KukaKinematics

- n: ros::NodeHandle
- iointPublisher: ros::Publisher
- jointCommands: trajectory_msgs::JointTrajectory - numJoints: const unsigned int
- posJoints: double**
- + States: enum
- + statesStr: std::vector<std::string>
- + sendRobotToPos(const States &)
- initializeTrajectoryPoint()

Detection

- n: ros::NodeHandle
- imgT: image transport::ImageTransport
- imageSubscriber: image_transport::Subscriber
- cv ptr: cv bridge::CvImagePtr
- OPENCV WINDOW: const std::string
- kuka: KukaKinematics &
- displmq: bool
- + Detection(KukaKinematics &, const bool &)
- + colorThresholder(const KukaKinematics::States &): std::string
- + readImg(const sensor msgs::ImageConstPtr &)

KukaGripper

- n: ros::NodeHandle
- gripperOn: ros::ServiceClient
- gripperOff: ros::ServiceClient
- gripperSubscriber: ros::Subscriber
- gripperState: bool
- + gripperToggle(const bool &)
- + getGripperState(): bool
- gripperCallback(const std msgs::Bool &)