

aml_lfd.ilqr.ilqr_traj
_follow.DDP_TrajFollowClass

- + idx
- + H
- + target_traj
- + reward
- + cost
- + model
- + model_bias
- + magic_factors
- + num_states
- + num_ctrls
- + num_links
- + right_arm
- + A
- + B
- + Mq
- + Cq
- + Q
- + Qf
- + R
- + Rf
- + Alist
- + Blist
- + Qlist
- + Rlist
- + Klist
- + target_xlist
- + target_ulist
- + dxlist
- + xlist
- + ulist
- + vout

- + __init__()
- + configure()
- + compute_dx()
- + euler_to_q()
- + quat_multiply()
- + err_simulate()
- + compose_dx()
- + simulate_f()
- + quaternion_from_axis
_rotation()
- + express_vector_in_quat
_frame()
- + rotate_vector()
- + stack_state()
- + linearized_dynamics()
- + ddp_for_trajectory
_following()
- + lqr_backups_for_trajectory
_following()
- + lqr_run_controller
_in_nonlinear_sim()
- + score_lqr_trajectory()