

controller_interface
::Controller< hardware
_interface::VelocityJointInterface >



mecanum_drive_controller
::MecanumDriveController

- name
- publish_period
- last_state_publish_time
- open_loop
- wheel0_jointHandle
- wheel1_jointHandle
- wheel2_jointHandle
- wheel3_jointHandle
- command
- command_struct
- sub_command
- odom_pub
- tf_odom_pub
- odometry
- odom_frame
- use_realigned_roller_joints
- wheels_k
- wheels_radius
- wheel_separation_x
- wheel_separation_y
- cmd_vel_timeout
- base_frame_id
- odom_frame_id
- enable_odom_tf
- wheel_joints_size
- last_cmd
- limiter_linX
- limiter_linY
- limiter_ang

- + MecanumDriveController()
- + init()
- + update()
- + starting()
- + stopping()
- brake()
- cmdVelCallback()
- setWheelParamsFromUrdF()
- getWheelRadius()
- setupRtPublishersMsg()