

PluginArmPRob3Kinematics

- urdf : VProperty<std::string>

- m_chain : KDL::Chain

- fksolver : KDL::ChainFkSolverPos_recursive *

- iksolver1v : KDL::ChainIkSolverVel_pinv *

- inv_pos_solver : KDL::ChainIkSolverPos_NR_JL *

- q_min : KDL::JntArray

- q_max : KDL::JntArray

- loadChainFromUrdf() : bool

+ setup()

+ computeDirectKinematics(joint_state : std::vector<double>, tool_pose : Transform3D) : bool

+ computeInverseKinematics(tool_pose : Transform3D, joint_state : std::vector<double>) : bool

+ computeInverseKinematics(tool_pose : Transform3D, joint_state : std::vector<double>, joint_init : std::vector<double>) : bool

+ computeLinearTrajectory(start : Transform3D, end : Transform3D, trajectory : JointTrajectory, lastJointState : std::vector<double>) : bool