```
baxter interface::limb
              ::Limb
aml robot.baxter robot.BaxterArm
+ a mean
   init
+ cuff cb()
+ get lfd status()
+ set sampling rate()
+ tuck arm()
+ untuck arm()
+ angles()
+ get state()
+ get end effector link name()
+ get base link name()
+ exec position cmd()
+ exec position cmd delta()
+ move to joint pos delta()
+ move to joint pos()
+ exec velocity cmd()
+ exec torque cmd()
+ move to joint position()
+ get ee pose()
+ get time in seconds()
+ get ee velocity()
+ get cartesian pos from
joints()
+ get cartesian vel from
ioints()
+ get_jacobian from joints()
+ get arm inertia()
+ set gripper speed()
+ set arm speed()
+ ik()
```