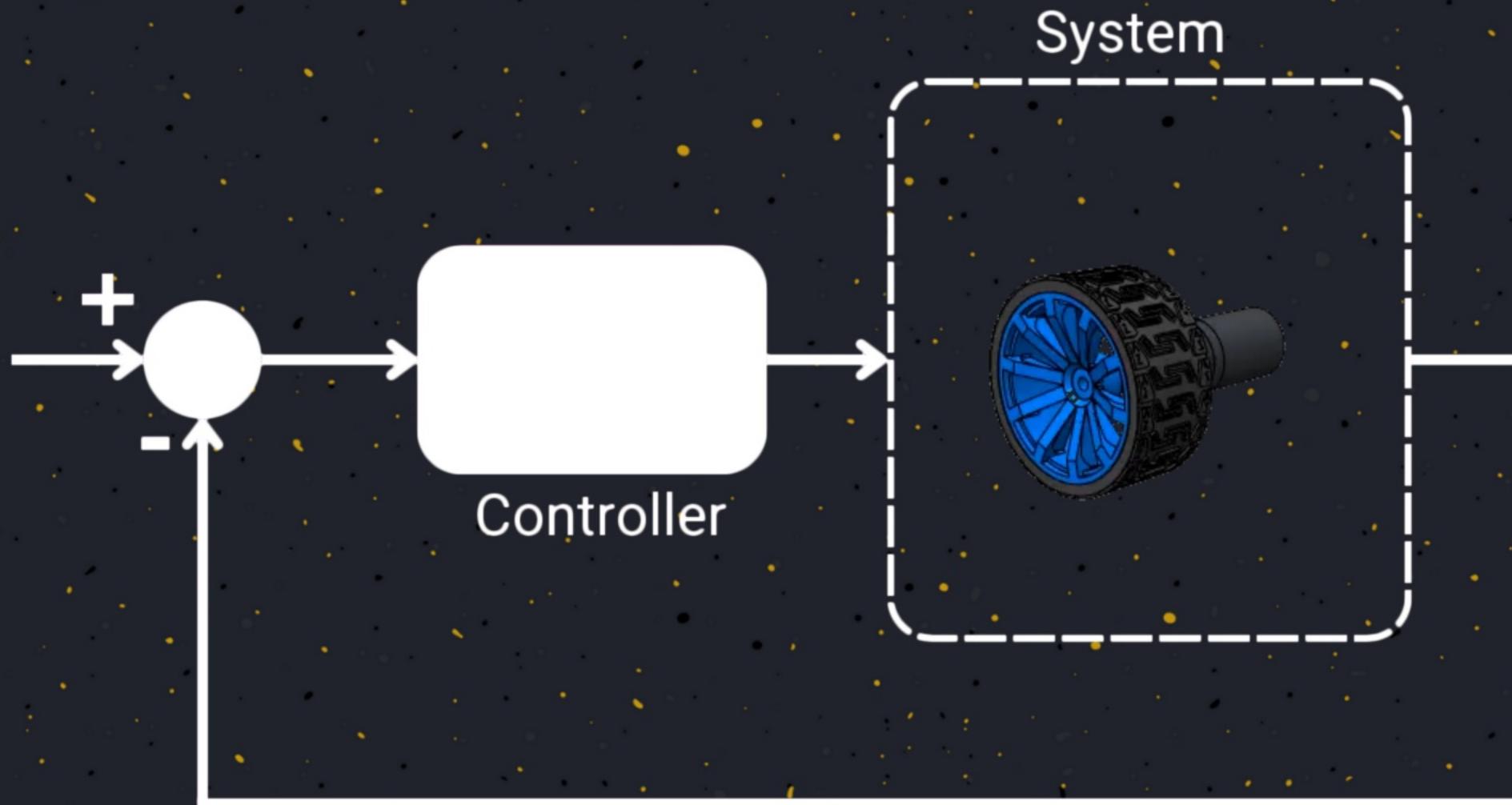
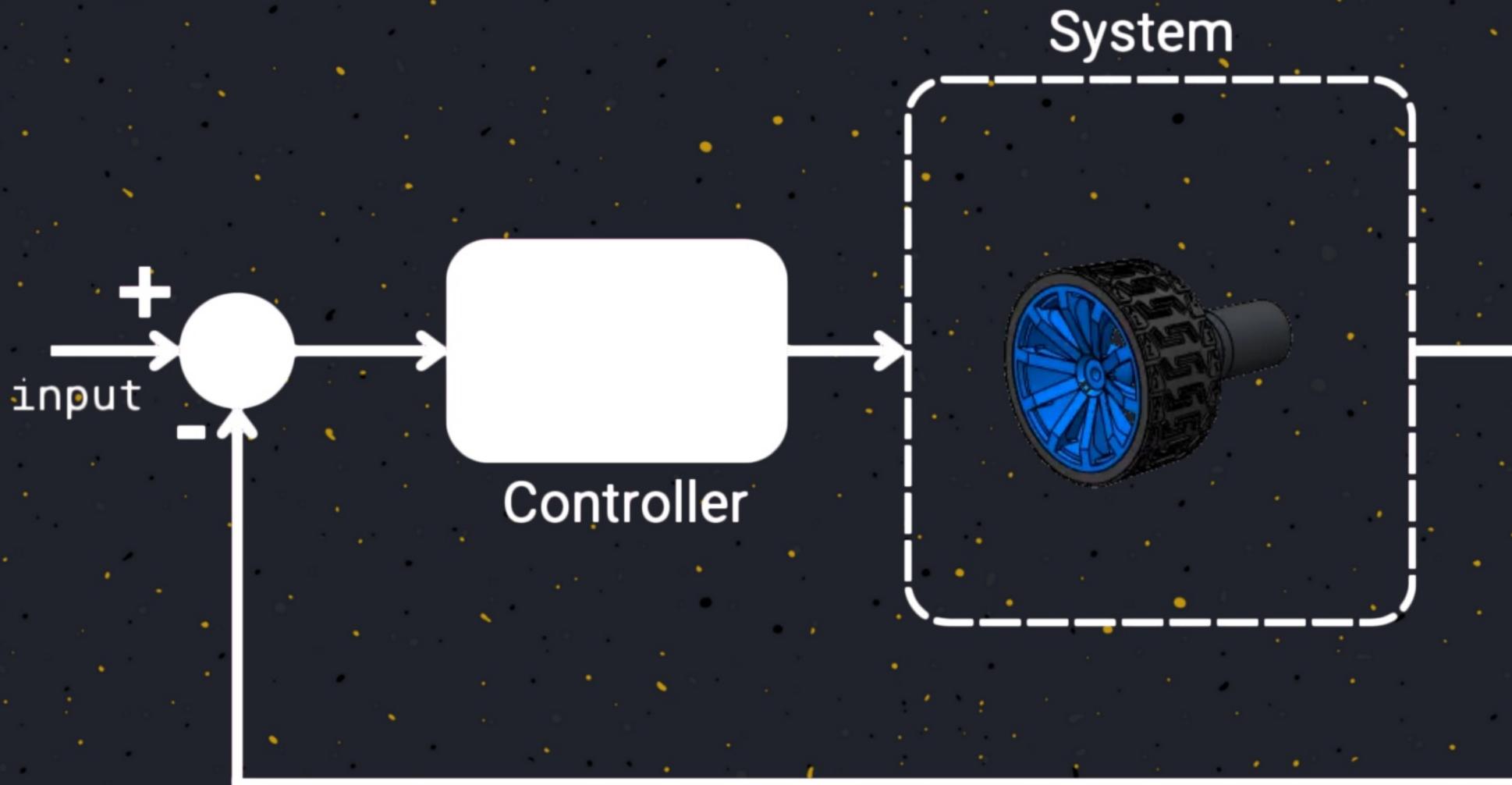


