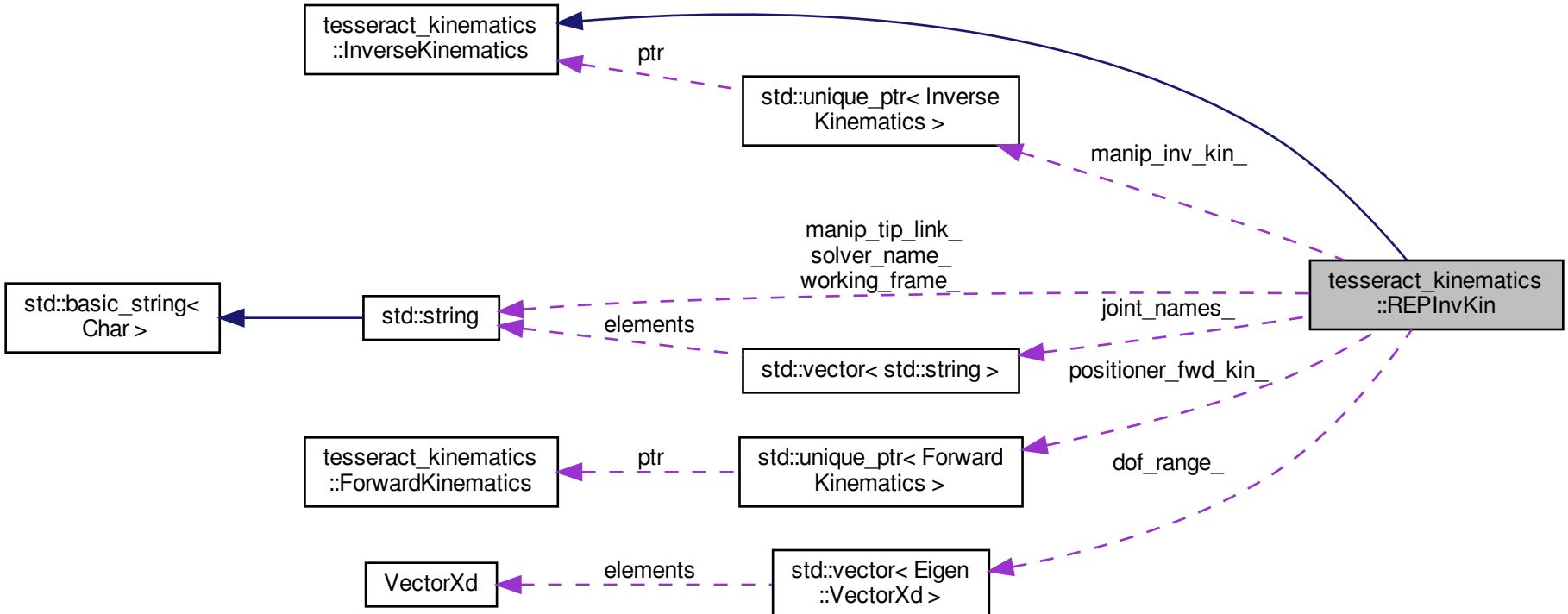
tesseract_kinematics
::InverseKinematics
ptr
std::unique_ptr< Inverse
Kinematics >
manip_inv_kin_
manip_tip_link_
solver_name_
working_frame_
tesseract_kinematics
::REPInvKin
std::basic_string<
Char >
std::string
elements
joint_names_
std::vector< std::string >
positioner_fwd_kin_
tesseract_kinematics
::ForwardKinematics
ptr
std::unique_ptr< Forward
Kinematics >
dof_range_
VectorXd
elements
std::vector< Eigen
::VectorXd >