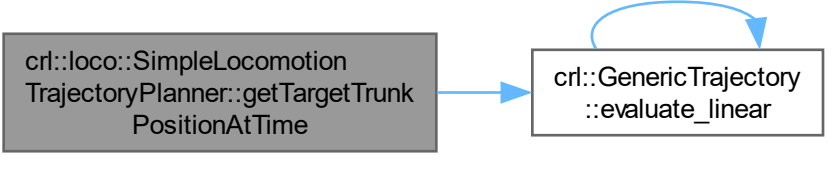
crl::loco::SimpleLocomotion
TrajectoryPlanner::getTargetTrunk
PositionAtTime
crl::GenericTrajectory
::evaluate_linear