```
robot controllers::
             Handle
       + Handle()
       + ~Handle()
       + getName()
       Handle()
       - operator=()
                Δ
   robot controllers::
            Controller
   - name
   + Controller()
   + ~Controller()
   + init()
   + start()
   + stop()
   + reset()
   + update()
   + getName()
   + getType()
   + getCommandedNames()
   + getClaimedNames()
robot controllers::
   CartesianWrenchController
- initialized
- manager
- enabled
root_link_
- last command
- desired wrench
- kdl_chain_
- jac_solver_
- jnt_pos_
jnt_eff

    jacobian

- feedback_pub
- command sub
- tf
joints
+ CartesianWrenchController()
+ ~CartesianWrenchController()
+ init()
+ start()
+ stop()
+ reset()
+ update()
+ getType()
+ getCommandedNames()
+ getClaimedNames()
+ command()
updateJoints()
```