-rigidBodyDynCJacobians(out M: matrix, out c_qv: vector, out Jc: matrix, out djcdq: vector, obj)

-rigidBodyDyn(out M: matrix, out c_qv: vector)

rigidBodyDynCJacobians(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, wf_R_b_arr: vector, wf_p_b: vector, q_j: vector, dq_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, q_j: vector, dq_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, q_j: vector, dq_j: vector, v_b: vector, idx_list: vector)

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