-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")

 $-visualize SimRobot (obj, stmPos: matrix, sim\_config: wbmSimConfig, sim\_tstep: double, vis\_ctrl: struct) \\$ 

-setTrajectoryDPts(out lnk\_traj: wbmLinkTrajectory, obj, lnk\_traj: wbmLinkTrajectory, vqT\_b: matrix, q\_j: matrix, nSteps: integer)

setPayloadLinkData(obj, pl\_idx: integer, pl\_lnk: struct)