```
hardware interface
          ::RobotHW
    franka hw::FrankaHW

    joint state interface

- franka state interface
position_joint_interface_velocity_joint_interface_
effort_joint_interface
- franka pose cartesian
 interface
franka_velocity_cartesian_interface_
- franka model interface

    position joint limit

 interface
velocity_joint_limit
 interface
effort joint limit
 interface
robot_state
joint_names_
- arm_id
- get internal controller
- get_limit_rate
get_cutoff_frequency

    position joint command

    velocity joint command

    effort_joint_command

    pose cartesian command

    velocity_cartesian

command
- run function

    controller_active

    current control mode

+ FrankaHW()
+ FrankaHW()
+ FrankaHW()
+ ~FrankaHW()
+ control()
+ update()
+ controllerActive()
+ checkForConflict()
+ doSwitch()
+ prepareSwitch()
+ getlointPositionCommand()
+ getJointVelocityCommand()
+ getJointEffortCommand()
+ enforceLimits()
+ reset()
controlCallback()
```