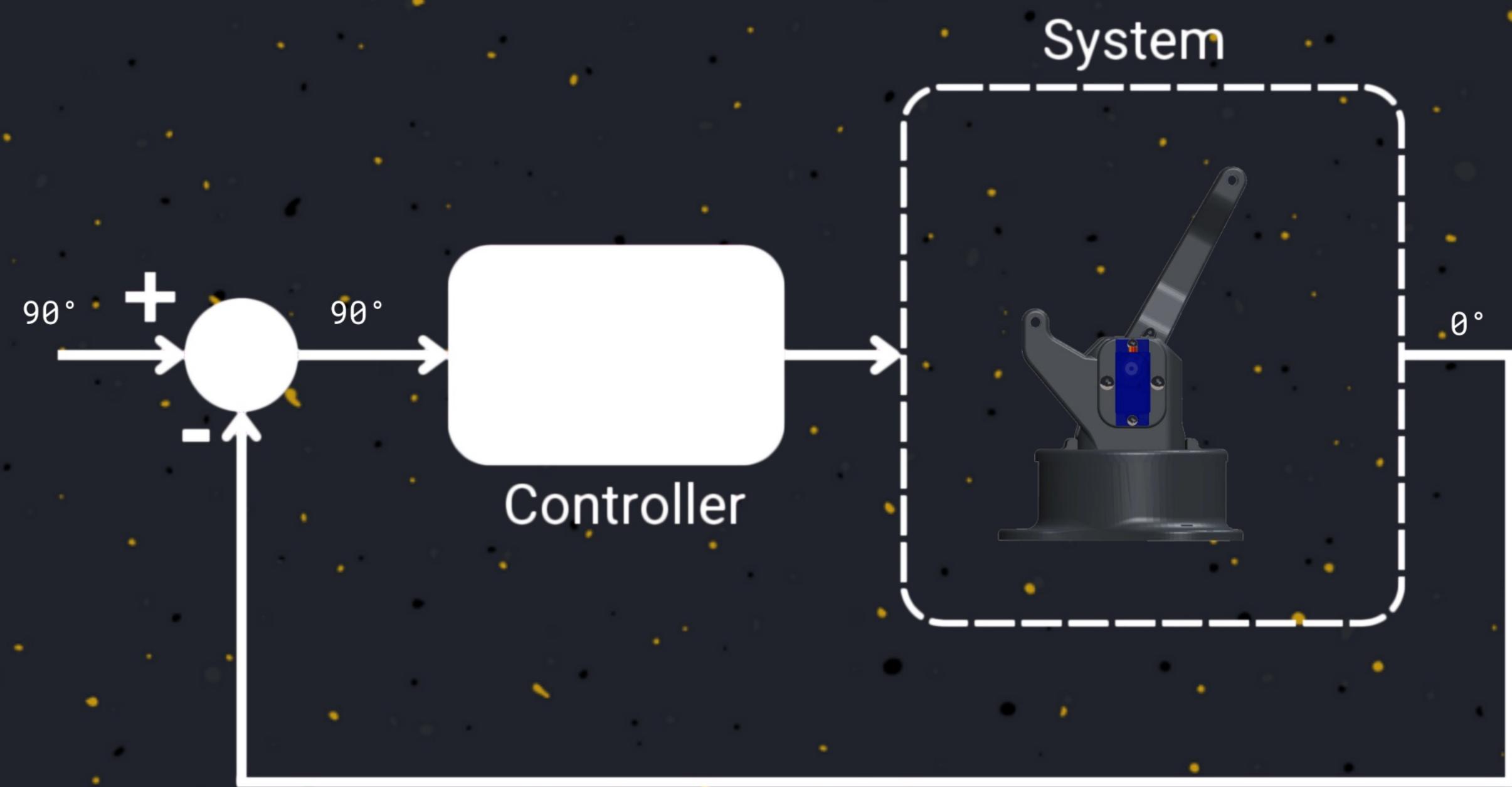




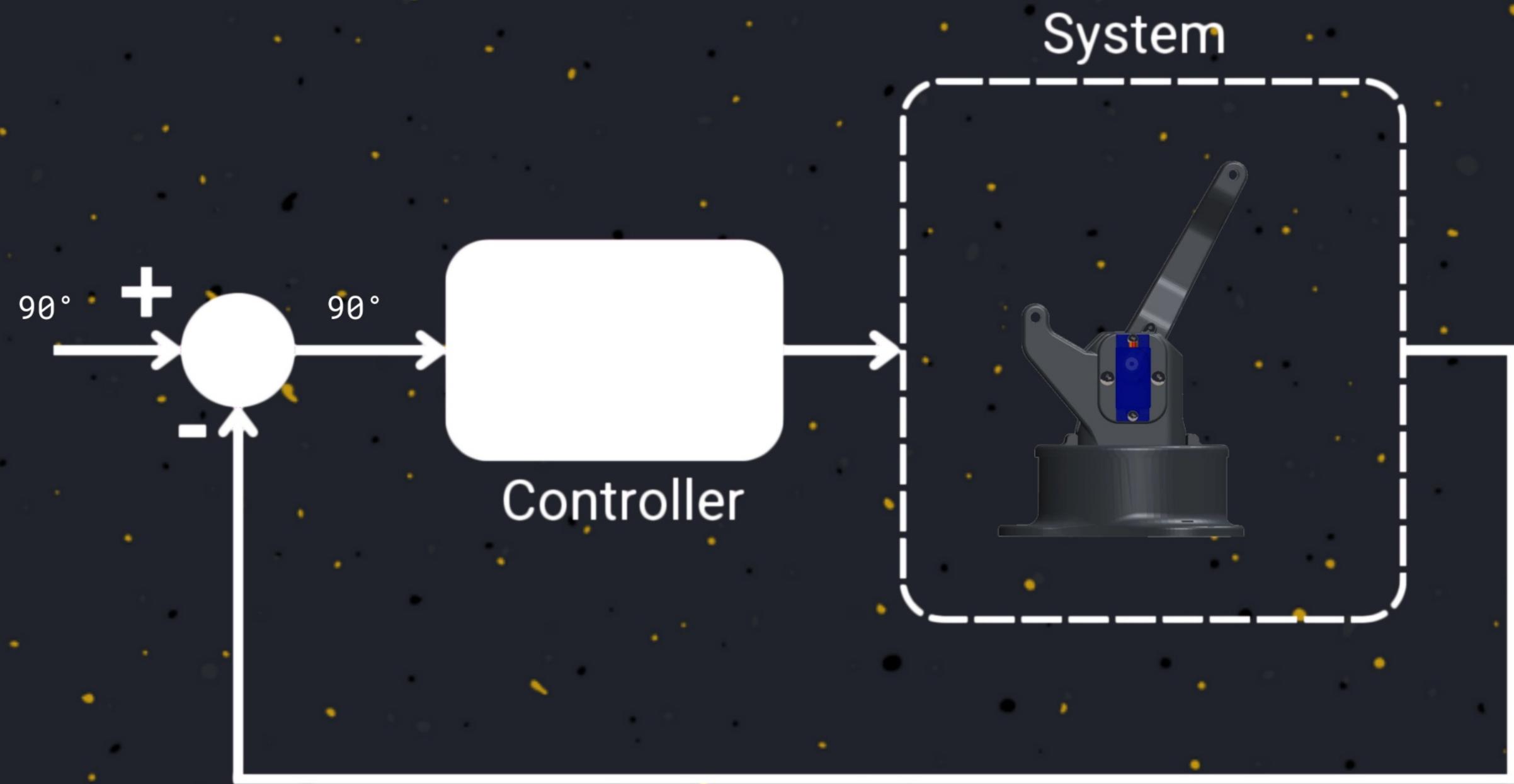
System



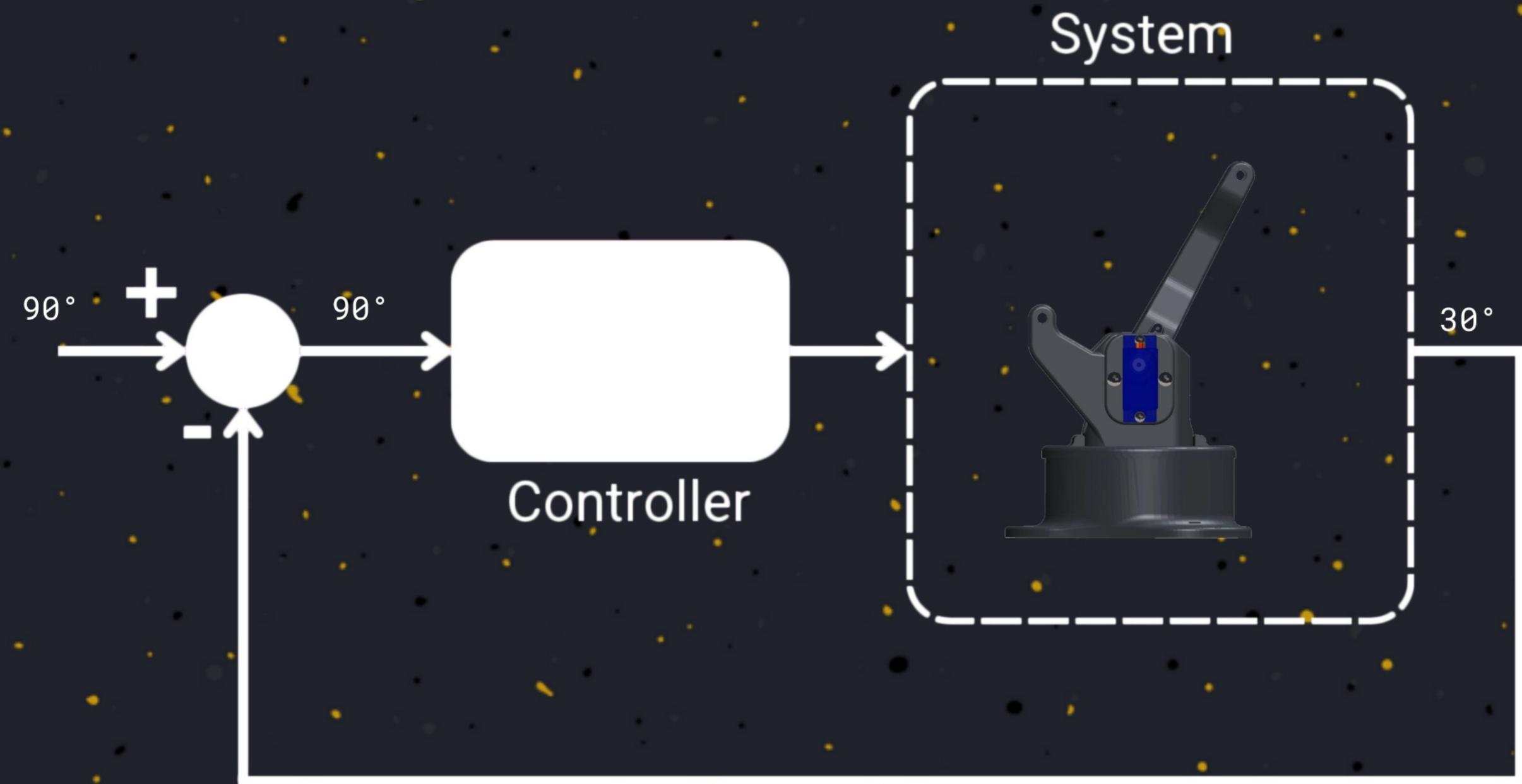
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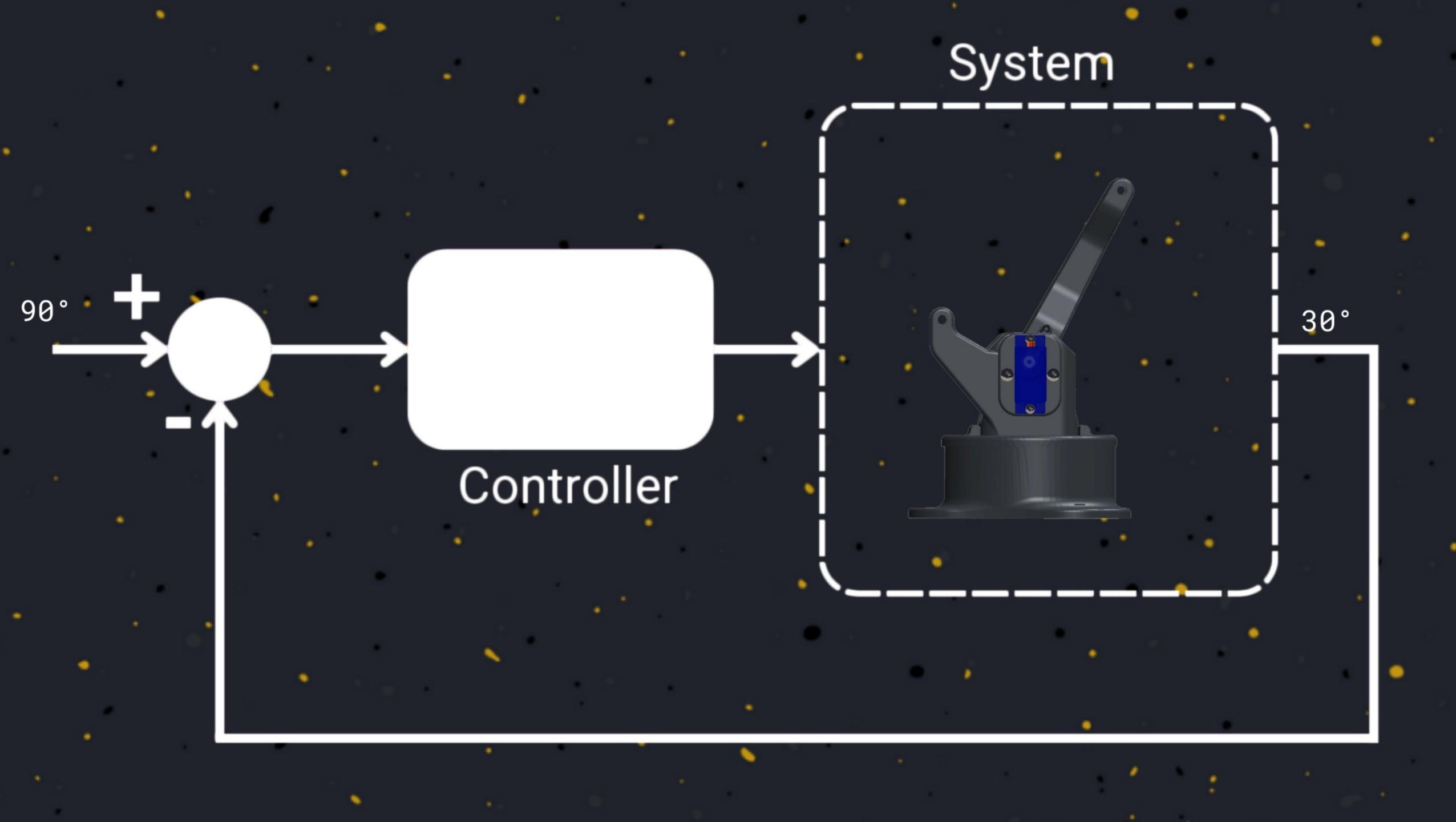


