

crl::loco::bFrameReference
MotionPlan::generateTrajectory

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graph LR; A["crl::loco::bFrameReference  
MotionPlan::generateTrajectory"] --> B["crl::loco::bFrameReference  
MotionPlan::getInitialConditions  
FromCurrentTrunkState"]; B --> C["crl::loco::bFrameReference  
MotionPlan::getBFrameStateFrom  
RBState"]
```

crl::loco::bFrameReference
MotionPlan::getInitialConditions
FromCurrentTrunkState

crl::loco::bFrameReference
MotionPlan::getBFrameStateFrom
RBState