机器人模型接口

/\*forward kinematics

\* serialLinkName: model name

\* r7kine: result

\*

\* return 0:right; other: wrong

\* \*/

**int** **Kine\_Forward**(**char**\* serialLinkName, R7\_KINE\* r7kine);

/\*inverse kinematics

\* serialLinkName: model name

\* r7kine: result

\*

\* return 0:right; other: wrong

\* \*/

**int** **Kine\_Inverse**(**char**\* serialLinkName, R7\_KINE\* r7kine);