ComputedTorqueControl -DynamicModel -KDL::Chain -PID Gains: struct +PID Controller: vector<> +computedTorqueControl(qd des,q m,qd m,error, velP, tauV:vector<double>): void **DynamicModel**

PID_Controller

-P, I, D Gains: double -previousError: double

-I: double

+control(in error:const double,inout controlVariable:double): void

-KDL::Wrenches

-KDL::ChainIdSolver RNE *

-KDL::Chain

+kdlInverseDynamicsSolver(in q,in qd,in qdd,

inout tau:KDL::JntArray): void
-createTransform(in gamma,beta,alpha:double,

in X,Y,Z:double): KDL::Frame