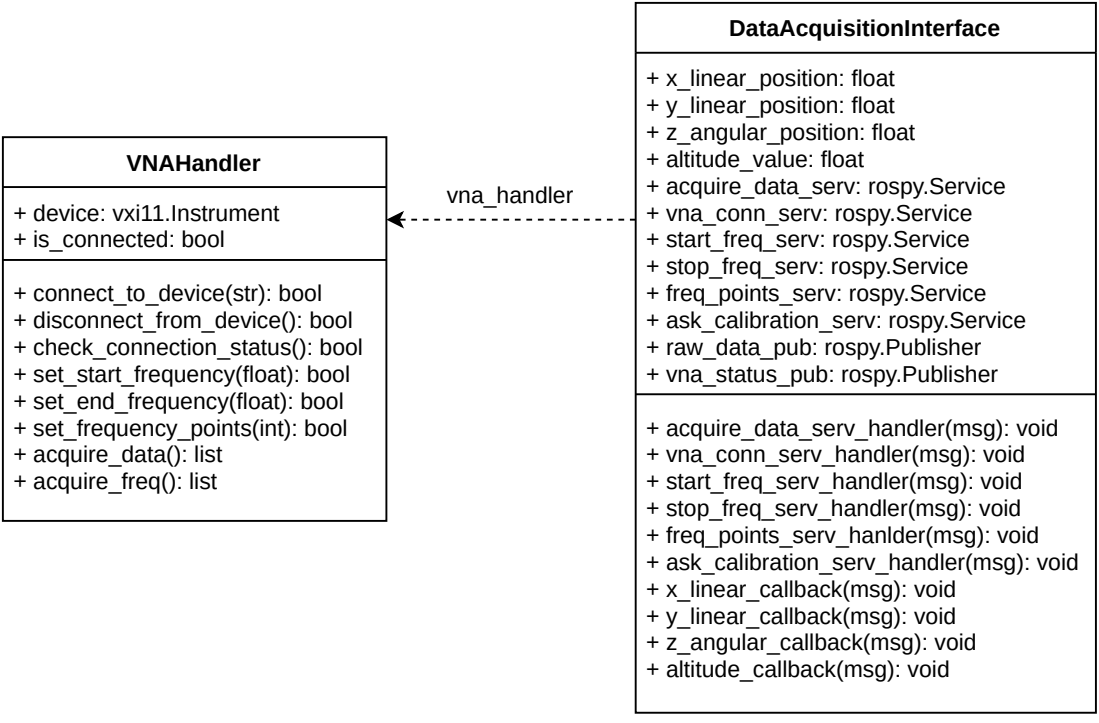
DataAcquisitionInterface
+ x_linear_position: float
+ y_linear_position: float
+ z_angular_position: float
+ altitude_value: float
+ acquire_data_serv: rospy.Service
+ vna_conn_serv: rospy.Service
+ start_freq_serv: rospy.Service
+ stop_freq_serv: rospy.Service
+ freq_points_serv: rospy.Service
+ ask_calibration_serv: rospy.Service
+ raw_data_pub: rospy.Publisher
+ vna_status_pub: rospy.Publisher
+ acquire_data_serv_handler(msg): void
+ vna_conn_serv_handler(msg): void
+ start_freq_serv_handler(msg): void
+ stop_freq_serv_handler(msg): void
+ freq_points_serv_hanlder(msg): void
+ ask_calibration_serv_handler(msg): void
+ x_linear_callback(msg): void
+ y_linear_callback(msg): void
+ z_angular_callback(msg): void
+ altitude_callback(msg): void
vna_handler
VNAHandler
+ device: vxi11.Instrument
+ is_connected: bool
+ connect_to_device(str): bool
+ disconnect_from_device(): bool
+ check_connection_status(): bool
+ set_start_frequency(float): bool
+ set_end_frequency(float): bool
+ set_frequency_points(int): bool
+ acquire_data(): list
+ acquire_freq(): list