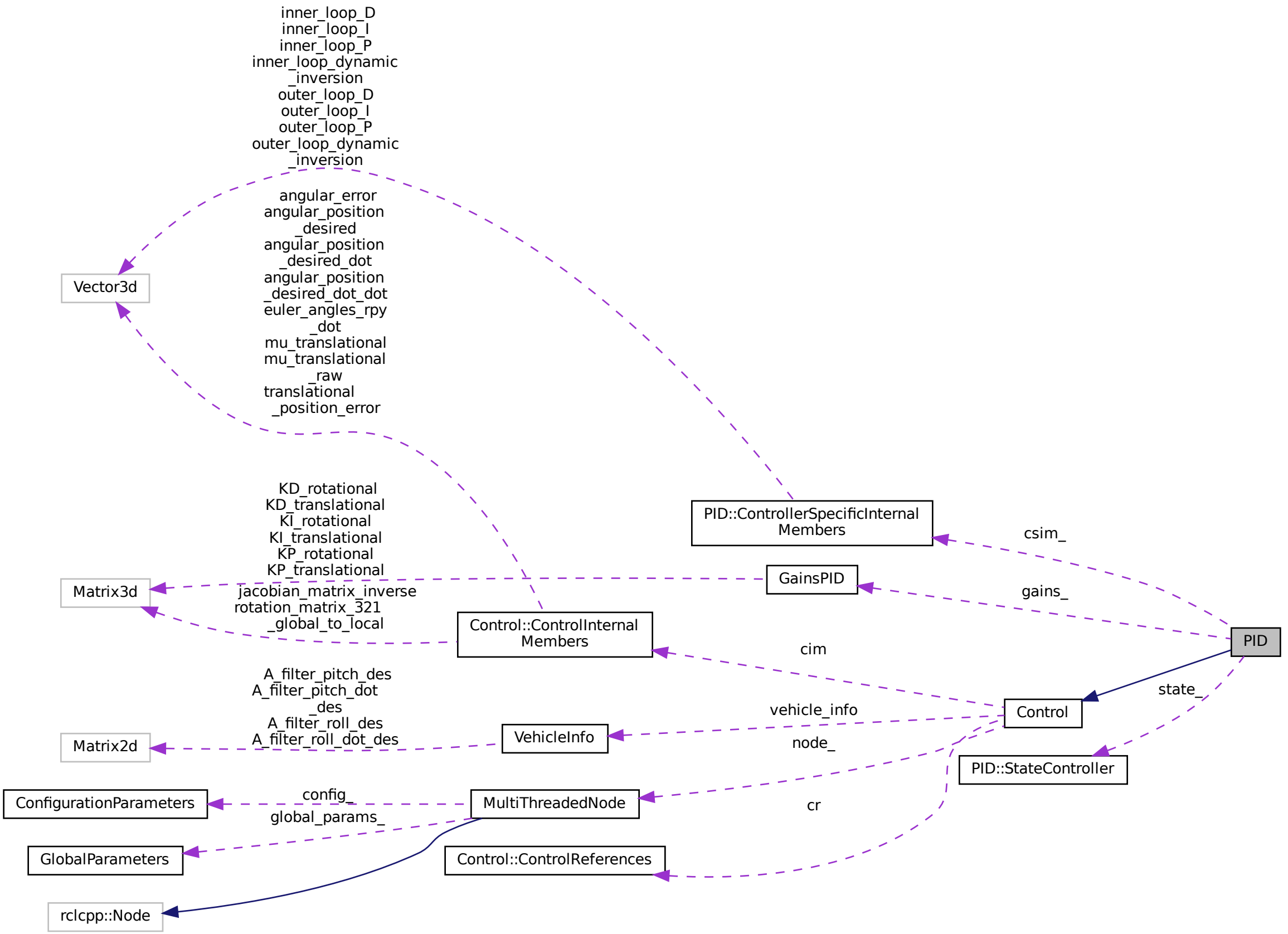
inner_loop_D
inner_loop_I
inner_loop_P
inner_loop_dynamic
_inversion
outer_loop_D
outer_loop_I
outer_loop_P
outer_loop_dynamic
_inversion
angular_error
angular_position
_desired
angular_position
_desired_dot
angular_position
_desired_dot_dot
euler_angles_rpy
_dot
mu_translational
mu_translational
_raw
translational
_position_error
Vector3d
KD_rotational
KD_translational
KI_rotational
KI_translational
KP_rotational
KP_translational
jacobian_matrix_inverse
rotation_matrix_321
_global_to_local
Matrix3d
PID::ControllerSpecificInternal
Members
csim_
GainsPID
gains_
Control::ControlInternal
Members
cim
PID
A_filter_pitch_des
A_filter_pitch_dot
_des
A_filter_roll_des
A_filter_roll_dot_des
Matrix2d
VehicleInfo
vehicle_info
node_
Control
state_
PID::StateController
ConfigurationParameters
config_
MultiThreadedNode
cr
global_params_
GlobalParameters
Control::ControlReferences
rclcpp::Node