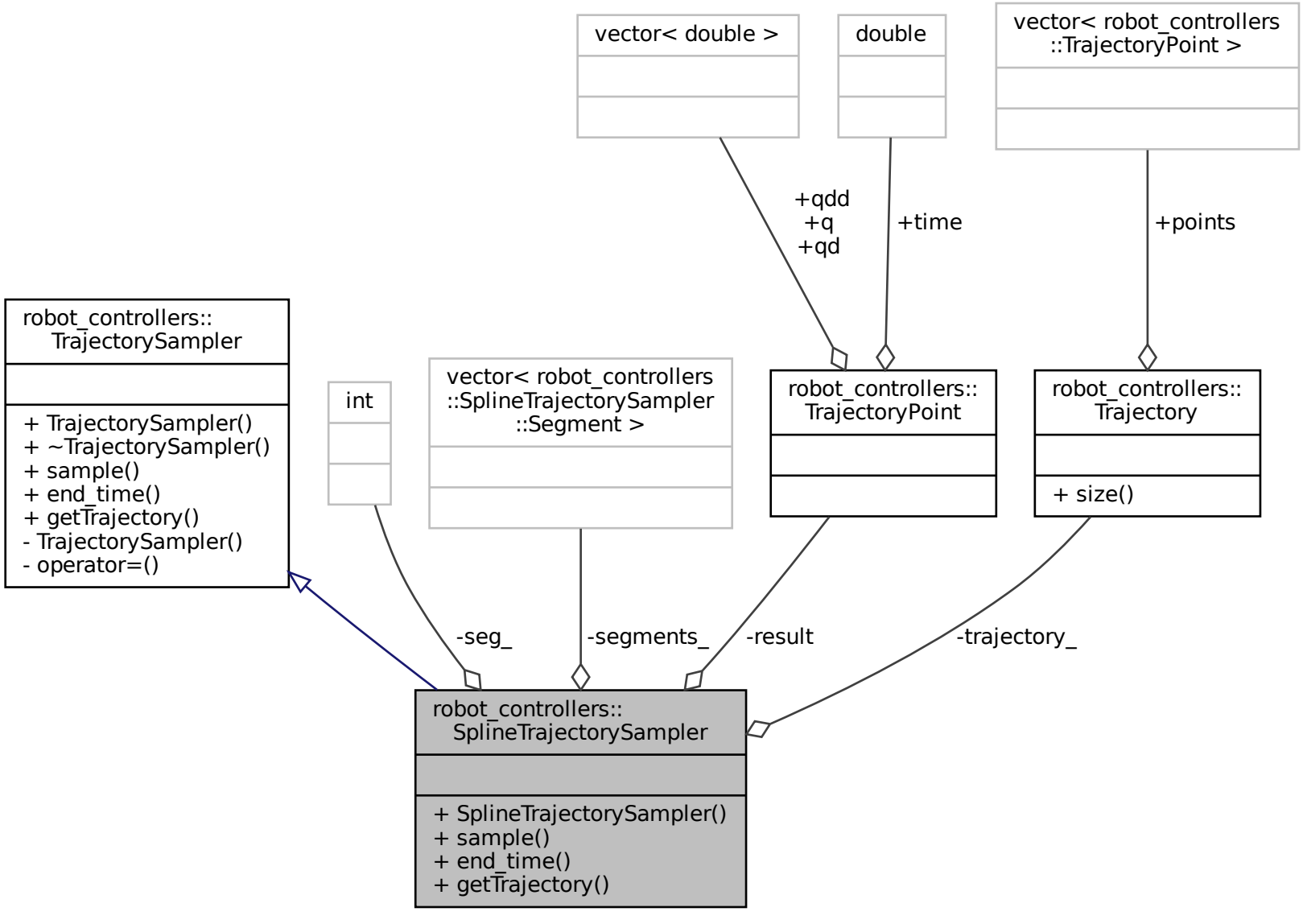
vector< double >
double
vector< robot_controllers ::TrajectoryPoint >
+qdd
+q
+qd
+time
+points
robot_controllers:: TrajectorySampler
+ TrajectorySampler()
+ ~TrajectorySampler()
+ sample()
+ end_time()
+ getTrajectory()
- TrajectorySampler()
- operator=()
int
vector< robot_controllers ::SplineTrajectorySampler ::Segment >
robot_controllers:: TrajectoryPoint
robot_controllers:: Trajectory
+ size()
-seg_
-segments_
-result
-trajectory_
robot_controllers:: SplineTrajectorySampler
+ SplineTrajectorySampler()
+ sample()
+ end_time()
+ getTrajectory()