

get_state.cpp

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Example usage:

```
#include "airbot_sdk.hpp"
using namespace airbot;

int main() {
    auto sdk = std::make_shared<AirbotSdk>("192.168.0.xxx", 50051);

    const auto joint_positions = sdk->GetJointPos();
    if (joint_positions.empty()) {
        sdk->GetLogger()->warn("GetJointPositions returned empty result");
    } else {
        sdk->GetLogger()->info("Joint Positions:");
        for (size_t i = 0; i < joint_positions.size(); ++i) {
            sdk->GetLogger()->info("  Joint {}: {}", i + 1, joint_positions[i]);
        }
    }

    const auto [position, orientation] = sdk->GetEndPose();
    if (position.empty() || orientation.empty()) {
        sdk->GetLogger()->warn("GetEndPose returned empty result");
    } else {
        sdk->GetLogger()->info("End Pose:");
        sdk->GetLogger()->info("  Position: [ {}, {}, {}]", position[0], position[1], position[2]);
        sdk->GetLogger()->info("  Orientation: [ {}, {}, {}, {}]", orientation[0], orientation[1], orientation[2], orientation[3]);
    }
    return 0;
}
```