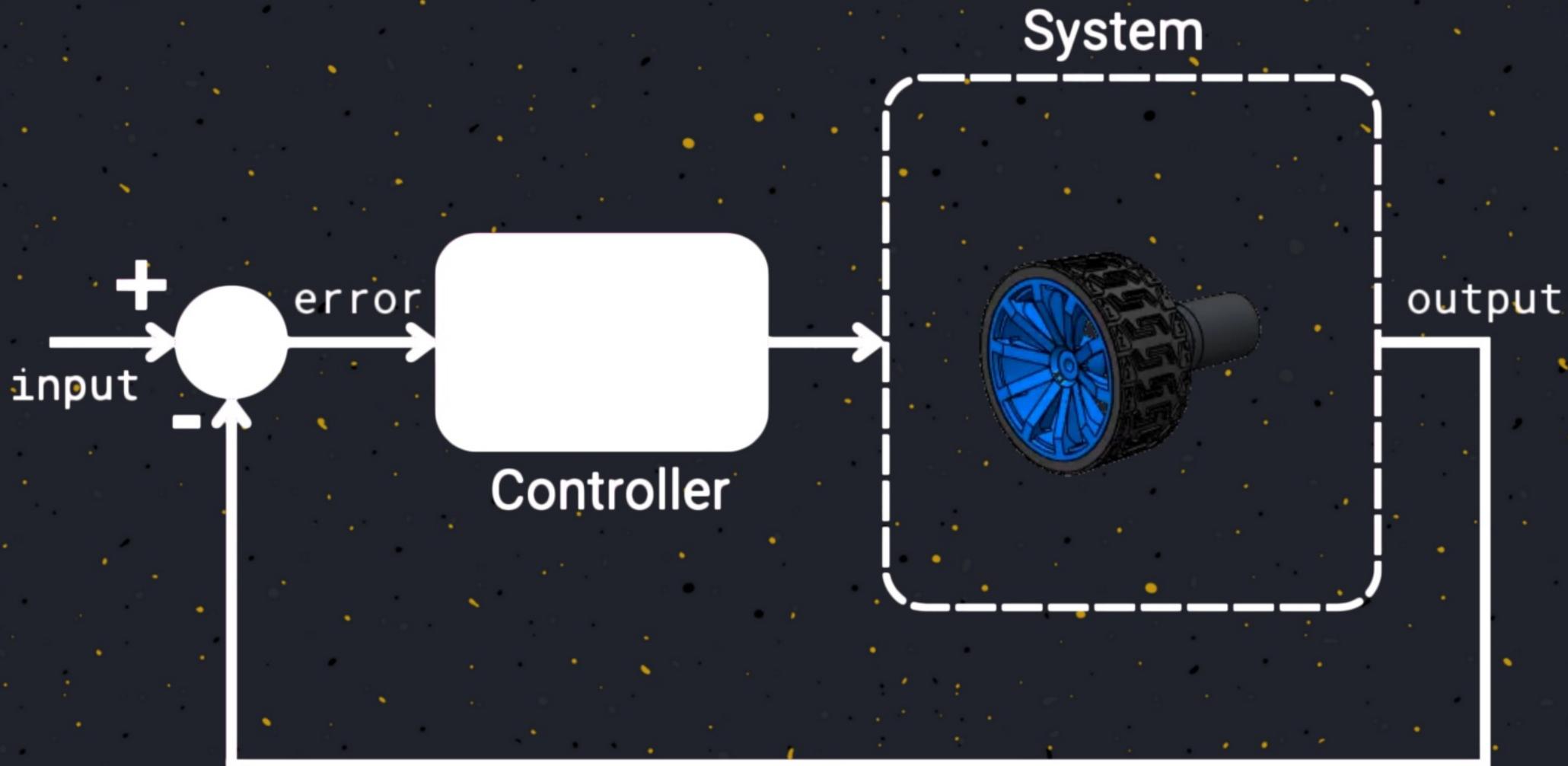
# ROS 2 Control



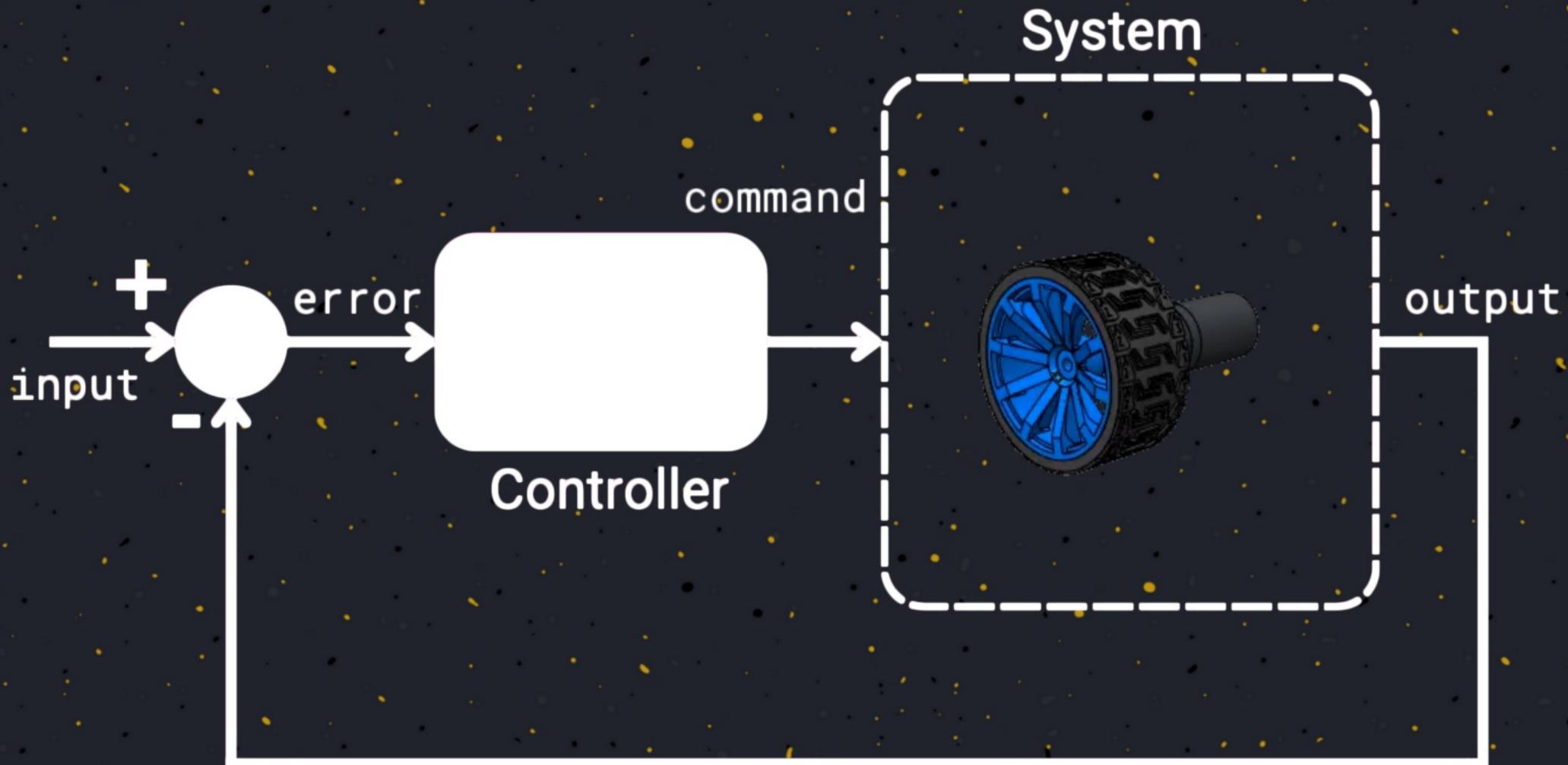
# ROS 2 Control



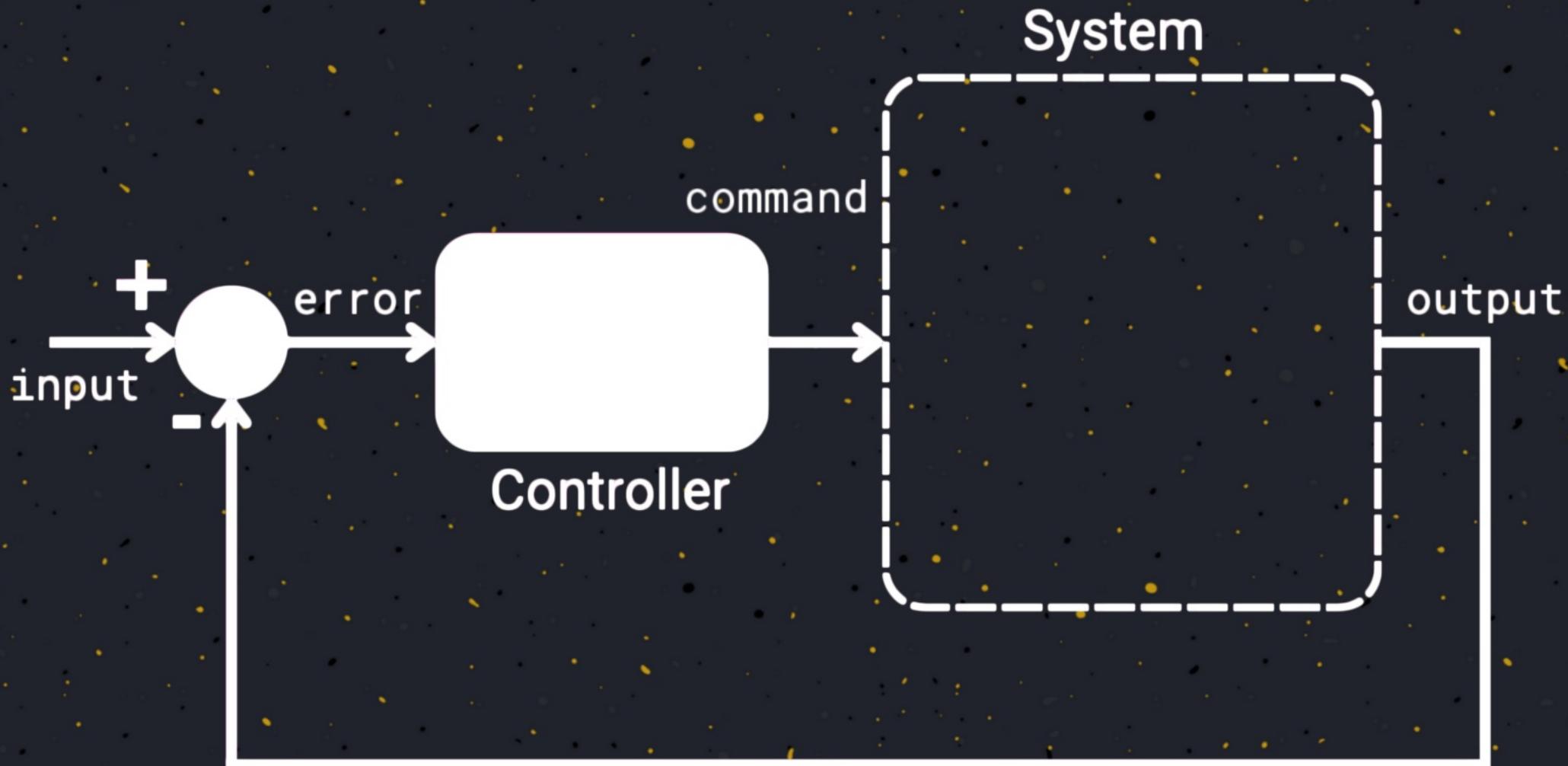
# ROS 2 Control



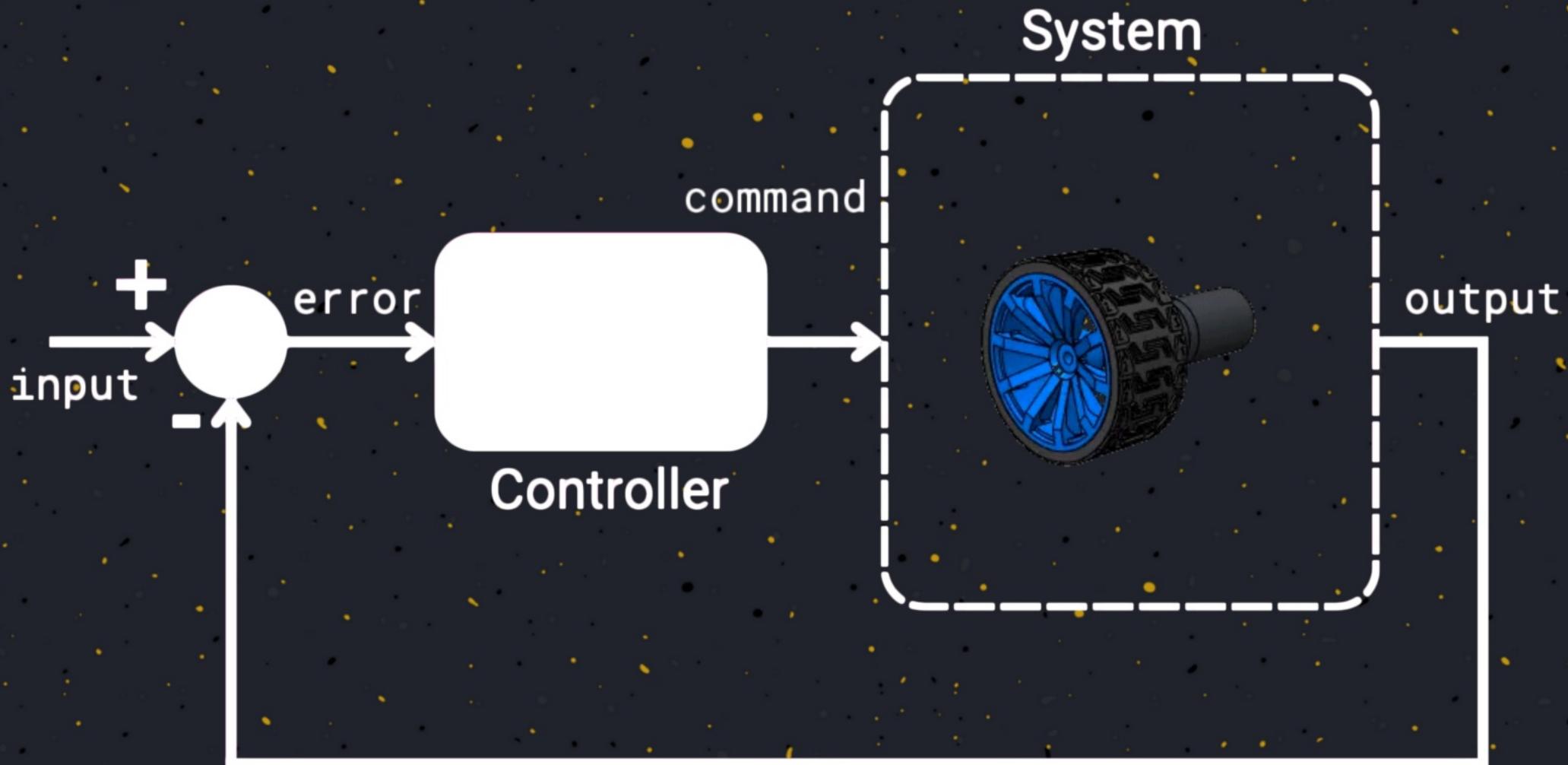
# ROS 2 Control



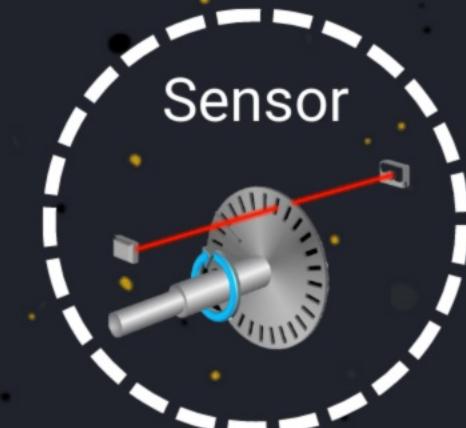
# ROS 2 Control



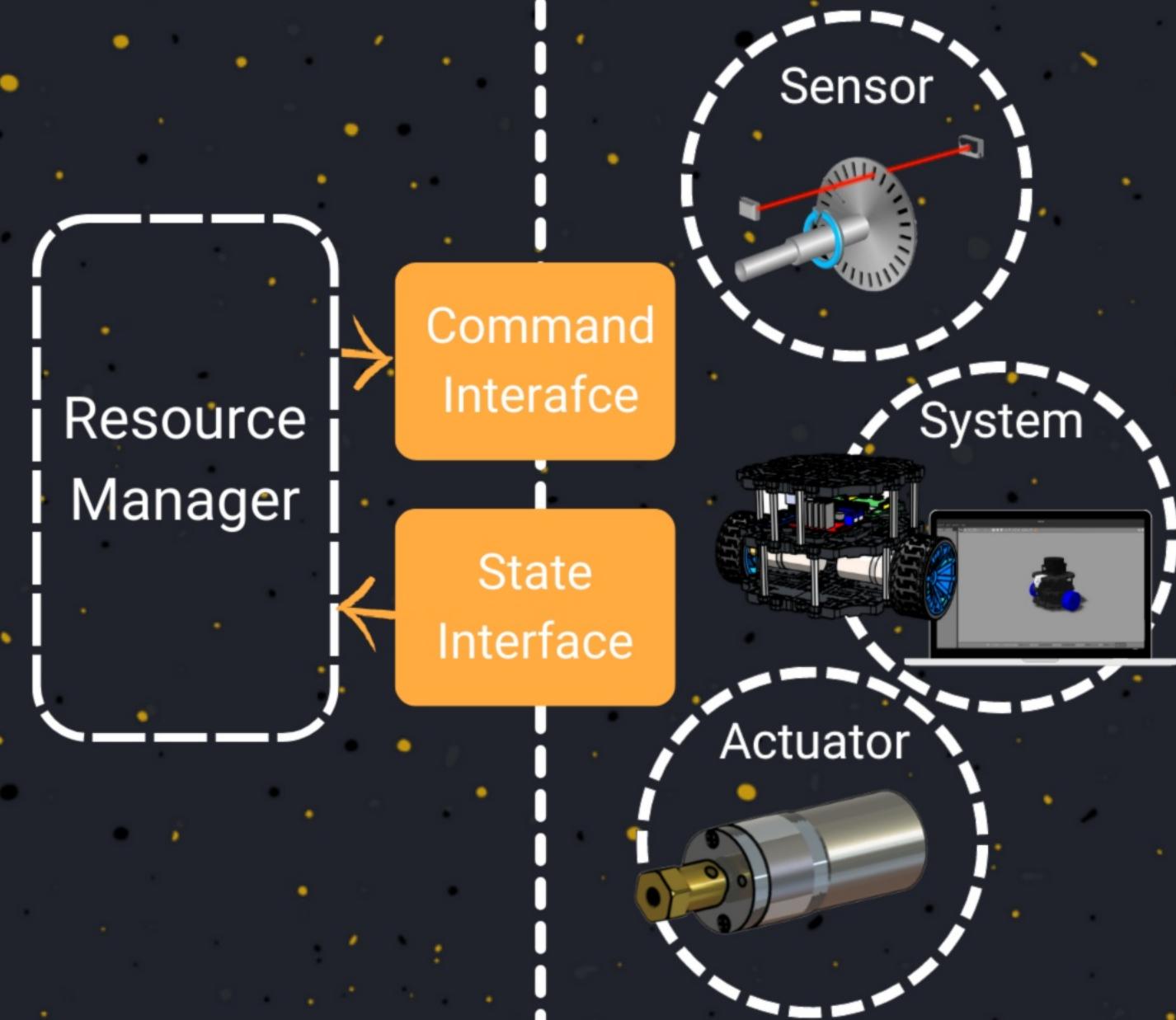
# ROS 2 Control

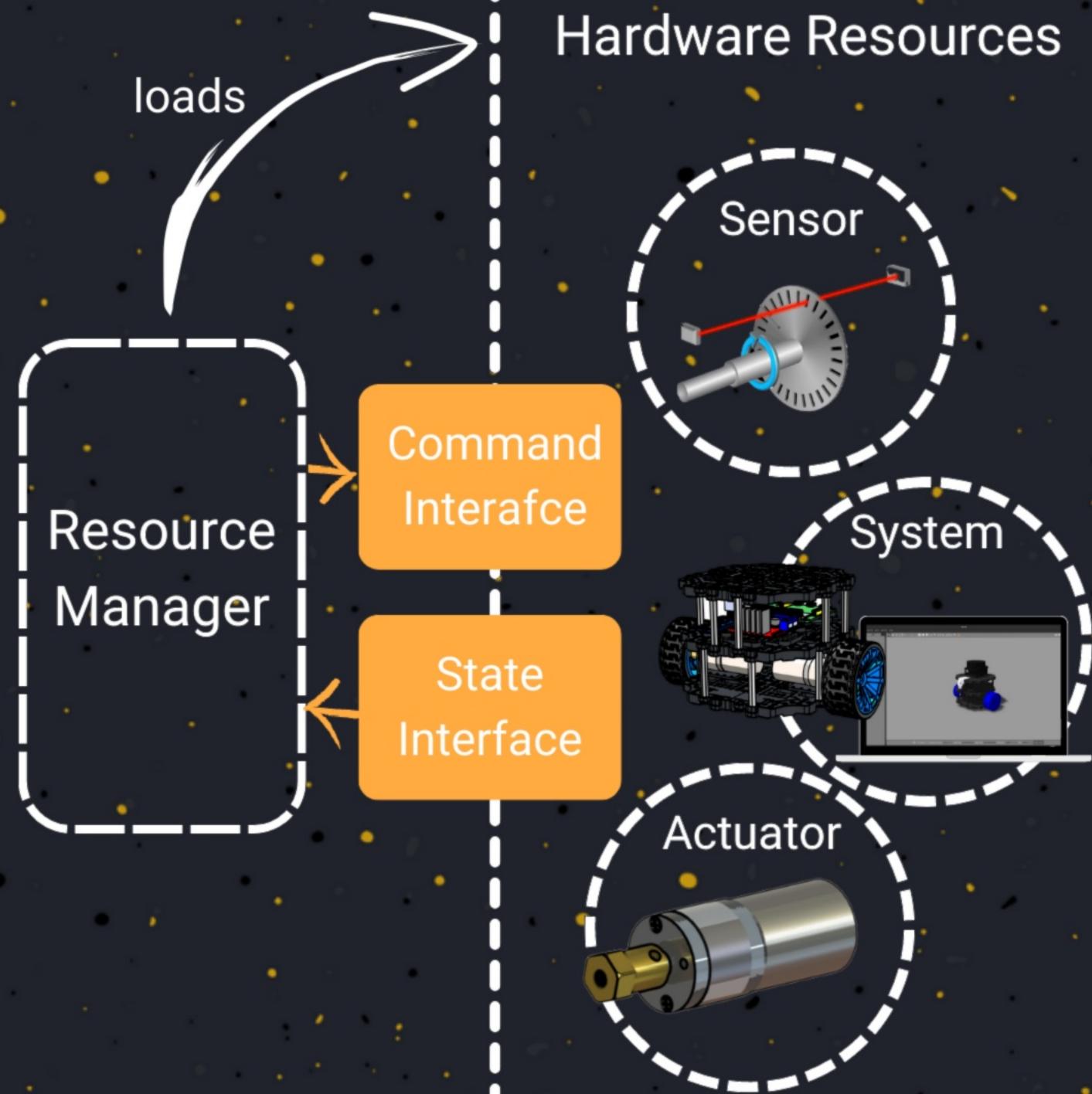


