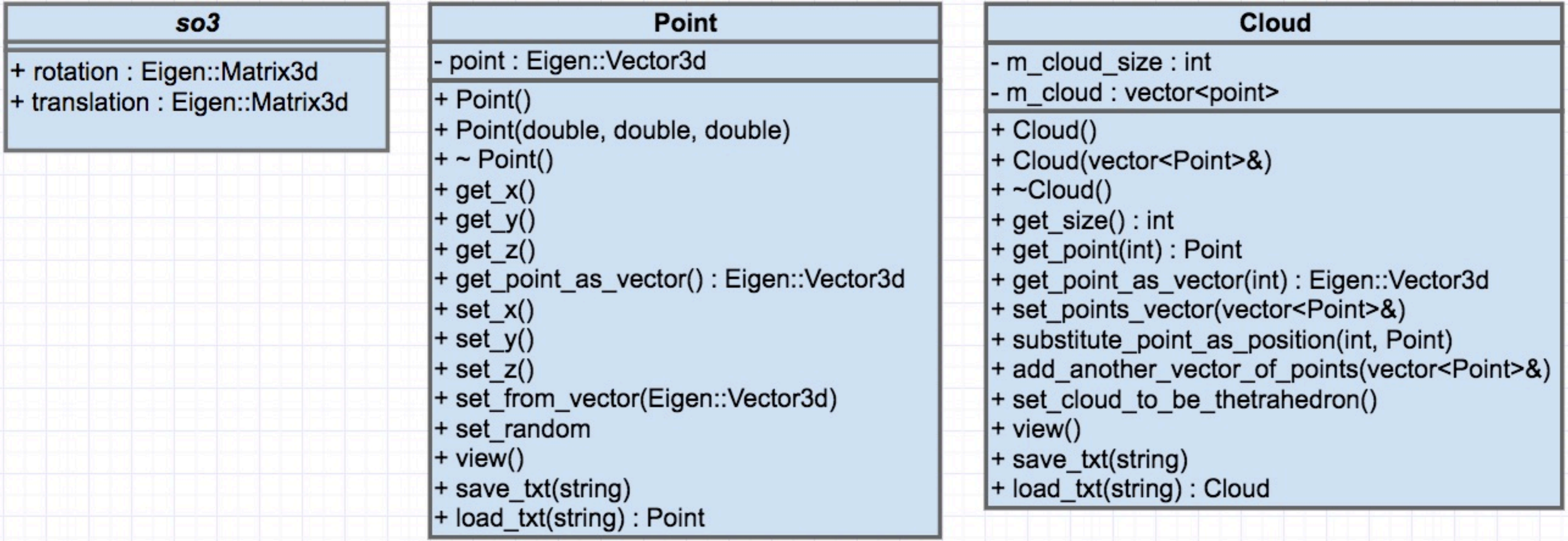
so3
+ rotation : Eigen::Matrix3d
+ translation : Eigen::Matrix3d
Point
- point : Eigen::Vector3d
+ Point()
+ Point(double, double, double)
+ ~ Point()
+ get_x()
+ get_y()
+ get_z()
+ get_point_as_vector() : Eigen::Vector3d
+ set_x()
+ set_y()
+ set_z()
+ set_from_vector(Eigen::Vector3d)
+ set_random
+ view()
+ save_txt(string)
+ load_txt(string) : Point
Cloud
- m_cloud_size : int
- m_cloud : vector<point>
+ Cloud()
+ Cloud(vector<Point>&)
+ ~Cloud()
+ get_size() : int
+ get_point(int) : Point
+ get_point_as_vector(int) : Eigen::Vector3d
+ set_points_vector(vector<Point>&)
+ substitute_point_as_position(int, Point)
+ add_another_vector_of_points(vector<Point>&)
+ set_cloud_to_be_thetrahedron()
+ view()
+ save_txt(string)
+ load_txt(string) : Cloud