

crl::loco::LocomotionTrajectory
Planner::getTargetTrunkAngularVelocityAtTime



```
graph LR; A[crl::loco::LocomotionTrajectoryPlanner::getTargetTrunkAngularVelocityAtTime] --> B[crl::loco::estimateAngularVelocity];
```

The diagram consists of two rectangular boxes connected by a blue arrow pointing from left to right. The left box is white with a black border and contains two lines of text: 'crl::loco::LocomotionTrajectory' and 'Planner::getTargetTrunkAngularVelocityAtTime'. The right box is gray with a black border and contains two lines of text: 'crl::loco::estimateAngular' and 'Velocity'.

crl::loco::estimateAngular
Velocity