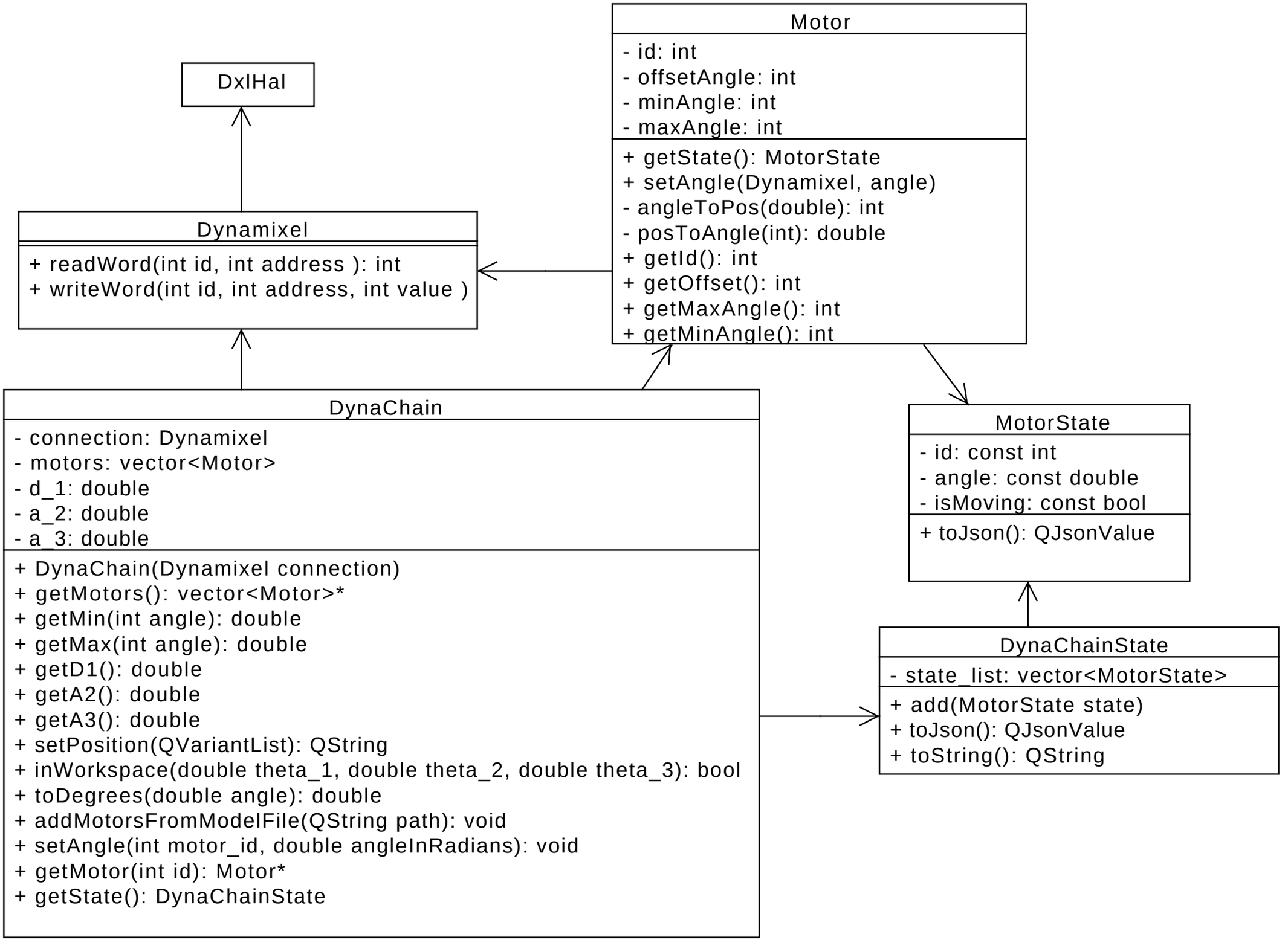
DxlHal
Motor
- id: int
- offsetAngle: int
- minAngle: int
- maxAngle: int
+ getState(): MotorState
+ setAngle(Dynamixel, angle)
- angleToPos(double): int
- posToAngle(int): double
+ getId(): int
+ getOffset(): int
+ getMaxAngle(): int
+ getMinAngle(): int
Dynamixel
+ readWord(int id, int address): int
+ writeWord(int id, int address, int value)
DynaChain
- connection: Dynamixel
- motors: vector<Motor>
- d_1: double
- a_2: double
- a_3: double
+ DynaChain(Dynamixel connection)
+ getMotors(): vector<Motor>*
+ getMin(int angle): double
+ getMax(int angle): double
+ getD1(): double
+ getA2(): double
+ getA3(): double
+ setPosition(QVariantList): QString
+ inWorkspace(double theta_1, double theta_2, double theta_3): bool
+ toDegrees(double angle): double
+ addMotorsFromModelFile(QString path): void
+ setAngle(int motor_id, double angleInRadians): void
+ getMotor(int id): Motor*
+ getState(): DynaChainState
MotorState
- id: const int
- angle: const double
- isMoving: const bool
+ toJson(): QJsonValue
DynaChainState
- state_list: vector<MotorState>
+ add(MotorState state)
+ toJson(): QJsonValue
+ toString(): QString