

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
+ 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()