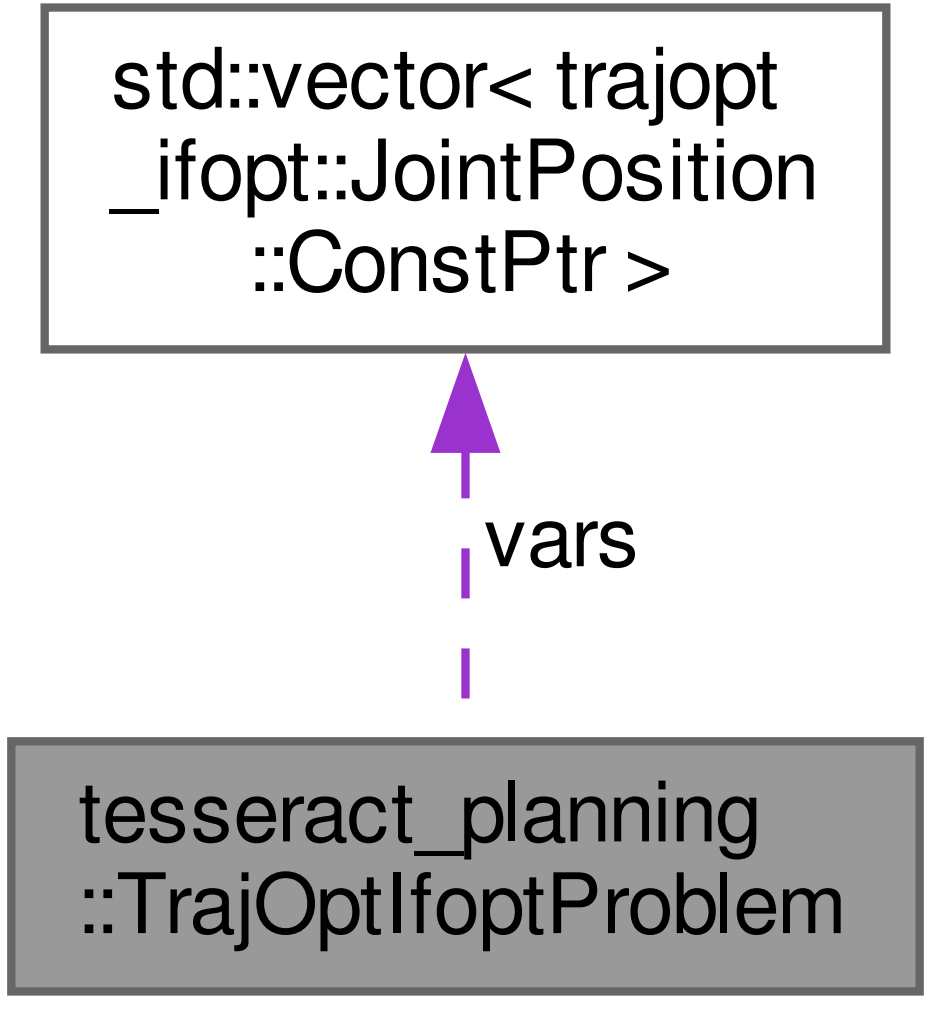
std::vector< trajopt
_ifopt::JointPosition
::ConstPtr >
vars
tesseract_planning
::TrajOptIfoptProblem