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

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

-setTrajectoryDPts(oùt lnk_raj: wbmLinkTrajectory, obj, lnk_traj: wbmLinkTrajectory, vqT_b: matrix, q_j: matrix, nSteps: integer)

-setPavloadLinkData(obi, pl_idx; integer, pl_lnk; struct)