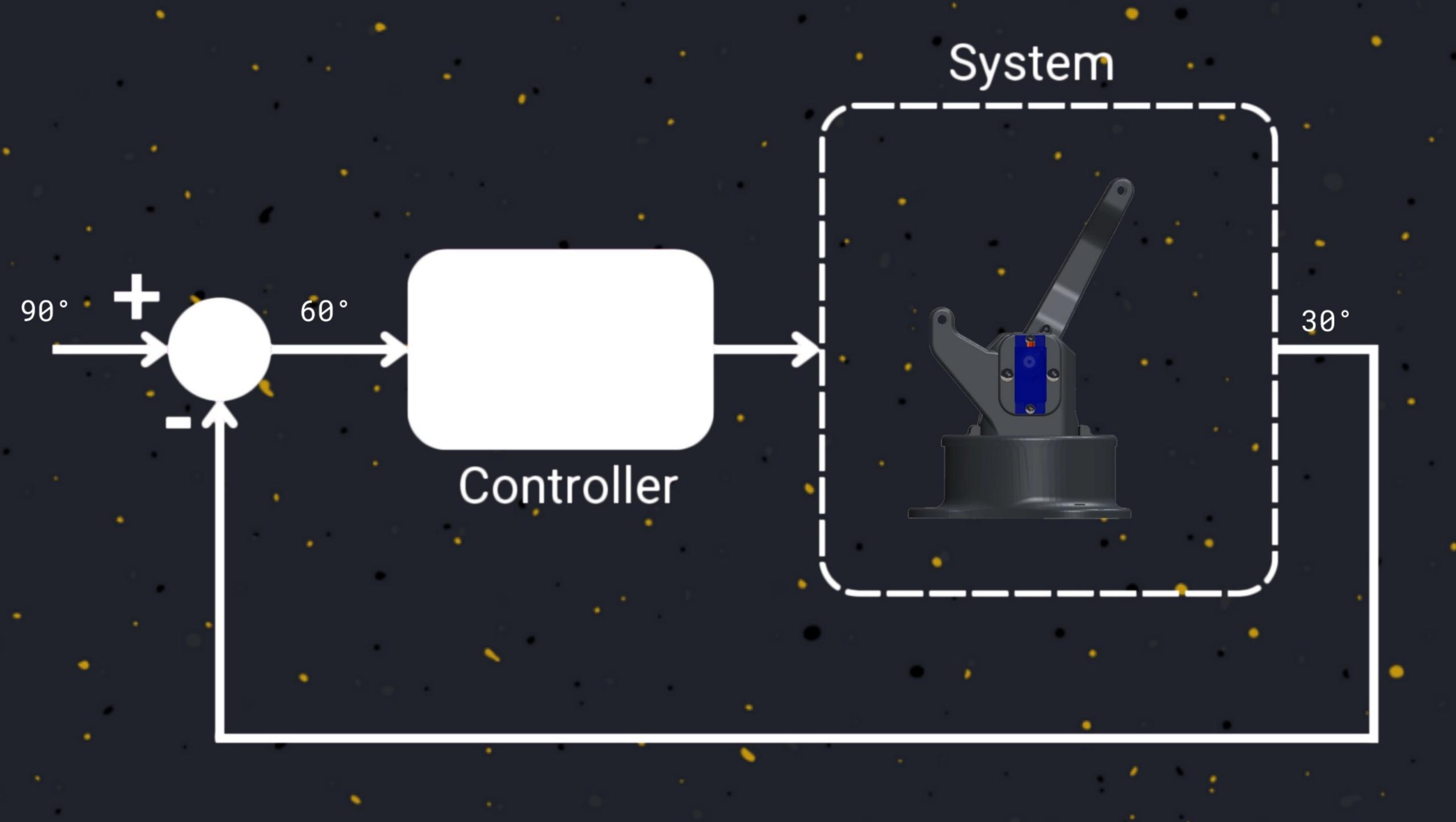
System

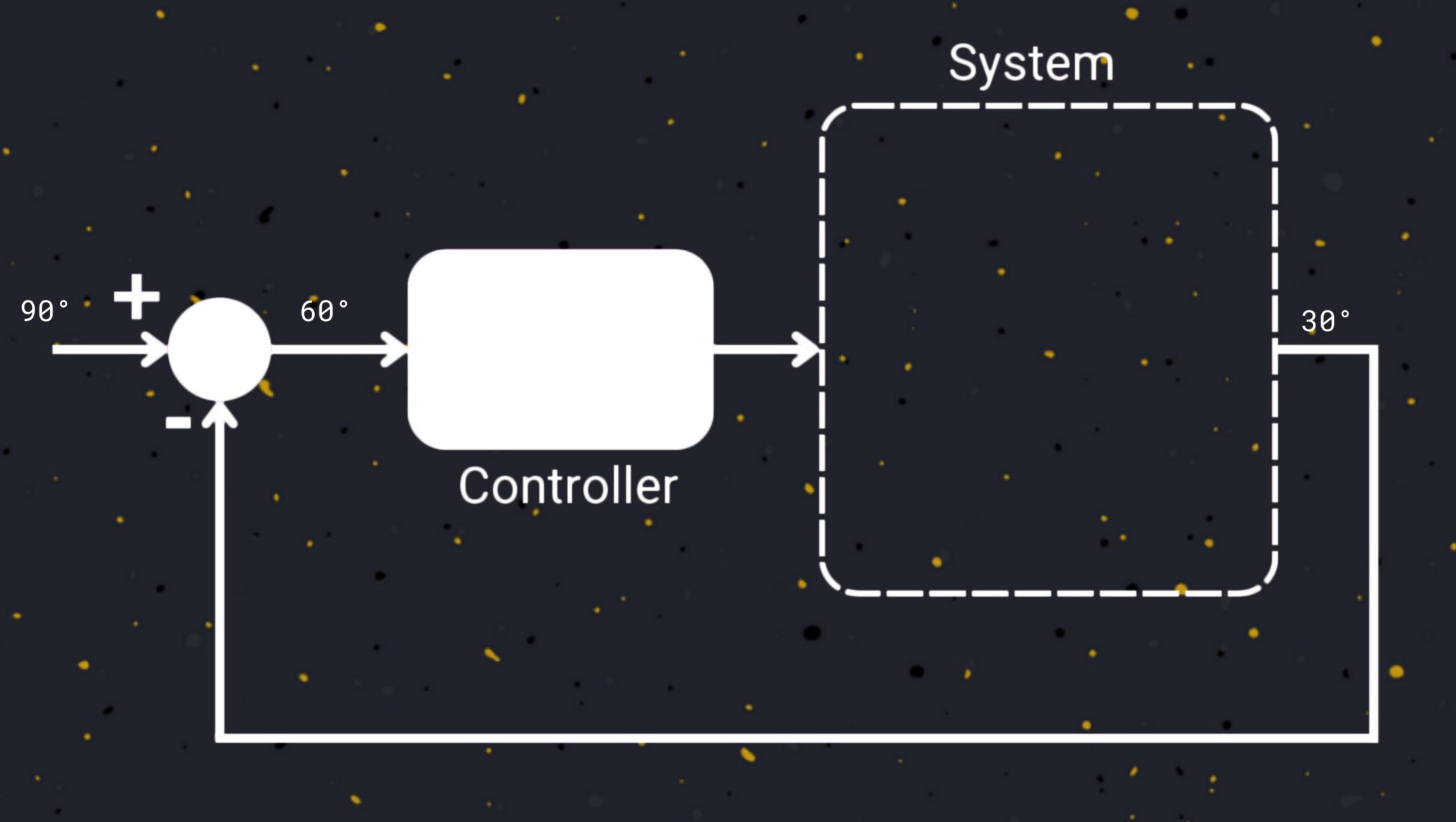


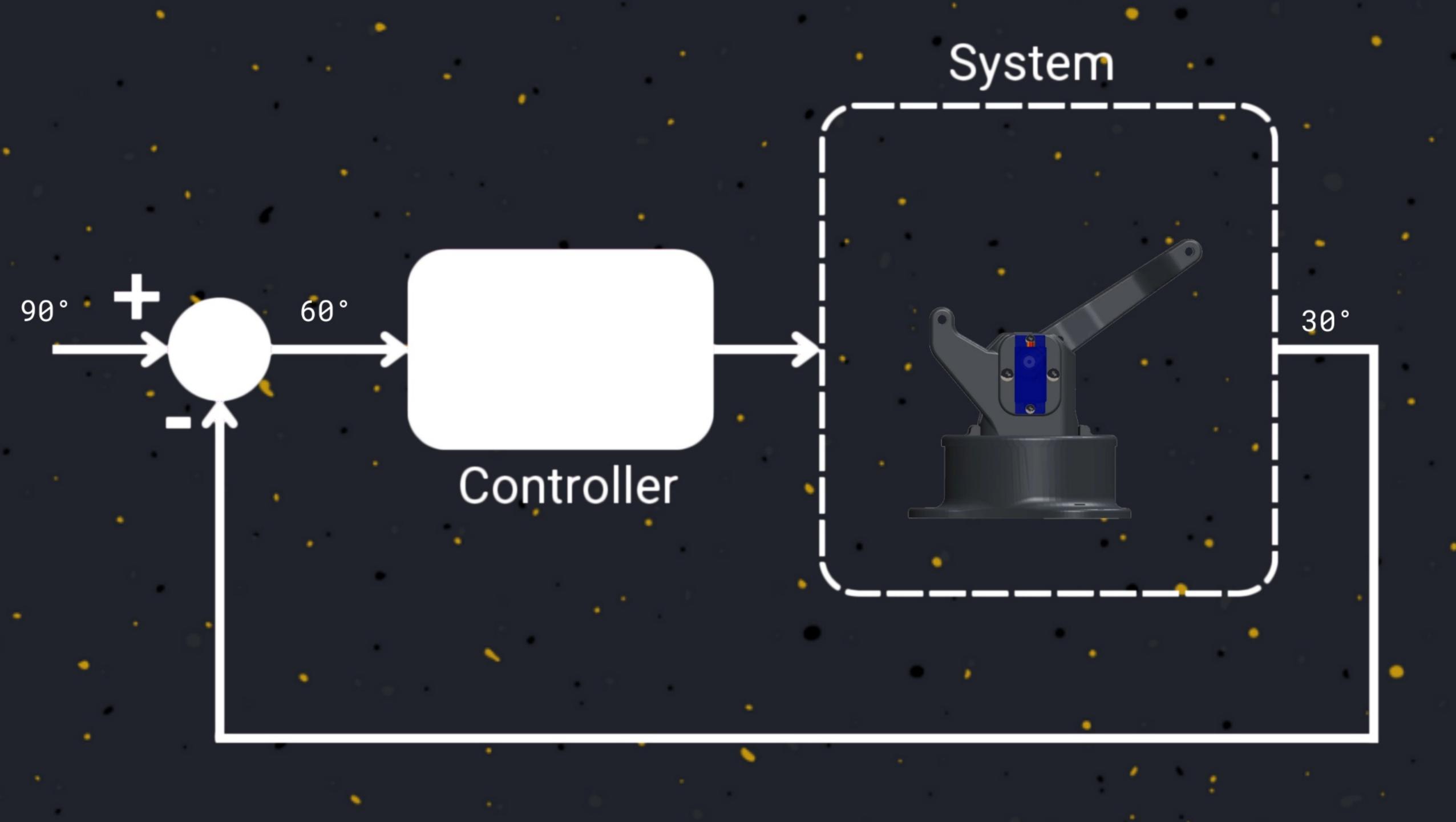
System



