

PickPlace

+ gripperState : ros::Subscriber
+ setPickPose : ros::ServiceServer
+ setPlacePose : ros::ServiceServer
+ pickPose : geometry_msgs/Pose
+ placePose : geometry_msgs/Pose
+ homePose : geometry_msgs/Pose
+ pickState : ros::ServiceClient
+ placeState : ros::ServiceClient

+ checkGripperState : bool
+ setPick: void
+ setPlace : void