robot_controllers::
    TrajectorySampler

+ TrajectorySampler()
+ ~TrajectorySampler()
+ sample()
+ end_time()
+ getTrajectory()
- TrajectorySampler()
- operator=()

robot_controllers::
    SplineTrajectorySampler

- segments_
- trajectory_
- result
- seg_

+ SplineTrajectorySampler()
+ sample()
+ end_time()
+ getTrajectory()