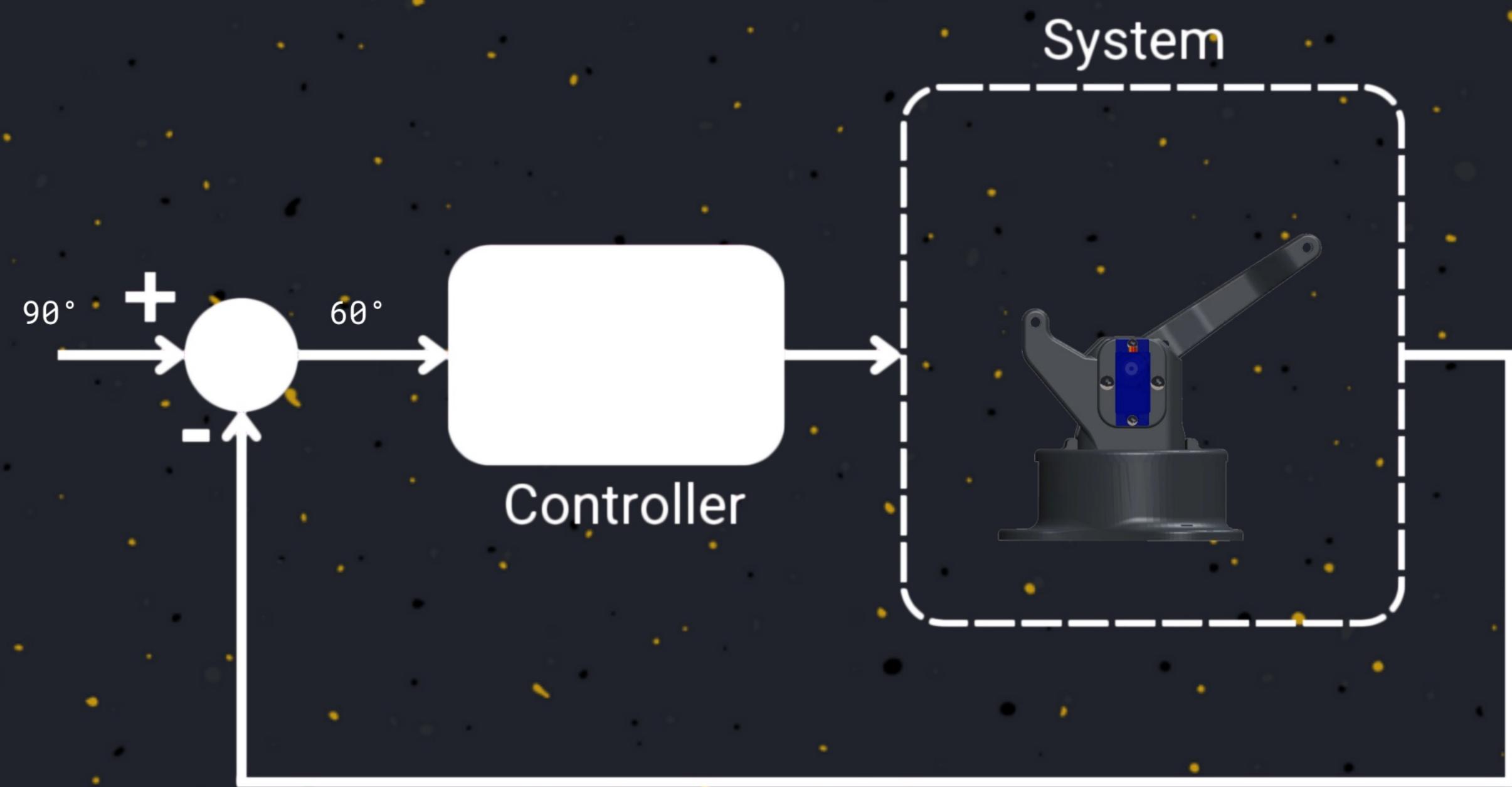


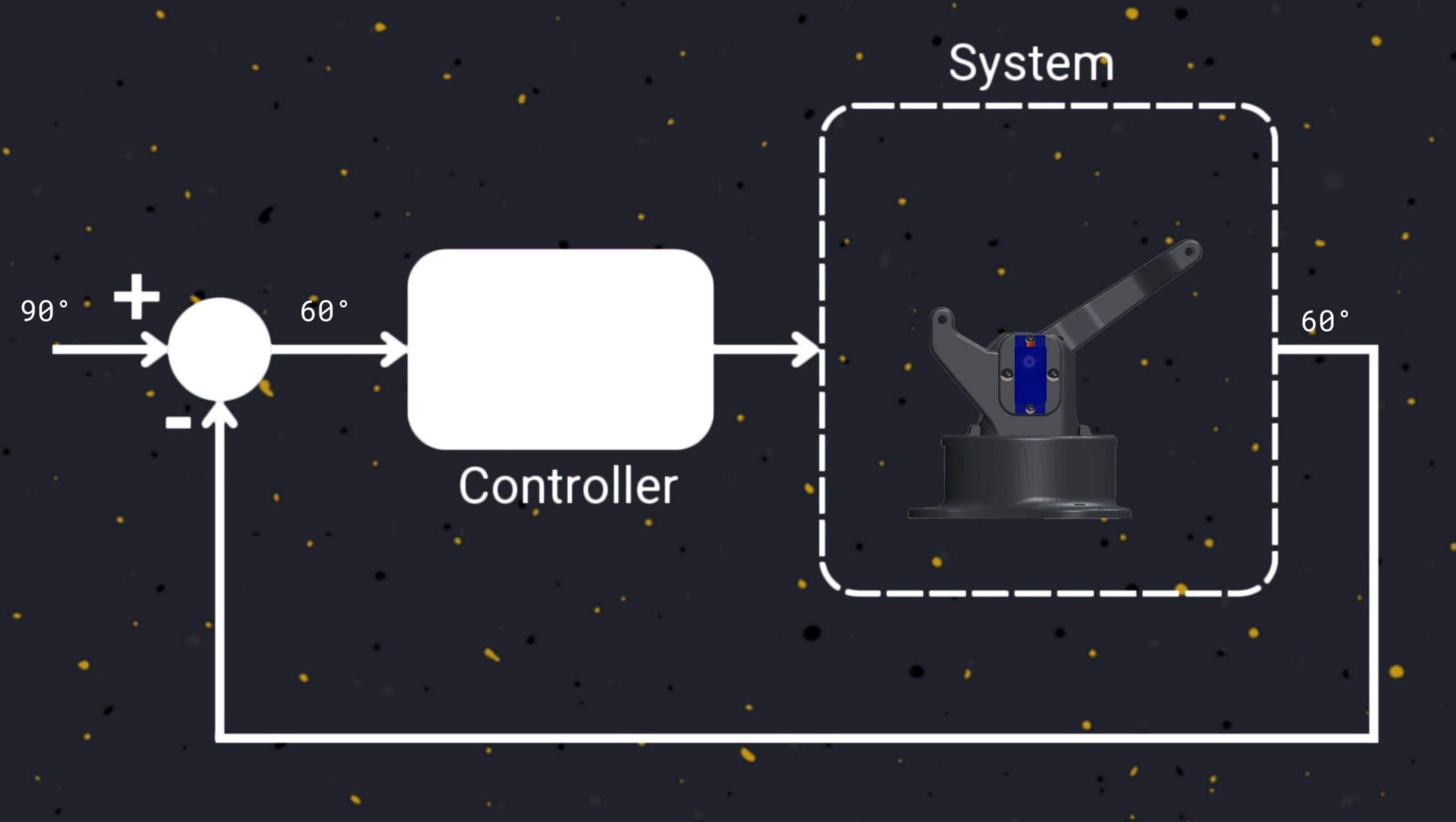


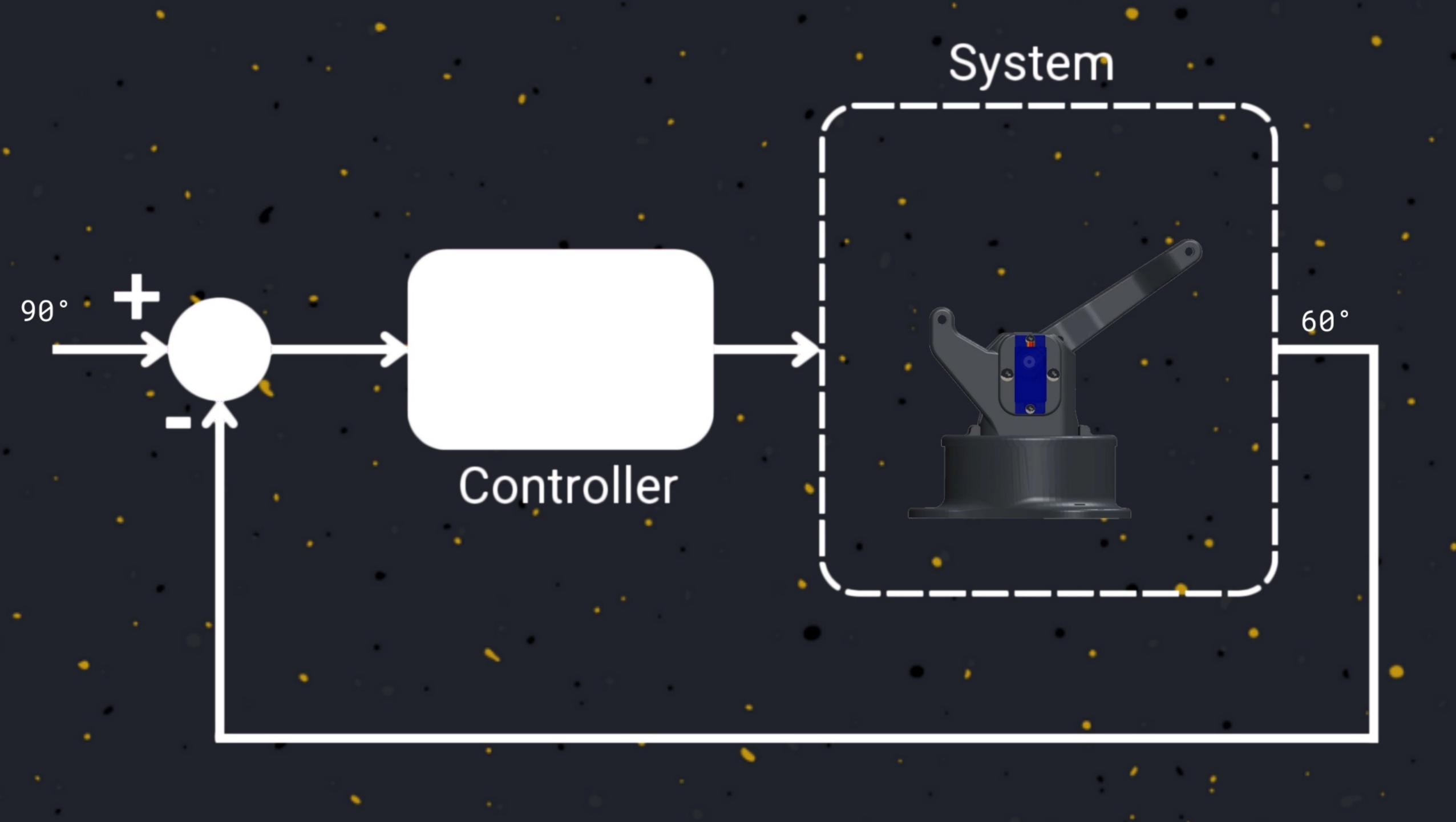


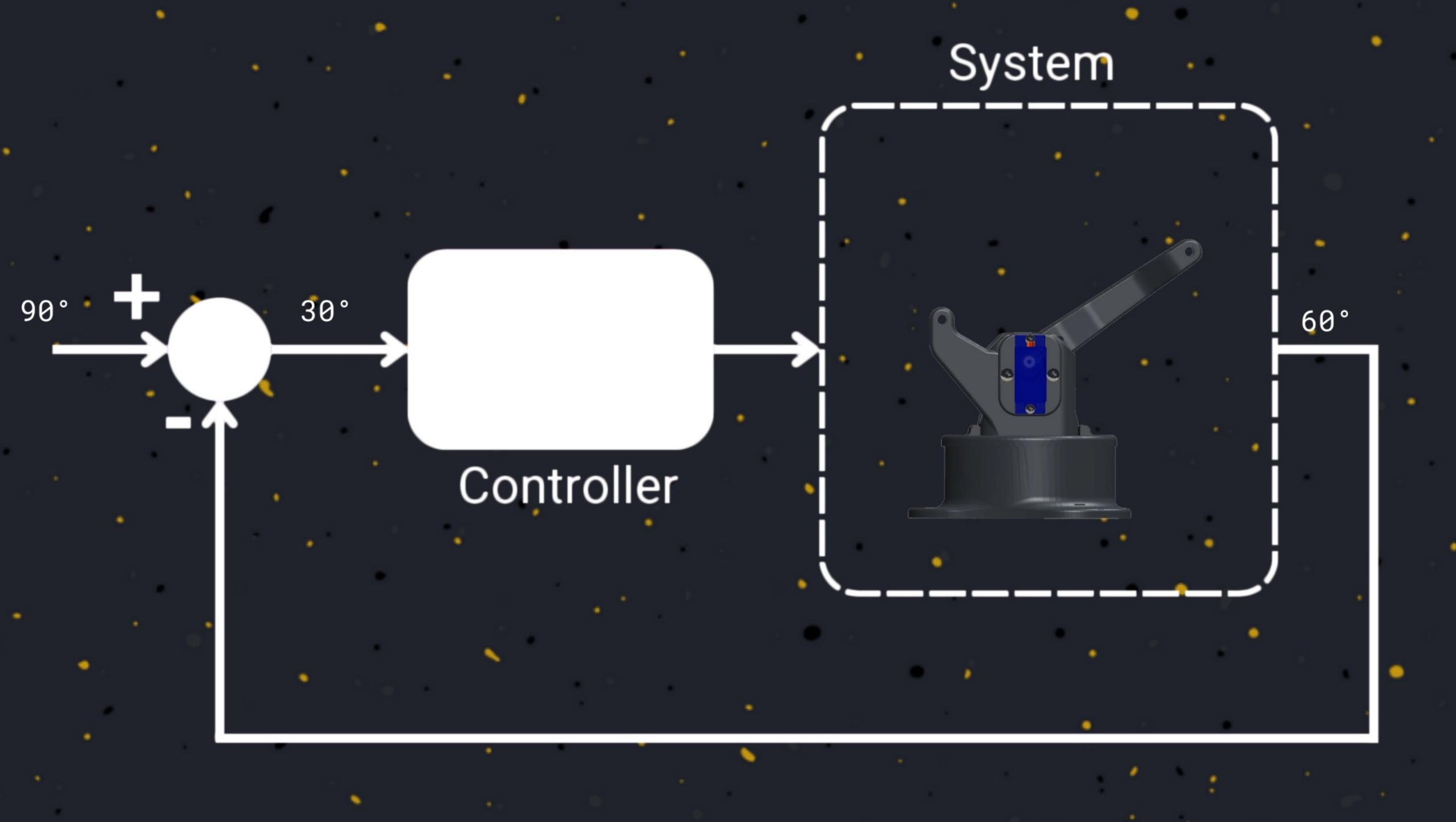