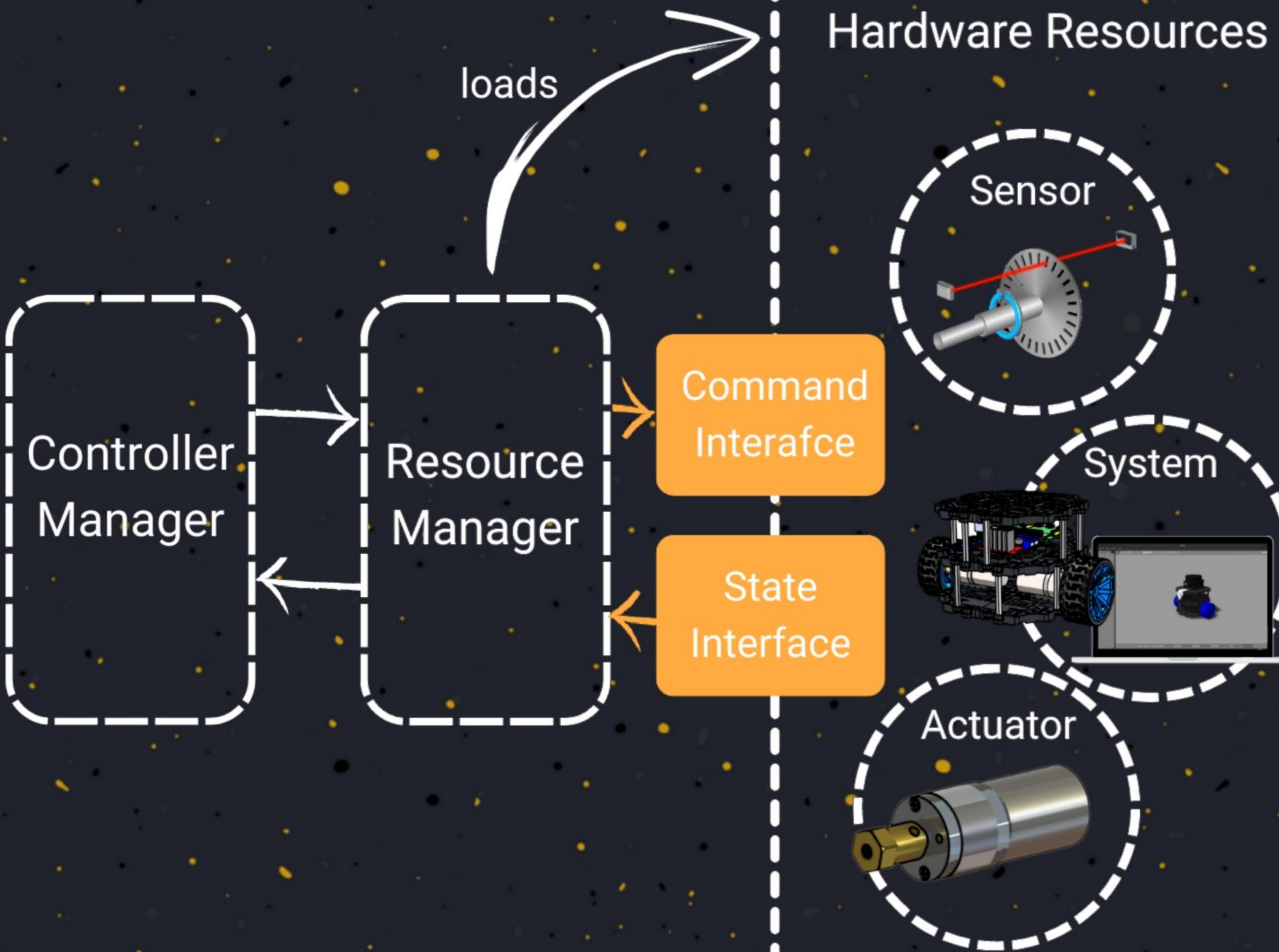
# Hardware Resources

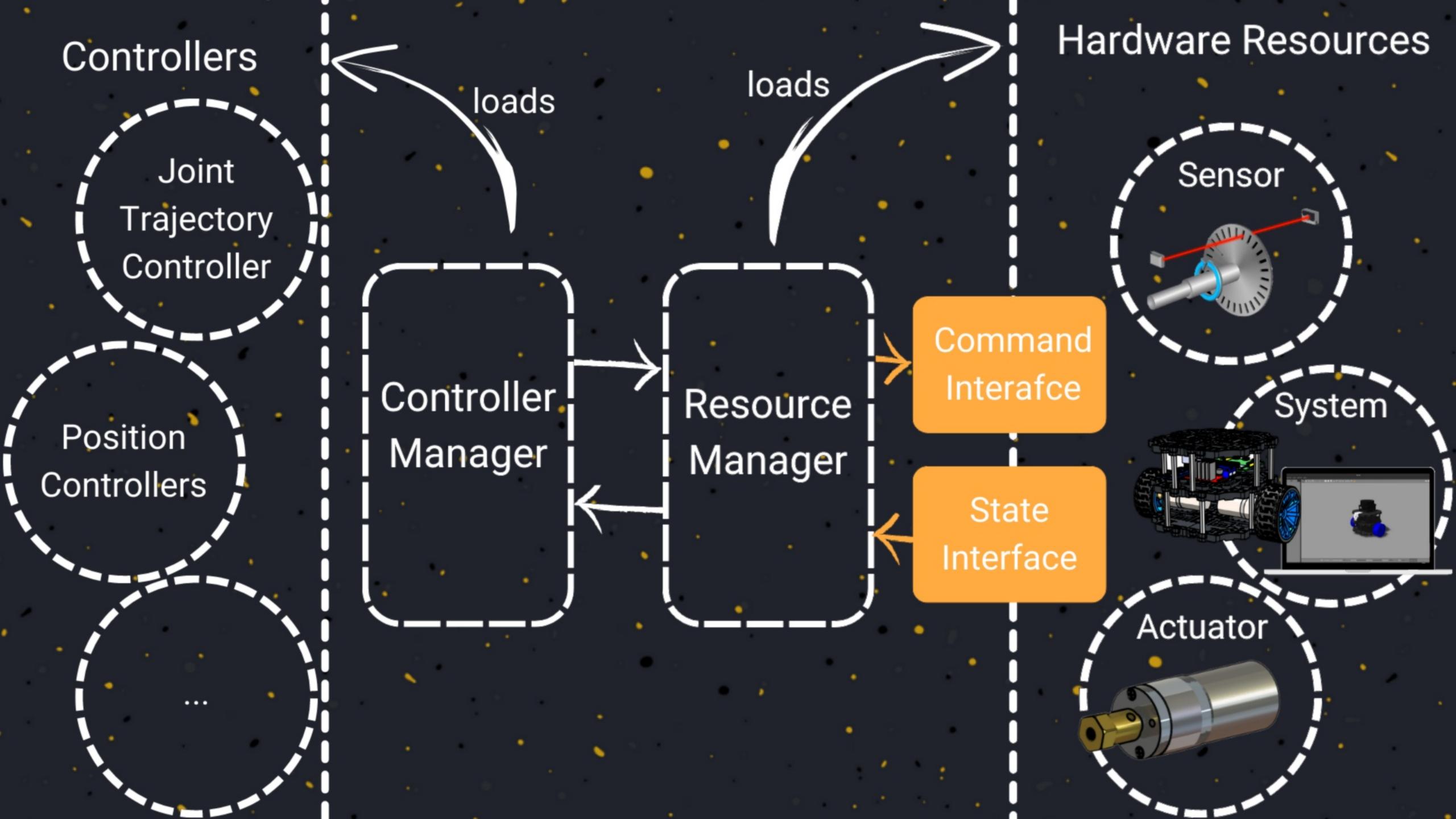


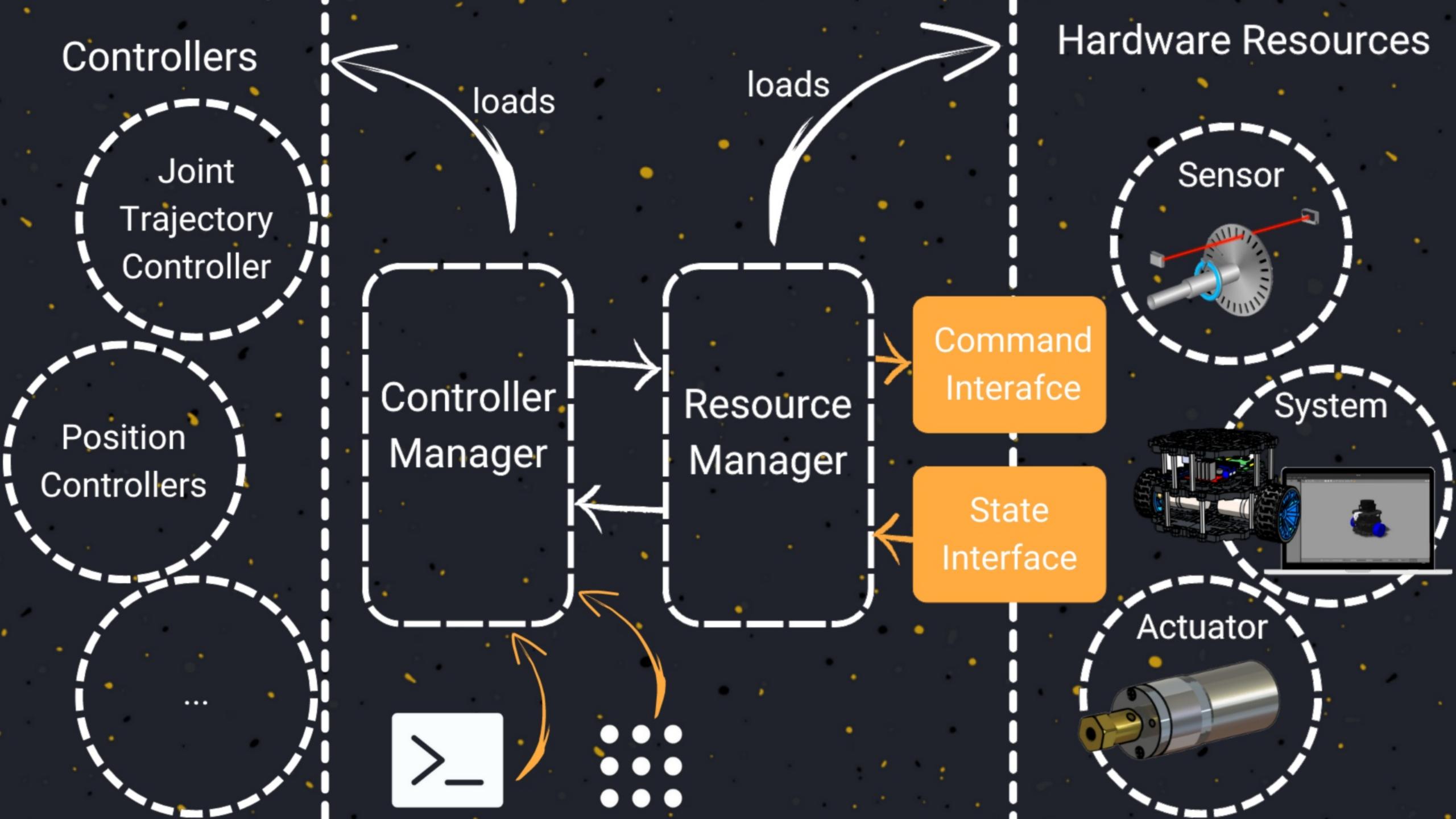
# Hardware Resources



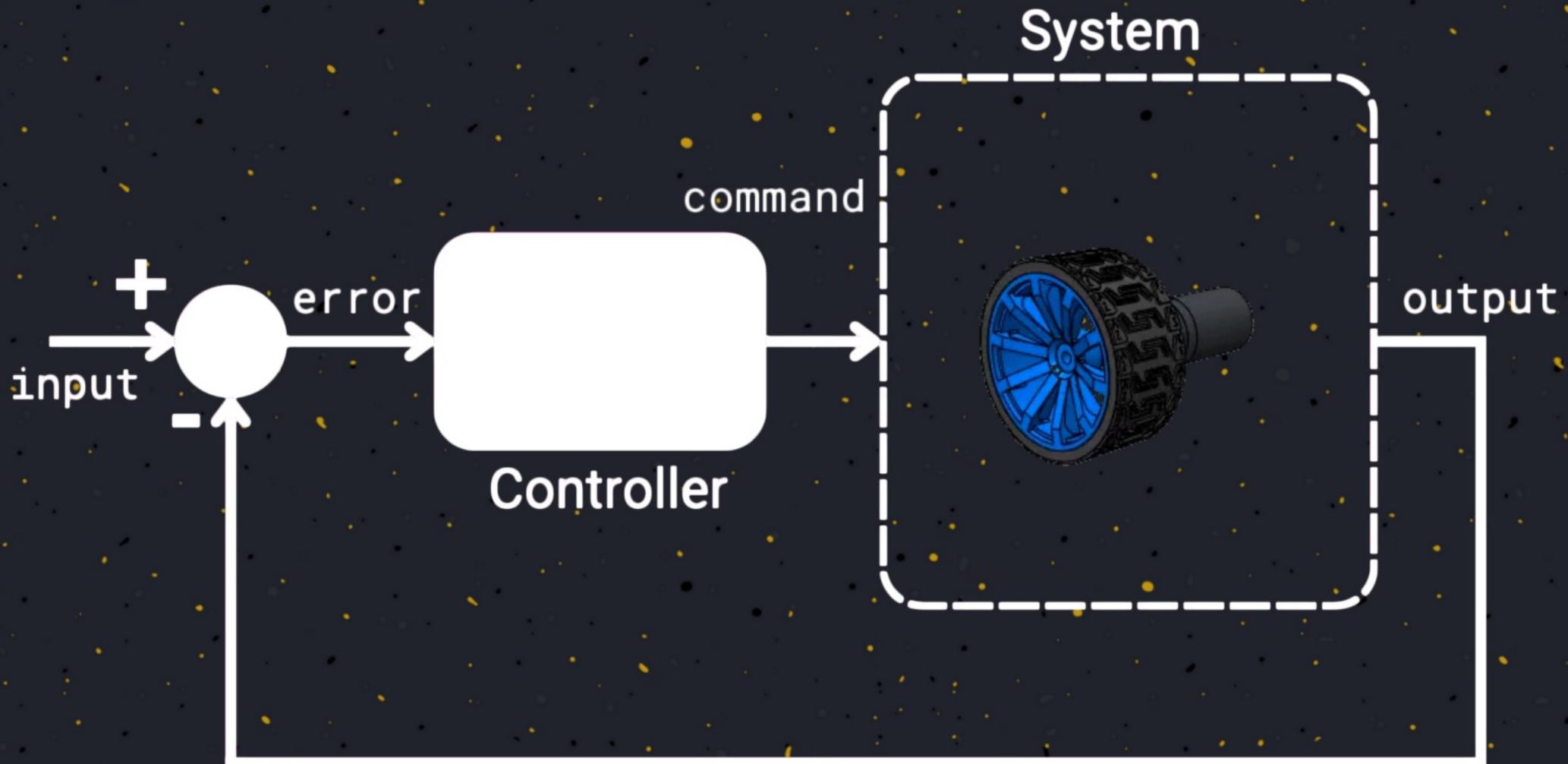






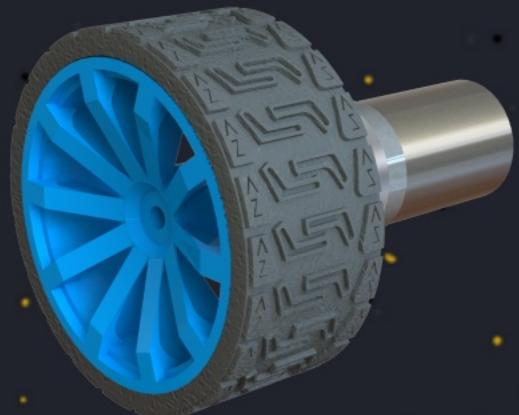


# ROS 2 Control





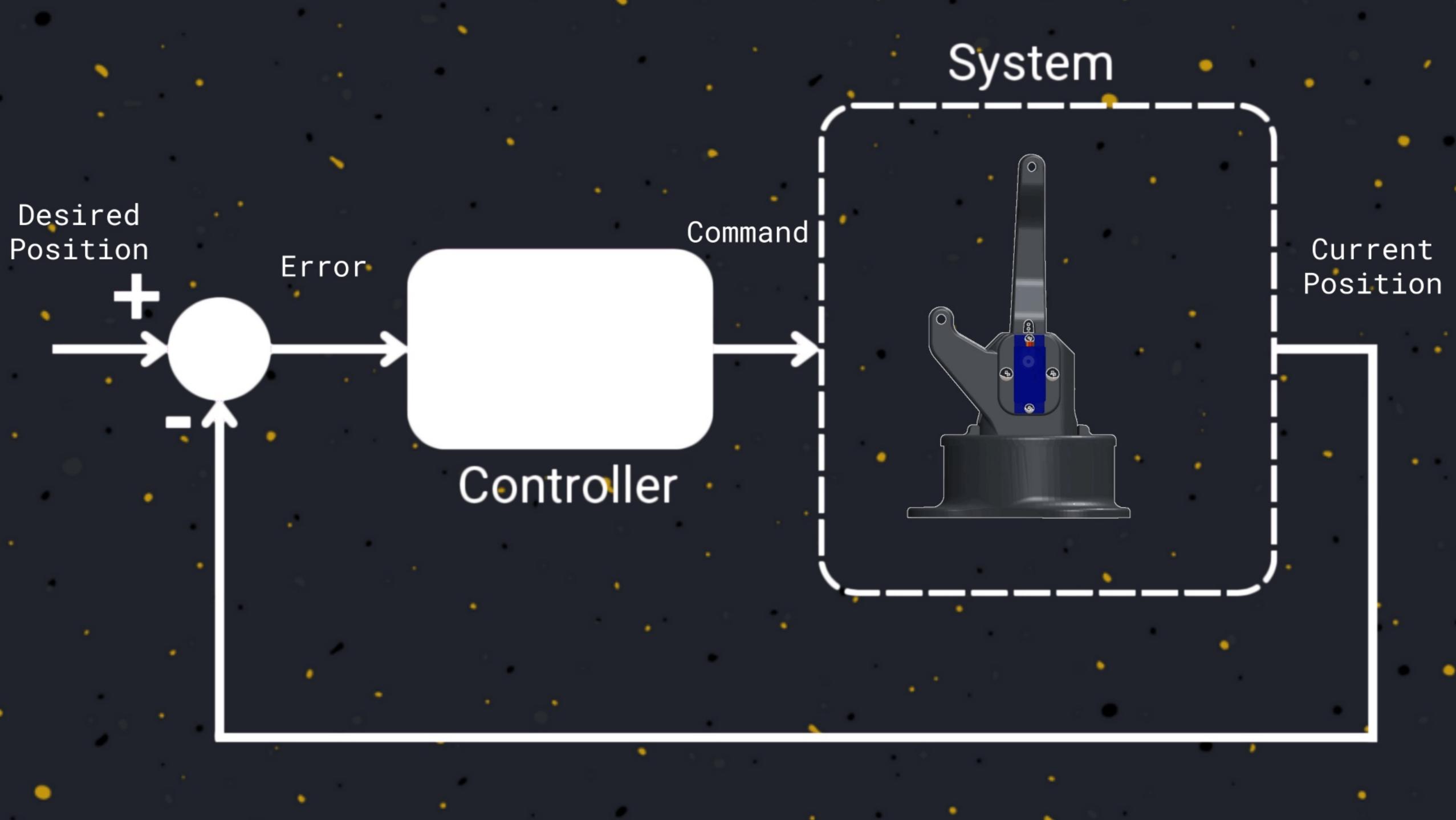
Position

