





# Carte actionneurs (arduino)

## Actionneurs

Pince
bool ouverture
int position
set_ouverture (bool ) : void
set_position (bool ) : void

Rack
bool ouverture
int position
set_ouverture (bool ) : void
set_position (bool ) : void

Barillet
int nbCerise
tourner() : void
vider() : void

AccdNode
NodeHandle nodeHandle
Pince *pince
Barillet *barillet
Rack *rack
Communication *communication
init()
start()

Communication
NodeHandle & nh
Pince &pince
Rack &rack
Barillet &barillet
serviceServer setPincePostitionService
serviceServer setPinceCerisePositionService
serviceServer tournerBarilletService
serviceServer viderBarilletService
init() : void
setPincePostitionCallback(request, response) : void
setPinceCerisePostitionCallback(request, response) : void
viderBarilletCallback(request, response) : void
tournerBarilletCallback(request, response) : : void

# Raspberry Pi

Robot
+ Pose
+ move(float distance, bool forward) + rotate(float angle, bool clockWise) + goTo() + ouvrirPince() + FermerPince() + MonterPince() + DescendrePince()



