```
robot
          controllers::
         Handle
 + Handle()
 + ~Handle()
 + getName()
 - Handle()
 operator=()
             Δ
robot
         controllers::
     JointHandle
+ JointHandle()
+ ~Jointnam
+ setPosition()
-*\/olocity()
     -JointHandle()
+ setVelocity()
+ setEffort()
 + getPosition()
+ getVelocity()
+ getEffort()
+ isContinuous()
+ getPositionMin()
+ getPositionMax()
+ getVelocityMax()
   getEffortMax()
   getName()
+ reset()
JointHandle()operator=()
gazebo::JointHandle
- joint
 desired_position_desired_velocity_desired_effort_
 mode
 position_pid
 velocity_pid_
velocity_limit
 velocity

    effort_limit

continuous
 applied_effort
 actual velocity
+ JointHandle()
+ ~JointHandle()
+ setPosition()
+ setVelocity()
+ setEffort()
+ getPosition()
+ getVelocity()
+ getEffort() + isContinuous()
+ getPositionMin()
+ getPositionMax()
+ getVelocityMax()
+ getEffortMax()
+ getName()
+ reset()
+ update()
JointHandle()
operator=()
```