+getBaseVelocities(out v b: vector, obi, stChi: vector)

+getBaseVelocities(out v_b: matrix, obj, stChi: matrix)
+get.stvChilnit(out stvChi: vector, obj)

+dispConfig(obj, prec: integer)
-initConfig(obj, robot_config: wbmBaseRobotConfig)

+get.robot_body(out robot_body: wbmBody, obj)
+get.robot_config(out robot_config: wbmBaseRobotConfig, obj)

+get.robot_params(out robot_params: wbmBaseRobotParams, obj)
+set.init_state(obj, stInit: wbmStateParams)
+get.init_state(out stInit: wbmStateParams, obj)

-getLinkName(out lnk_name: string, obj, lnk_list: vector, idx: integer)

-getJointValues(out int_q: vector, out int_q: vector, obj, q_j: vector, dq_j: vector, joint_idx: integer[1..*], len: integer) -checkInitStateDimensions(out result: logical, obj, stInit: wbmStateParams)

+get.styLen(out styLen; integer, obi)

+get.vqTInit(out vqT_b: vector, obj)

+get.stvgT(out vgT b: vector, obi)

+joints.name: string[1..*] {readOnly}

+getChainTable(out chn_tbl: table, obj) +getJointTable(out jnt_tbl: table, obj)

+getChainIndices(out jnt idx: vector, obj, chain name: string)

+getJointIndex(out jnt_idx: integer, obj, joint_name: string)
+getJointNames(out jnt_names: string[1..*], obj, joint_idx: vector)

 $+ wbmBody(out\ obj:\ wbmBody,\ chain_names:\ string[1..^*],\ chain_idx:\ matrix,\ joint_names:\ string[1..^*],\ joint_idx:\ vector)$

+nJoints: integer {readOnly}