**aml_ctrl.controllers.os
_controllers.os_moveit
_baxter_controller.BaxterMoveIt
Controller**

+ robot
+ scene
+ left_group_configured
+ right_group_configured
+ both_group_configured
+ display_trajectory
_publisher
+ group_left_arm
+ group_right_arm
+ group_both_arms

+ __init__()
+ add_static_objects
_to_scene()
+ set_group_handles()
+ set_tolerance()
+ get_group_handle()
+ get_plan()
+ execute_plan()
+ clear_pose_targets()
+ clean_shutdown()
+ plan_both_arms()
+ self_test()