Use **mm** , **s**, **N**, and **radian** as data units

Driver of Arms:

* Basic function:
  + moveJ(joint, v, a,solve\_space = ’J’): joint (6 or 7 dimension) ,an array
  + moveP(position, v, a, solve\_space = ’L’): position (6 dimension), an array (‘sxyz’, x,y,z,r,p,y)
  + getState(): return joint and position
  + verifyState(name, target, error = 0.2): whether the arm reaches the goal status.
* extern function:
  + more data return
  + continue waypoint control
  + setIO(name, value)
  + movePs
  + …

Driver of Cameras:

* Basic function:
  + getFrame(): return frame, and Class frame contains color, depth, Infrared, point cloud. And color, depth, Infrared, and point cloud also are list.
  + getIntrinsicParameters(): return internal parameters of the camera, a list (fx,fy,cx,cy,d), and d is a list (k1,k2,p1,p2,k3) for radial distortion, centrifugal distortion and thin lens distortion.
* extern function:
  + setParameters(): set exposure, color temperature .etc.
  + …

Driver of Gripper:

* Basic function:
  + switch(open=True): open or close the gripper
* extern function:
  + getDistance(): return the distance between 2 finger
  + getForce(): return the Clamping force
  + setDistance(): open or close, set the distance between 2 finger
  + setVelocity(): open or close, set the Velocity
  + setForce(): close, set the Clamping force
  + …

Driver of ForceSensor:

* Basic function:
  + getStatus(): return 6 axes Force and Torque
* extern function:
  + ***to be added***