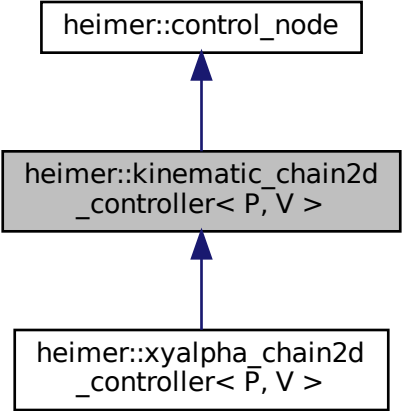


heimer::control_node



```
graph BT; A[heimer::xyalpha_chain2d_controller< P̄, V >] --> B[heimer::kinematic_chain2d_controller< P, V >]; B --> C[heimer::control_node];
```

heimer::kinematic_chain2d
_controller< P, V >

heimer::xyalpha_chain2d
_controller< \bar{P} , V >