RigidBody

+position: vec3
+orientation: quat
+scale: vec3
+mass: float
+invMass: float
+isStatic: bool
+isAwake: bool
+transform: mat4
+frictionCoef: float
+restitutionCoef: float
-linVelocity: vec3
-angVelocity: vec3
-linAcceleration: vec3
-angAcceleration: vec3
-lastFrameAcceleration: vec3
-forceAccumulator: vec3
-torqueAccumulator: vec3
-motion: float
-linDamping: float
-angDamping: float
-inertiaTensor: mat3
-invInertiaTensorWorld: mat3

+RigidBody(in position:vec3,in scale:vec3,in orientation:quat)
+updateTransformMatrix(): void
+updateInvInertiaTensorWorld(): void
+setMass(in mass:float,in isInverse:bool=false): void
+setInertiaTensor(in inertiaTensor:mat3): void
+clearAccumulators(): void
+resetMovement(): void
+integrate(in deltaTime:float): void
+applyForce(in force:vec3): void
+applyForceAtWorldPoint(in force:rigid3,in point:vec3,): void
+applyForceAtLocalPoint(in force:vec3,in point:vec3): void
+applyTorqueAtLocalPoint(in torque:vec3,in point:vec3): void
+applyLinearImpulse(in impulse:vec3): void
+toString(): string