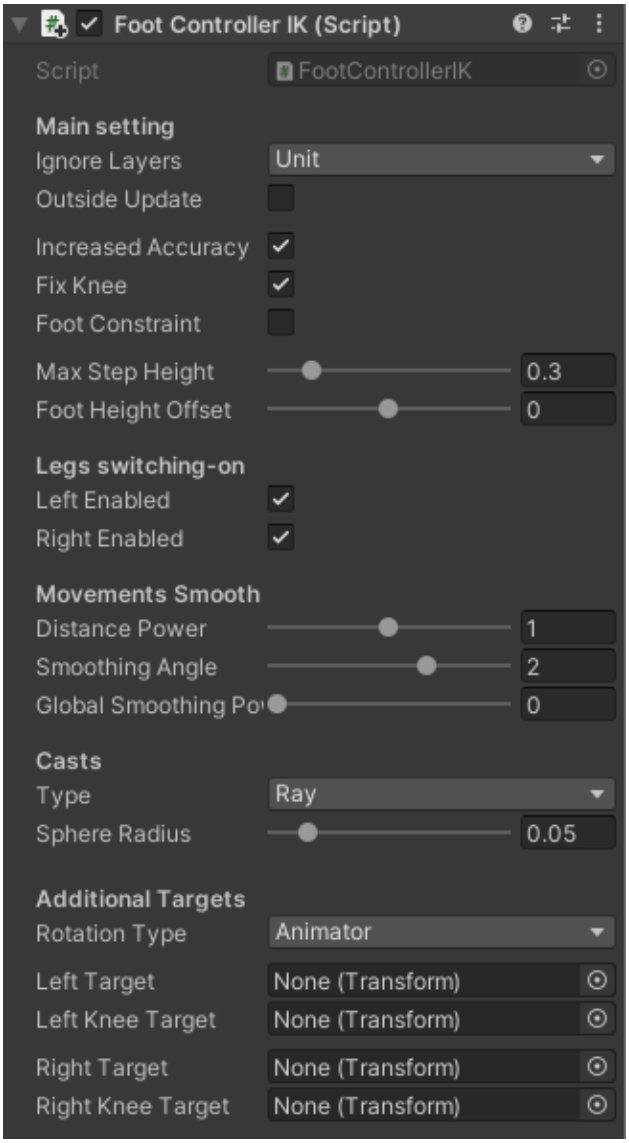

Requirements:
Animation Type must be Humanoid
Do not use «Optimaze Game Object»

How to use:
Add component «FootControllerIK» to GameObject.

Ropofoo has two ways of use:

1. Foots placement on any surface calculated with IK system.
2. Target IK system for foots and knees.

Approaches can be combined.

Rotation and position of foots and knees are calculated at the runtime. Smooth movements when it is needed.

No special settings or animation curves required.

Change settings parameters to fine-tune character movement behavior.

Ignore Layers	Selected layers will be avoided by «FootControllerIK» calculating legs position and rotation. Recommendation: select character layer.
Outside Update	Setting "true" will disable component. Invoke FIKA.FootIK() in outside LateUpdate to run component.
Increased Accuracy	Setting "true" will enable addition raycast from toes' bones for better foot positioning. Toes' bones are required for proper work.
Fix Knee	Use to avoid unnatural knees bending.
Foot Constraint	Use to avoid wide angles of foot rotation on surface.
Max Step Height	Max height on which character can step up.
Foot Height Offset	Offset of foot position on surface.
Left Enabled	Enable left foot inverse kinematics.
Right Enabled	Enable right foot inverse kinematics.
Distance Power	Distance of current movement used for foot position smoothing. Zero value will disable smoothing.
Smoothing Angle	Angle used for foot rotation smoothing. Zero value disables smoothing.
Global Smoothing Power	Global smoothing power. Zero value disables smoothing.
Type (CastType)	Current type of the cast which is used to check surface under the character. Ray – raycast is used; Sphere – spherecast is used; RayAndSphere – if ray do not hit then spherecast will be used.
Sphere Radius	Radius for Spherecast.

Rotation Type	Current type of foot rotation. Target is required for proper work. RawTarget – set target rotation to foot; AddTarget – target rotation will be added to foot rotation; Direction – foot normal will look at hips; Animator – foot will be rotated by animator.
Left Target	Target for left foot inverse kinematics.
Left Knee Target	Target for left knee inverse kinematics. Creates new plane for left leg rotation.
Right Target	Target for right foot inverse kinematics.
Right Knee Target	Target for right knee inverse kinematics. Creates new plane for right leg rotation.