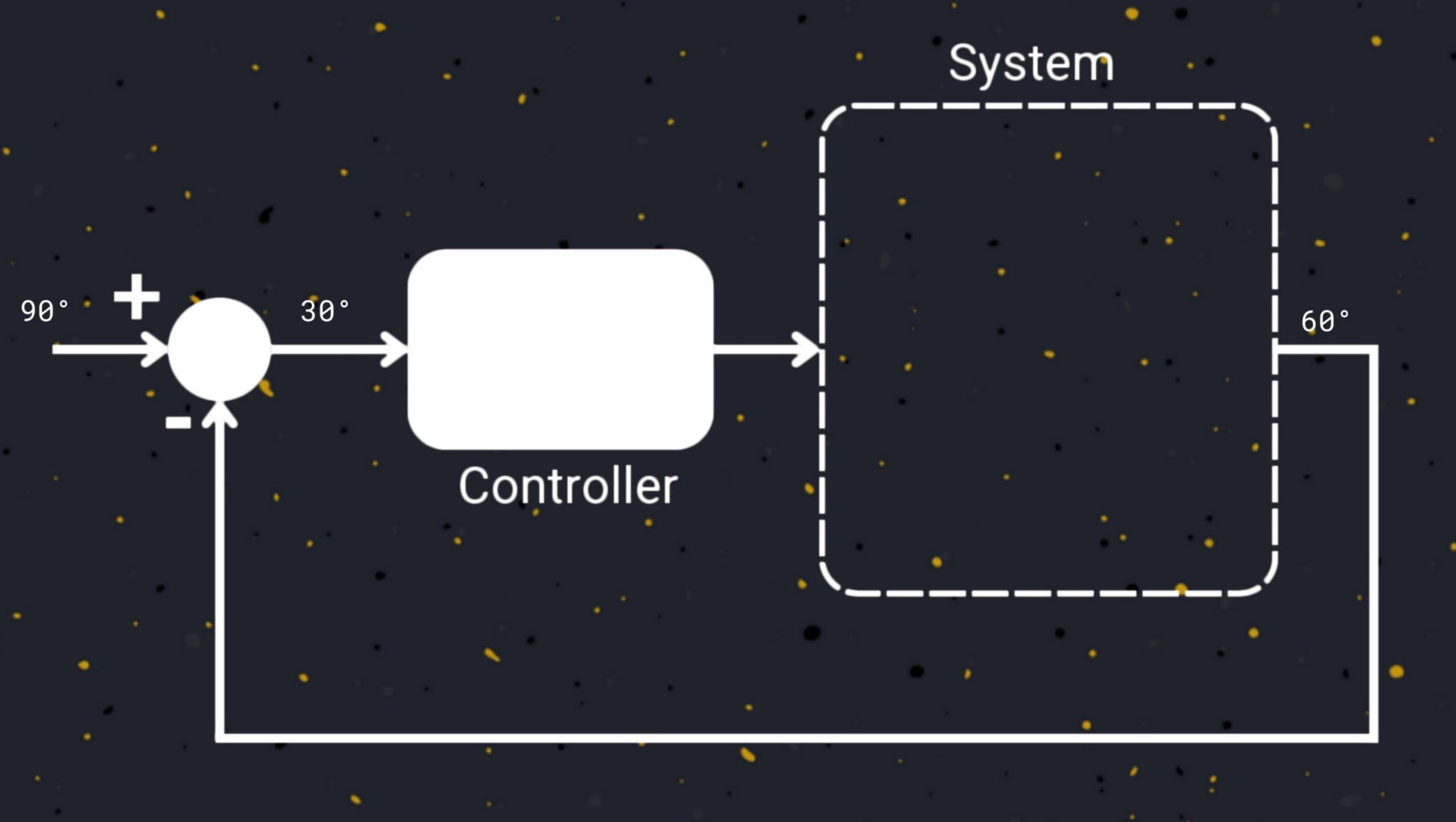
System

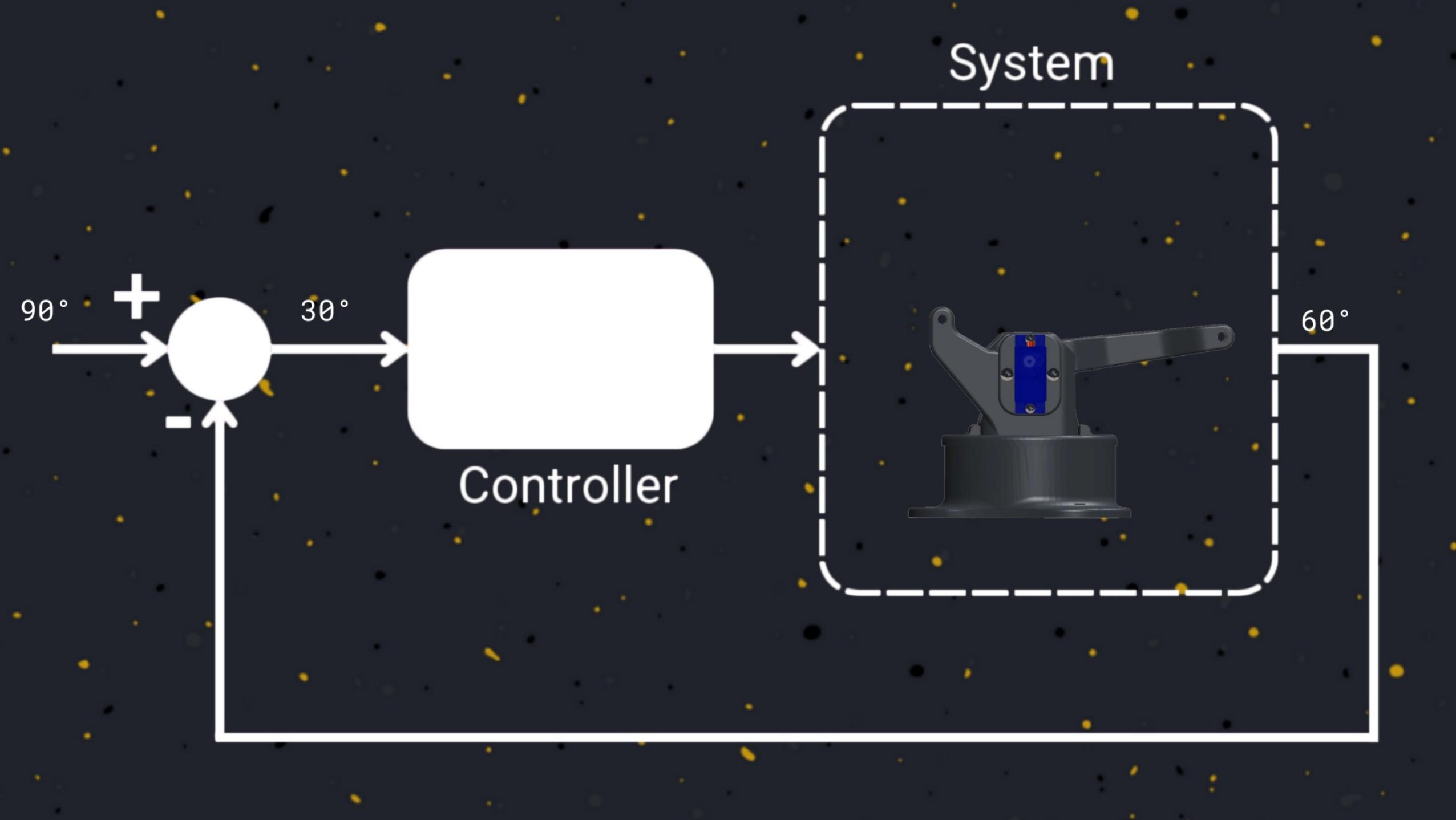




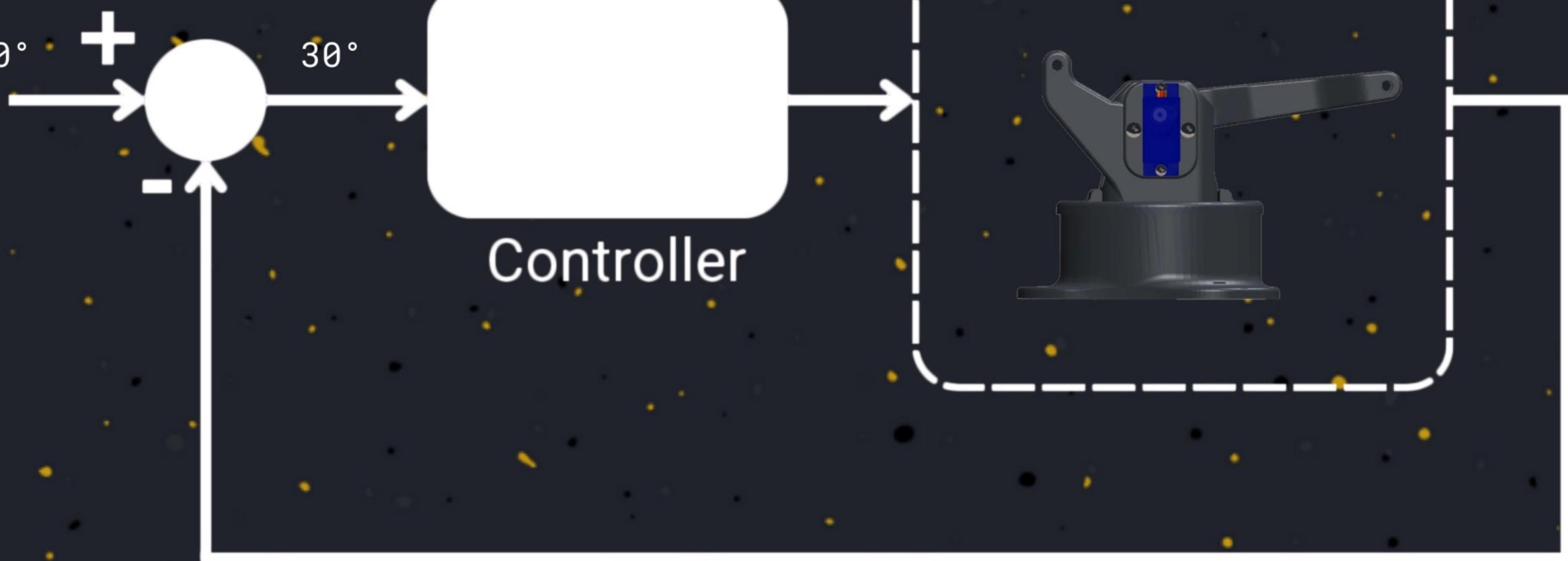




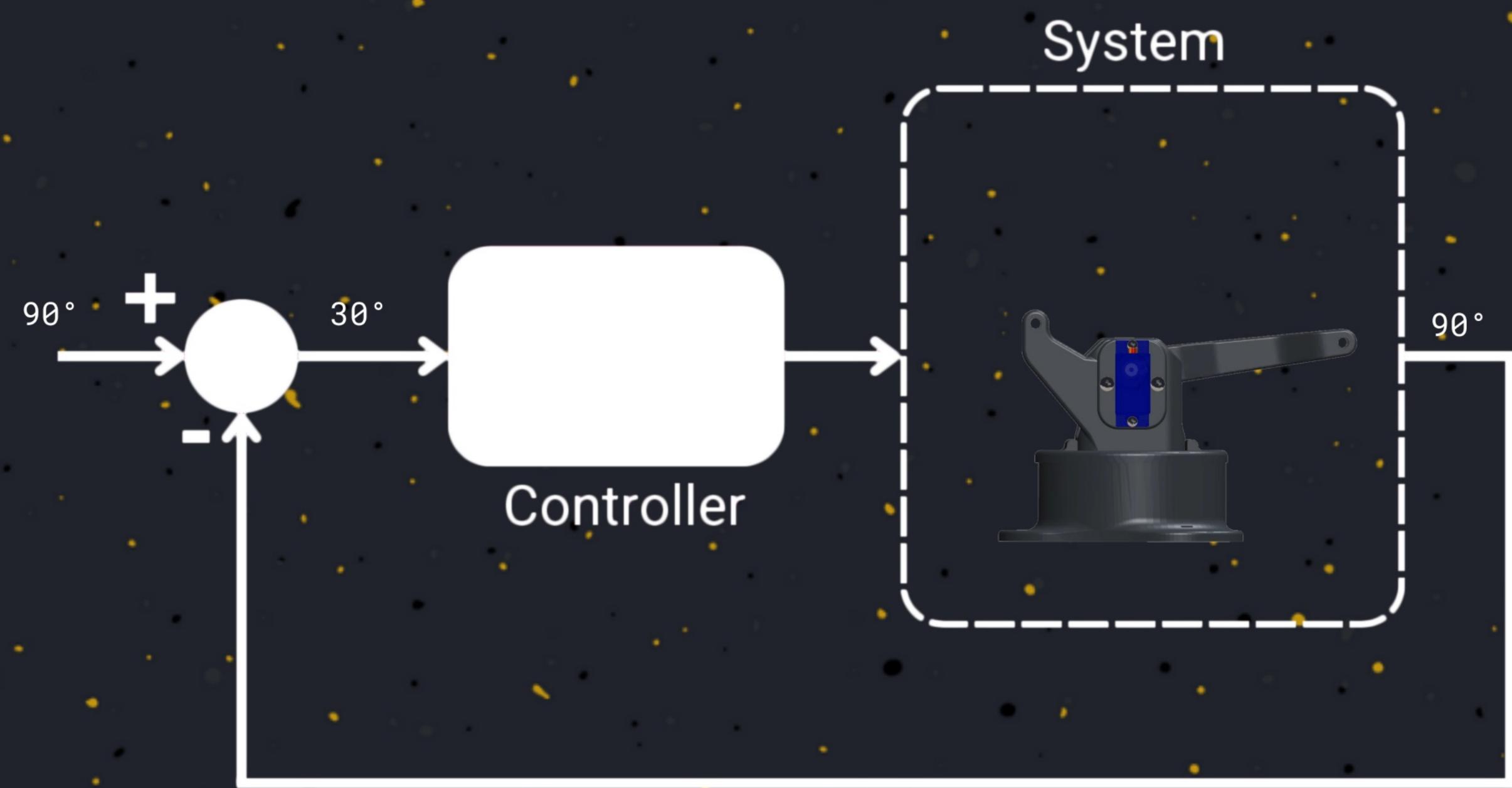




