

Guidance loop

${}_{\mathcal{N}}\hat{S}, {}_{\mathcal{G}}\hat{P}, \varepsilon_p, X_i, X_f$

Guidance/
steering laws

${}_{\mathcal{N}}q^T, {}_{\mathcal{N}}\omega^T, {}_{\mathcal{N}}\alpha^T$

Control loop

Σ

Attitude
controller

Gyrostat
dynamics