```
robot controllers::
          .
Handle
    + Handle()
    + ~Handle()
    + getName()
    - Handle()
    operator=()
robot controllers::
        Controller
- name
+ Controller()
+ ~Controller()
+ init()
+ start()
+ stop()
+ reset()
+ update()
+ getName()
+ getType()
+ getCommandedNames()
+ getClaimedNames()
robot controllers::
   PointHeadController
- initialized
- manager_
- result
sampler_sampler_mutex_
stop_with_action_last_sample_
- preempted
root_link
- head_pan
- head tilt
server
- kdl tree
- listener
+ PointHeadController()
+ ~PointHeadController()
+ init()
+ start()
+ stop()
+ reset()
+ update()
+ getType()
+ getCommandedNames()
+ getClaimedNames()
executeCb()
```