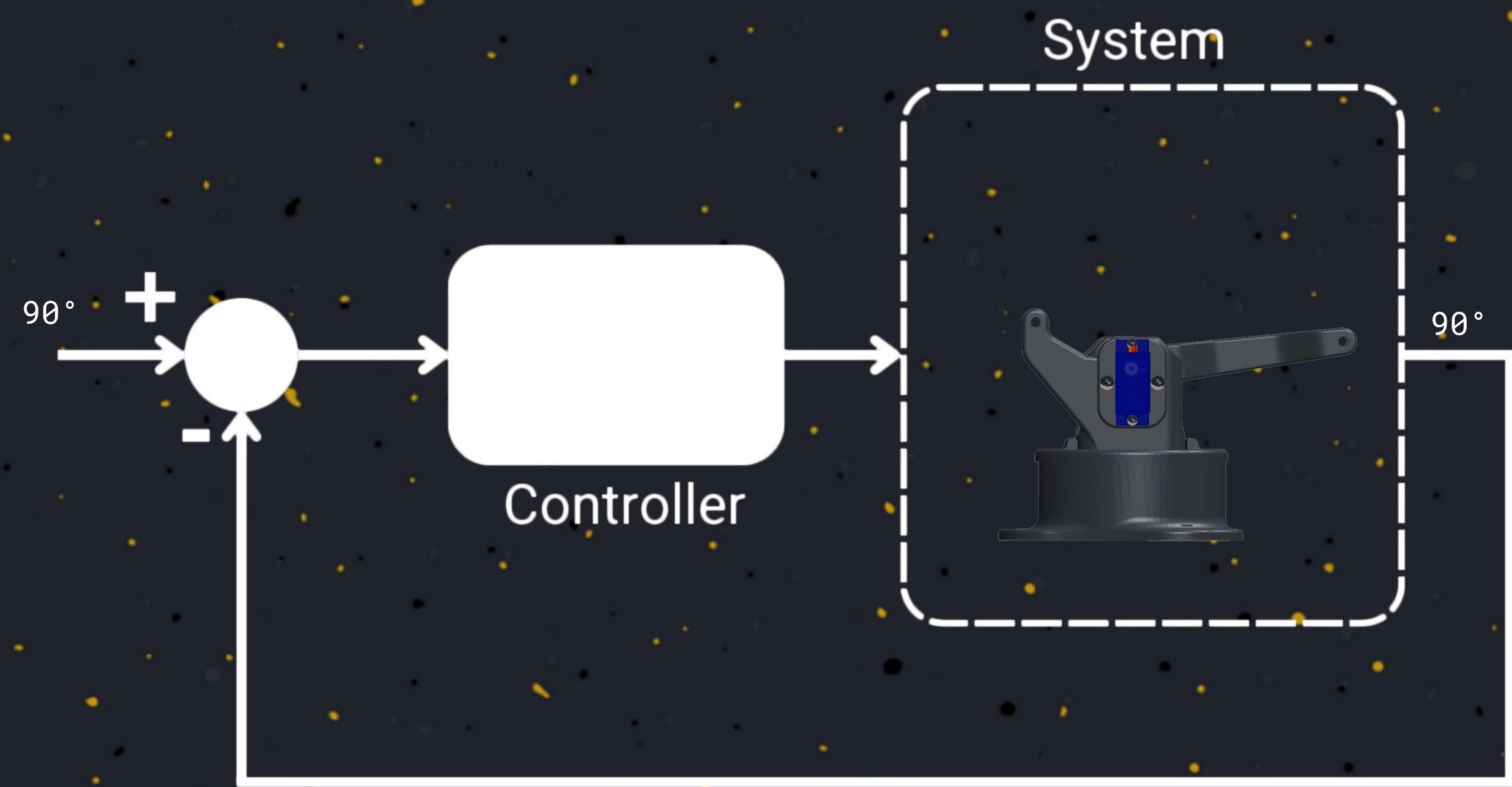
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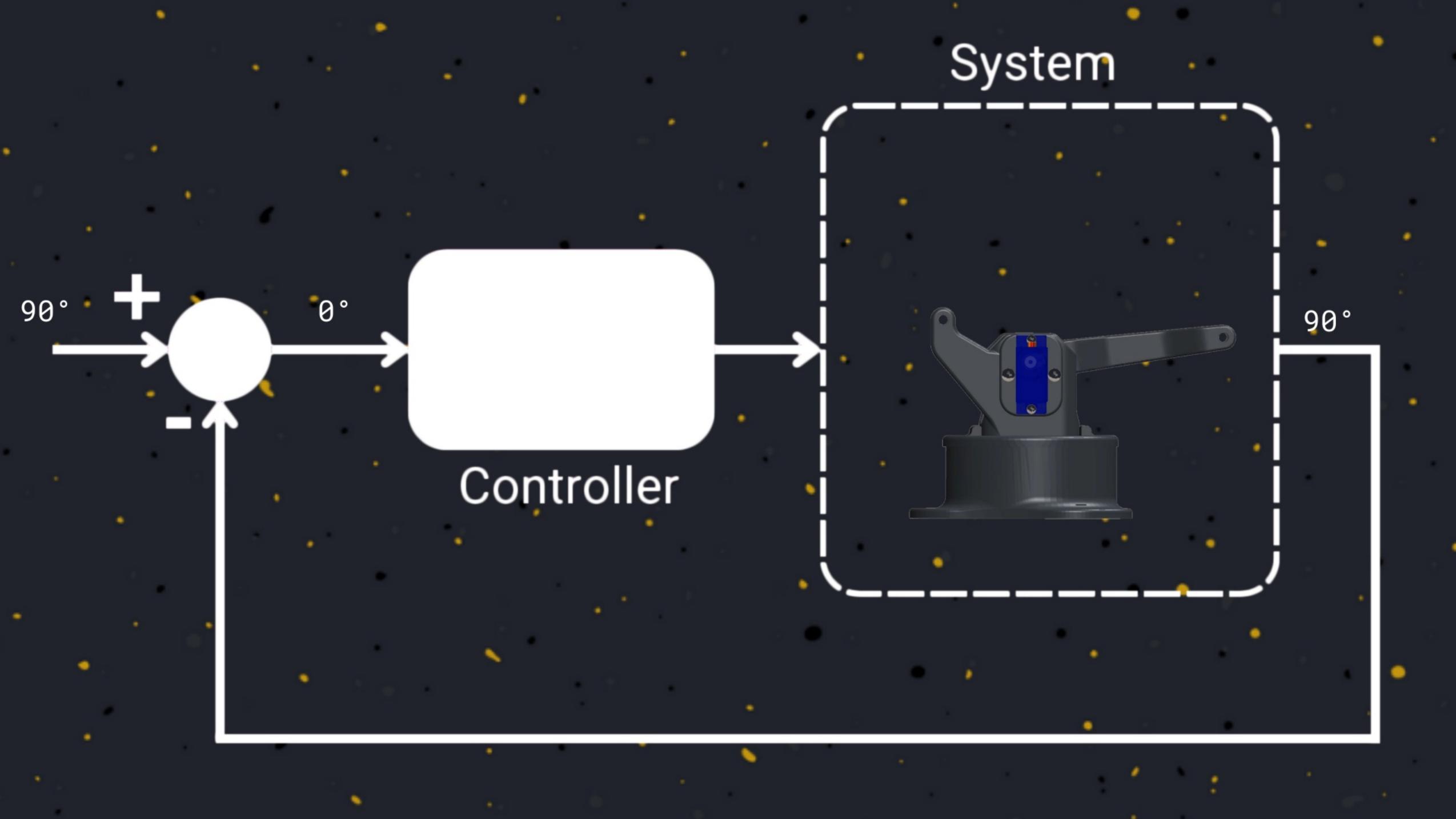


