## #RCM #T\_FL\_EE #T\_0\_EE #T\_0\_Q4 #T\_FL\_Q5 #T\_FL\_Q6 # jointAnglesTar # jointAnglesAct # DEG\_TO\_RAD und 9 mehr ... # checkTCP() # calcInvKin() # buildAffine3d()

## NumericKinematic

cycleTimeSubLBR PARAMETERS

- nh

- 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 ...