```
robot
          controllers::
         .
Handle
 + Handle()
 + ~Handle()
 + getName()
  - Handle()
 - operator=()
             Δ
robot
         controllers::
      JointHandle
+ JointHandle()
+ ~JointHandle
+ setPosition()
     -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_
- 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=()
```