Position and Attitude Response of Model A.1 Compared to PID x_{ref} z_{ref} x_{RL} z_{RL} 15 2 x_{PID} z_{PID} x Position [m] z Position [m] RL model failed at 5.2 seconds. -2 y_{ref} -20 y_{RL} y_{PID} -252 8 10 2 8 10 2 10 75 75 ϕ_{RL} ψ_{RL} ϕ_{PID} $heta_{PID}$ ψ_{PID}) 50 50 50 ϕ Angle [degree] ψ Angle [degree] θ Angle [degree] 25 2525 -50-50-50-75-75-752 10 10 2 8 10 Time [s] Time [s] Time [s]