createConfigStateCL(out clnk_conf: struct, obj, cstate: logical[2], clink_l: string, clink_r: string, q_j: vector, rtype: string = "eul")

-setTrajectoryDPts(out lnk traj: wbmLinkTrajectory, obj, lnk traj: wbmLinkTrajectory, vqT b: matrix, q j: matrix, nSteps: integer)

visualizeSimRobot(obj, stmPos: matrix, sim_config: wbmSimConfig, sim_tstep: double, vis_ctrl: struct)

setPayloadLinkData(obj, pl_idx: integer, pl_lnk: struct)

-createConfigStateCL(out clnk_conf: struct, obj, cstate: logical[2], clink_l: string, clink_r: string, q_j: vector, k_p: double, rtype: string = "eul")
-createConfigStateCL(out clnk_conf: struct, obj, cstate: logical[2], clink_l: string, clink_r: string, q_j: vector, k_p: double, k_v: double, rtype: string = "eul")
-createConfigStateCL(out clnk_conf: struct, obj, cstate: logical[2], clink_l: string, clink_r: string, veT_lnk: matrix, k_p: double, k_v: double, rtype: string = "eul")
-createConfigStateCL(out clnk_conf: struct, obj, cstate: logical[2], clink_l: string, clink_r: string, vqT_lnk: matrix, k_p: double, k_v: double, rtype: string = "eul")