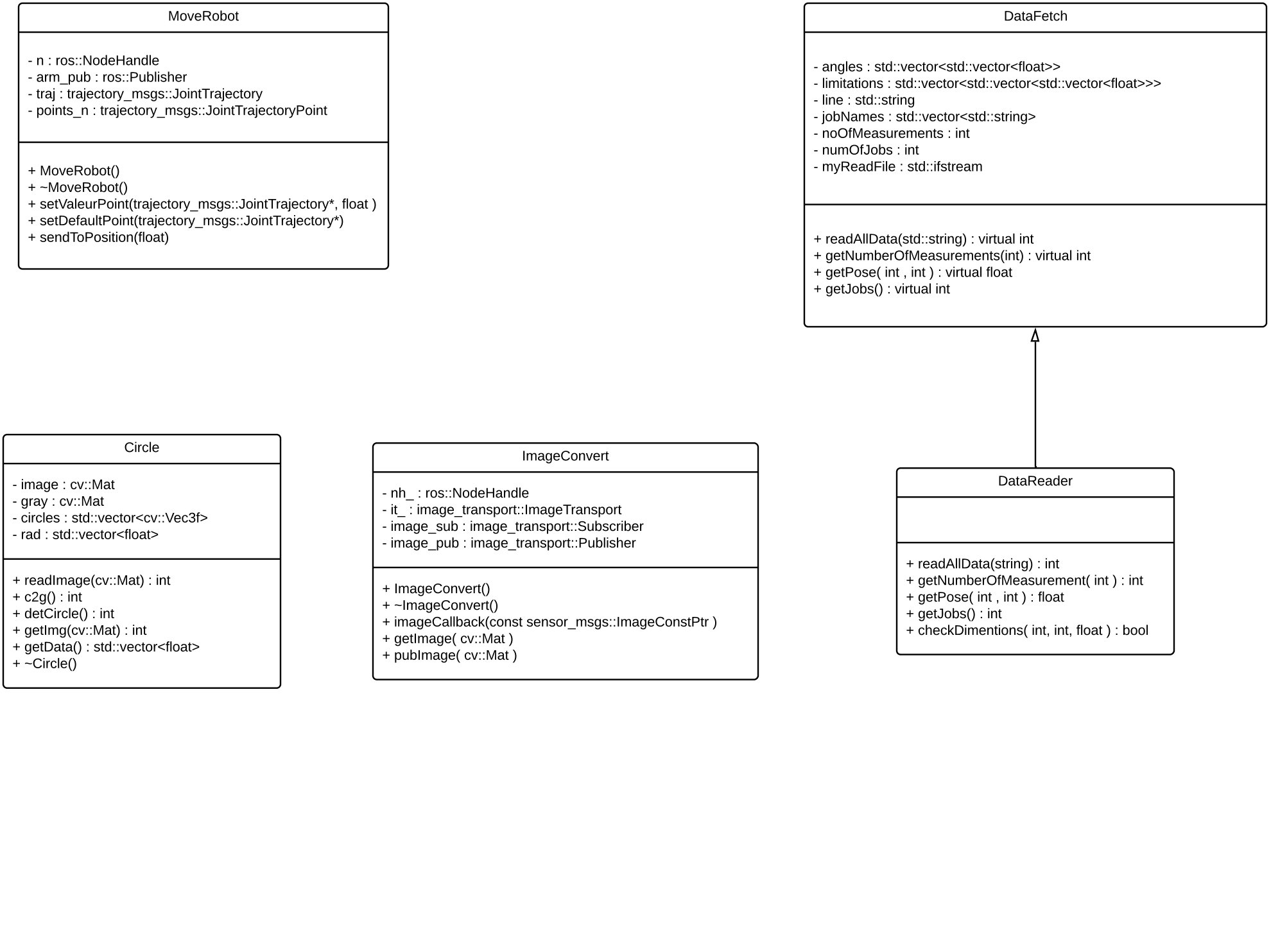
MoveRobot
- n : ros::NodeHandle
- arm_pub : ros::Publisher
- traj : trajectory_msgs::JointTrajectory
- points_n : trajectory_msgs::JointTrajectoryPoint
+ MoveRobot()
+ ~MoveRobot()
+ setValeurPoint(trajectory_msgs::JointTrajectory*, float)
+ setDefaultPoint(trajectory_msgs::JointTrajectory*)
+ sendToPosition(float)
DataFetch
- angles : std::vector<std::vector<float>>
- limitations : std::vector<std::vector<std::vector<float>>>
- line : std::string
- jobNames : std::vector<std::string>
- noOfMeasurements : int
- numOfJobs : int
- myReadFile : std::ifstream
+ readAllData(std::string) : virtual int
+ getNumberOfMeasurements(int) : virtual int
+ getPose(int , int) : virtual float
+ getJobs() : virtual int
Circle
- image : cv::Mat
- gray : cv::Mat
- circles : std::vector<cv::Vec3f>
- rad : std::vector<float>
+ readImage(cv::Mat) : int
+ c2g() : int
+ detCircle() : int
+ getImg(cv::Mat) : int
+ getData() : std::vector<float>
+ ~Circle()
ImageConvert
- nh_ : ros::NodeHandle
- it_ : image_transport::ImageTransport
- image_sub : image_transport::Subscriber
- image_pub : image_transport::Publisher
+ ImageConvert()
+ ~ImageConvert()
+ imageCallback(const sensor_msgs::ImageConstPtr)
+ getImage(cv::Mat)
+ pubImage(cv::Mat)
DataReader
+ readAllData(string) : int
+ getNumberOfMeasurement(int) : int
+ getPose(int , int) : float
+ getJobs() : int
+ checkDimentions(int, int, float) : bool