KukaKinematics

- n: ros::NodeHandle
- jointPublisher: ros::Publisher
- jointCommands: trajectory_msgs::JointTrajectory
- numJoints: const unsigned int
- posJoints: double**
- statesStr: std::vector<std::string>
+ States: enum

+ KukaKinematics()
+ sendRobotToPos(const enum &)
- initializeTrajectoryPoint()
+ ~KukaKinematics()

KukaGripper

- n: ros::NodeHandle
- gripperOn: ros::ServiceClient
- gripperOff: ros::ServiceClient
- gripperSubscriber: ros::Subscriber
- gripperState: bool

+ KukaGripper()
+ gripperToggle(const bool &)
+ getGripperState(): bool
- gripperCallback(const std_msgs::Bool &)
+ ~KukaGripper()

Detection

- n: ros::NodeHandle
- imgT: image_transport::ImageTransport
- imageSubscriber: image_transport::Subscriber
- cv_ptr: cv_bridge::CvImagePtr
- OPENCV_WINDOW: const std::string
- kuka: KukaKinematics &
- dispImg: bool

+ Detection(KukaKinematics &, const bool &)
+ colorThresholder(const KukaKinematics::States &): std::string
- readImg(const sensor_msgs::ImageConstPtr &)
+ ~Detection()