```
robot controllers::
    TrajectorySampler
  + TrajectorySampler()
  + ~TrajectorySampler()
  + sample()
  + end time()
  + getTrajectory()
  TrajectorySampler()
  operator=()
robot controllers::
  SplineTrajectorySampler
- segments

    trajectory
```

+ SplineTrajectorySampler()

resultseg

+ sample() + end\_time() + getTrajectory()