

Detection

- n: ros::NodeHandle
- imgT: image transport::ImageTransport
- imageSubscriber: image transport::Subscriber
- cv_ptr: cv_bridge::CvImagePtr
- OPENCV WINDOW: const std::string
- kuka: KukaKinematics &
- displmg: bool
- + Detection(KukaKinematics &, const bool &)
- + colorThresholder(const KukaKinematics::States &):
- std::string
- + readImg(const sensor_msgs::ImageConstPtr &)

KukaGripper

- n: ros::NodeHandle
- gripperOn: ros::ServiceClient
- gripperOff: ros::ServiceClient
- gripperSubscriber: ros::Subscriber
- gripperState: bool
- + gripperToggle(const bool &)
- + getGripperState(): bool
- gripperCallback(const std msgs::Bool &)