

kinematics::robot< T >

- + links
- + flange2hand
- + handeye
- + ref2cam
- + cameraYaw
- + tanH
- + tanV
- + cam
- + hand\_surf
- + hand\_points
- + target\_surf
- + target\_points

- + jnt2pos()
- + pos2jnt()
- + robot()
- + command()
- + rviz()