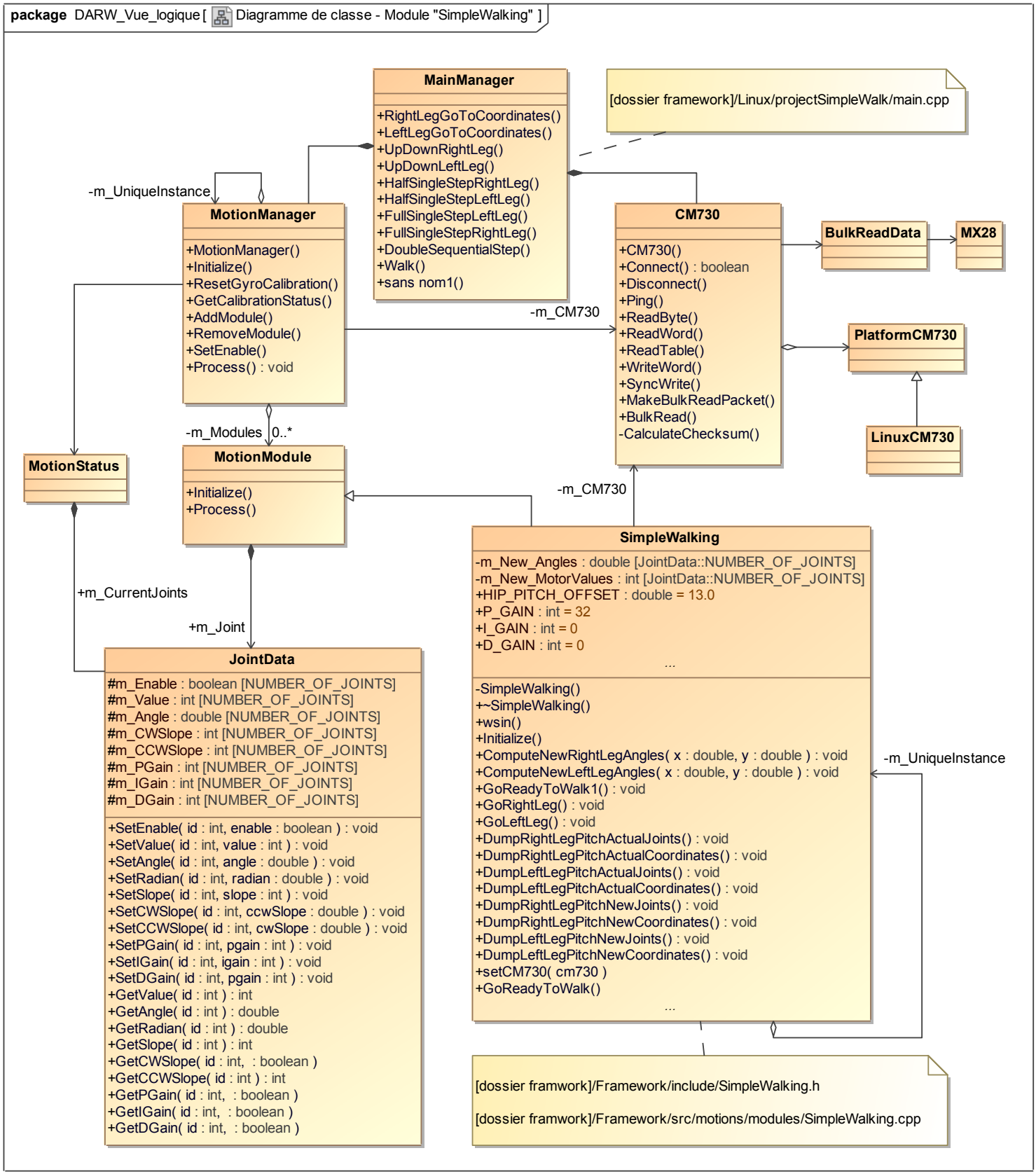
package DARW_Vue_logique [Diagramme de classe - Module "SimpleWalking"]
MainManager
+RightLegGoToCoordinates()
+LeftLegGoToCoordinates()
+UpDownRightLeg()
+UpDownLeftLeg()
+HalfSingleStepRightLeg()
+HalfSingleStepLeftLeg()
+FullSingleStepLeftLeg()
+FullSingleStepRightLeg()
+DoubleSequentialStep()
+Walk()
+sans nom1()
[dossier framework]/Linux/projectSimpleWalk/main.cpp
-m_UniqueInstance
MotionManager
+MotionManager()
+Initialize()
+ResetGyroCalibration()
+GetCalibrationStatus()
+AddModule()
+RemoveModule()
+SetEnable()
+Process() : void
-m_CM730
CM730
+CM730()
+Connect() : boolean
+Disconnect()
+Ping()
+ReadByte()
+ReadWord()
+ReadTable()
+WriteWord()
+SyncWrite()
+MakeBulkReadPacket()
+BulkRead()
-CalculateChecksum()
BulkReadData
MX28
PlatformCM730
LinuxCM730
-m_Modules
0..*
MotionStatus
MotionModule
+Initialize()
+Process()
-m_CM730
SimpleWalking
-m_New_Angles : double [JointData::NUMBER_OF_JOINTS]
-m_New_MotorValues : int [JointData::NUMBER_OF_JOINTS]
+HIP_PITCH_OFFSET : double = 13.0
+P_GAIN : int = 32
+I_GAIN : int = 0
+D_GAIN : int = 0
...
-SimpleWalking()
+~SimpleWalking()
+wsin()
+Initialize()
+ComputeNewRightLegAngles(x : double, y : double) : void
+ComputeNewLeftLegAngles(x : double, y : double) : void
+GoReadyToWalk1() : void
+GoRightLeg() : void
+GoLeftLeg() : void
+DumpRightLegPitchActualJoints() : void
+DumpRightLegPitchActualCoordinates() : void
