

+ __init__()

+ cuff_cb()

+ tuck()

+ untuck()

+ angles()

+ state()

+ n_cmd()

+ n_joints()

+ ee_pose()

+ jacobian()

+ inertia()

+ ee_velocity()

+ q_mean()

+ get_lfd_status()

+ set_sampling_rate()

+ set_gripper_speed()

+ end_effector_link_name()

+ exec_position_cmd_delta()

+ move_to_joint_pos_delta()

+ move_to_joint_position()

+ set_arm_speed()

+ base_link_name()

+ exec_position_cmd()

+ exec_velocity_cmd()

+ exec_torque_cmd()

+ time_in_seconds()

+ forward_kinematics()

+ cartesian_velocity()

+ set_gripper_speed() + set arm speed()

+ inverse_kinematics()