gidBodyDynCJacobians(out M: matrix, out c_qv: vector, out Jc: matrix, out djcdq: vector, obj)
gidBodyDynCJacobians(out M: matrix, out c_qv: vector, out Jc: matrix, out djcdq: vector, obj, idx_list: vector)

-rigidBodyDyn(out M: matrix, out c_qv: vector)
-rigidBodyDyn(out M: matrix, out c_qv: vector, wf_R_b_arr: vector, wf_p_b: vector, q_i: vector, d_i: vector, v_b: vector)

ngideodyDynCJacobians(out M: matrix, out c_qv: vector, out Jc: matrix, out djcdq: vector, obj. ix_list vector, wf_p_b: vector, d_j: vector, d_j: vector, v_b: vector)
rigidBodyDynCJacobians(out M: matrix, out c_qv: vector, out Jc: matrix, out djcdq: vector, obj. wf_R_b_arr: vector, wf_p_b: vector, d_j: vector, d_j: vector, v_b: vector)
rigidBodyDynCJacobians(out M: matrix, out c_qv: vector, out Jc: matrix, out djcdq: vector, obj. wf_R_b_arr: vector, wf_p_b: vector, d_j: vector, d_j: vector, v_b: vector, idx_list: vector)