

panda_traj

Trajectory
Generation

X^{traj}
 v^{traj}
 \dot{v}^{traj}

torque_qp

controller.cpp

Cartesian PID
Controller

\dot{v}^*

X^{curr}
 v^{curr}

Robot model

q, \dot{q}

Quadratic
Programming
based
computed torque

$J(q)$
 $M(q)$
...

τ^{opt}

if sim:=true

panda_simulation.cpp

Gazebo
Simulation

if sim:=false

panda_control.cpp

Real robot