System



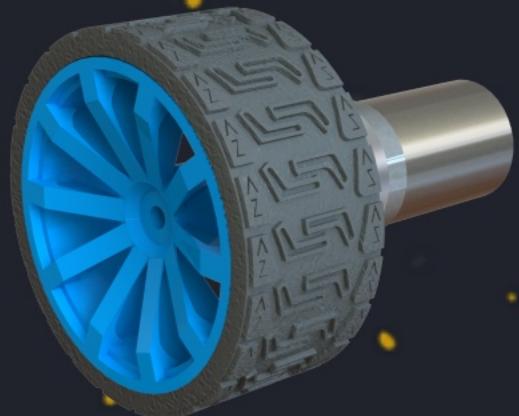
System







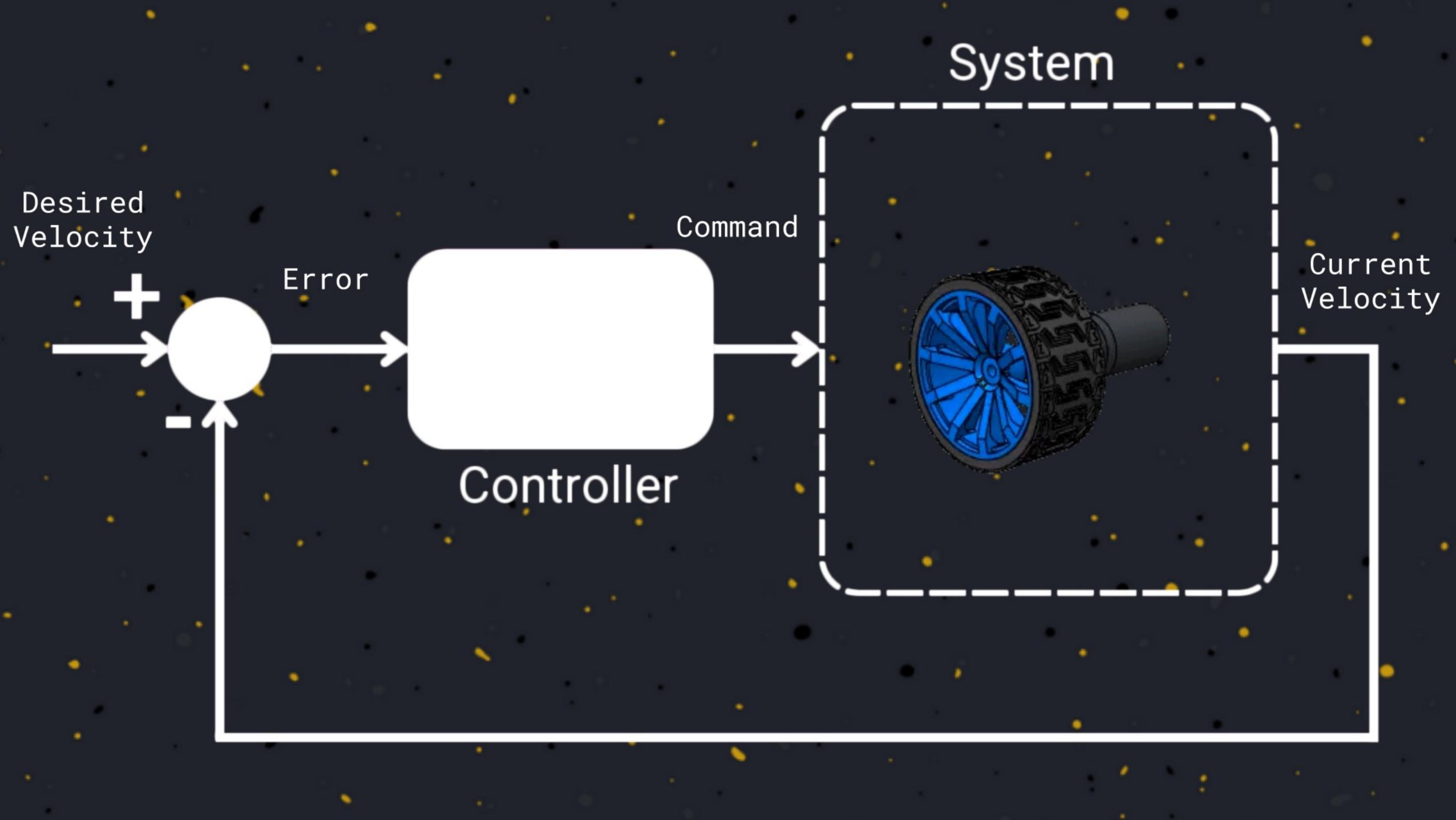
Position



Velocity

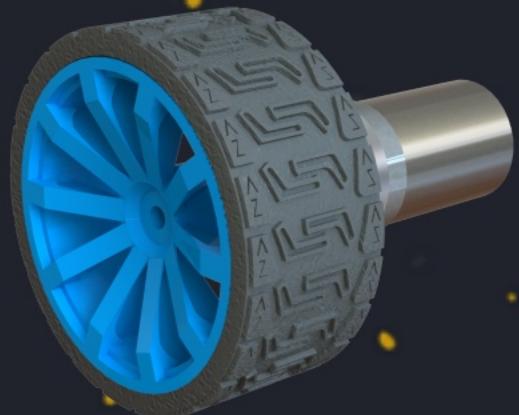


Effort





Position



Velocity



Effort

System

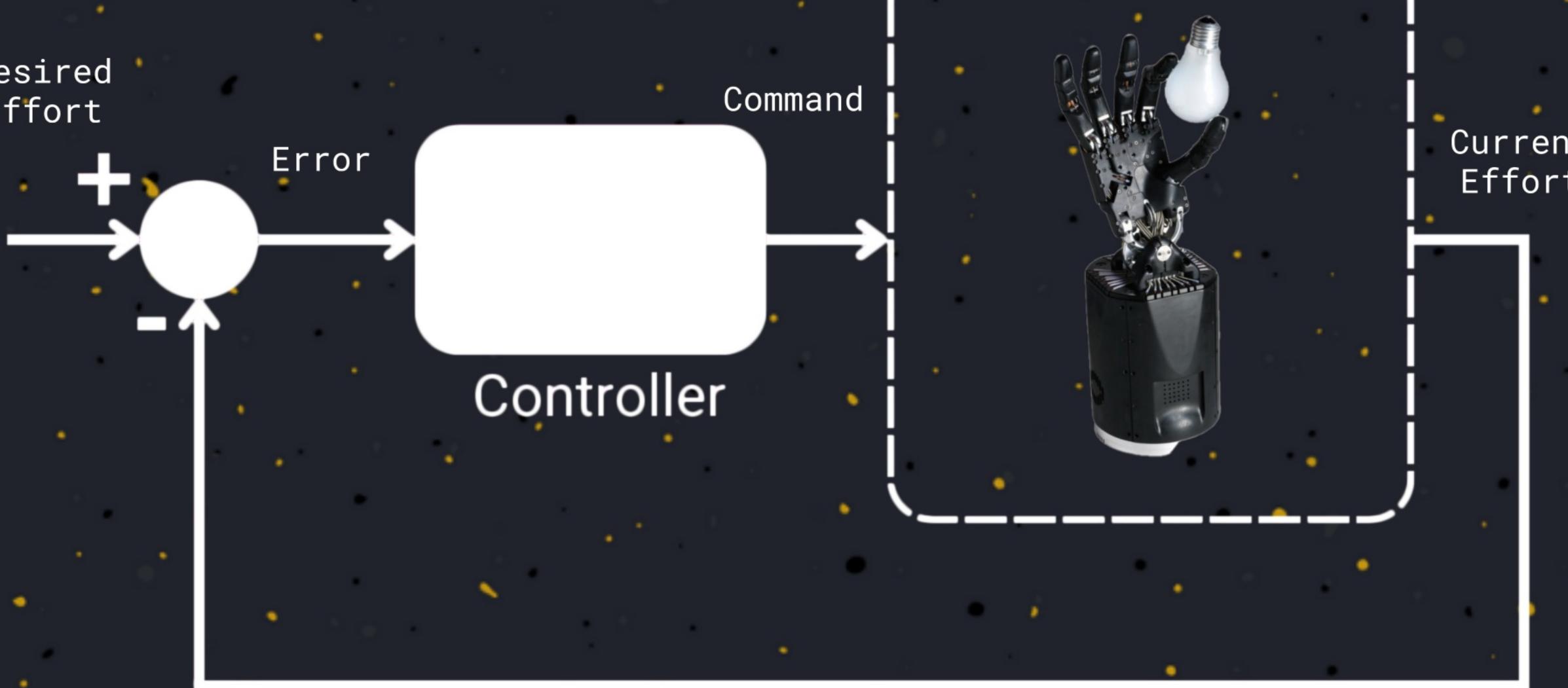
Desired  
Effort

Error

Command

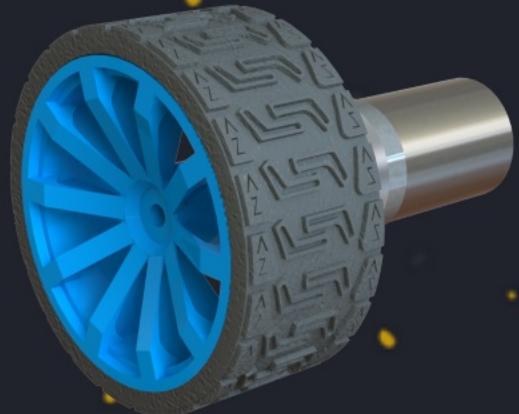
Controller

Current  
Effort





Position

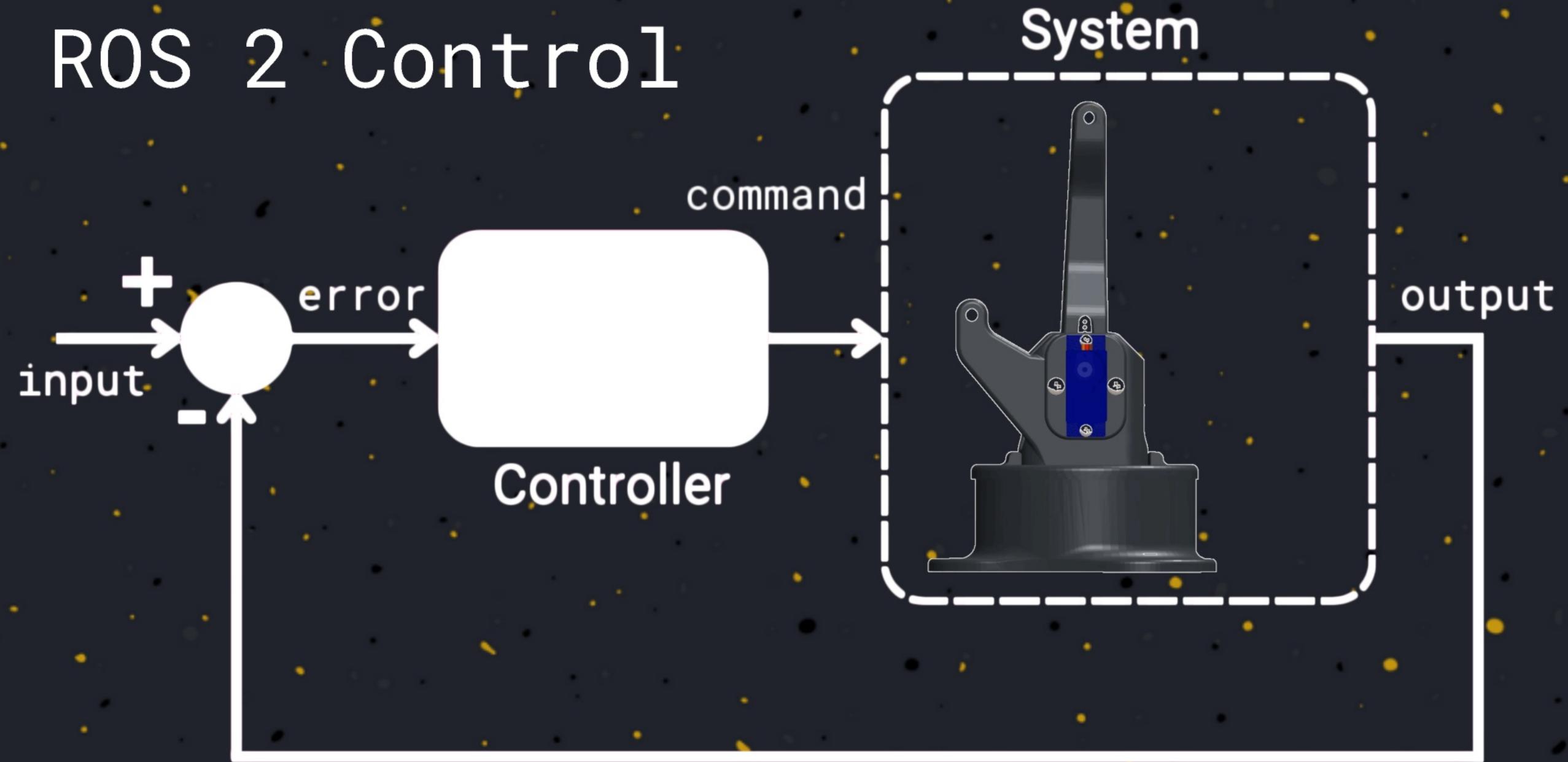


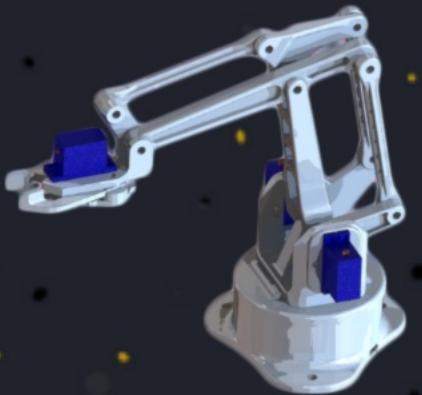
Velocity



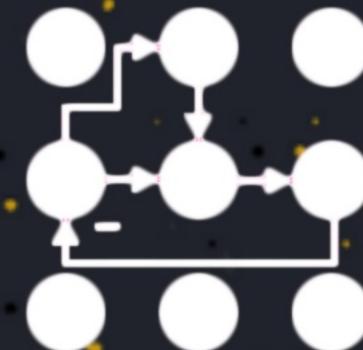
Effort

# ROS 2 Control

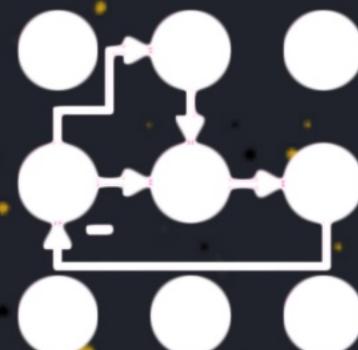


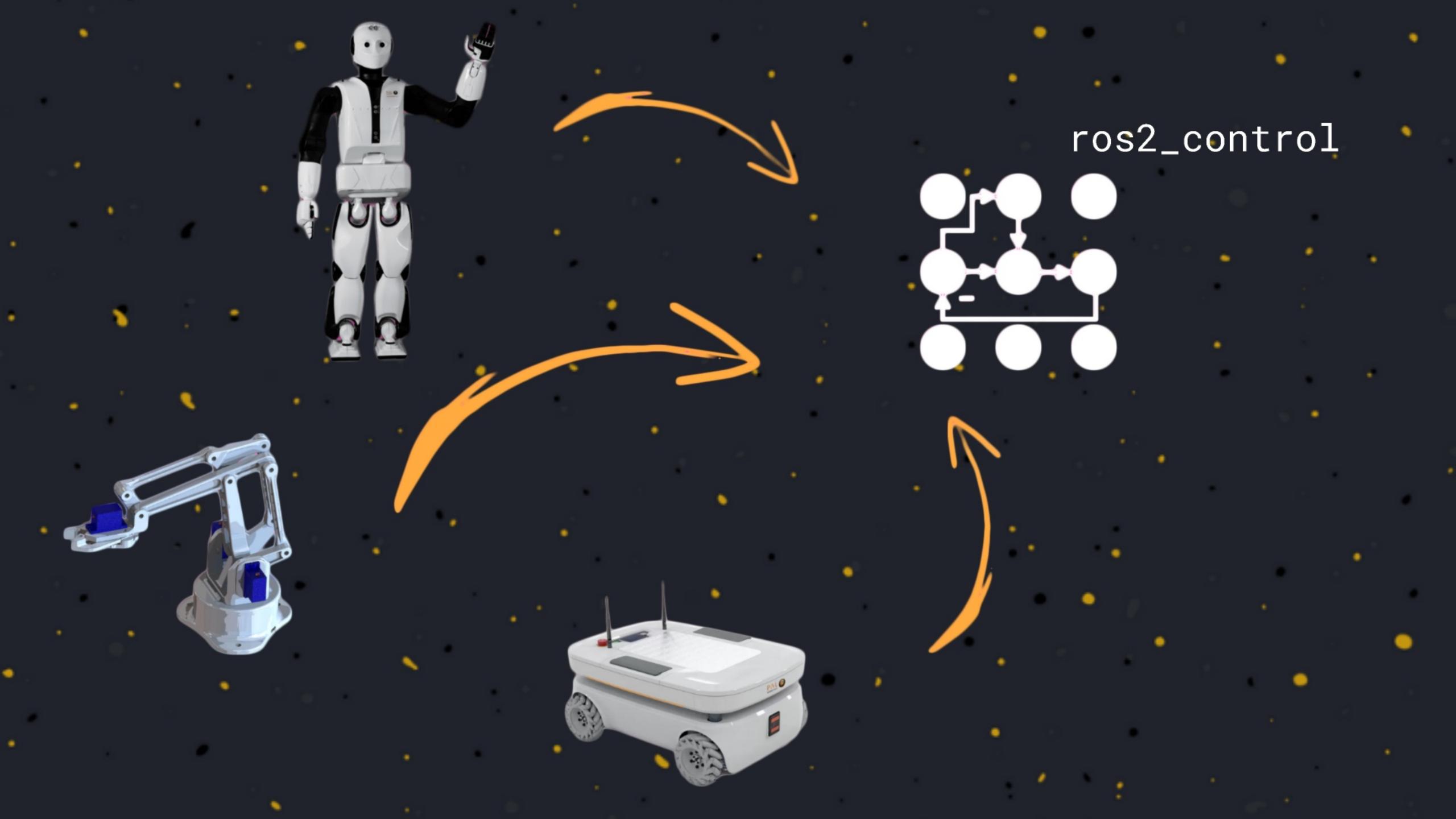


ros2\_control

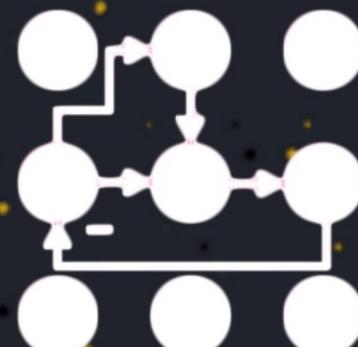


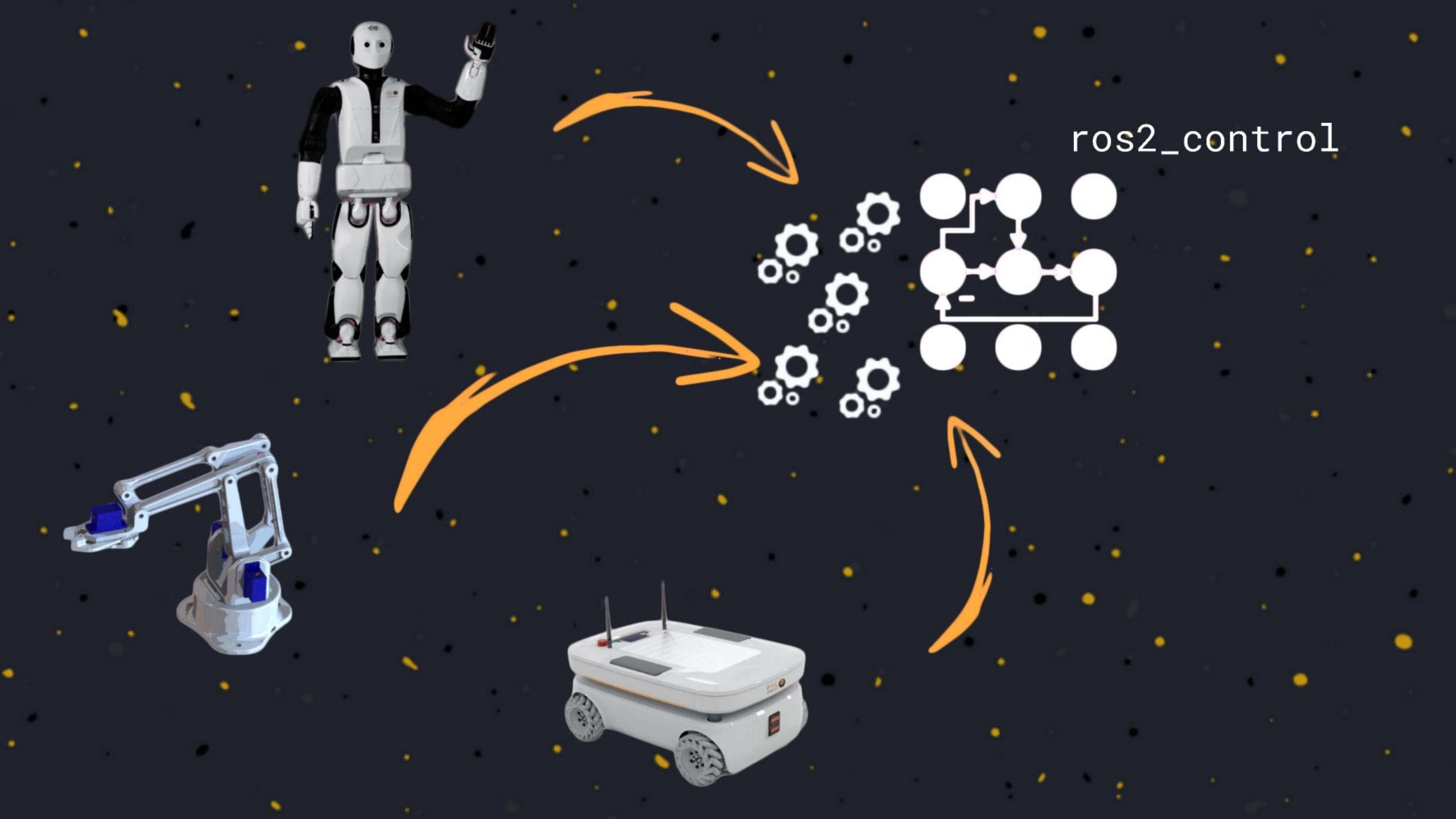
ros2\_control



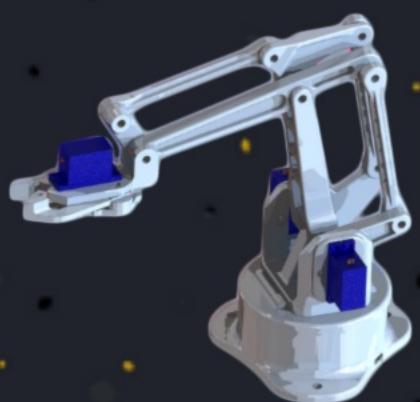


