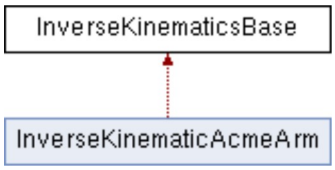
InverseKinematicsBase Class Reference abstract

Inheritance diagram for InverseKinematicsBase:



Public Member Functions

virtual	**~InverseKinematicsBase** () Virtual Destructor for the IK Base Class. More...
virtual std::vector< JointPtr >	**computeIK** (Eigen::Matrix4d)=0 Method to compute Inverse Kinematics. Required of all Derived Classes. More...

Constructor & Destructor Documentation

◆ ~InverseKinematicsBase()

InverseKinematicsBase::~InverseKinematicsBase ( ) virtual

Virtual Destructor for the IK Base Class.

Parameters

None.

Returns

None.

Member Function Documentation

◆ computeIK()

virtual std::vector<JointPtr> InverseKinematicsBase::computeIK (Eigen::Matrix4d) pure virtual

Method to compute Inverse Kinematics. Required of all Derived Classes.

Parameters

Coordinate. A 4x4 Matrix from Eigen

Returns

std::vector<JointPtr> A vector of joints (From which configurations can be retrieved)

Implemented in **InverseKinematicAcmeArm**.

The documentation for this class was generated from the following files:

- C:/Users/ethan/Desktop/Doxygen Environment/ENPM808X_Midterm-master/include/**InverseKinematics.hpp**
- C:/Users/ethan/Desktop/Doxygen Environment/ENPM808X_Midterm-master/app/InverseKinematics.cpp