youbot_Arm
+ youbot_Arm()
+ set_armPosition(obj, position)
+ set_armVelocity(obj, velocitiy)
+ set_armTorques(obj, torques)
+ get_armDaten()
+ setPID_secSpeed(joint, p, i, d, i_clip)
+ setPID_secPos(joint, p, i ,d,i_clip)
+ setPID_firstPos(joint, p,i,d,i_clip)
+ setPID_firstSpeed(joint,p,i,d,i_clip)
+ setPID_current(joint,p,i,d,i_clip)
+ getPIDParam()
+ call_Calibarate()
+ call_SwitchOnMotors()
+ call_SwitchOffMotors()
+ stopArm()
+ stowArm()
+ centerArm()