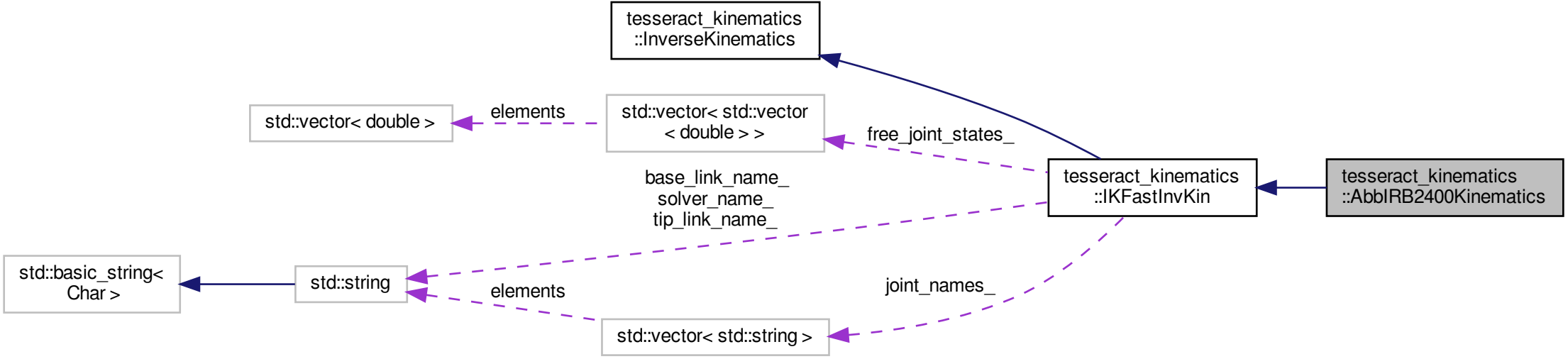
tesseract_kinematics
::InverseKinematics
std::vector< double >
elements
std::vector< std::vector
< double > >
free_joint_states_
tesseract_kinematics
::IKFastInvKin
tesseract_kinematics
::AbbIRB2400Kinematics
base_link_name_
solver_name_
tip_link_name_
std::basic_string<
Char >
std::string
elements
joint_names_
std::vector< std::string >