

```
controller_interface
::MultiInterfaceController
< franka_hw::FrankaModelInterface,
  hardware_interface::EffortJointInterface,
  franka_hw::FrankaStateInterface >
```



```
franka_example_controllers
::CartesianImpedanceExampleController
```

- state_handle_
- model_handle_
- joint_handles_
- filter_params_
- nullspace_stiffness_
- nullspace_stiffness_target_
- delta_tau_max_
- cartesian_stiffness_
- cartesian_stiffness_target_
- cartesian_damping_
- cartesian_damping_target_
- q_d_nullspace_
- position_d_
- orientation_d_
- position_d_target_
- orientation_d_target_
- dynamic_server_compliance_param_
- dynamic_reconfigure_compliance_param_node_
- sub_equilibrium_pose_

- + init()
- + starting()
- + update()
- saturateTorqueRate()
- complianceParamCallback()
- equilibriumPoseCallback()