

controller\_interface  
::Controller< hardware  
\_interface::VelocityJointInterface >



mecanum\_drive\_controller  
::MecanumDriveController

- name
- publish\_period
- last\_state\_publish\_time
- open\_loop
- wheel0\_jointHandle
- wheel1\_jointHandle
- wheel2\_jointHandle
- wheel3\_jointHandle
- command
- command\_struct
- sub\_command
- odom\_pub
- tf\_odom\_pub
- odometry
- odom\_frame
- use\_realigned\_roller\_joints
- wheels\_k
- wheels\_radius
- wheel\_separation\_x
- wheel\_separation\_y
- cmd\_vel\_timeout
- base\_frame\_id
- odom\_frame\_id
- enable\_odom\_tf
- wheel\_joints\_size
- last\_cmd
- limiter\_linX
- limiter\_linY
- limiter\_ang

- + MecanumDriveController()
- + init()
- + update()
- + starting()
- + stopping()
- brake()
- cmdVelCallback()
- setWheelParamsFromUrdF()
- getWheelRadius()
- setupRtPublishersMsg()