# CAMeLiD: Control Adaptation via Meta-Learning Dynamics

James Harrison*,[1], Apoorva Sharma*,[1],
Roberto Calandra[2], Marco Pavone[1]

Autonomous Systems Lab

We develop a Bayesian meta-learning model that is capable of **fast, efficient online updates** and is trained for multi-step probabilistic predictions.

Using this model, we build a control algorithm that captures online model uncertainty and **automatically trades off safety and performance**.
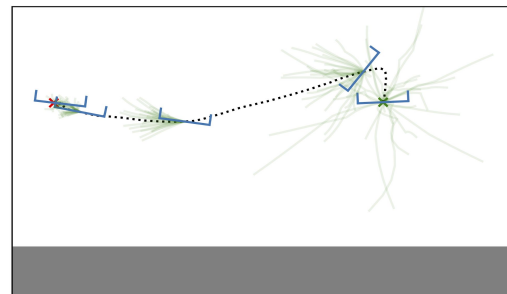
CAMeLiD controlling a quadrotor with a random attached mass. By incorporating model uncertainty into control, we successfully stabilize.

Point estimate meta-learning-based control algorithm results in the quadrotor crashing.

[1]Stanford University, [2]UC Berkeley

{jharrison,apoorva,pavone}@stanford.edu, roberto.calandra@berkeley.edu