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

```
franka_example_controllers
::JointImpedanceExampleController

- cartesian_pose_handle_
- model_handle_
- joint_handles_
- radius_
- acceleration_time_
- vel_max_
- angle_
- vel_current_
- k_gains_
- d_gains_
- coriolis_factor_
- dq_filtered_
- initial_pose_
- rate_trigger_
- last_tau_d_
- torques_publisher_
- kDeltaTauMax

+ init()
+ starting()
+ update()
- saturateTorqueRate()
```