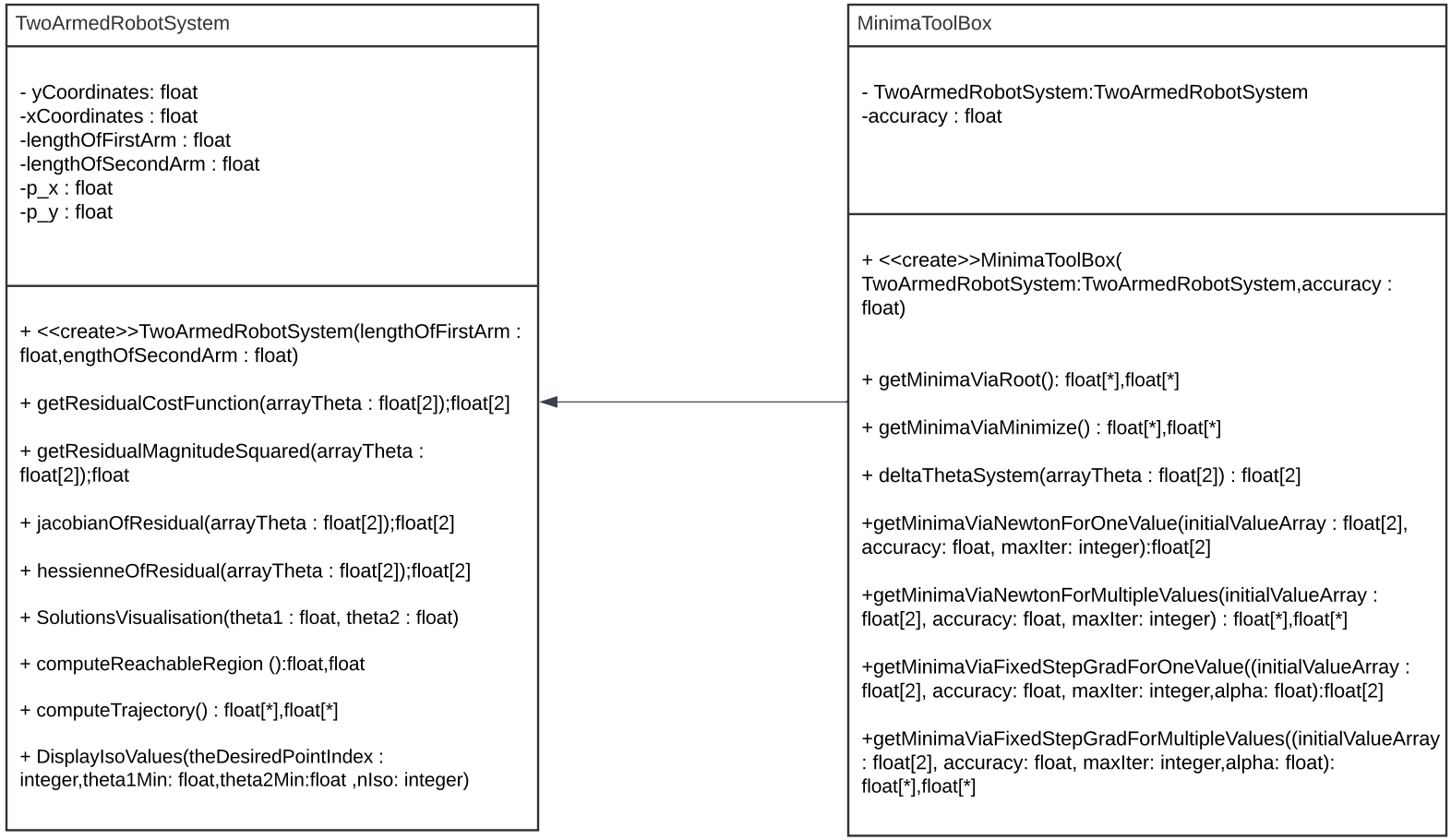
TwoArmedRobotSystem
- yCoordinates: float
-xCoordinates : float
-lengthOfFirstArm : float
-lengthOfSecondArm : float
-p_x : float
-p_y : float
+ <<create>>TwoArmedRobotSystem(lengthOfFirstArm : float,engthOfSecondArm : float)
+ getResidualCostFunction(arrayTheta : float[2]);float[2]
+ getResidualMagnitudeSquared(arrayTheta : float[2]);float
+ jacobianOfResidual(arrayTheta : float[2]);float[2]
+ hessienneOfResidual(arrayTheta : float[2]);float[2]
+ SolutionsVisualisation(theta1 : float, theta2 : float)
+ computeReachableRegion ():float,float
+ computeTrajectory() : float[*],float[*]
+ DisplayIsoValues(theDesiredPointIndex : integer,theta1Min: float,theta2Min:float ,nIso: integer)
MinimaToolBox
- TwoArmedRobotSystem:TwoArmedRobotSystem
-accuracy : float
+ <<create>>MinimaToolBox(TwoArmedRobotSystem:TwoArmedRobotSystem,accuracy : float)
+ getMinimaViaRoot(): float[*],float[*]
+ getMinimaViaMinimize() : float[*],float[*]
+ deltaThetaSystem(arrayTheta : float[2]) : float[2]
+getMinimaViaNewtonForOneValue(initialValueArray : float[2], accuracy: float, maxIter: integer):float[2]
+getMinimaViaNewtonForMultipleValues(initialValueArray : float[2], accuracy: float, maxIter: integer) : float[*],float[*]
+getMinimaViaFixedStepGradForOneValue((initialValueArray : float[2], accuracy: float, maxIter: integer,alpha: float):float[2]
+getMinimaViaFixedStepGradForMultipleValues((initialValueArray : float[2], accuracy: float, maxIter: integer,alpha: float): float[*],float[*]