aml_lfd.lqr.ddp_traj _follow_base.DDPTrajFollow

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

+ __init__()
+ configure()
+ compute_dx()
+ err_simulate()
+ compose_dx()
+ simulate_f()
+ linearized_dynamics()
+ ddp_for_trajectory _following()
+ lqr_backups_for_trajectory _following()
+ lqr_run_controller _in_nonlinear_sim()
+ score_lqr_trajectory()
+ get_real_state()