ros2\_control

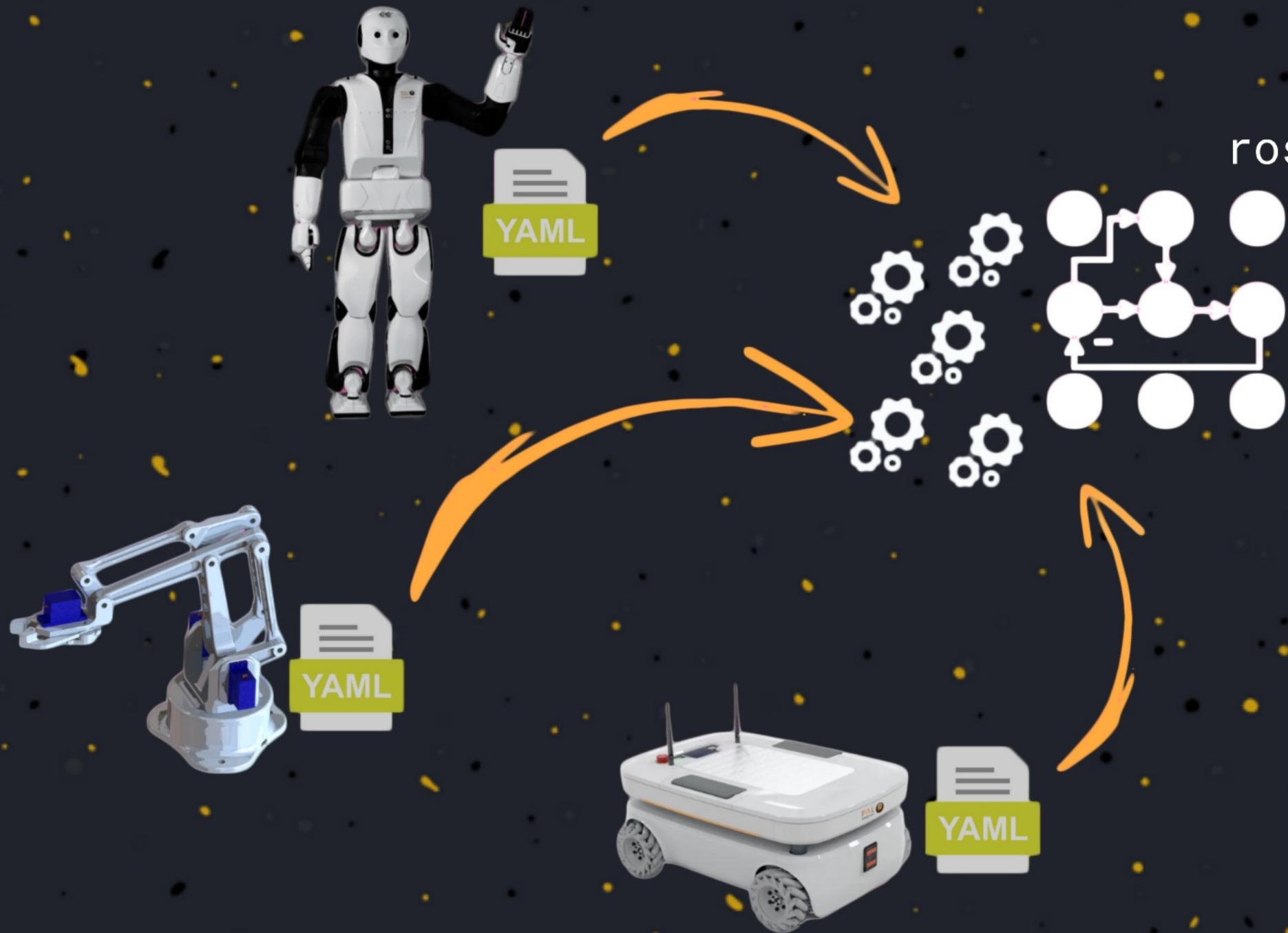




ros2\_control



ros2\_control



```
controller_manager: → Node Name
  ros_parameters:
    update_rate: 10 # Hz

  arm_controller:
    type: joint_trajectory_controller/JointTrajectoryController

  # gripper_controller:
  #   type: forward_command_controller/ForwardCommandController

  gripper_controller:
    type: joint_trajectory_controller/JointTrajectoryController

  joint_state_broadcaster:
    type: joint_state_broadcaster/JointStateBroadcaster
```



```
controller_manager:  
ros_parameters:  
    update_rate: 10 # Hz
```



Node Name  
Parameter



```
arm_controller:  
    type: joint_trajectory_controller/JointTrajectoryController  
  
#gripper_controller:  
