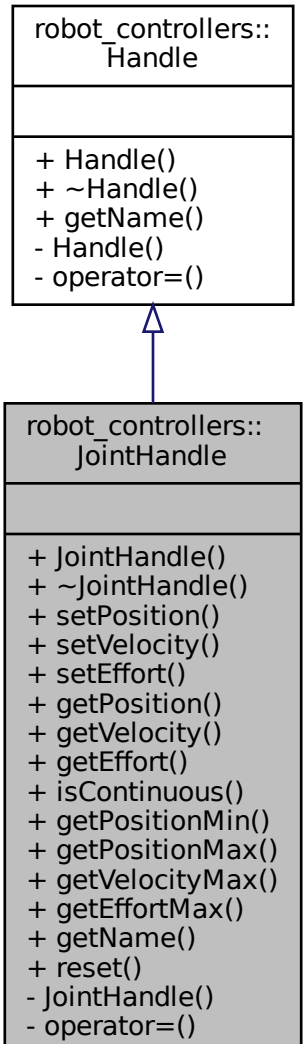
robot_controllers::
Handle
+ Handle()
+ ~Handle()
+ getName()
- Handle()
- operator=()
robot_controllers::
JointHandle
+ JointHandle()
+ ~JointHandle()
+ setPosition()
+ setVelocity()
+ setEffort()
+ getPosition()
+ getVelocity()
+ getEffort()
+ isContinuous()
+ getPositionMin()
+ getPositionMax()
+ getVelocityMax()
+ getEffortMax()
+ getName()
+ reset()
- JointHandle()
- operator=()