eateConfigStateCL(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")

«use»

visualizeSimRobot(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)