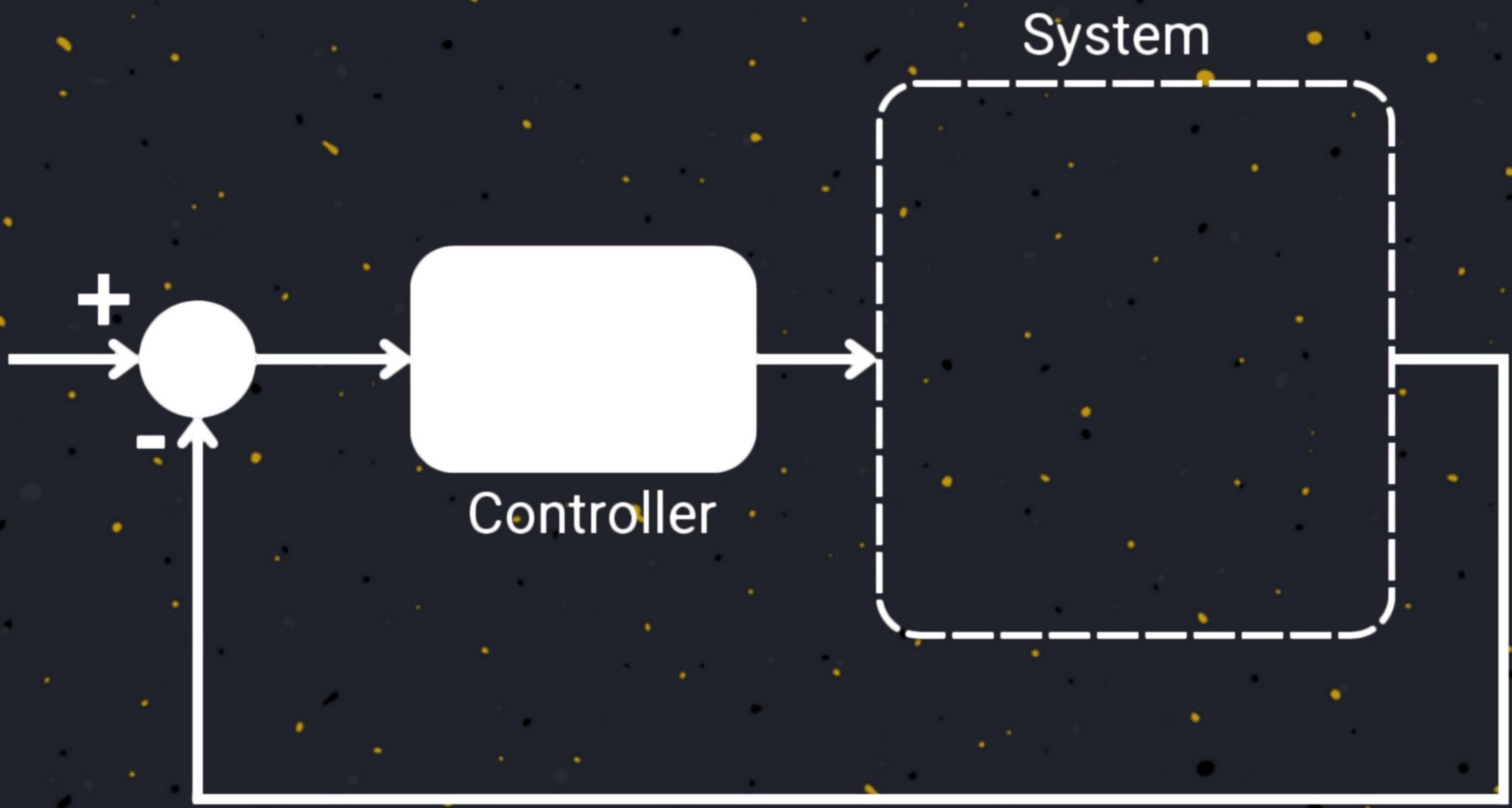


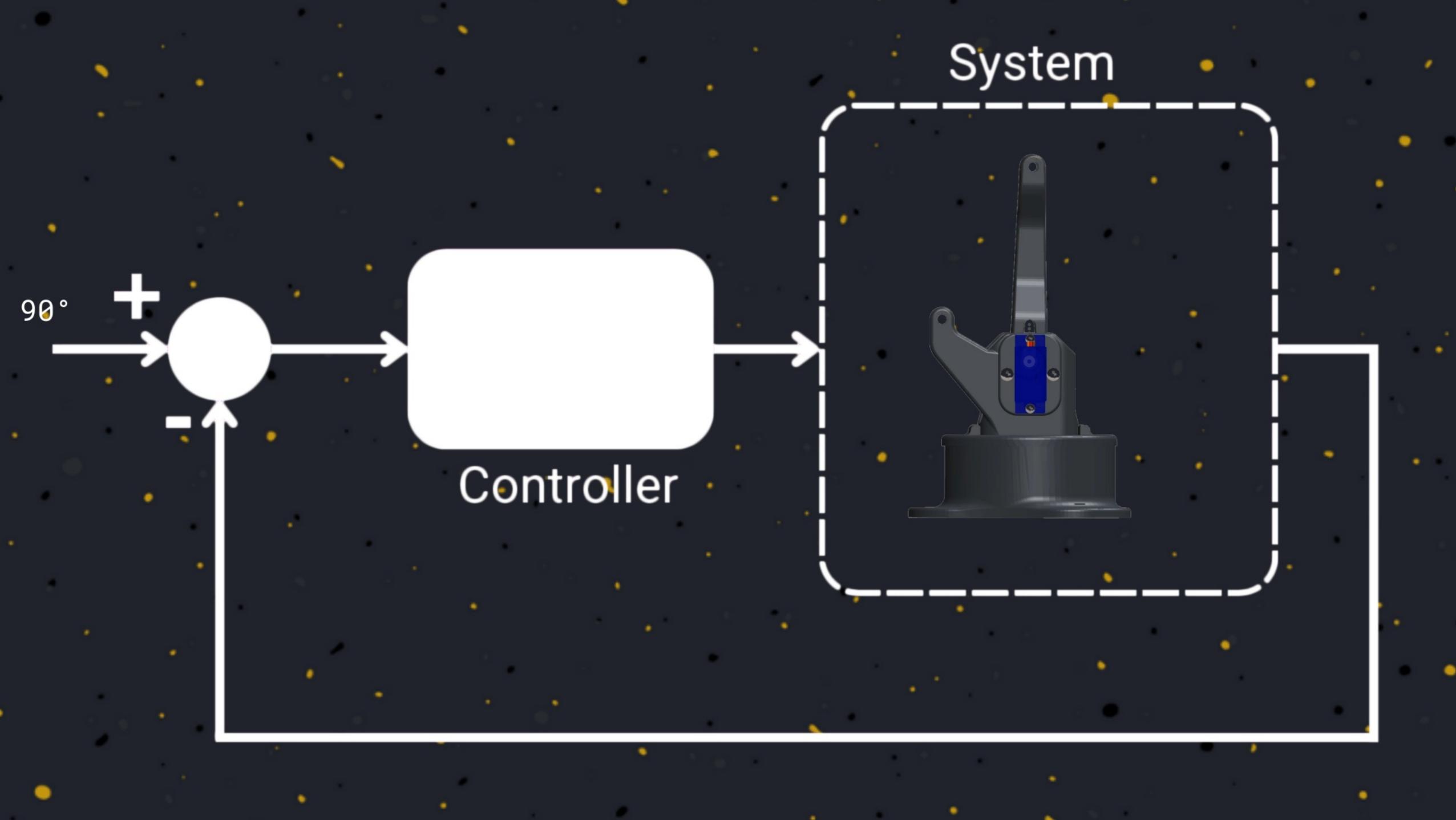
Velocity

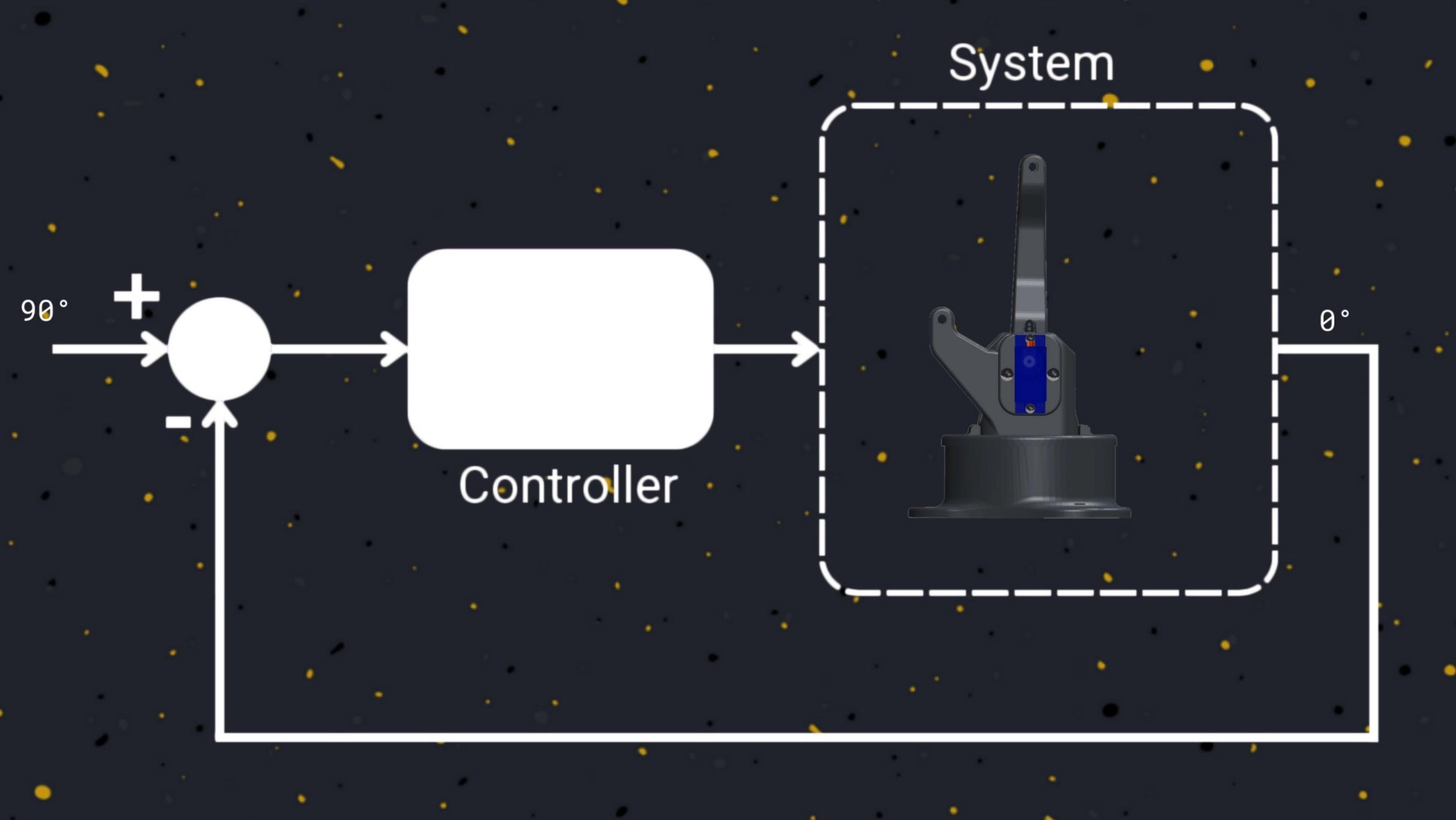


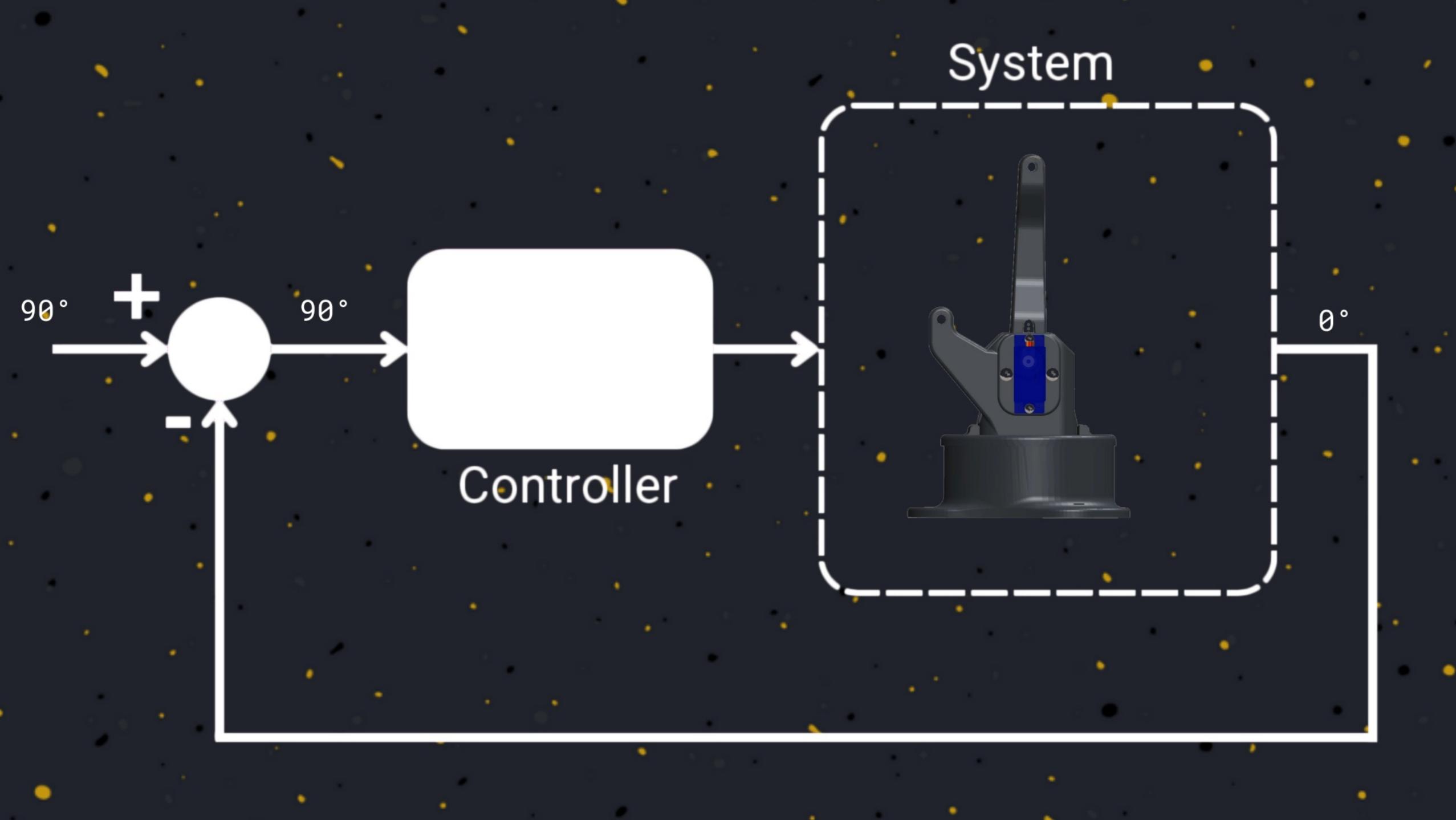
Effort

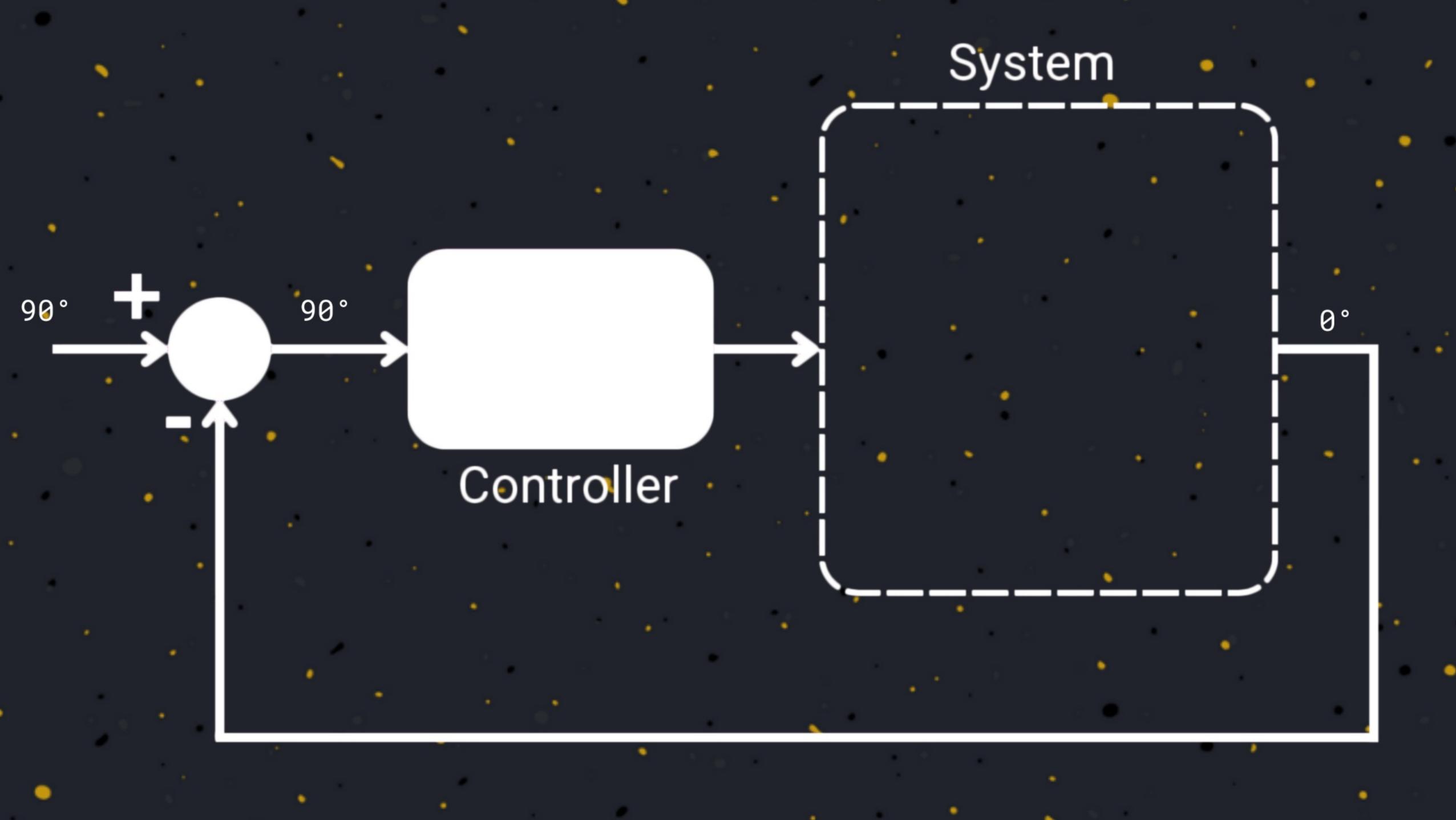


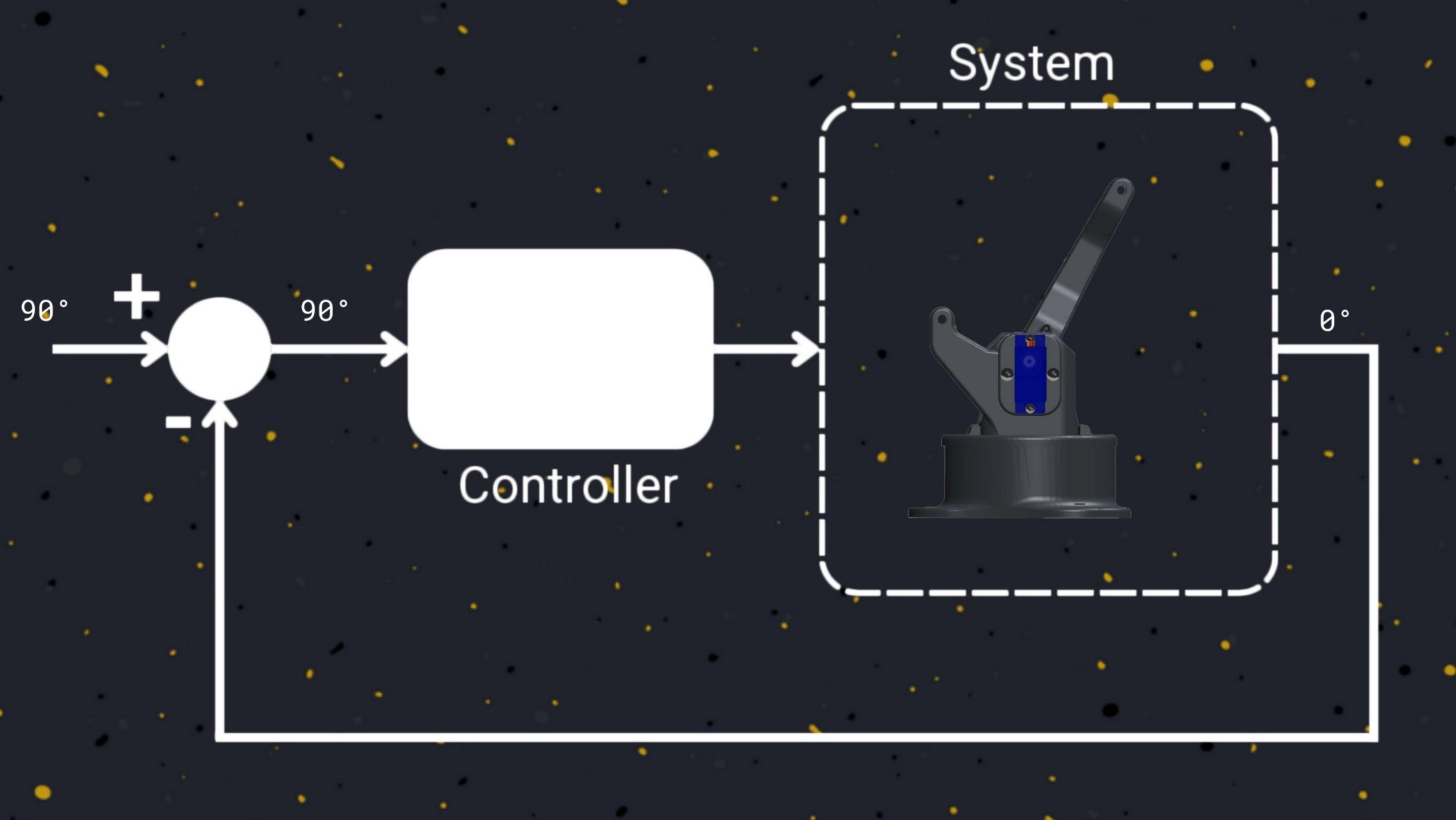


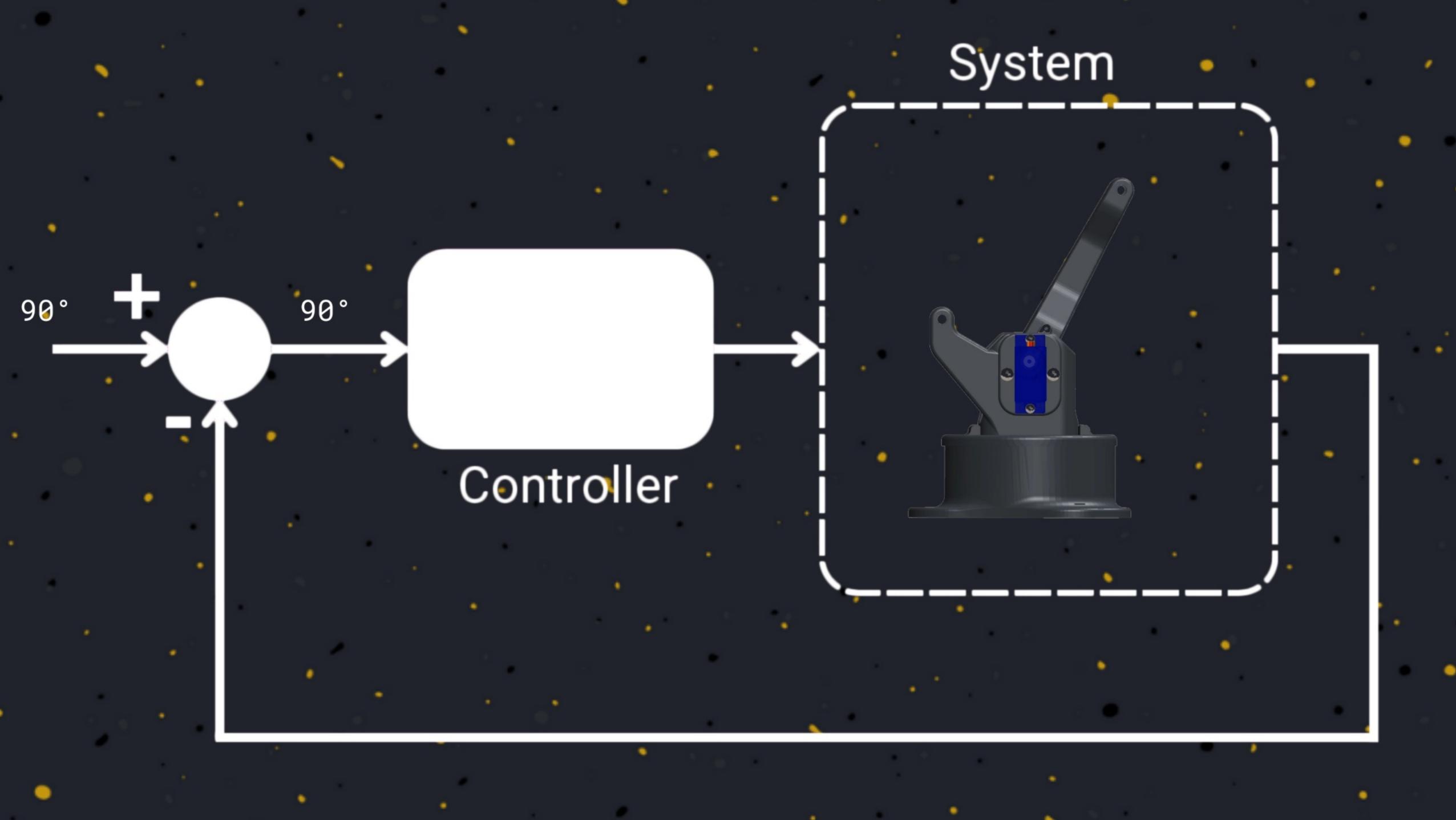


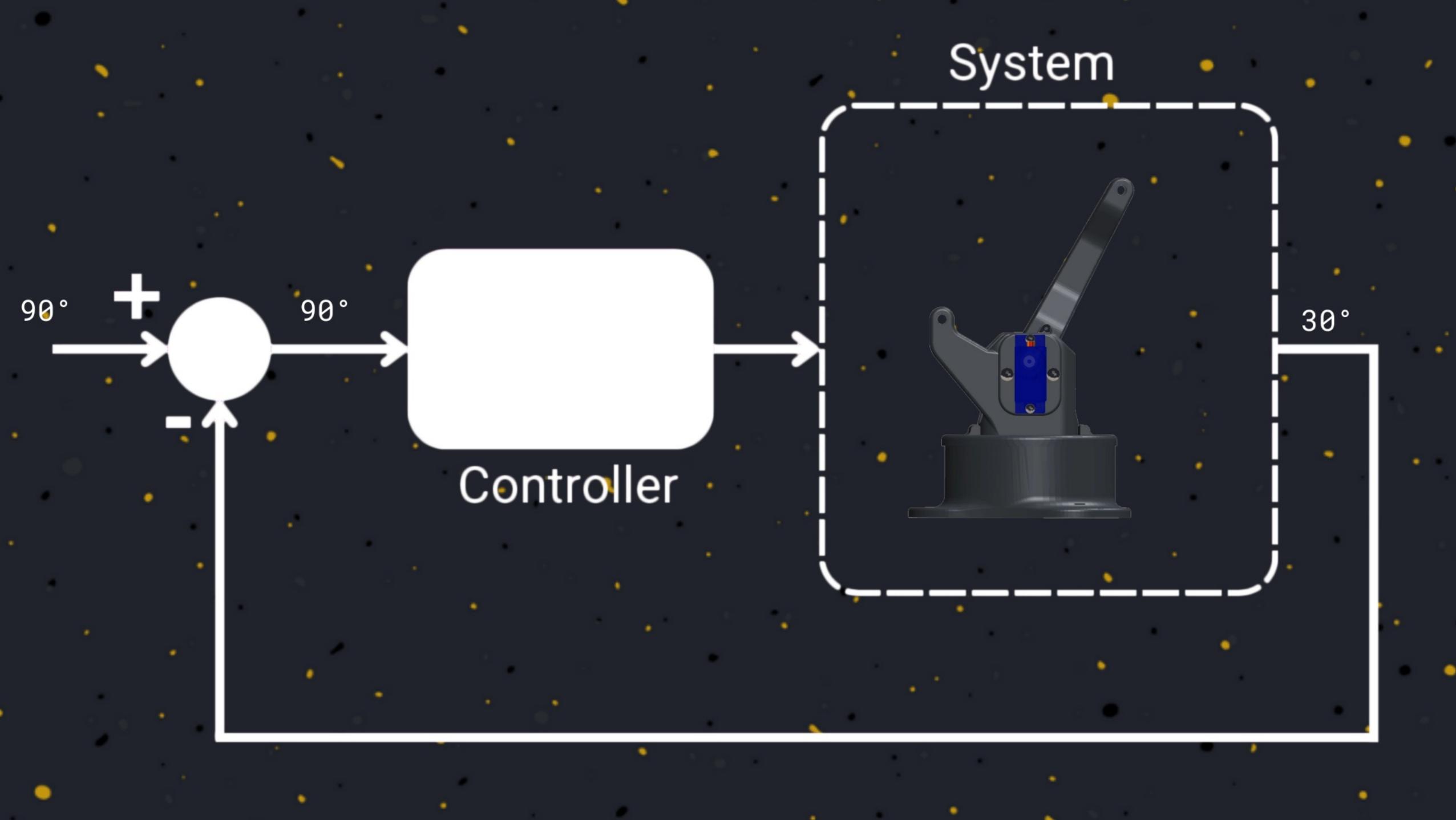


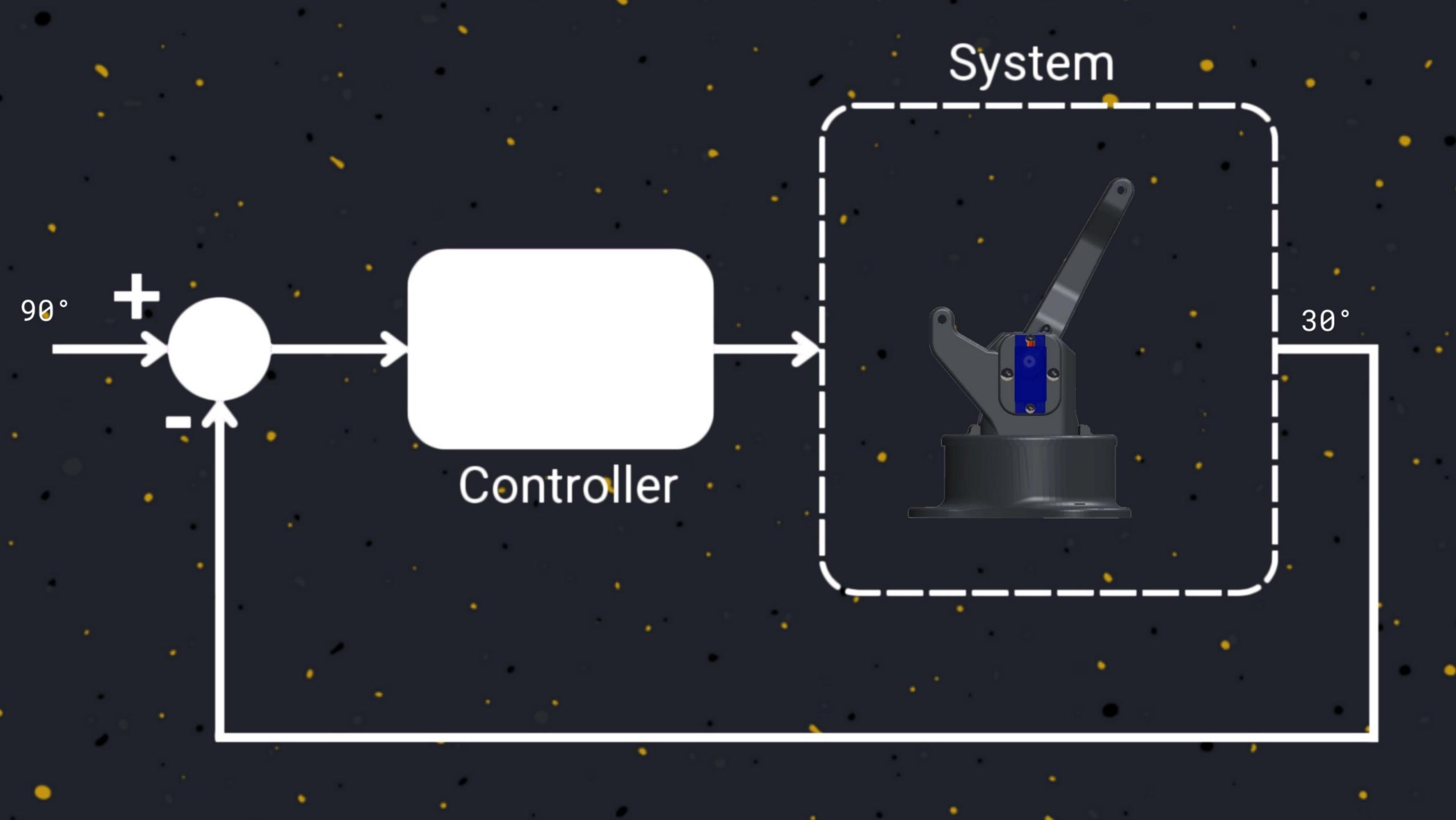


