```
baxter interface::limb
              ··I imb
aml_robot.baxter_robot.BaxterArm
+ a mean
   init ()
+ tuck arm()
+ untuck arm()
+ angles()
+ get end effector link name()
+ get base link name()
+ exec_position_cmd()
+ exec_position_cmd2()
+ move to joint pos delta()
+ move to joint pos()
+ exec_velocity_cmd()
+ exec torque cmd()
+ move_to_joint_position()
+ get_ee_pose()
+ get ee velocity()
+ get cartesian pos from
ioints()
+ get cartesian vel from
ioints()
+ get jacobian from joints()
+ get arm inertia()
```