

youbot_Arm

- positionPub: Sting
- velocityPub: Sting
- torquesPub: String

- + youbot_Arm()
- + set_armPosition(obj, position)
- + set_armVelocity(obj, velocity)
- + 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()