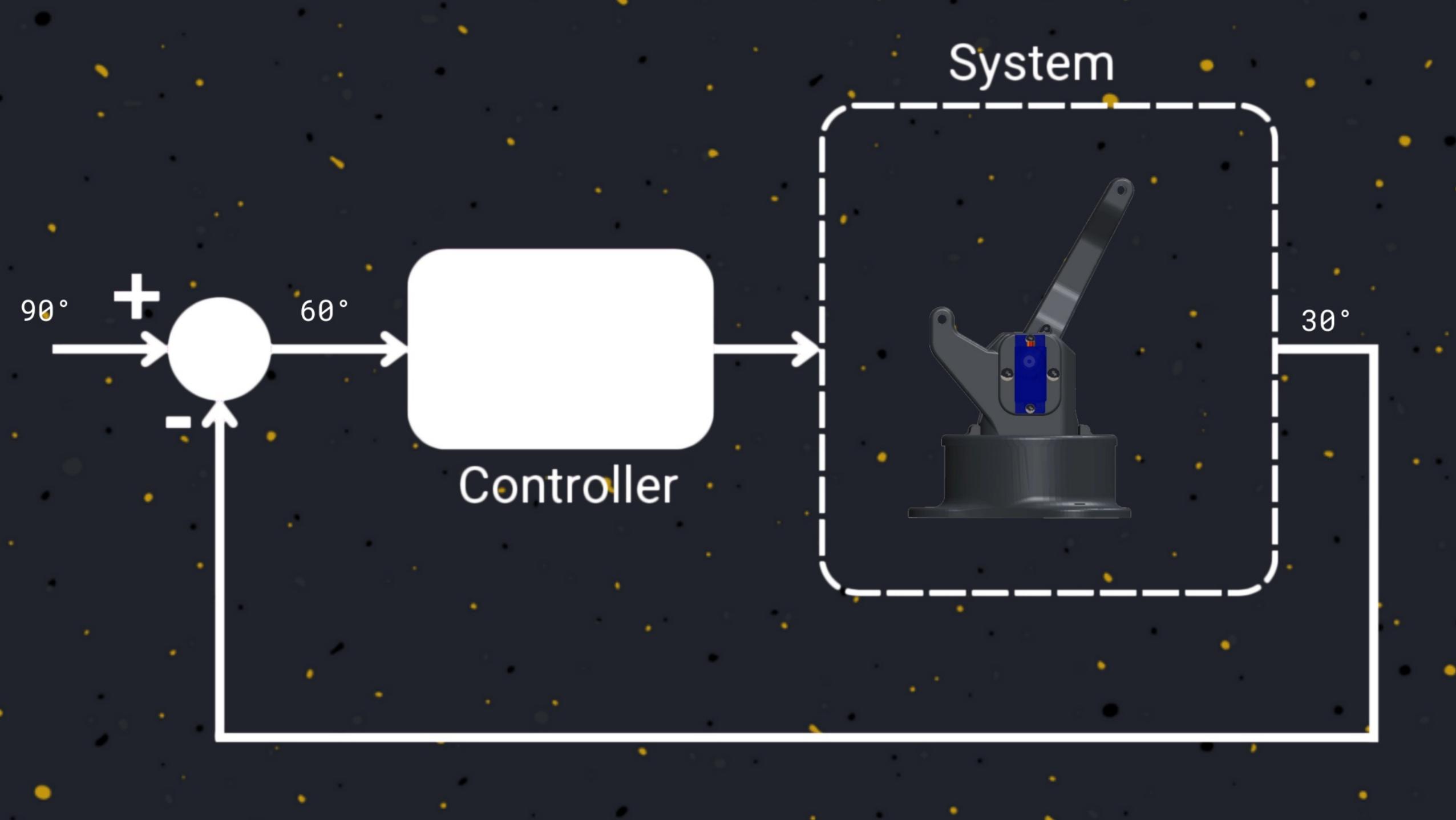


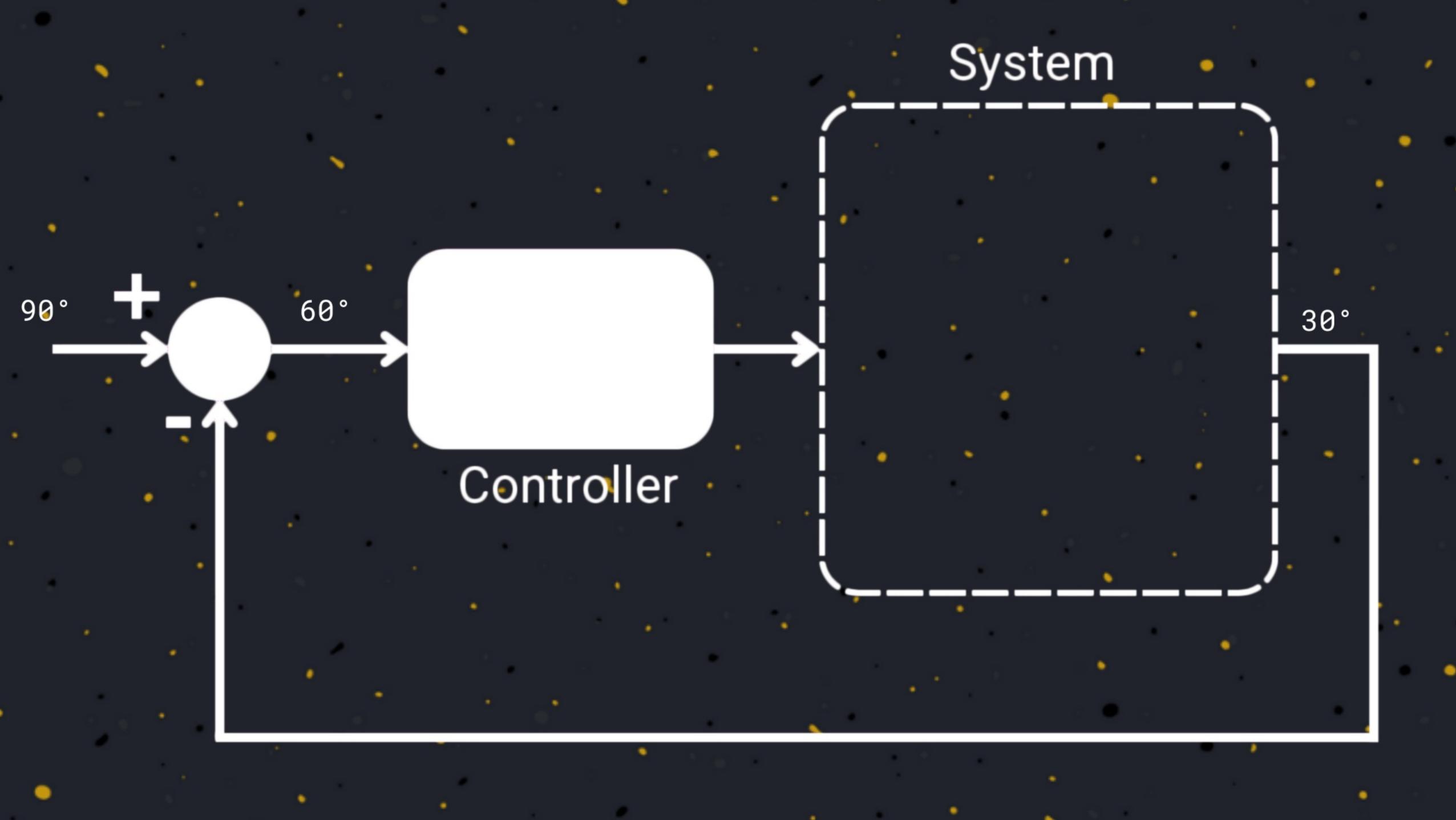


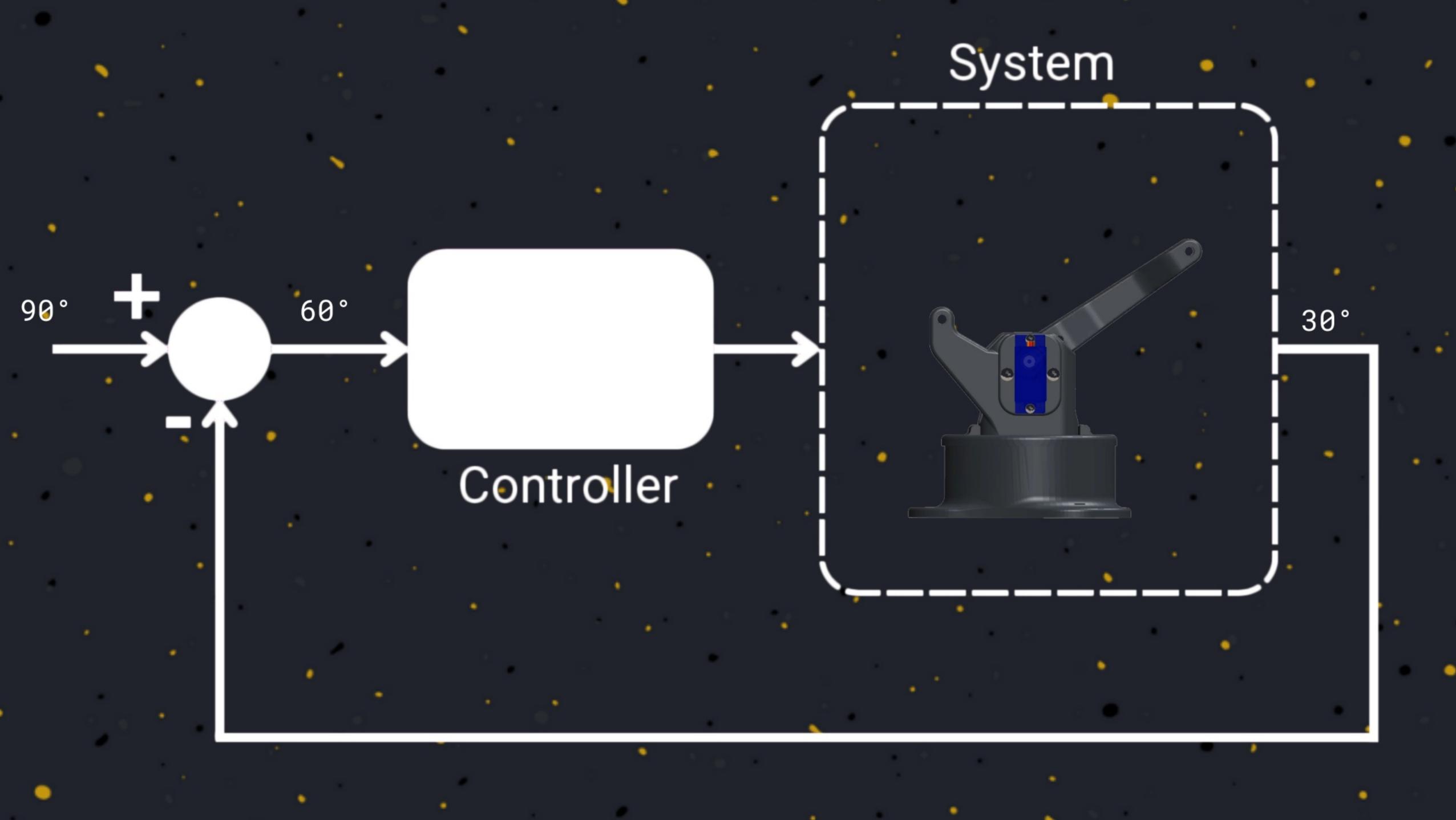


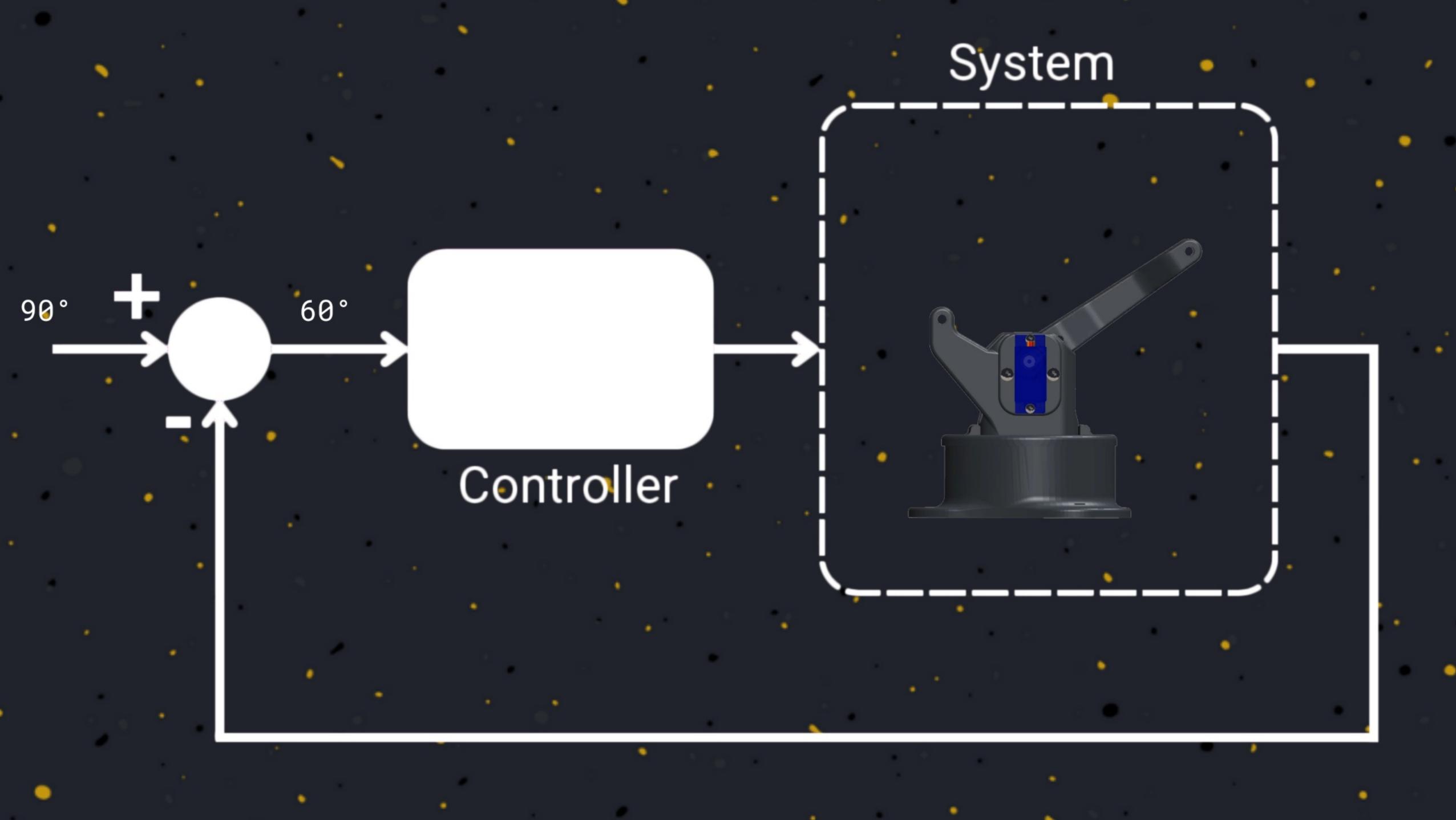


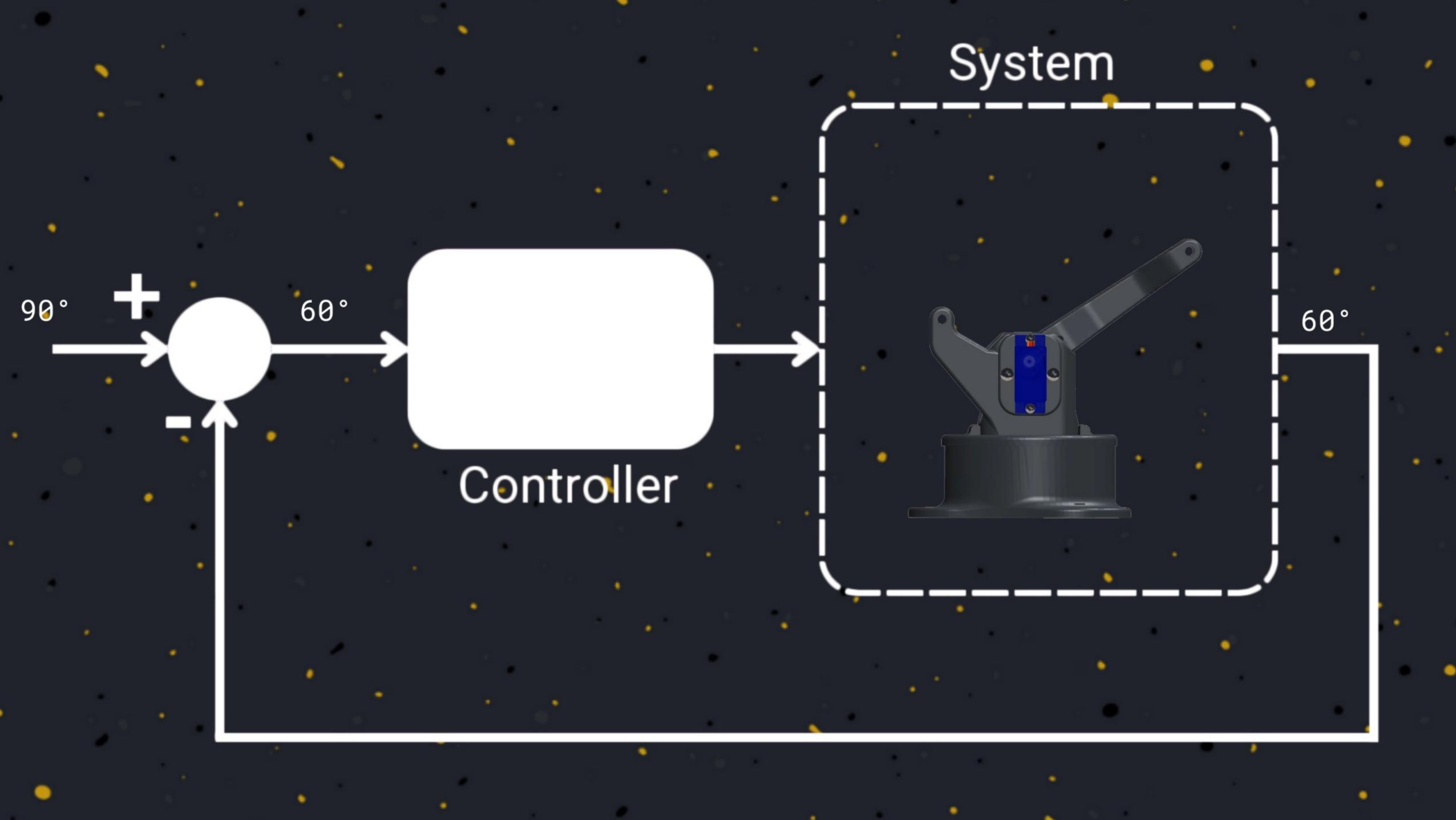


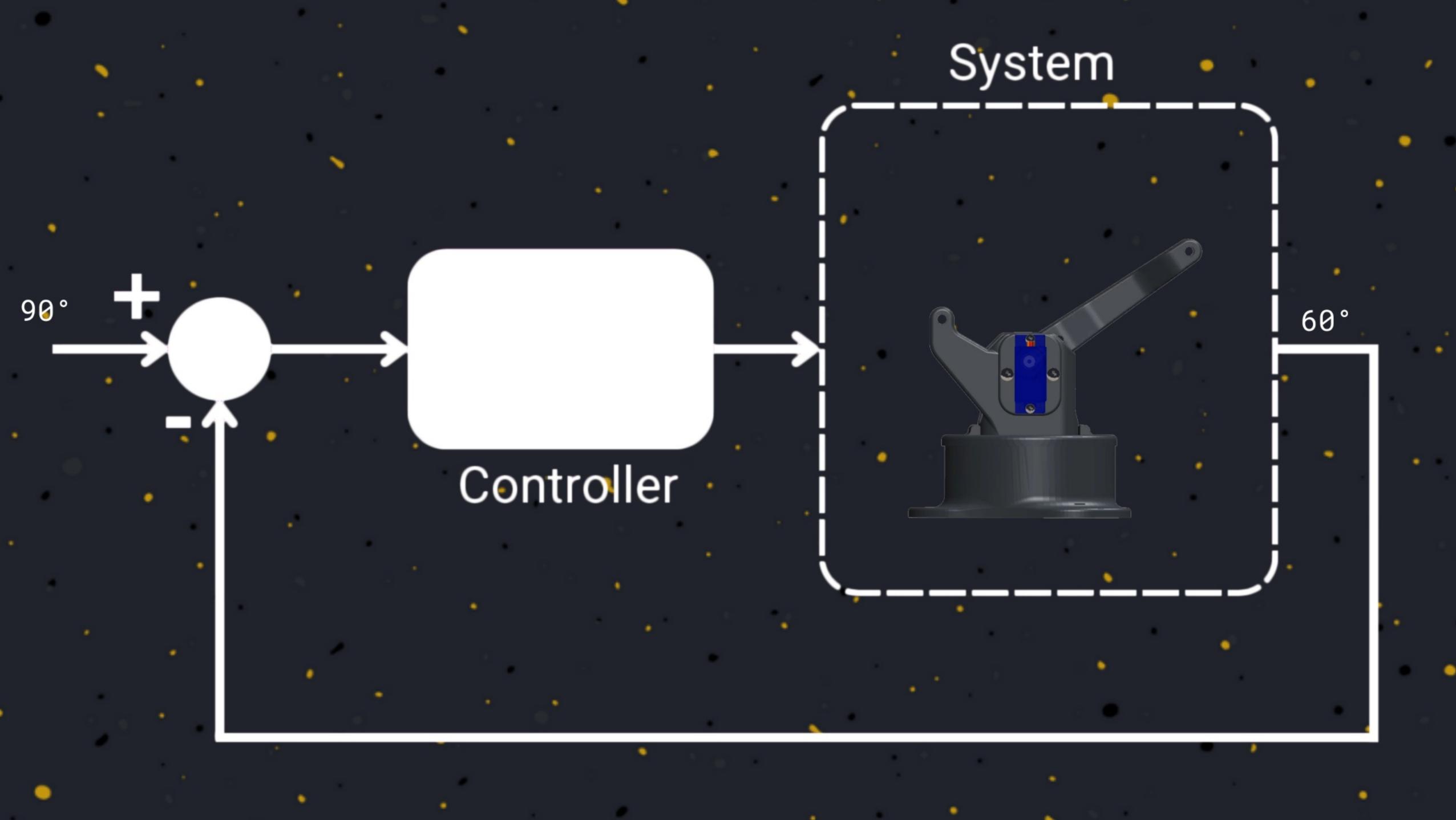


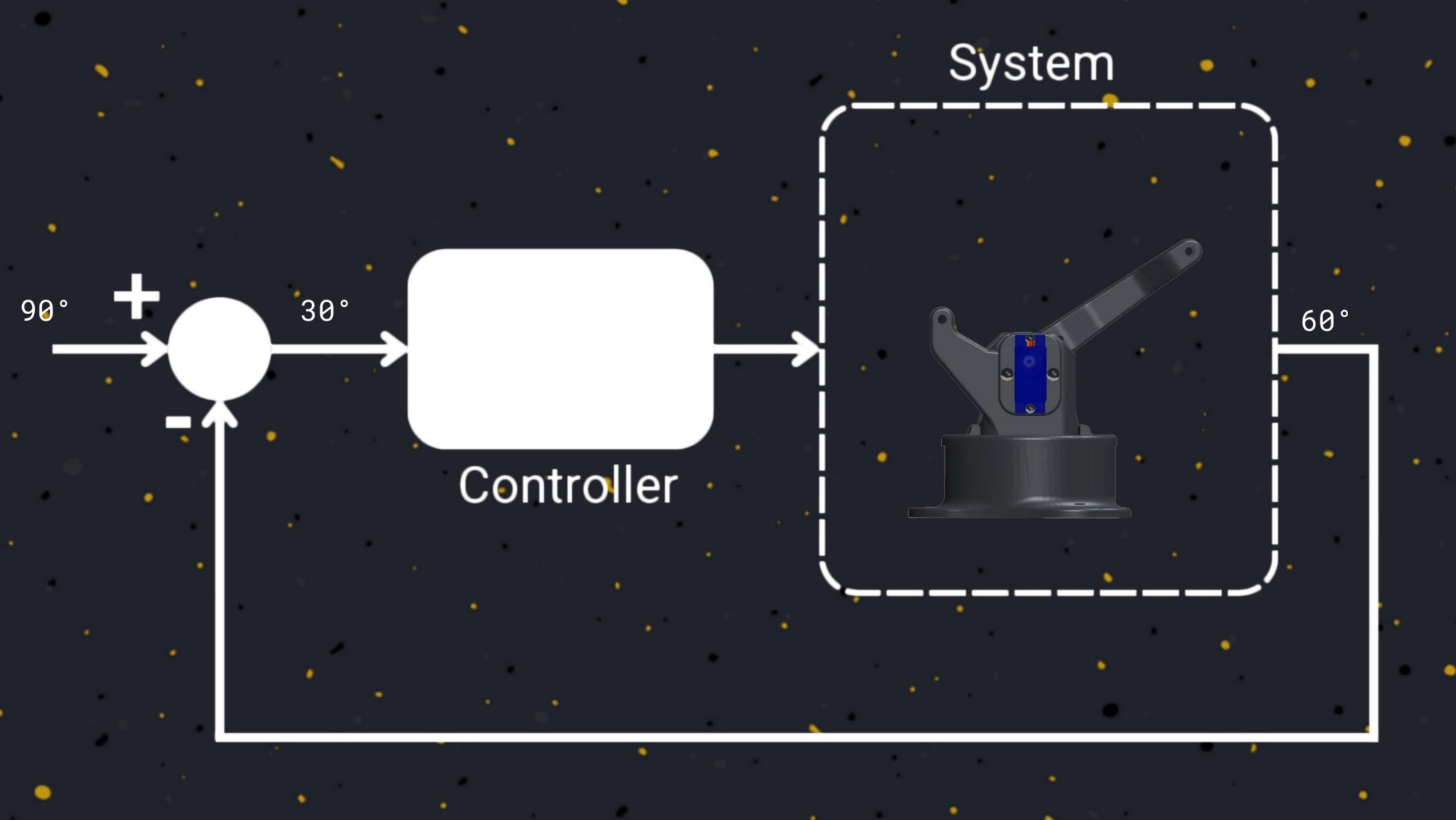


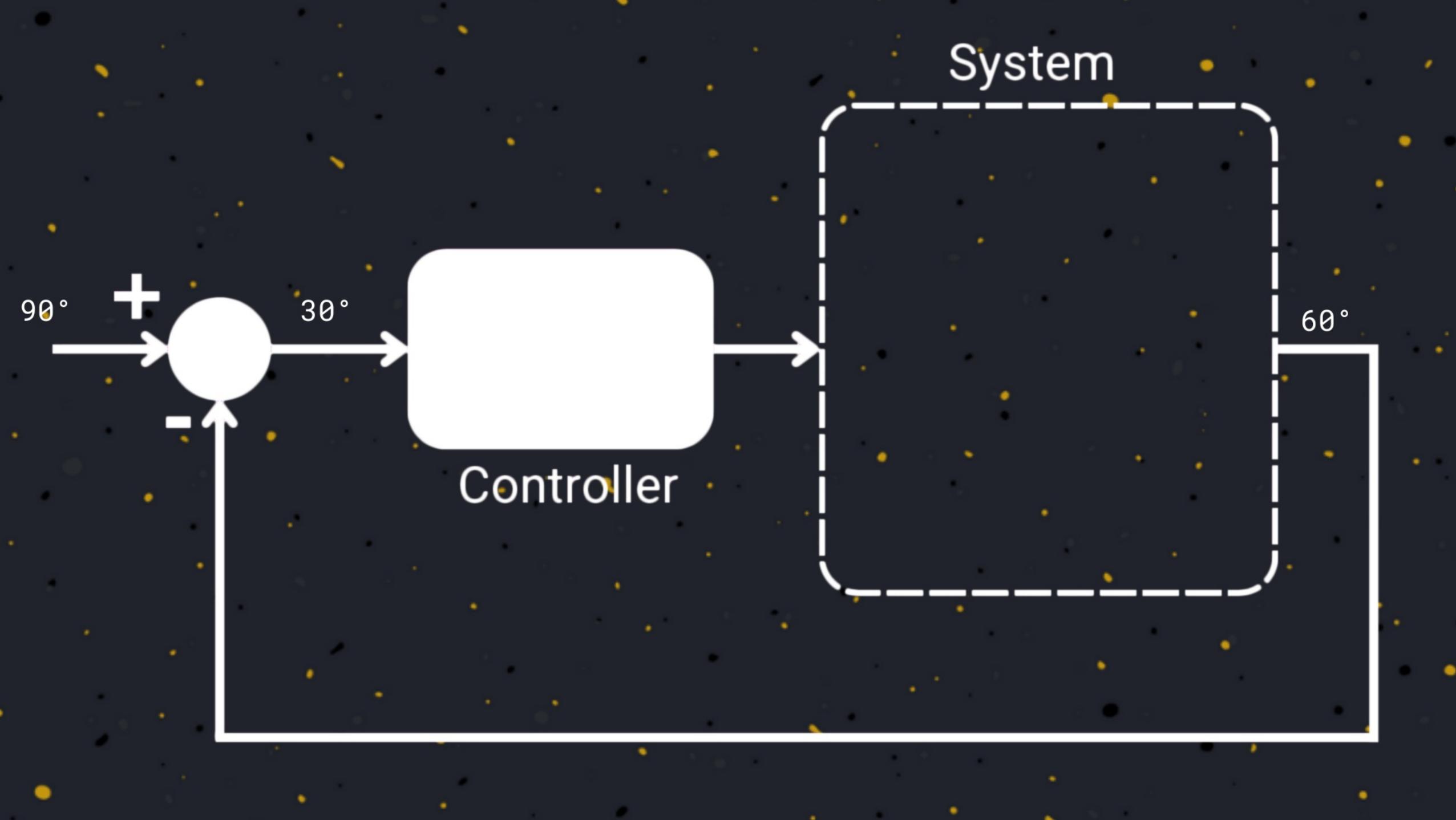


