ICommander

- # startPositionLBR
- # TCP
- #RCM
- # apertureLimit
- # heightSafety
- # buttons
- # velocitySub
- # Q4StateSub
- # Q5StateSub
- # Q6pStateSub und 33 mehr ...
- + setGripperStatus()
- + configurationCallback()
- # statemachineThread()
- # calcQ6()
- # commandVelocities()
- # loop()
- # QuaternionFromEuler()

GeometricKinematicCommander

- IbrTargetPositionPub
- velocity_
- nh
- T 0 FL
- + GeometricKinematicCommander()
- statemachineThread()
- calcQ6()
- commandVelocities()
- buttonCheck()
- getControlDevice()
- flangeCallback()
- loop()
- Q4StateCallback()
- Q5StateCallback()
- Q6nStateCallback()
- Q6pStateCallback()
- velocityCallback()
- buttonCallback()

NumericKinematicCommander

- nh
- IbrJointAnglePub
- IbrJointAngleSub
- startPositionLBR
- IbrJointAngles
- + NumericKinematicCommander()
- statemachineThread()
- configurationCallback()
- buttonCheck()
- getControlDevice()
- calcQ6()
- commandVelocities()
- IbrJointAngleCallback()
- Q4StateCallback()
- Q5StateCallback()
- Q6nStateCallback()
- Q6pStateCallback()
- buttonCallback()
- loop()