createConfigStateCL(out clink_conf: struct, obj, cstate: logical[2], clink_l: string, clink_r: string, vqT_lnk: matrix, k_p: double, k_v: double, rtype: string = "eul")
visualizeSimRobot(obj, pos_out: matrix, sim_config: wbmSimConfig, sim_tstep: double, vis_ctrl: struct)

«use»