

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>];
```