

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

crl::loco::GeneralizedCoordinates
RobotRepresentation::getQFromReducedState

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

crl::loco::IK_Solver
::solve

crl::loco::GeneralizedCoordinates
RobotRepresentation::setQ

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graph LR; A[crl::loco::GeneralizedCoordinates  
RobotRepresentation::getQAndQDotFrom  
ReducedState] --> D[crl::loco::GeneralizedCoordinates  
RobotRepresentation::setQ]; B[crl::loco::GeneralizedCoordinates  
RobotRepresentation::getQFromReducedState] --> D; C[crl::loco::GeneralizedCoordinates  
RobotRepresentation::integrateGenerlized  
AccelerationsForwardInTime] --> D; E[crl::loco::IK_Solver  
::solve] --> D;
```