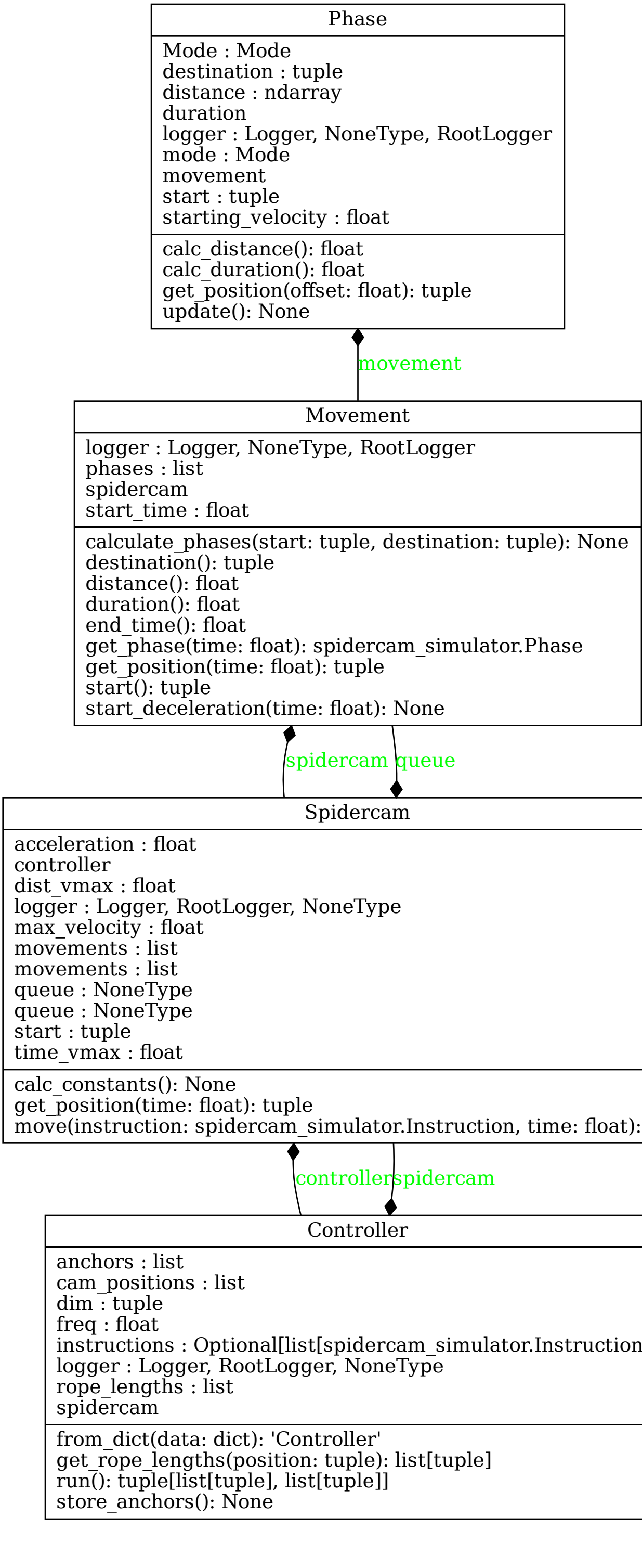
Phase
Mode : Mode
destination : tuple
distance : ndarray
duration
logger : Logger, NoneType, RootLogger
mode : Mode
movement
start : tuple
starting_velocity : float
calc_distance(): float
calc_duration(): float
get_position(offset: float): tuple
update(): None
movement
Movement
logger : Logger, NoneType, RootLogger
phases : list
spidercam
start_time : float
calculate_phases(start: tuple, destination: tuple): None
destination(): tuple
distance(): float
duration(): float
end_time(): float
get_phase(time: float): spidercam_simulator.Phase
get_position(time: float): tuple
start(): tuple
start_deceleration(time: float): None
spidercam
queue
Spidercam
acceleration : float
controller
dist_vmax : float
logger : Logger, RootLogger, NoneType
max_velocity : float
movements : list
movements : list
queue : NoneType
queue : NoneType
start : tuple
time_vmax : float
calc_constants(): None
get_position(time: float): tuple
move(instruction: spidercam_simulator.Instruction, time: float): None
controller
spidercam
Controller
anchors : list
cam_positions : list
dim : tuple
freq : float
instructions : Optional[list[spidercam_simulator.Instruction]]
logger : Logger, RootLogger, NoneType
rope_lengths : list
spidercam
from_dict(data: dict): 'Controller'
get_rope_lengths(position: tuple): list[tuple]
run(): tuple[list[tuple], list[tuple]]
store_anchors(): None