

crl::loco::GeneralizedCoordinates  
RobotRepresentation::getQAndQDotFrom  
ReducedState

crl::loco::GeneralizedCoordinates  
RobotRepresentation::getQFromReducedState

crl::loco::GeneralizedCoordinates  
RobotRepresentation::integrateGenerlized  
AccelerationsForwardInTime

crl::loco::GeneralizedCoordinates  
RobotRepresentation::setQDot

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graph LR; A["crl::loco::GeneralizedCoordinates<br/>RobotRepresentation::getQAndQDotFrom<br/>ReducedState"] --> D["crl::loco::GeneralizedCoordinates<br/>RobotRepresentation::setQDot"]; B["crl::loco::GeneralizedCoordinates<br/>RobotRepresentation::getQFromReducedState"] --> D; C["crl::loco::GeneralizedCoordinates<br/>RobotRepresentation::integrateGenerlized<br/>AccelerationsForwardInTime"] --> D;
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