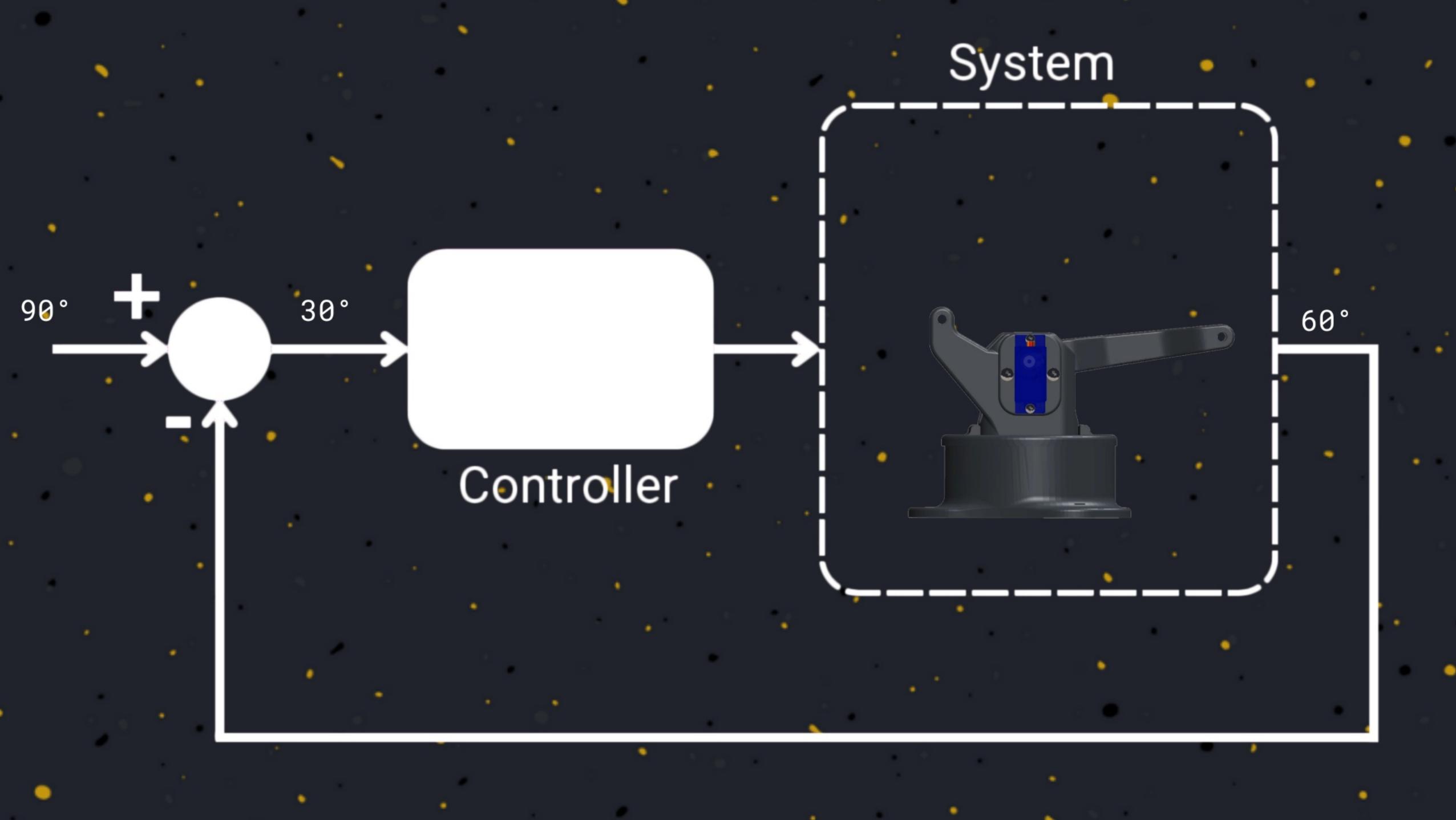


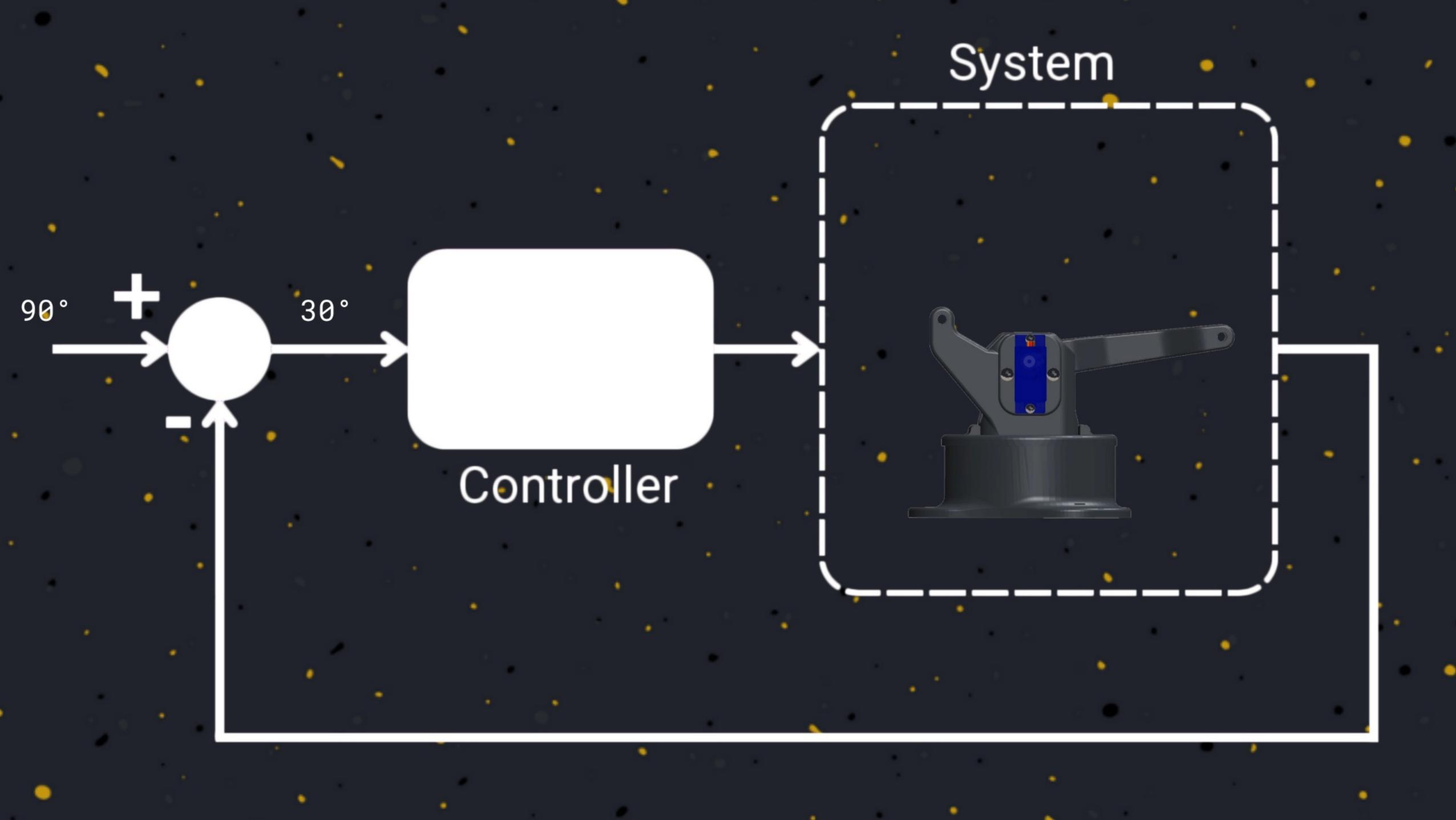


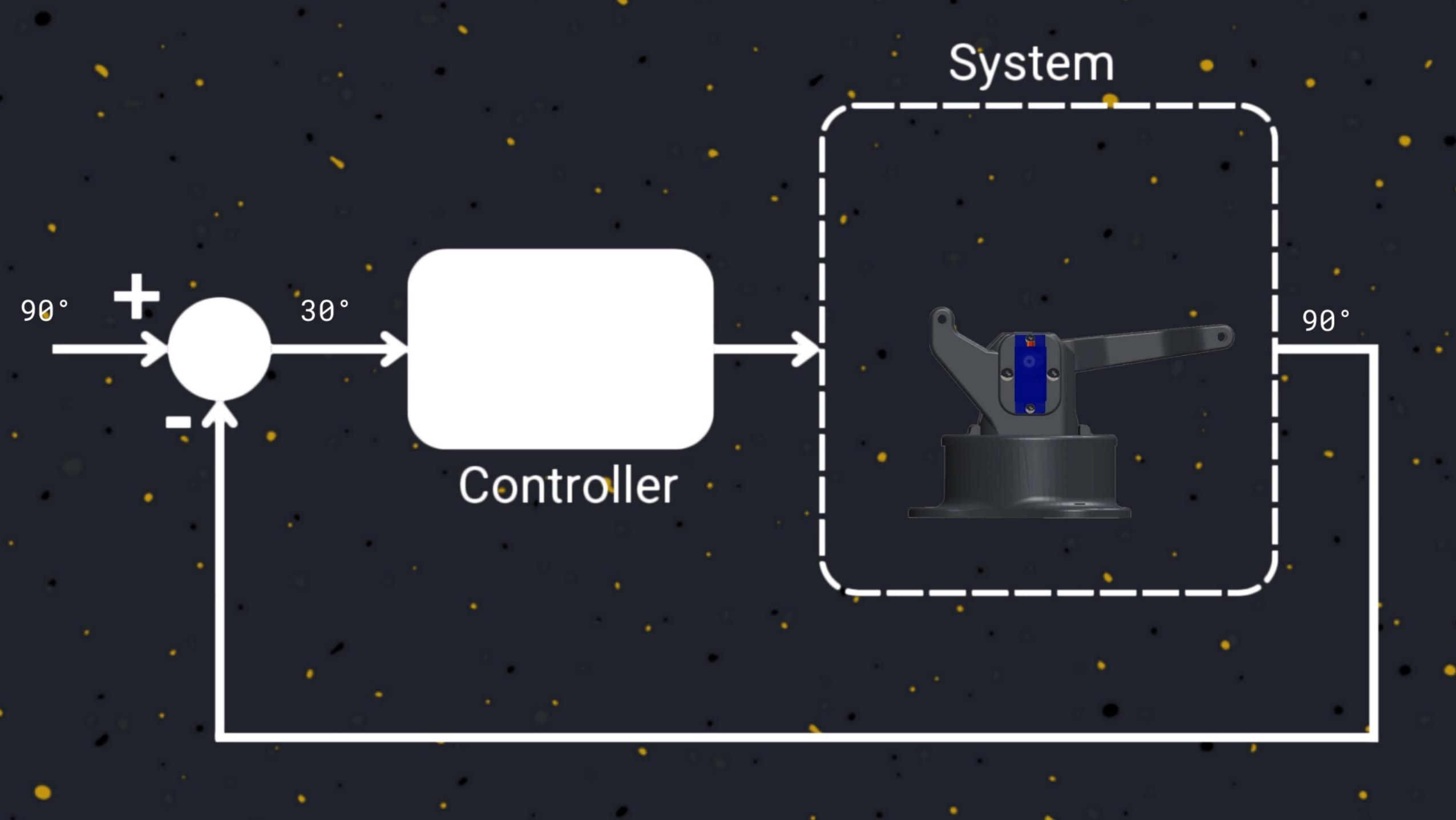


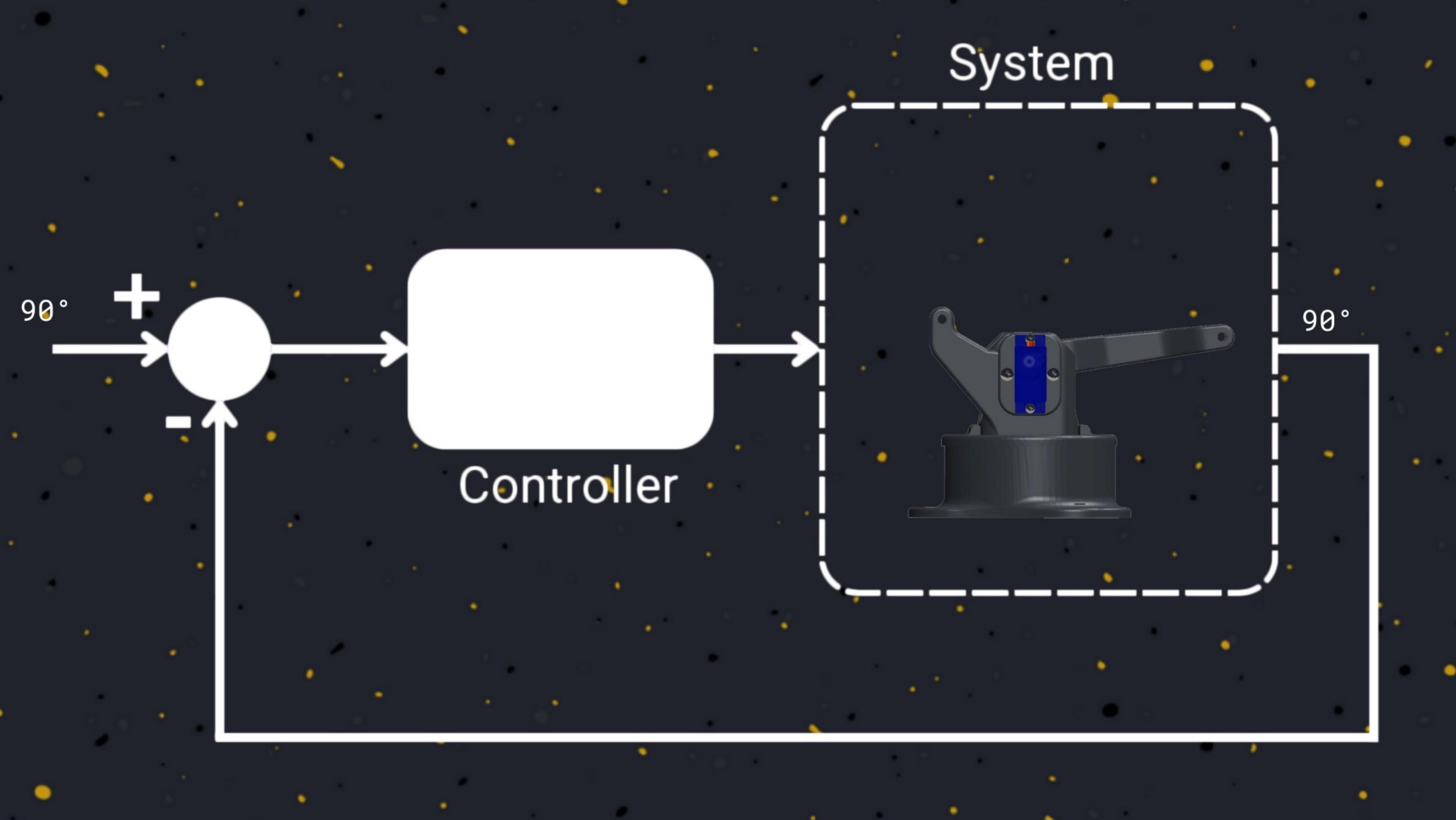


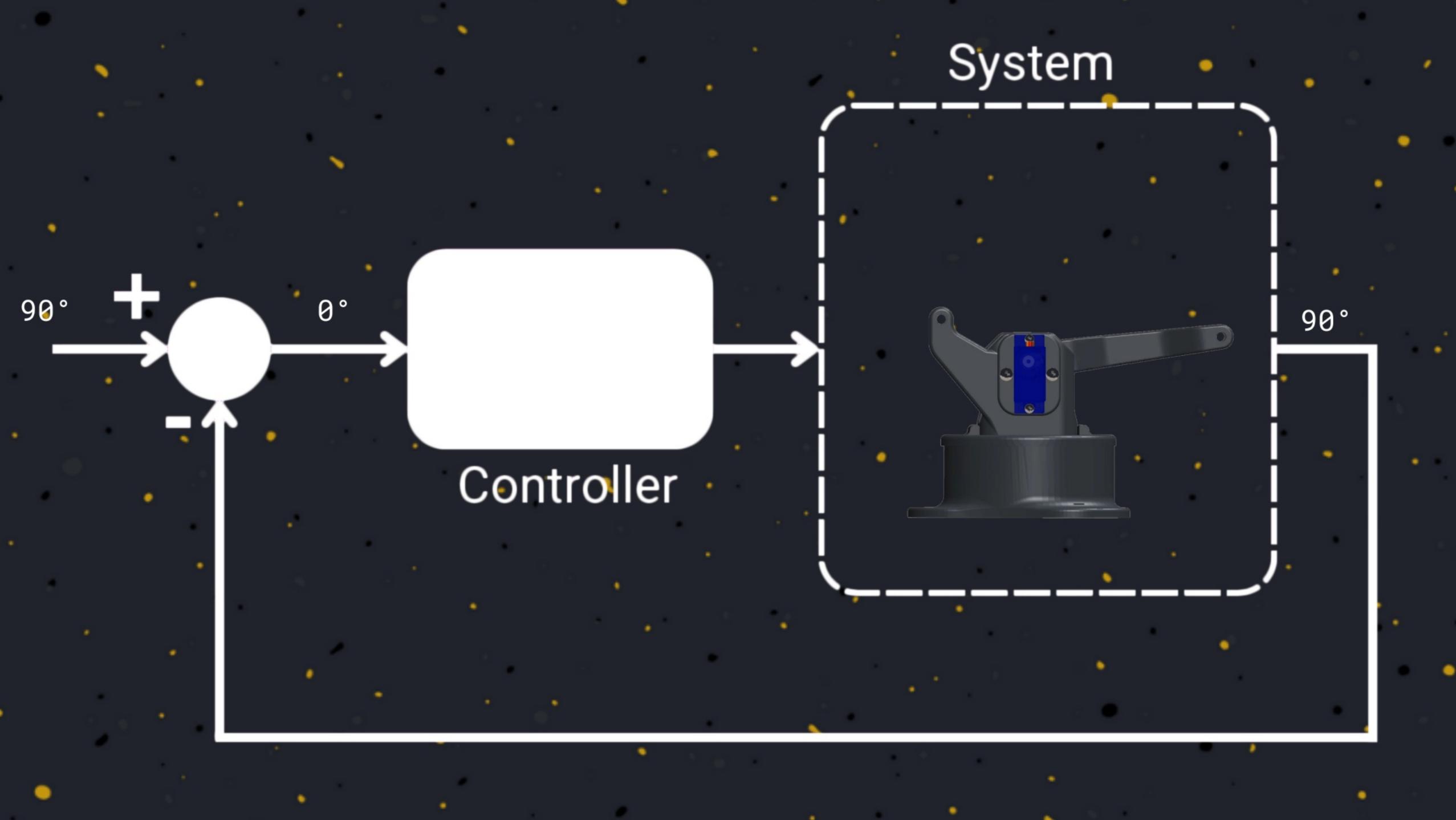






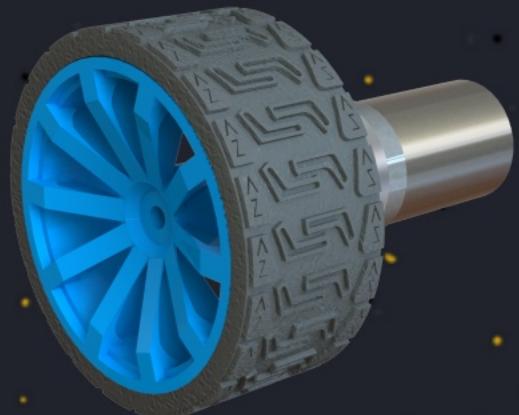








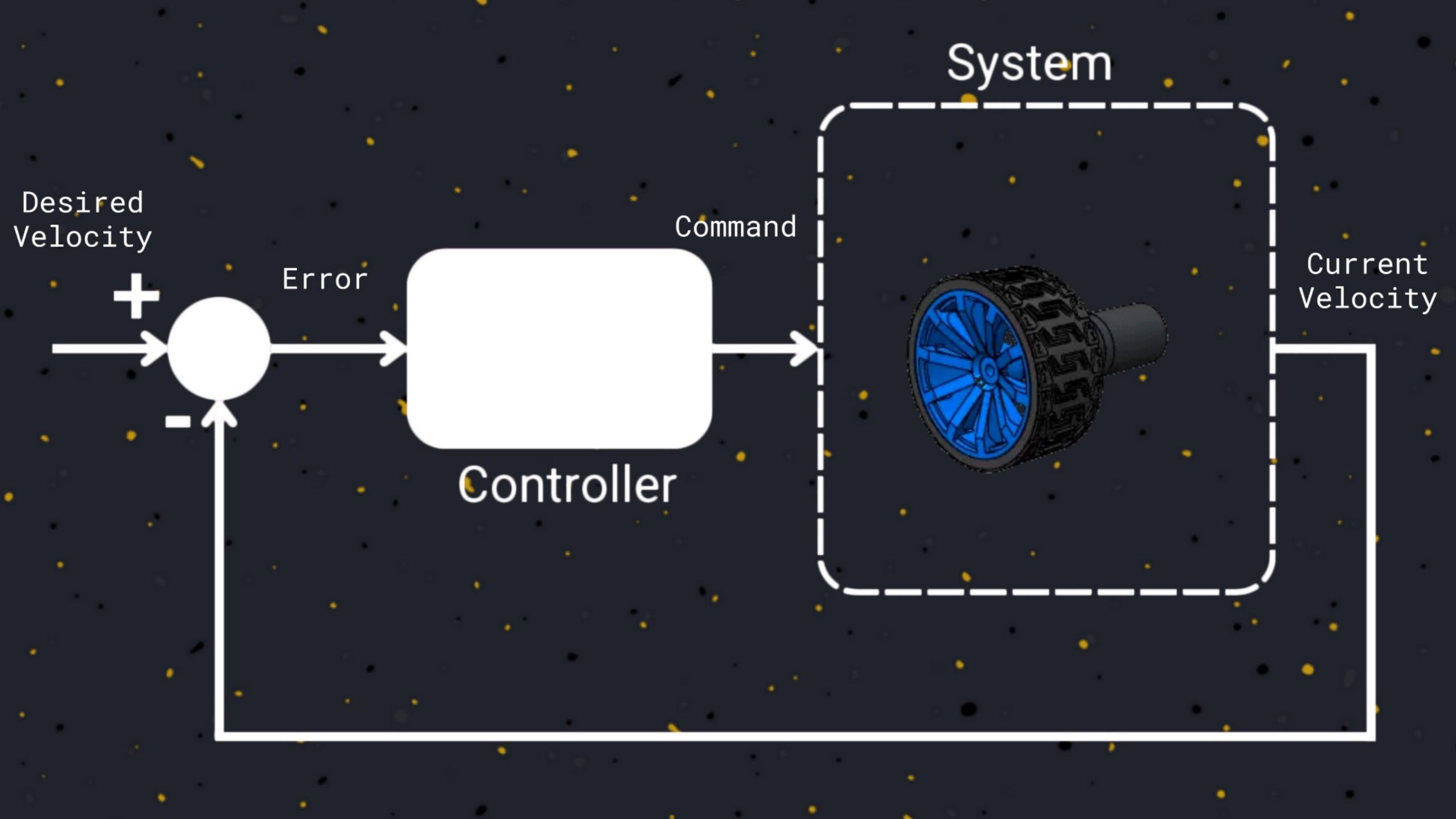
Position



Velocity

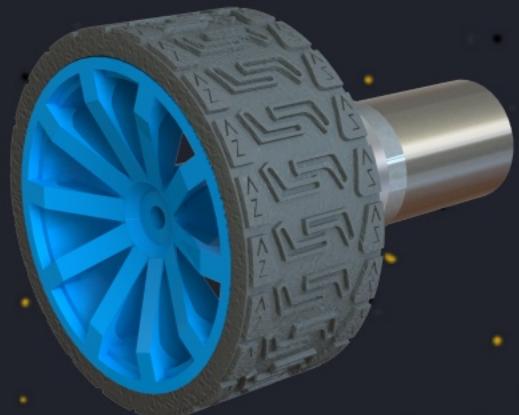


Effort





