

descartes\_light::Position  
Sampler< FloatType >

std::shared\_ptr< Descartes  
Collision >

tesseract\_planning  
::DescartesRobotSampler  
< FloatType >

collision\_

```
graph LR; A[tesseract_planning::DescartesRobotSampler< FloatType >] --> B[descartes_light::PositionSampler< FloatType >]; A -.->|collision_| C[std::shared_ptr< DescartesCollision >];
```