

«Interface»



motor\_control.h



+ open\_port()



+ close\_port()



+ enable\_torque()



+ disable\_torque()



+ set\_goal\_position()



+ set\_goal\_speed()



+ read\_current\_position()



+ read\_current\_speed()



+ read\_load()



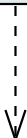
+ read\_error()



+ read\_temperature()



+ read\_supply\_voltage()



«Interface»



dynamixel\_sdk.h