ITrajectory

startPositionTrajectory_
endPositionTrajectory_
startPosition_
currentPosition
pathParameterStart_
pathIncrement
cycleTime_
speed_
pathParameter_

+ calculateNextPoint()
+ setSpeed()

LineTrajectory

- coefficients
- trajectoryExecutionTime_
- steps_
- cycleTime_

+ LineTrajectory()
+ calculateNextPoint()