```
baxter interface::limb
              ::Limb
aml robot.baxter robot.BaxterArm
+ q_mean
   init
        ()
+ cuff cb()
+ get lfd status()
+ set_sampling_rate()
+ tuck arm()
+ untuck arm()
+ angles()
+ get_end_effector_link_name()
+ get base link name()
+ exec_position_cmd()
+ exec_position_cmd delta()
+ move to joint pos delta()
+ move_to_joint_pos()
+ exec velocity cmd()
+ exec_torque_cmd()
+ move_to_joint_position()
+ get ee pose()
+ get time in seconds()
+ get ee velocity()
+ get cartesian pos from
ioints()
+ get cartesian vel from
joints()
+ get_jacobian_from_joints()
+ get arm inertia()
+ ik()
```