+DumpLeftLegPitchActualJoints() : void
+DumpLeftLegPitchActualCoordinates() : void
+DumpRightLegPitchNewJoints() : void
+DumpRightLegPitchNewCoordinates() : void
+DumpLeftLegPitchNewJoints() : void
+DumpLeftLegPitchNewCoordinates() : void
+setCM730(cm730)
+GoReadyToWalk()
...
-m_UniqueInstance
+m_CurrentJoints
+m_Joint
JointData
#m_Enable : boolean [NUMBER_OF_JOINTS]
#m_Value : int [NUMBER_OF_JOINTS]
#m_Angle : double [NUMBER_OF_JOINTS]
#m_CWSlope : int [NUMBER_OF_JOINTS]
#m_CCWSlope : int [NUMBER_OF_JOINTS]
#m_PGain : int [NUMBER_OF_JOINTS]
#m_IGain : int [NUMBER_OF_JOINTS]
#m_DGain : int [NUMBER_OF_JOINTS]
+SetEnable(id : int, enable : boolean) : void
+SetValue(id : int, value : int) : void
+SetAngle(id : int, angle : double) : void
+SetRadian(id : int, radian : double) : void
+SetSlope(id : int, slope : int) : void
+SetCWSlope(id : int, ccwSlope : double) : void
+SetCCWSlope(id : int, cwSlope : double) : void
+SetPGain(id : int, pgain : int) : void
+SetIGain(id : int, igain : int) : void
+SetDGain(id : int, pgain : int) : void
+GetValue(id : int) : int
+GetAngle(id : int) : double
+GetRadian(id : int) : double
+GetSlope(id : int) : int
+GetCWSlope(id : int, : boolean)
+GetCCWSlope(id : int) : int
+GetPGain(id : int, : boolean)
+GetIGain(id : int, : boolean)
+GetDGain(id : int, : boolean)
[dossier framwork]/Framework/include/SimpleWalking.h
[dossier framwork]/Framework/src/motions/modules/SimpleWalking.cpp