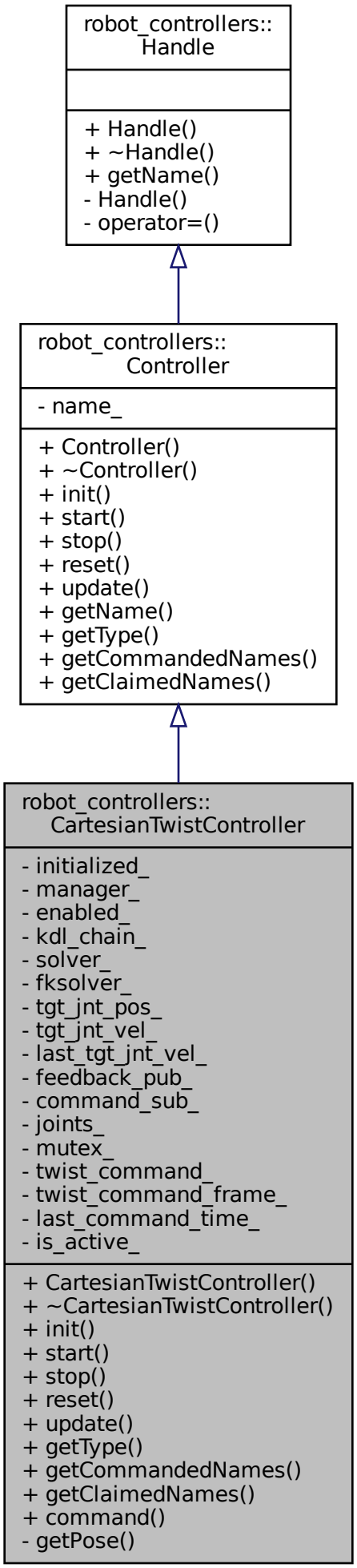
robot_controllers::
Handle
+ Handle()
+ ~Handle()
+ getName()
- Handle()
- operator=()
robot_controllers::
Controller
- name_
+ Controller()
+ ~Controller()
+ init()
+ start()
+ stop()
+ reset()
+ update()
+ getName()
+ getType()
+ getCommandedNames()
+ getClaimedNames()
robot_controllers::
CartesianTwistController
- initialized_
- manager_
- enabled_
- kdl_chain_
- solver_
- fksolver_
- tgt_jnt_pos_
- tgt_jnt_vel_
- last_tgt_jnt_vel_
- feedback_pub_
- command_sub_
- joints_
- mutex_
- twist_command_
- twist_command_frame_
- last_command_time_
- is_active_
+ CartesianTwistController()
+ ~CartesianTwistController()
+ init()
+ start()
+ stop()
+ reset()
+ update()
+ getType()
+ getCommandedNames()
+ getClaimedNames()
+ command()
- getPose()