Symbol	Name	Class Name	Typedef	Base Class
$\mathbf{q} \in \mathbb{R}^{DOF}$	Joint Position	`JointPosition`	`JPos`	`VectorDof`
$\dot{\mathbf{q}} \in \mathbb{R}^{DOF}$	Joint Velocity	`JointVelocity`	`JVel`	`VectorDof`
$\ddot{\mathbf{q}} \in \mathbb{R}^{DOF}$	Joint Acceleration	`JointAcceleration`	`JAcc`	`VectorDof`
$\boldsymbol{\tau}_\mathrm{q} \in \mathbb{R}^{DOF}$	Joint Effort	`JointEffort`	`JTorque`	`VectorDof`
$\mathbf{x} \in \mathbb{R}^3$	Linear Position	`LinearPosition`	`LPos`	`Vector3`
$\dot{\mathbf{x}} \in \mathbb{R}^3$	Linear Velocity	`LinearVelocity`	`LVel`	`Vector3`
$\ddot{\mathbf{x}} \in \mathbb{R}^3$	Linear Acceleration	`LinearAcceleration`	`LAcc`	`Vector3`
$\mathbf{Q} \in \mathbb{H}$	Angular Position	`AngularPosition`	`APos`	`Quaternion`
$\boldsymbol{\omega} \in \mathbb{R}^3$	Angular Velocity	`AngularVelocity`	`AVel`	`Vector3`
$\boldsymbol{\alpha} = \dot{\boldsymbol{\omega}} \in \mathbb{R}^3$	Angular Acceleration	`AngularAcceleration`	`AAcc`	`Vector3`
$\mathbf{X} = [\mathbf{x}, \mathbf{Q}] \in \mathbb{R}^7$	Cartesian Position	`CartesianPosition`	`CPos`	`Vector7`
$\dot{\mathbf{X}} = [\dot{\mathbf{x}}, \boldsymbol{\omega}] \in \mathbb{R}^6$	Cartesian Velocity	`CartesianVelocity`	`CVel`	`Vector6`
$\ddot{\mathbf{X}} = [\ddot{\mathbf{x}}, \boldsymbol{\alpha}] \in \mathbb{R}^6$	Cartesian Acceleration	`CartesianAcceleration`	`CAcc`	`Vector6`
$\mathbf{T} \in \mathbb{R}^{4\times4}$	Homogeneous Transformation	`HomogeneousTransformation`	`HTf`	`Transform3`
$\mathbf{f} \in \mathbb{R}^3$	Force	`Force`	`Force`	`Vector3`
$\boldsymbol{\mu} \in \mathbb{R}^3$	Moment	`Moment`	`Moment`	`Vector3`
$\mathbf{W} = [\mathbf{f}, \boldsymbol{\mu}] \in \mathbb{R}^6$	Wrench	`Wrench`	`Wrench`	`Vector6`
$\mathbf{FT} = \mathbf{W} = [\mathbf{f}, \boldsymbol{\mu}] \in \mathbb{R}^6$	Force Torque Sensor	`ForceTorqueSensor`	`FTSensor`	`Wrench`
$\mathbf{IMU} = [\ddot{\mathbf{x}}, \mathbf{Q}, \boldsymbol{\omega}]$	Inertial Measurement Unit Sensor	`ImuSensor`	`ImuSensor`	`[LAcc, APos, AVel]`
$\mathbf{p} \in \mathbb{R}^3$	Zero Moment Point (ZMP)	`ZeroMomentPoint`	`Zmp`	`LinearPosition`
$\dot{\mathbf{p}} \in \mathbb{R}^3$	ZMP Velocity	`ZeroMomentPointP`	`ZmpP`	`LinearVelocity`
$\ddot{\mathbf{p}} \in \mathbb{R}^3$	ZMP Acceleration	`ZeroMomentPointPP`	`ZmpPP`	`LinearAcceleration`
$\boldsymbol{\zeta} \in \mathbb{R}^3$	Divergent Component of Motion (DCM)	`DivergentComponentOfMotion`	`Dcm`	`LinearPosition`
$\dot{\boldsymbol{\zeta}} \in \mathbb{R}^3$	DCM Velocity	`DivergentComponentOfMotionP`	`DcmPP`	`LinearVelocity`
$\ddot{\boldsymbol{\zeta}} \in \mathbb{R}^3$	DCM Acceleration	`DivergentComponentOfMotionPP`	`DcmPP`	`LinearAcceleration`
$\mathbf{r}_i \in \mathbb{R}^3$	Virtual Repellent Point (VRP)	`VirtualRepellentPoint`	`Vrp`	`LinearPosition`
$\boldsymbol{\zeta}_i \in \mathbb{R}^3$	DCM way point (DCMWP)	`DcmWayPoint`	`DcmWp`	`LinearPosition`
$\boldsymbol{\zeta}_{\mathrm{DS,ini},i} \in \mathbb{R}^3$	Initial double support way point for the DCM	`DcmDoubleSupportInitialWayPoint`	`DcmDsIWp`	`LinearPosition`
$\boldsymbol{\zeta}_{\mathrm{DS,final},i} \in \mathbb{R}^3$	Final double support way point for the DCM	`DcmDoubleSupportFinalWayPoint`	`DcmDsFWp`	`LinearPosition`
$\dot{\boldsymbol{\zeta}}_{\mathrm{DS,ini},i} \in \mathbb{R}^3$	Velocity of the initial double support way point for the DCM	`DcmDoubleSupportInitialWayPointP`	`DcmDsIWpP`	`LinearVelocity`
$\dot{\boldsymbol{\zeta}}_{\mathrm{DS,final},i} \in \mathbb{R}^3$	Velocity of the final double support way point for the DCM	`DcmDoubleSupportFinalWayPointP`	`DcmDsFWpP`	`LinearVelocity`
$\mathbf{DCMPS} = \left[\mathbf{r}_i, \boldsymbol{\zeta}_i, \boldsymbol{\zeta}_{\mathrm{DS,ini},i}, \boldsymbol{\zeta}_{\mathrm{DS,final},i}, \dot{\boldsymbol{\zeta}}_{\mathrm{DS,ini},i} \dot{\boldsymbol{\zeta}}_{\mathrm{DS,final},i}\right]$	DCM Point Set	`DcmPointSet`	`DcmPs`	`[Vrp, DcmWp, DcmDsIWp, DcmDsFWp, DcmDsIWpP, DcmDsFWpP]`
$\mathbf{X}_{\mathrm{FS},i} \in \mathbb{R}^7$	Foot Step Cartesian Position	`FootStepCartesianPosition`	`FsCPos`	`CartesianPosition`
$l_i \in \{\mathrm{L, R}\}$	Leg Identifier (Left/Right leg)	`FootStepLegIdentifier`	`FsLId`	`LegIdentifier`
$s_i \in \{0, 1\}$	Foot Step End Flag	`FootStepEndFlag`	`FsEndF`	`bool`
$n_i \in \mathbb{R}_0^+$	Foot Step Number	`FootStepNumber`	`FsNum`	`unsigned int`
$\mathbf{FS} = \left[\mathbf{X}_{\mathrm{FS},i}, l_i, s_i, n_i\right]$	Foot Step	`FootStep`	`Fs`	`[FSCPos, FsLId, FsEndF, FsNum]`