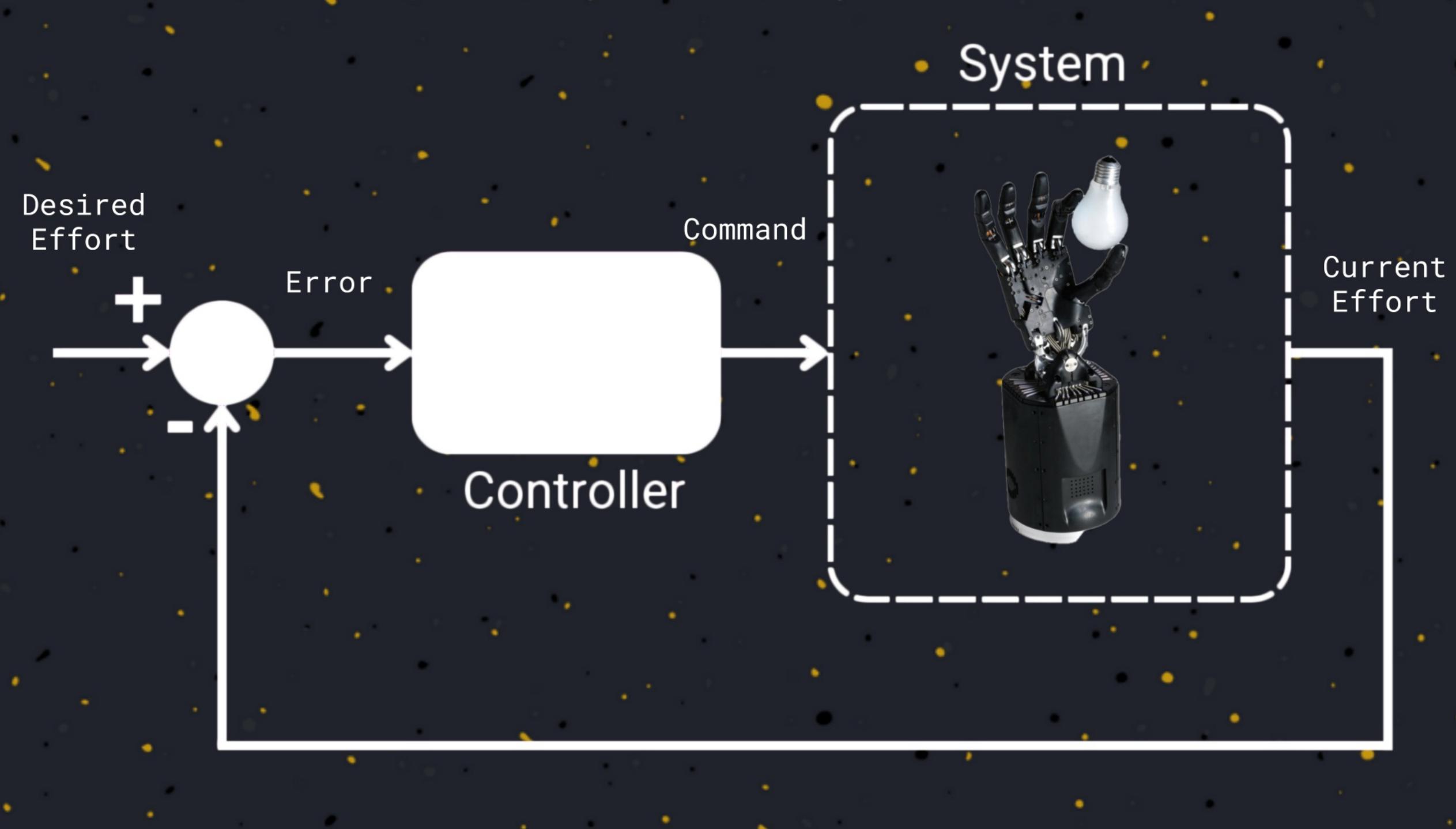
Position



Velocity

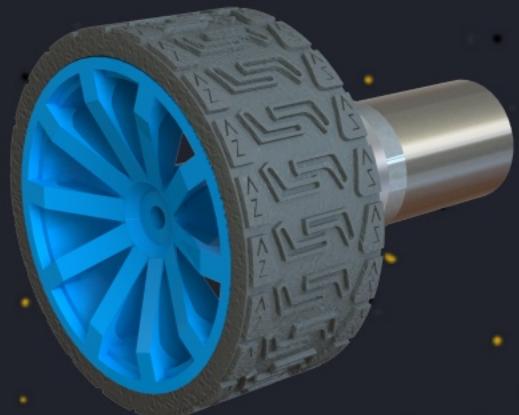


Effort





Position

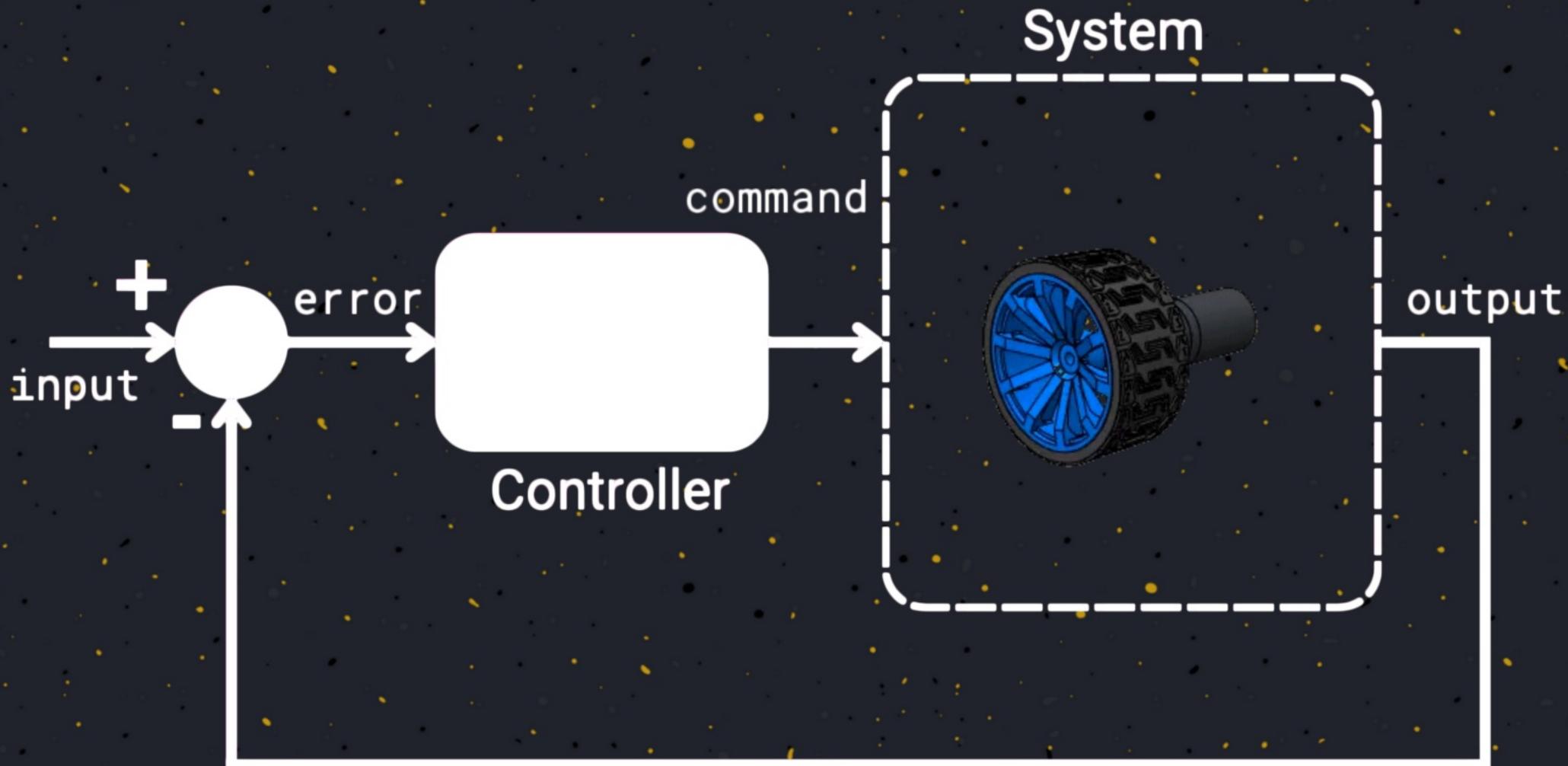


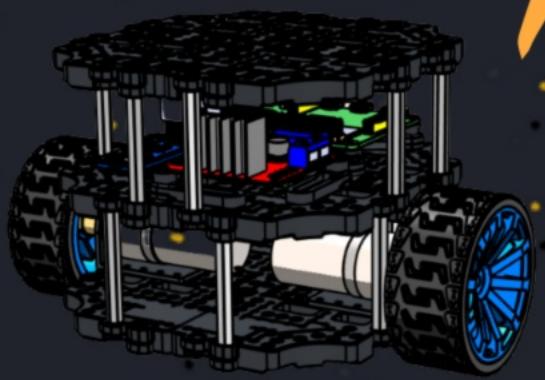
Velocity



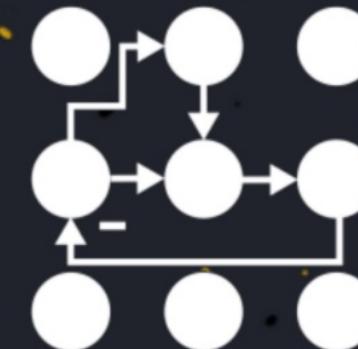
Effort

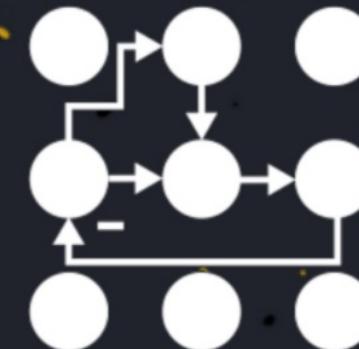
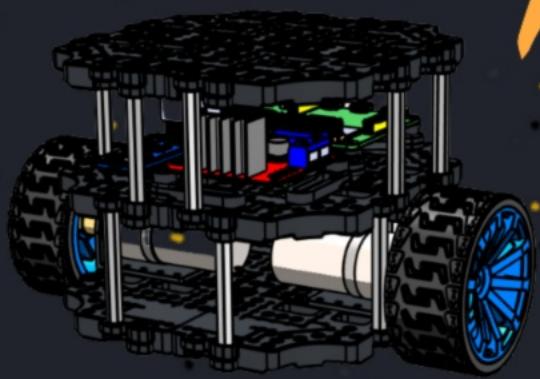
# ROS 2 Control





