Coordinate control

```
send_coord

description: set the coordinates of the joints of a single robot arm
parameters:
1.robot arm joint: id(1-6)
2.coordinate
3.the speed at which the robot arm executes running, (0-100)
returned value: none
```

```
send_coords

description: set the coordinates of the joints of the robot arm
parameters:
1. list: Including the list of coordinates and postures, and having a length of
6, which are [x, y, z, rx, ry, rz] successively
2. speed 0-100(int type)
2. mode 0 or 1
returned value: none
```