

robot world goal target joint_variables constraint

the_desired_motion_direction
time_variable
velocity_v
cartisian_chain
threshold_model
pose_1
pose_dmp
int_o
feature_variable
object_classes
acc_a
the_element_of_zernike_moments
the_maimum_force
hmm
object
repression_graph
pddl_definition
velocity
the_approaching_position
and_optionally_the_desired_motion_distance
object_pose_est_and_place_pose