

Camera pose is necessary to convert  
where does it come from?

Class
- field: type
+ method(attributes: type) -> return type

☐ : In place

☒ : Developed

~~asd~~ : Tested in system

Could go into GUI

VisionModule
- GUI_frame: numpy.ndarray(NXM) - current_frame: numpy.ndarray(NXM)
+ classify_cell(frames: list<frame: numpy.ndarray(NXM)>) -> cell_class: list<model: str, probability: float> + cell_detection(frame: numpy.ndarray(NXM)) -> cell_positions: list<position: numpy.ndarray(2x1)> + assess_quality(frame: numpy.ndarray(NXM), bbs_positions: list<position: numpy.ndarray(2x1)>) -> scores: list<score: float> + frame_to_world(position: numpy.ndarray(2x1)) -> pose: numpy.ndarray(4x4) + verify_pickup(position: numpy.ndarray(2x1)) -> pickedup: bool + write_qualities(frame: numpy.ndarray(NXM), qualities_positions: list<position: numpy.ndarray(2x1)>, qualities_positions: list<position: numpy.ndarray(2x1)>) -> drawn_frame: numpy.ndarray(NXM) + draw_bbs(frame: numpy.ndarray(NXM), bbs_positions: list<position: numpy.ndarray(2x1)>) -> drawn_frame: numpy.ndarray(NXM)

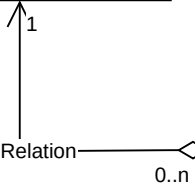
RobotModule
- home_position: numpy.ndarray(6x1)
+ pick_and_place(pick_pose: numpy.ndarray(4x4), place_pose: numpy.ndarray(4x4)) -> void

Behaviour
- pack_state: PackState - gui: Gui - vision_module: VisionModule - robot_module: RobotModule

All the behaviour should have the same pack\_state, gui, visionmodule and robotmodel object, which will be initialized in the in the tree and then passed as arguments in the construction of each behaviour. Not all the behaviour should have all the component, just the ones they are using

Packstate
- cells list<cell: Cell>

Cell
- model: str - size: tuple<diameter: float, height: float> - quality: float - pose: numpy.ndarray(4x4) - frame_pos: numpy.nadarray(2x1) - sorted: bool



BehaviourTree
- pack_state: PackState

GuiState
- elements: list<element>
+ connected_methods() -> void

Gui state is similar to behaviour, each gui state will have its unique combination of elements on the gui and methods

Gui
- showing_frame: numpy.ndarray(NXM) - active_state: int - states: list<GuiState> - wait_interaction: bool - chosen_model: str - chosen_locations: list<position: numpy.ndarray(2x1)>
+ update(active_id: int) -> void + ask_for_help(query: str) -> void