```
state_interfaces:state_start_joint_7/effort
                                                                                       joint_state_broadcaster:state_end_joint_7/effort
                                                                                       joint_state_broadcaster:state_end_joint_6/effort
        state_interfaces:state_start_joint_6/effort
        state\_interfaces:state\_start\_joint\_1/effort
                                                                                       joint_state_broadcaster:state_end_joint_1/effort
                                                                                       joint_state_broadcaster:state_end_joint_2/effort
        state_interfaces:state_start_joint_2/effort
                                                                                       joint_state_broadcaster:state_end_joint_3/effort
        state_interfaces:state_start_joint_3/effort
                                                                                       joint_state_broadcaster:state_end_joint_5/effort
        state\_interfaces:state\_start\_joint\_5/effort
                                                                                      joint_state_broadcaster:state_end_joint_4/effort
        state_interfaces:state_start_joint_4/effort
   twist_controller:command_start_tcp/twist.angular.z
                                                                                   command_interfaces:command_end_tcp/twist.angular.z
    twist\_controller:command\_start\_tcp/twist.linear.z
                                                                                    command\_interfaces: command\_end\_tcp/twist.linear.z
                                                                                   command_interfaces:command_end_tcp/twist.angular.x
   twist_controller:command_start_tcp/twist.angular.x
    twist\_controller:command\_start\_tcp/twist.linear.x
                                                                                    command\_interfaces: command\_end\_tcp/twist.linear.x
   twist\_controller:command\_start\_tcp/twist.angular.y
                                                                                   command\_interfaces: command\_end\_tcp/twist.angular.y
    twist\_controller:command\_start\_tcp/twist.linear.y
                                                                                    command_interfaces:command_end_tcp/twist.linear.y
joint_trajectory_controller:command_start_joint_5/position
                                                                                     command_interfaces:command_end_joint_5/position
joint_trajectory_controller:command_start_joint_6/position
                                                                                     command\_interfaces: command\_end\_joint\_6/position
joint_trajectory_controller:command_start_joint_3/position
                                                                                    command interfaces:command end joint 3/position
joint_trajectory_controller:command_start_joint_7/position
                                                                                     command_interfaces:command_end_joint_7/position
joint\_trajectory\_controller: command\_start\_joint\_1/position
                                                                                     command_interfaces:command_end_joint_1/position
joint_trajectory_controller:command_start_joint_4/position
                                                                                     command_interfaces:command_end_joint_4/position
joint_trajectory_controller:command_start_joint_2/position
                                                                                     command interfaces:command end joint 2/position
                                                                                    joint_trajectory_controller:state_end_joint_5/velocity
       state_interfaces:state_start_joint_5/velocity
                                                                                     joint_state_broadcaster:state_end_joint_5/velocity
                                                                                    joint_trajectory_controller:state_end_joint_2/velocity
       state_interfaces:state_start_joint_2/velocity
                                                                                     joint_state_broadcaster:state_end_joint_2/velocity
                                                                                    joint_trajectory_controller:state_end_joint_5/position
       state_interfaces:state_start_joint_5/position
                                                                                     joint_state_broadcaster:state_end_joint_5/position
                                                                                    joint_trajectory_controller:state_end_joint_4/velocity
       state_interfaces:state_start_joint_4/velocity
                                                                                     joint_state_broadcaster:state_end_joint_4/velocity
                                                                                    joint_trajectory_controller:state_end_joint_6/position
       state_interfaces:state_start_joint_6/position
                                                                                     joint_state_broadcaster:state_end_joint_6/position
                                                                                    joint_trajectory_controller:state_end_joint_7/velocity
       state_interfaces:state_start_joint_7/velocity
                                                                                     joint_state_broadcaster:state_end_joint_7/velocity
                                                                                    joint\_trajectory\_controller: state\_end\_joint\_3/position
       state_interfaces:state_start_joint_3/position
                                                                                     joint_state_broadcaster:state_end_joint_3/position
                                                                                    joint_trajectory_controller:state_end_joint_7/position
       state_interfaces:state_start_joint_7/position
                                                                                     joint_state_broadcaster:state_end_joint_7/position
                                                                                    joint_trajectory_controller:state_end_joint_1/position
       state_interfaces:state_start_joint_1/position
                                                                                     joint_state_broadcaster:state_end_joint_1/position
                                                                                    joint_trajectory_controller:state_end_joint_4/position
       state_interfaces:state_start_joint_4/position
                                                                                     joint\_state\_broadcaster: state\_end\_joint\_4/position
                                                                                     joint_trajectory_controller:state_end_joint_6/velocity
       state_interfaces:state_start_joint_6/velocity
                                                                                     joint\_state\_broadcaster: state\_end\_joint\_6/velocity
                                                                                    joint_trajectory_controller:state_end_joint_1/velocity
       state_interfaces:state_start_joint_1/velocity
                                                                                      joint_state_broadcaster:state_end_joint_1/velocity
                                                                                    joint_trajectory_controller:state_end_joint_3/velocity
       state_interfaces:state_start_joint_3/velocity
                                                                                     joint_state_broadcaster:state_end_joint_3/velocity
                                                                                    joint_trajectory_controller:state_end_joint_2/position
       state_interfaces:state_start_joint_2/position
                                                                                     joint_state_broadcaster:state_end_joint_2/position
                   command interfaces
                      joint 1/position
                      joint_2/position
                      joint_3/position
                      joint_4/position
                      joint_5/position
                      joint_6/position
                      joint_7/position
                      state_interfaces
                       joint_1/effort
                      joint\_1/position
                      joint_1/velocity
                       joint_2/effort
                      joint_2/position
                      joint_2/velocity
                       joint_3/effort
                      joint_3/position
                      joint_3/velocity
                       joint_4/effort
                      joint_4/position
                      joint_4/velocity
                       joint_5/effort
                      joint_5/position
                      joint_5/velocity
                       joint_6/effort
                      joint_6/position
                      joint_6/velocity
                       joint_7/effort
                      joint_7/position
                      joint_7/velocity
                  joint_state_broadcaster
                    joint_1/effort
                   joint_1/position
                   joint_1/velocity
                    joint_2/effort
                   joint_2/position
                   joint_2/velocity
                    joint_3/effort
                   joint_3/position
                   joint_3/velocity
                    joint_4/effort
                   joint_4/position
                   joint_4/velocity
                    joint_5/effort
                   joint_5/position
                   joint_5/velocity
                    joint_6/effort
                   joint_6/position
                   joint_6/velocity
                    joint_7/effort
                   joint_7/position
                   joint_7/velocity
                      twist controller
                      tcp/twist.angular.x
                      tcp/twist.angular.y
                      tcp/twist.angular.z
                       tcp/twist.linear.x
                       tcp/twist.linear.y
                       tcp/twist.linear.z
                joint_trajectory_controller
            joint_1/position
                               joint_1/position
             joint_1/velocity
            joint_2/position
                               joint_2/position
             joint_2/velocity
            joint_3/position
                               joint_3/position
             joint_3/velocity
             joint_4/position
                               joint_4/position
             joint_4/velocity
                               joint_5/position
             joint_5/position
             joint_5/velocity
                               joint_6/position
            joint_6/position
             joint_6/velocity
                               joint_7/position
             joint_7/position
```

joint_7/velocity