#    type: forward_command_controller/ForwardCommandController  
  
gripper_controller:  
    type: joint_trajectory_controller/JointTrajectoryController  
  
joint_state_broadcaster:  
    type: joint_state_broadcaster/JointStateBroadcaster
```

controller\_manager:

ros\_parameters:

update\_rate: 10 # Hz

arm\_controller:

type: joint\_trajectory\_controller/JointTrajectoryController

#gripper\_controller:

# type: forward\_command\_controller/ForwardCommandController

gripper\_controller:

type: joint\_trajectory\_controller/JointTrajectoryController

joint\_state\_broadcaster:

type: joint\_state\_broadcaster/JointStateBroadcaster

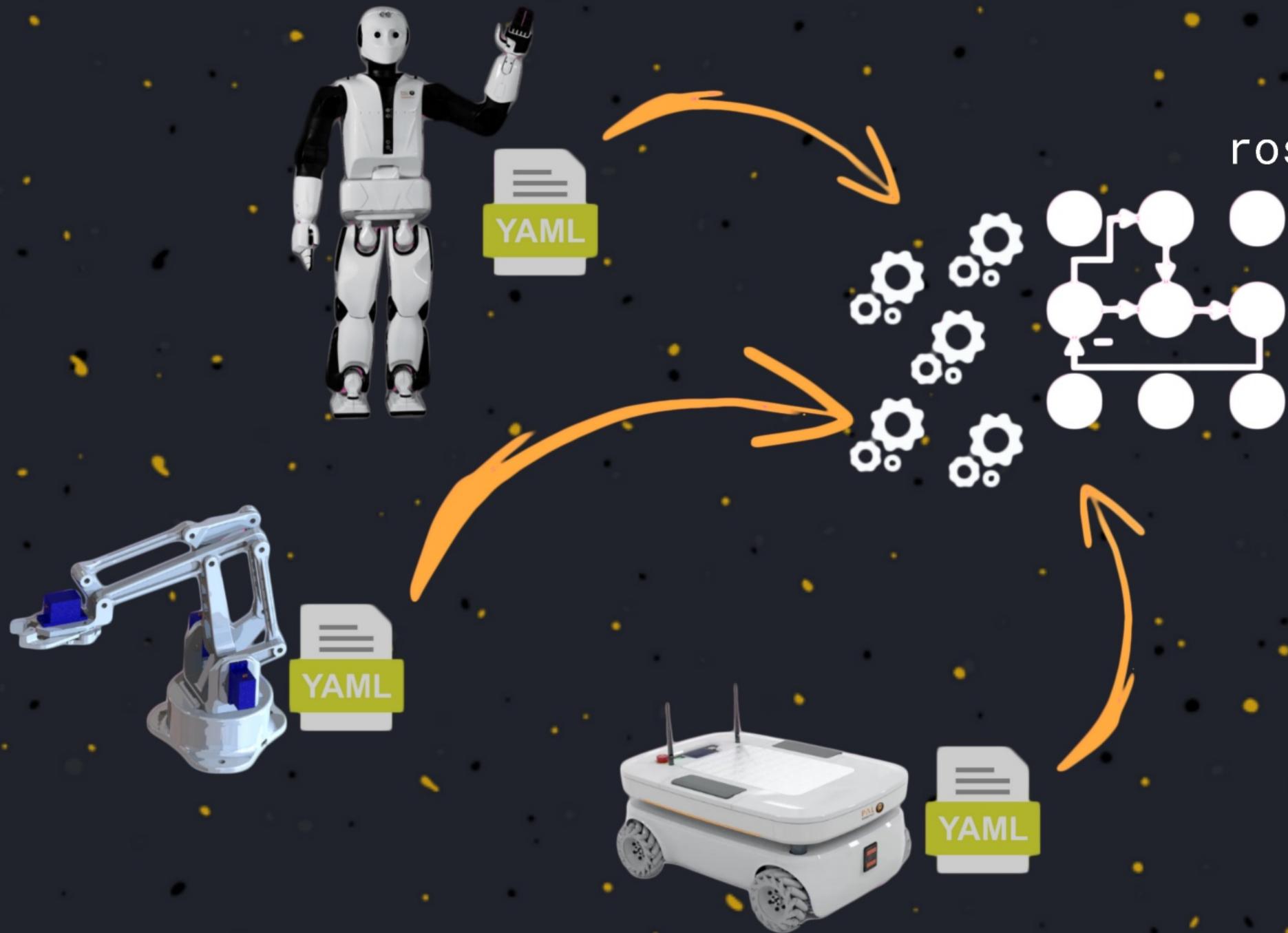
Node Name  
Parameter

Value

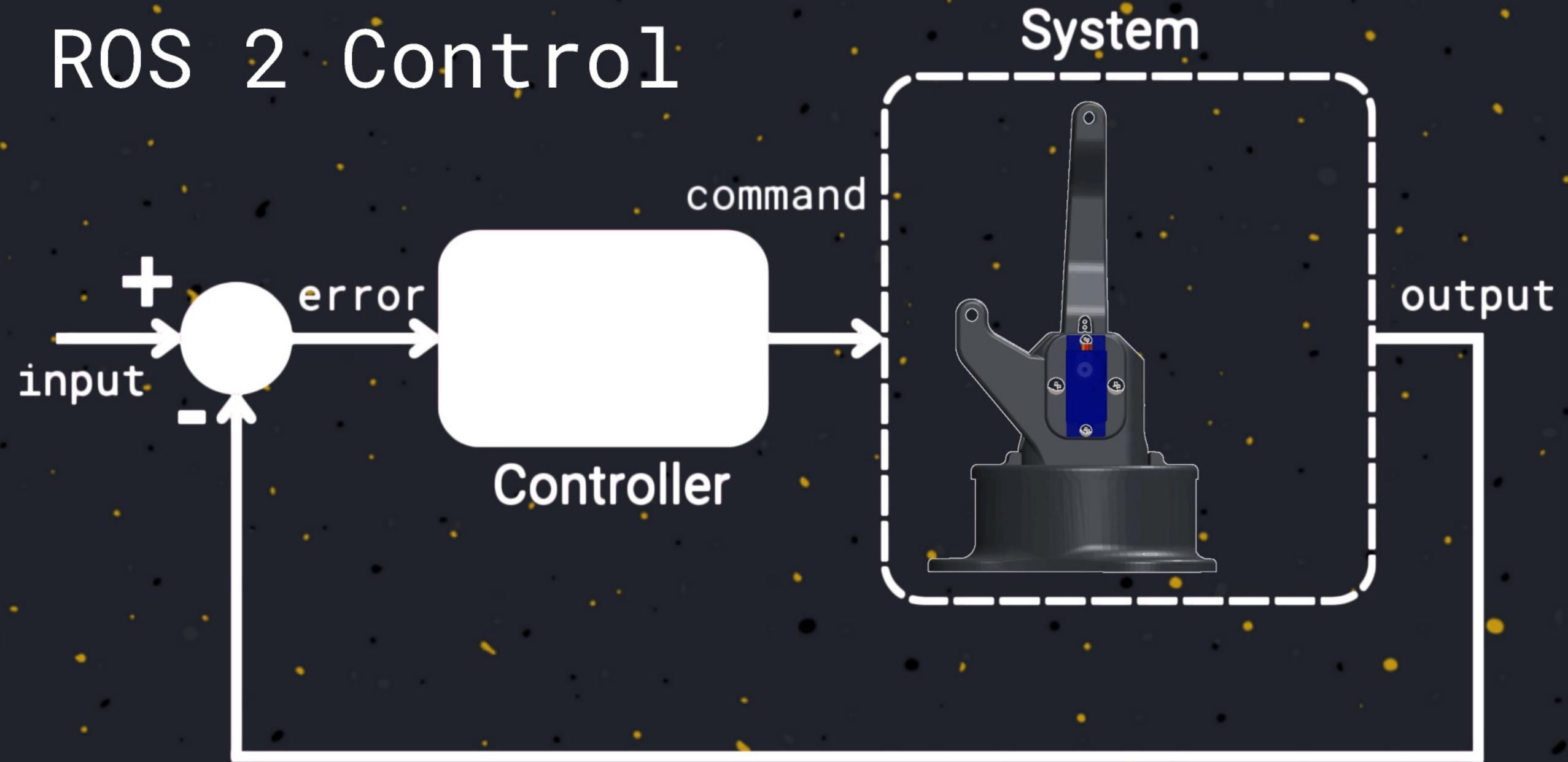


YAML

ros2\_control



# ROS 2 Control



# Arduinobot

