```
aml robot.mujoco.mujoco
    robot.MujocoRobot
  init ()
+ set sampling rate()
+ robot state set start
end index()
+ get ee pose()
+ get_compensation_forces()
+ get ee velocity()
+ reset model()
+ untuck arm()
+ set qpos()
+ set qvel()
+ set_qacc()
+ inv dyn()
```

+ exec\_torque\_cmd()
+ exec\_position\_cmd()
+ exec position cmd delta()