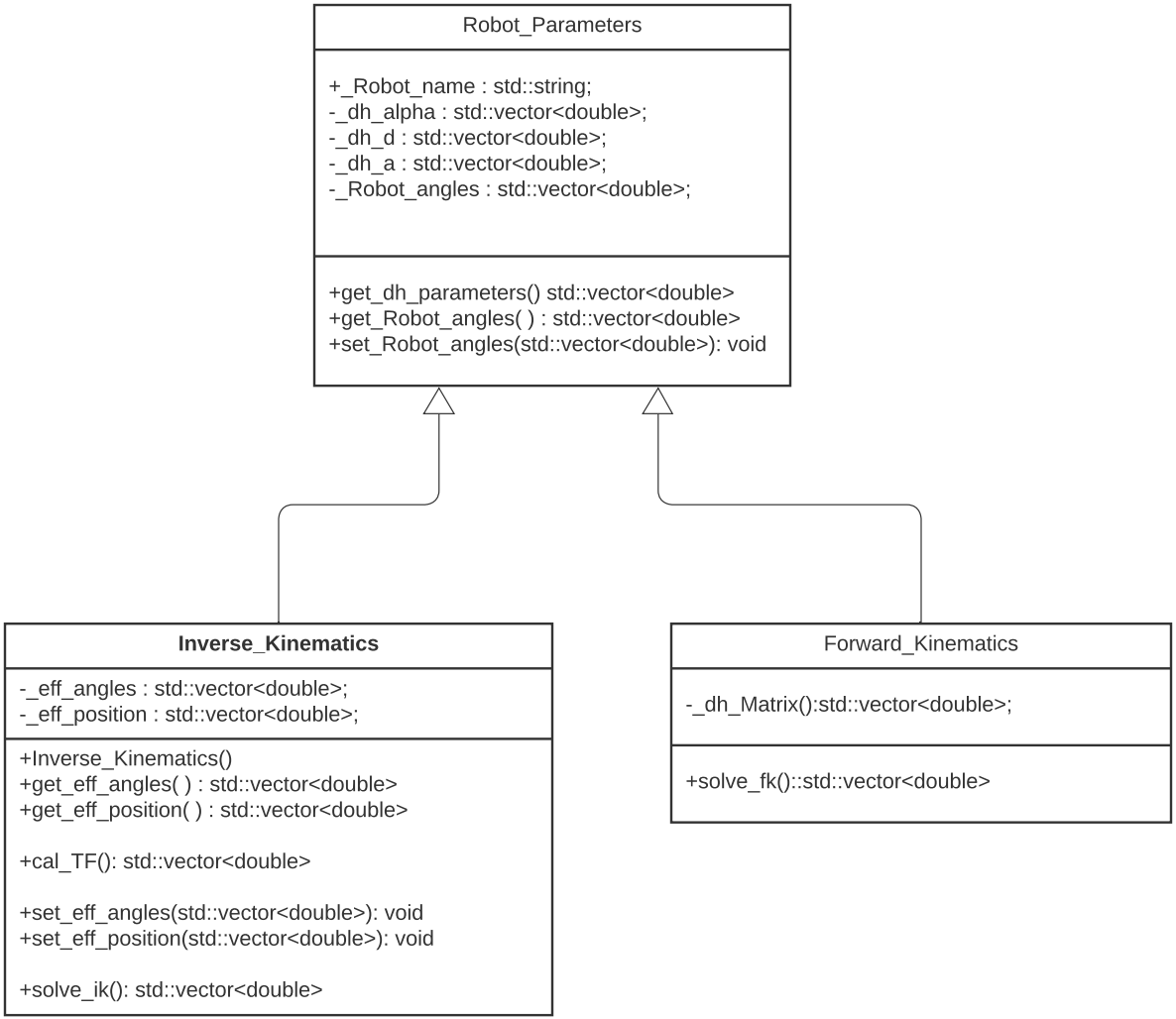
Robot_Parameters
+_Robot_name : std::string;
-_dh_alpha : std::vector<double>;
-_dh_d : std::vector<double>;
-_dh_a : std::vector<double>;
-_Robot_angles : std::vector<double>;
+get_dh_parameters() std::vector<double>
+get_Robot_angles( ) : std::vector<double>
+set_Robot_angles(std::vector<double>): void
Inverse_Kinematics
-_eff_angles : std::vector<double>;
-_eff_position : std::vector<double>;
+Inverse_Kinematics()
+get_eff_angles( ) : std::vector<double>
+get_eff_position( ) : std::vector<double>
+cal_TF(): std::vector<double>
+set_eff_angles(std::vector<double>): void
+set_eff_position(std::vector<double>): void
+solve_ik(): std::vector<double>
Forward_Kinematics
-_dh_Matrix():std::vector<double>;
+solve_fk()::std::vector<double>