PluginArmPRob3Kinematics
- 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