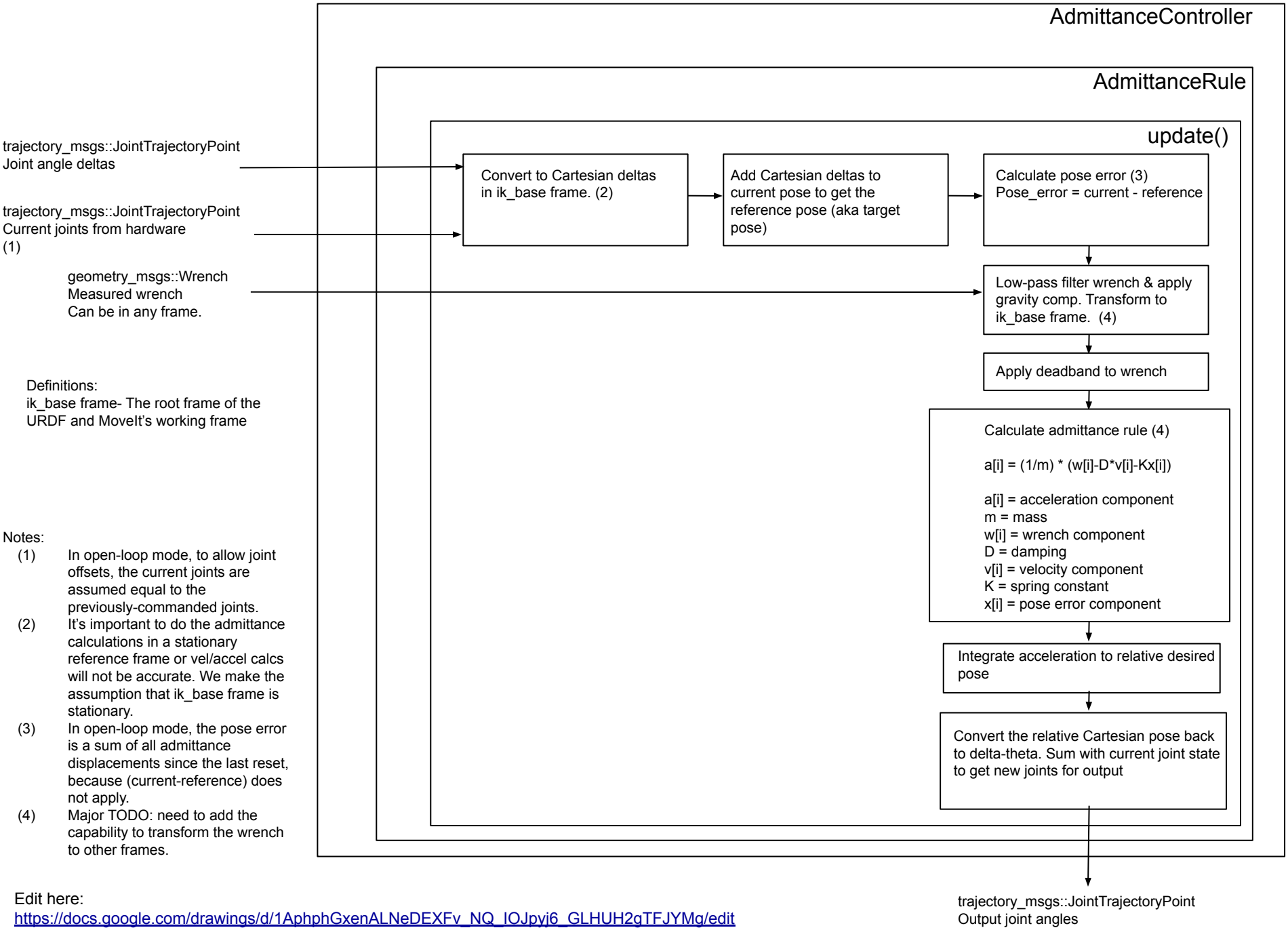

Definitions:
ik_base frame- The root frame of the URDF and MoveIt's working frame

Notes:

(1) In open-loop mode, to allow joint offsets, the current joints are assumed equal to the previously-commanded joints.

(2) It's important to do the admittance calculations in a stationary reference frame or vel/accel calcs will not be accurate. We make the assumption that ik_base frame is stationary.

(3) In open-loop mode, the pose error is a sum of all admittance displacements since the last reset, because (current-reference) does not apply.

(4) Major TODO: need to add the capability to transform the wrench to other frames.

Edit here:
https://docs.google.com/drawings/d/1AphphGxenALNeDEXFv_NQ_IOJpyj6_GLHUH2gTFJYMg/edit