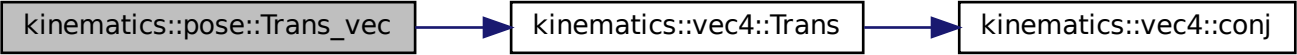


kinematics::pose::Trans_vec



```
graph LR; A[kinematics::pose::Trans_vec] --> B[kinematics::vec4::Trans]; B --> C[kinematics::vec4::conj];
```

kinematics::vec4::Trans

kinematics::vec4::conj