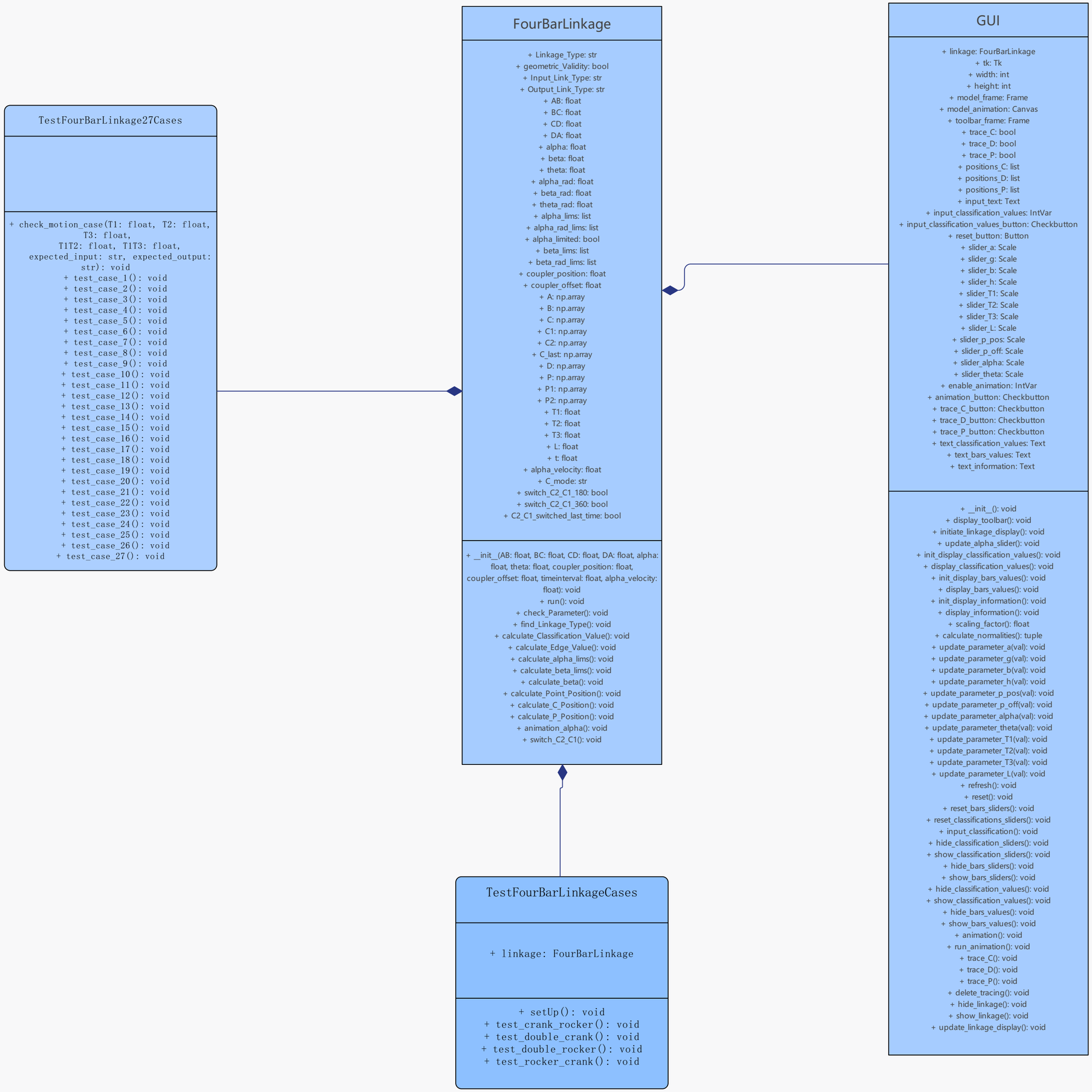
TestFourBarLinkage27Cases
+ check_motion_case(T1: float, T2: float, T3: float, T1T2: float, T1T3: float, expected_input: str, expected_output: str): void
+ test_case_1(): void
+ test_case_2(): void
+ test_case_3(): void
+ test_case_4(): void
+ test_case_5(): void
+ test_case_6(): void
+ test_case_7(): void
+ test_case_8(): void
+ test_case_9(): void
+ test_case_10(): void
+ test_case_11(): void
+ test_case_12(): void
+ test_case_13(): void
+ test_case_14(): void
+ test_case_15(): void
+ test_case_16(): void
+ test_case_17(): void
+ test_case_18(): void
+ test_case_19(): void
+ test_case_20(): void
+ test_case_21(): void
+ test_case_22(): void
+ test_case_23(): void
+ test_case_24(): void
+ test_case_25(): void
+ test_case_26(): void
+ test_case_27(): void
FourBarLinkage
+ Linkage_Type: str
+ geometric_Validity: bool
+ Input_Link_Type: str
+ Output_Link_Type: str
+ AB: float
+ BC: float
+ CD: float
+ DA: float
+ alpha: float
+ beta: float
+ theta: float
+ alpha_rad: float
+ beta_rad: float
+ theta_rad: float
+ alpha_lims: list
+ alpha_rad_lims: list
+ alpha_limited: bool
+ beta_lims: list
+ beta_rad_lims: list
+ coupler_position: float
+ coupler_offset: float
+ A: np.array
+ B: np.array
+ C: np.array
+ C1: np.array
+ C2: np.array
+ C_last: np.array
+ D: np.array
+ P: np.array
+ P1: np.array
+ P2: np.array
+ T1: float
+ T2: float
+ T3: float
+ L: float
+ t: float
+ alpha_velocity: float
+ C_mode: str
+ switch_C2_C1_180: bool
+ switch_C2_C1_360: bool
+ C2_C1_switched_last_time: bool
+ __init__(AB: float, BC: float, CD: float, DA: float, alpha: float, theta: float, coupler_position: float, coupler_offset: float, timeinterval: float, alpha_velocity: float): void
+ run(): void
+ check_Parameter(): void
+ find_Linkage_Type(): void
+ calculate_Classification_Value(): void
+ calculate_Edge_Value(): void
+ calculate_alpha_lims(): void
+ calculate_beta_lims(): void
+ calculate_beta(): void
+ calculate_Point_Position(): void
+ calculate_C_Position(): void
+ calculate_P_Position(): void
+ animation_alpha(): void
+ switch_C2_C1(): void
GUI
+ linkage: FourBarLinkage
+ tk: Tk
+ width: int
+ height: int
+ model_frame: Frame
+ model_animation: Canvas
+ toolbar_frame: Frame
+ trace_C: bool
