```
descartes light::Waypoint
  Sampler< FloatType >
                                                tesseract_planning
std::shared ptr< Descartes
                                 is_valid_
                                                ::DescartesRobotSampler
    VertexEvaluator >
                                                     < FloatType >
                                collision
std::shared_ptr< Descartes
```

Collision >