

```
controller_interface  
::Controller< hardware  
_interface::PositionJointInterface >
```

```
classDiagram
    class controller_interface {
        <<abstract>>
        <<interface>>
        Controller(hardware_interface::PositionJointInterface)
    }
    class panda_simulation_JointPositionController {
        joint_handles_
        gains_vec_
        command_
        sub_command_
        init()
        update()
        setCommandCallback()
        starting()
        stopping()
    }
    controller_interface <|-- panda_simulation_JointPositionController
```

panda_simulation::JointPosition
Controller

- joint_handles_
- gains_vec_
- command_
- sub_command_

- init()
- update()
- setCommandCallback()
- starting()
- stopping()