

object



aml_robot.baxter_kinematics.baxter_kinematics

- + __init__()
- + print_robot_description()
- + print_kdl_chain()
- + joints_to_kdl()
- + kdl_to_mat()
- + forward_position_kinematics()
- + forward_velocity_kinematics()
- + inverse_kinematics()
- + jacobian()
- + jacobian_transpose()
- + jacobian_pseudo_inverse()
- + inertia()
- + cart_inertia()