

Control

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- offboard_control_mode_publishers_: std::vector<OffboardControlModePublisher>
- trajectory_setpoint_publishers_: std::vector<TrajectorySetpointPublisher>
- vehicle_command_publishers_: std::vector<VehicleCommandPublisher>
- vehicle_local_position_subscribers_: std::vector<VehicleLocalPositionSubscriber>
- timestamp_: std::atomic<uint64_t>
- offboard_setpoint_counter_: int
- timer_: rclcpp::TimerBase::SharedPtr
- num_drones_: int
- num_setpoints_: int
- offboard_arm_sent_: bool
- setpoints_: std::vector<std::vector<std::array<float, 4>>>
- setpoint_counter_: int
- local_positions_: std::vector<std::array<float, 3>>
- reached_setpoint_: std::vector<bool>

+ Control()
+ publish_offboard_control_mode(OffboardControlModePublisher): void
+ publish_trajectory_setpoint(TrajectorySetpointPublisher, float, float, float, float): void
+ arm(VehicleCommandPublisher): void
+ offboard_mode(VehicleCommandPublisher): void
+ publish_vehicle_command(VehicleCommandPublisher, uint16_t, float, float): void
+ publish_default_setpoints(): void
+ vehicle_local_position_callback(int, VehicleLocalPosition::SharedPtr): void
```