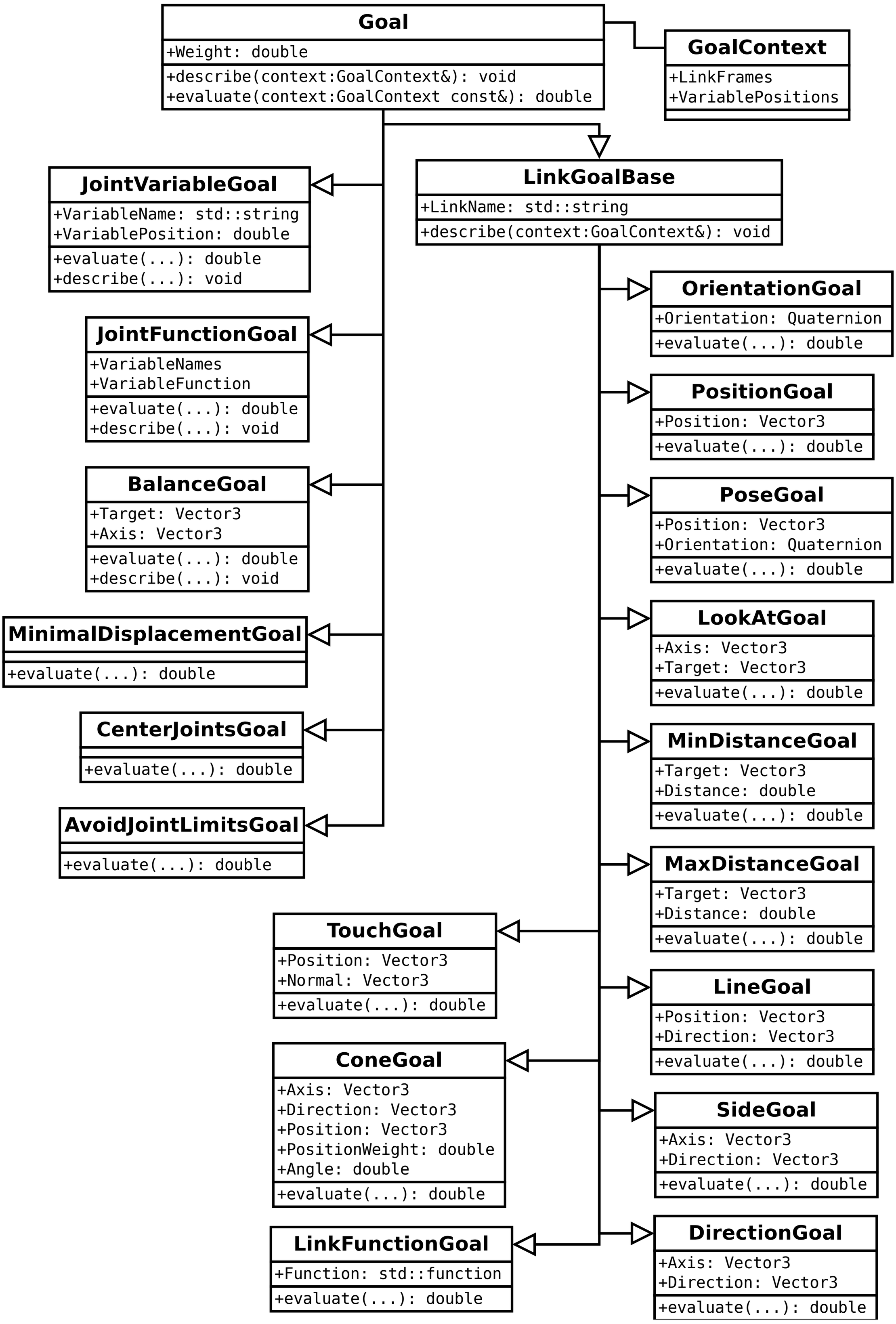
Goal
+Weight: double
+describe(context:GoalContext&): void
+evaluate(context:GoalContext const&): double
GoalContext
+LinkFrames
+VariablePositions
JointVariableGoal
+VariableName: std::string
+VariablePosition: double
+evaluate(...): double
+describe(...): void
LinkGoalBase
+LinkName: std::string
+describe(context:GoalContext&): void
JointFunctionGoal
+VariableNames
+VariableFunction
+evaluate(...): double
+describe(...): void
BalanceGoal
+Target: Vector3
+Axis: Vector3
+evaluate(...): double
+describe(...): void
MinimalDisplacementGoal
+evaluate(...): double
CenterJointsGoal
+evaluate(...): double
AvoidJointLimitsGoal
+evaluate(...): double
TouchGoal
+Position: Vector3
+Normal: Vector3
+evaluate(...): double
ConeGoal
+Axis: Vector3
+Direction: Vector3
+Position: Vector3
+PositionWeight: double
+Angle: double
+evaluate(...): double
LinkFunctionGoal
+Function: std::function
+evaluate(...): double
OrientationGoal
+Orientation: Quaternion
+evaluate(...): double
PositionGoal
+Position: Vector3
+evaluate(...): double
PoseGoal
+Position: Vector3
+Orientation: Quaternion
+evaluate(...): double
LookAtGoal
+Axis: Vector3
+Target: Vector3
+evaluate(...): double
MinDistanceGoal
+Target: Vector3
+Distance: double
+evaluate(...): double
MaxDistanceGoal
+Target: Vector3
+Distance: double
+evaluate(...): double
LineGoal
+Position: Vector3
+Direction: Vector3
+evaluate(...): double
SideGoal
+Axis: Vector3
+Direction: Vector3
+evaluate(...): double
DirectionGoal
+Axis: Vector3
+Direction: Vector3
+evaluate(...): double