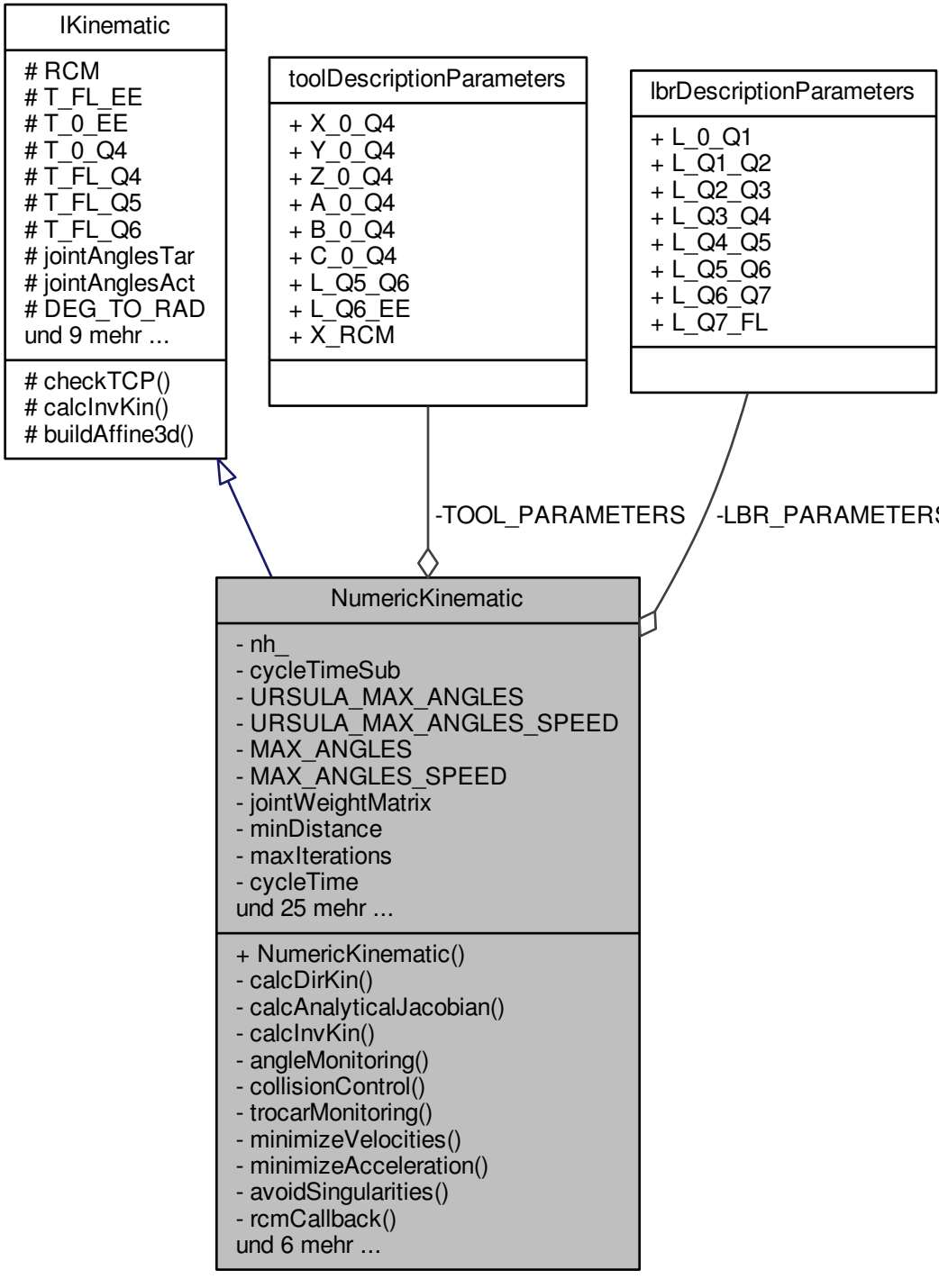
IKinematic
RCM
T_FL_EE
T_0_EE
T_0_Q4
T_FL_Q4
T_FL_Q5
T_FL_Q6
jointAnglesTar
jointAnglesAct
DEG_TO_RAD
und 9 mehr ...
checkTCP()
calcInvKin()
buildAffine3d()
toolDescriptionParameters
+ X_0_Q4
+ Y_0_Q4
+ Z_0_Q4
+ A_0_Q4
+ B_0_Q4
+ C_0_Q4
+ L_Q5_Q6
+ L_Q6_EE
+ X_RCM
lbrDescriptionParameters
+ L_0_Q1
+ L_Q1_Q2
+ L_Q2_Q3
+ L_Q3_Q4
+ L_Q4_Q5
+ L_Q5_Q6
+ L_Q6_Q7
+ L_Q7_FL
-TOOL_PARAMETERS
-LBR_PARAMETERS
NumericKinematic
- nh_
- cycleTimeSub
- URSULA_MAX_ANGLES
- URSULA_MAX_ANGLES_SPEED
- MAX_ANGLES
- MAX_ANGLES_SPEED
- jointWeightMatrix
- minDistance
- maxIterations
- cycleTime
und 25 mehr ...
+ NumericKinematic()
- calcDirKin()
- calcAnalyticalJacobian()
- calcInvKin()
- angleMonitoring()
- collisionControl()
- trocarMonitoring()
- minimizeVelocities()
- minimizeAcceleration()
- avoidSingularities()
- rcmCallback()
und 6 mehr ...