+ trace_D: bool
+ trace_P: bool
+ positions_C: list
+ positions_D: list
+ positions_P: list
+ input_text: Text
+ input_classification_values: IntVar
+ input_classification_values_button: Checkbutton
+ reset_button: Button
+ slider_a: Scale
+ slider_g: Scale
+ slider_b: Scale
+ slider_h: Scale
+ slider_T1: Scale
+ slider_T2: Scale
+ slider_T3: Scale
+ slider_L: Scale
+ slider_p_pos: Scale
+ slider_p_off: Scale
+ slider_alpha: Scale
+ slider_theta: Scale
+ enable_animation: IntVar
+ animation_button: Checkbutton
+ trace_C_button: Checkbutton
+ trace_D_button: Checkbutton
+ trace_P_button: Checkbutton
+ text_classification_values: Text
+ text_bars_values: Text
+ text_information: Text
+ __init__(): void
+ display_toolbar(): void
+ initiate_linkage_display(): void
+ update_alpha_slider(): void
+ init_display_classification_values(): void
+ display_classification_values(): void
+ init_display_bars_values(): void
+ display_bars_values(): void
+ init_display_information(): void
+ display_information(): void
+ scaling_factor(): float
+ calculate_normalities(): tuple
+ update_parameter_a(val): void
+ update_parameter_g(val): void
+ update_parameter_b(val): void
+ update_parameter_h(val): void
+ update_parameter_p_pos(val): void
+ update_parameter_p_off(val): void
+ update_parameter_alpha(val): void
+ update_parameter_theta(val): void
+ update_parameter_T1(val): void
+ update_parameter_T2(val): void
+ update_parameter_T3(val): void
+ update_parameter_L(val): void
+ refresh(): void
+ reset(): void
+ reset_bars_sliders(): void
+ reset_classifications_sliders(): void
+ input_classification(): void
+ hide_classification_sliders(): void
+ show_classification_sliders(): void
+ hide_bars_sliders(): void
+ show_bars_sliders(): void
+ hide_classification_values(): void
+ show_classification_values(): void
+ hide_bars_values(): void
+ show_bars_values(): void
+ animation(): void
+ run_animation(): void
+ trace_C(): void
+ trace_D(): void
+ trace_P(): void
+ delete_tracing(): void
+ hide_linkage(): void
+ show_linkage(): void
+ update_linkage_display(): void
TestFourBarLinkageCases
+ linkage: FourBarLinkage
+ setUp(): void
+ test_crank_rocker(): void
+ test_double_crank(): void
+ test_double_rocker(): void
+ test_rocker_crank(): void