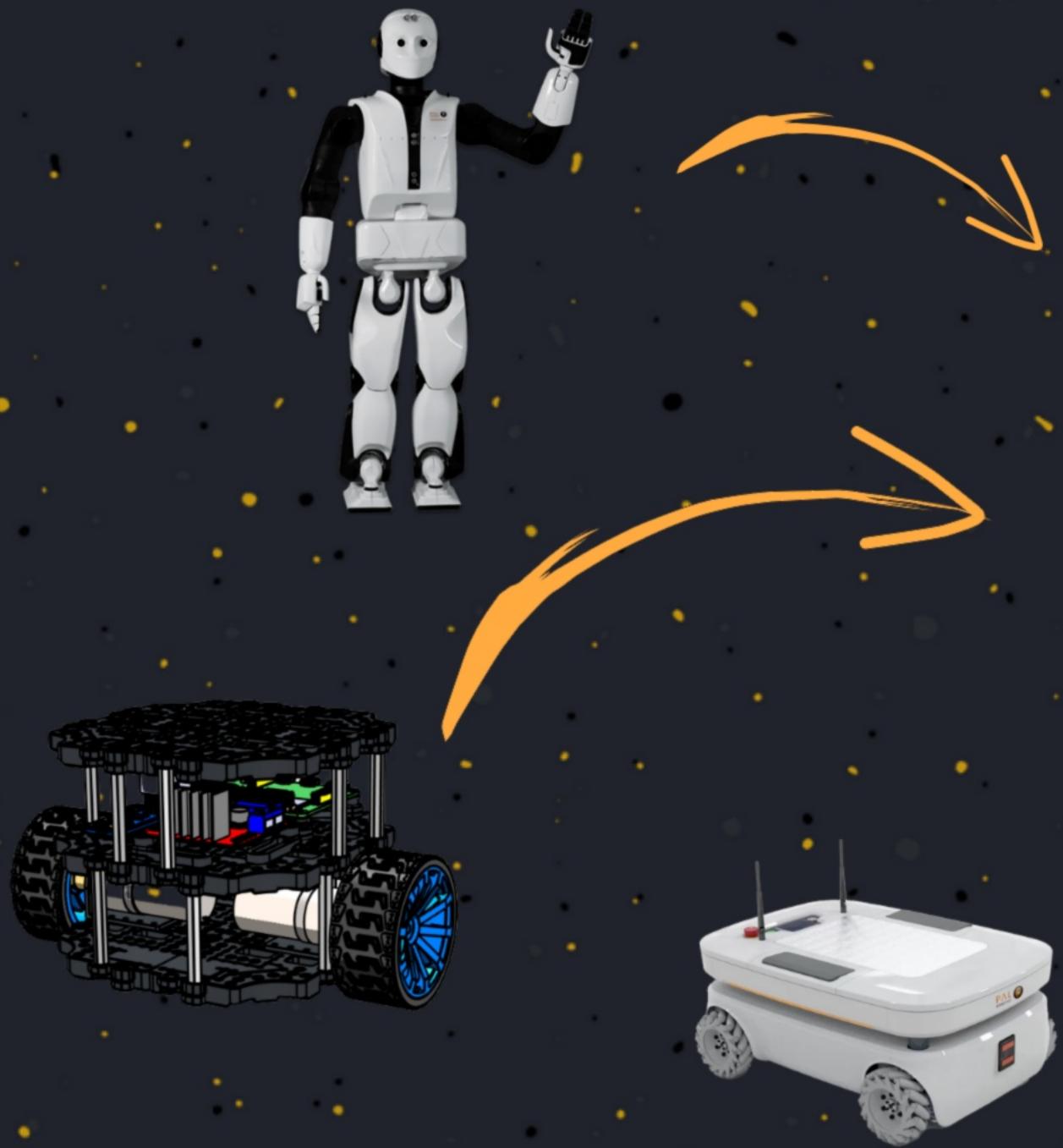
ros2\_control



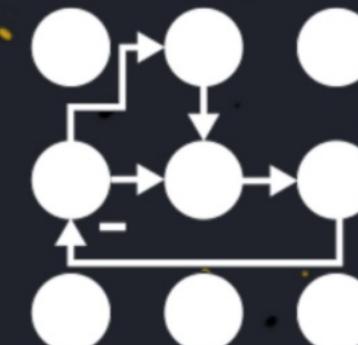


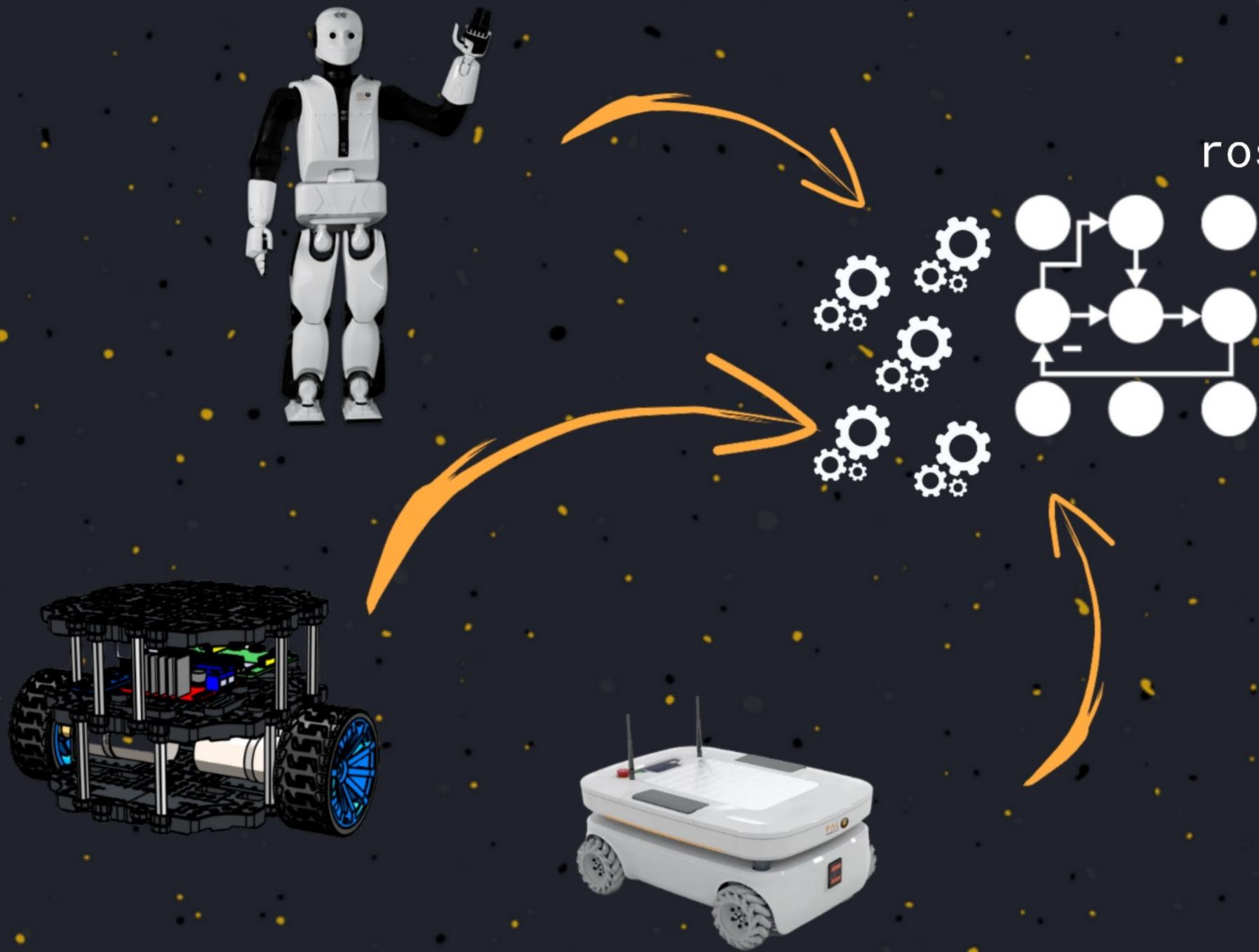
ros2\_control

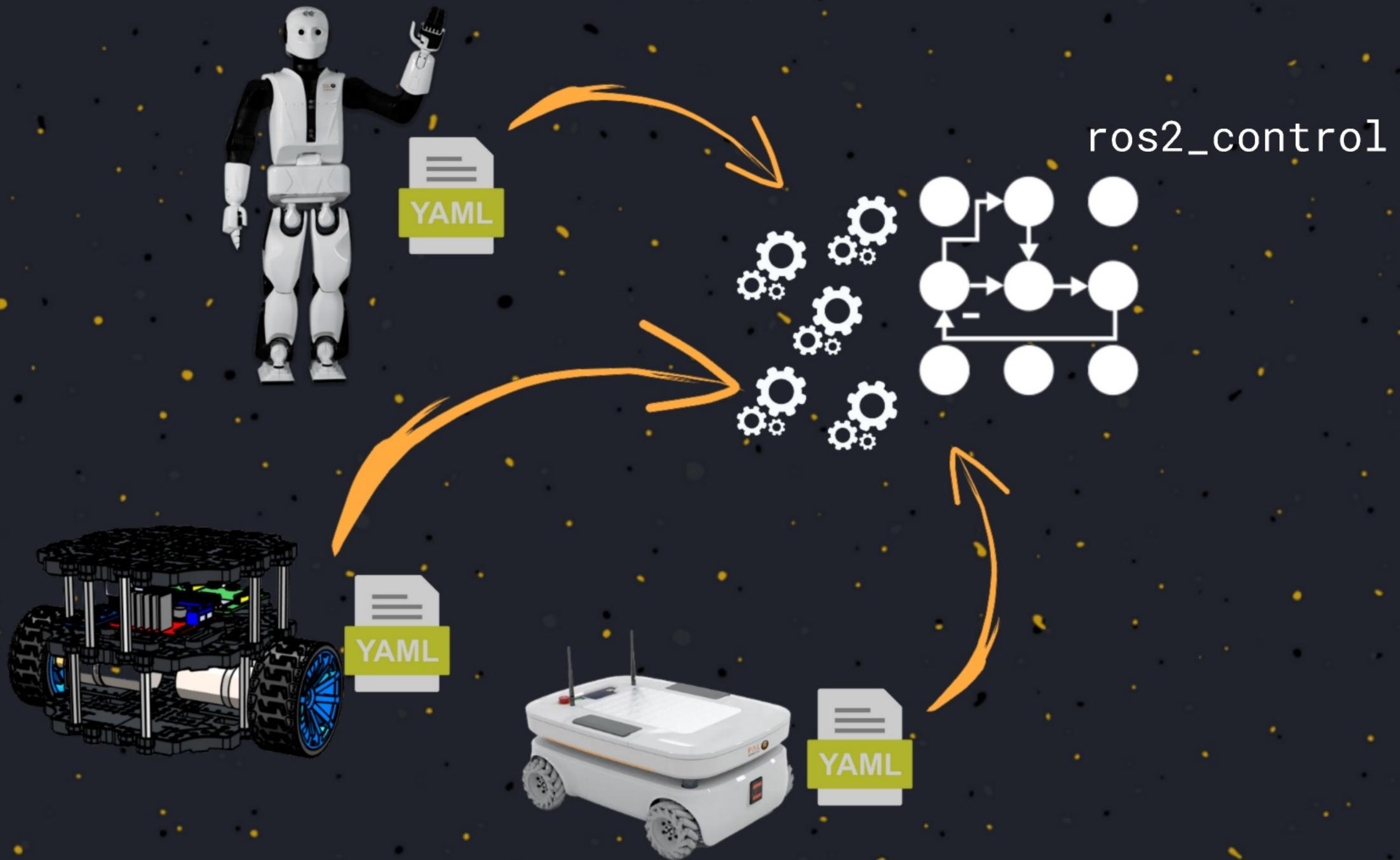




ros2\_control







```
controller_manager:
```

→ Node Name

```
  ros__parameters:
```

```
    update_rate: 100 # Hz
```

```
    use_sim_time: true
```

```
joint_state_broadcaster:
```

```
  type: joint_state_broadcaster/JointStateBroadcaster
```

```
simple_velocity_controller:
```

```
  type: velocity_controllers/JointGroupVelocityController
```

```
simple_velocity_controller:
```

```
  ros__parameters:
```

```
    joints:
```

```
      - wheel_left_joint
```

```
      - wheel_right_joint
```

YAML

```
controller_manager:  
  ros__parameters:  
    update_rate: 100 # Hz  
    use_sim_time: true
```



```
joint_state_broadcaster:  
  type: joint_state_broadcaster/JointStateBroadcaster
```

```
simple_velocity_controller:  
  type: velocity_controllers/JointGroupVelocityController
```

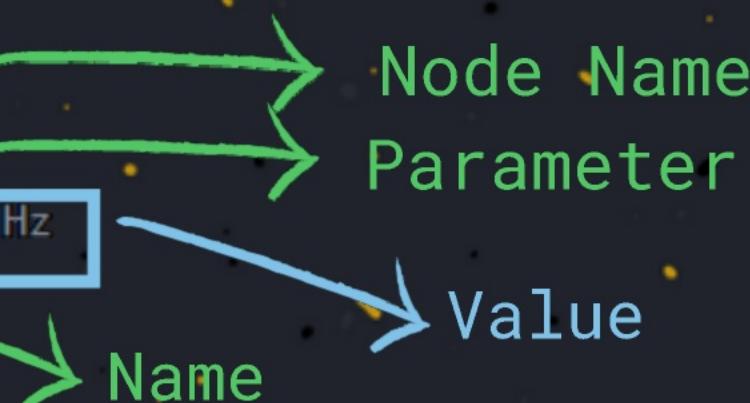
```
simple_velocity_controller:  
  ros__parameters:  
    joints:  
      - wheel_left_joint  
      - wheel_right_joint
```

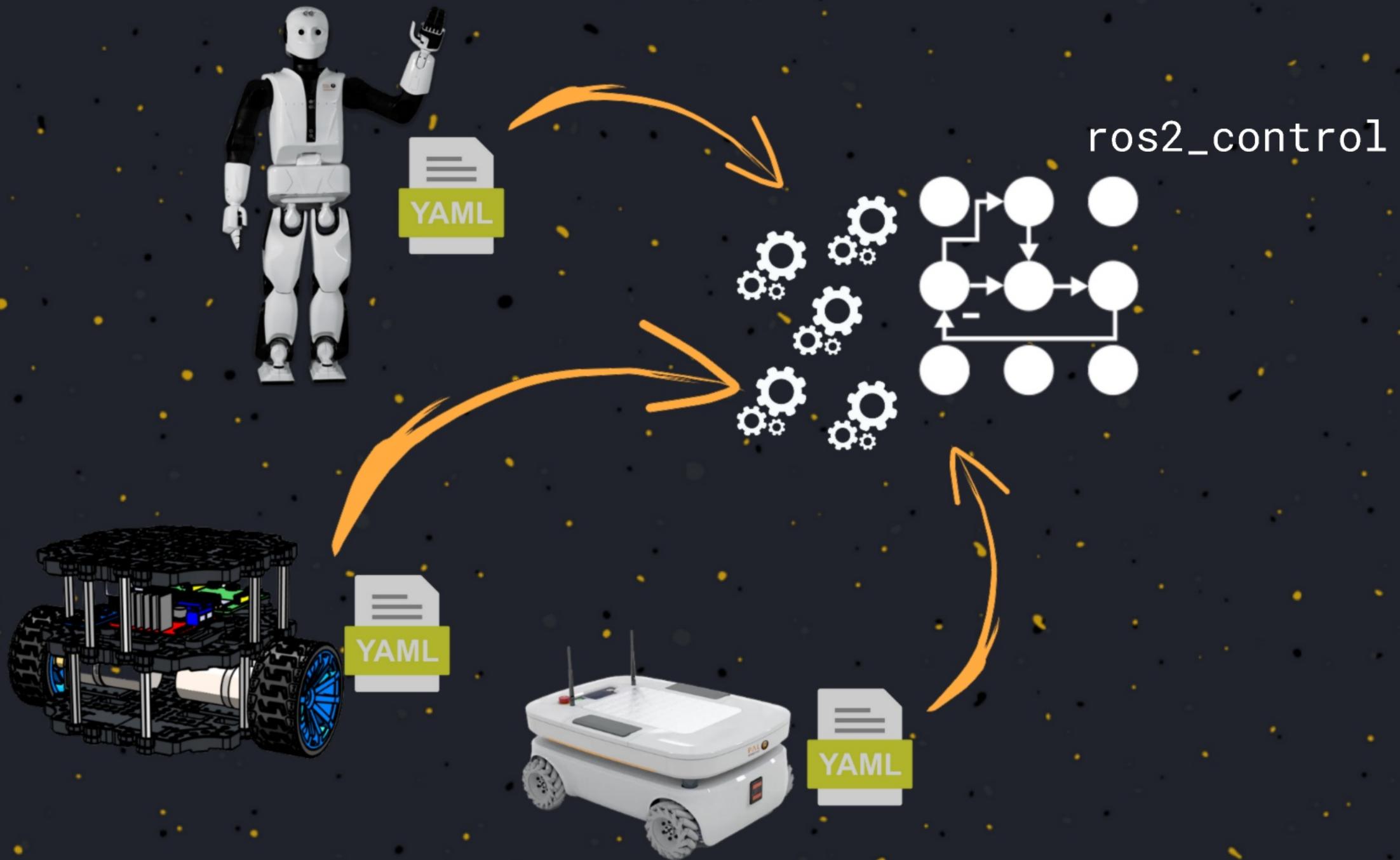




YAML

```
controller_manager:  
  ros__parameters:  
    update_rate: 100 # Hz  
    use_sim_time: true  
  
joint_state_broadcaster:  
  type: joint_state_broadcaster/JointStateBroadcaster  
  
simple_velocity_controller:  
  type: velocity_controllers/JointGroupVelocityController  
  
simple_velocity_controller:  
  ros__parameters:  
    joints:  
      - wheel_left_joint  
      - wheel_right_joint
```





# ROS 2 Control

