IKinematic

RCM
T_FL_EE
T_0_EE
T_0_Q4
T_FL_Q4
T_FL_Q5
T_FL_Q6
jointAnglesTar
jointAnglesAct
DEG_TO_RAD
und 9 mehr ...

checkTCP()
calcInvKin()
buildAffine3d()

GeometricKinematic

- nh_
- TOOL_PARAMETERS
- T_0_FL
- rcmServer
- directKinematicsServer
- inverseKinematicsServer

+ GeometricKinematic()
+ getT_0_FL()
+ getT_0_Q4()
+ setAngles()
- calcDirKin()
- calcInvKin()
- rcmCallback()
- directKinematicsCallback()
- inverseKinematicsCallback()
- buildAffine3d()

NumericKinematic

- nh_
- cycleTimeSub
- LBR_PARAMETERS
- TOOL_PARAMETERS
- URSULA_MAX_ANGLES
- URSULA_MAX_ANGLES_SPEED
- MAX_ANGLES
- MAX_ANGLES_SPEED
- jointWeightMatrix
- minDistance
und 27 mehr ...

+ NumericKinematic()
- calcDirKin()
- calcAnalyticalJacobian()
- calcInvKin()
- angleMonitoring()
- collisionControl()
- trocarMonitoring()
- minimizeVelocities()
- minimizeAcceleration()
- avoidSingularities()
- rcmCallback()
und 6 mehr ...