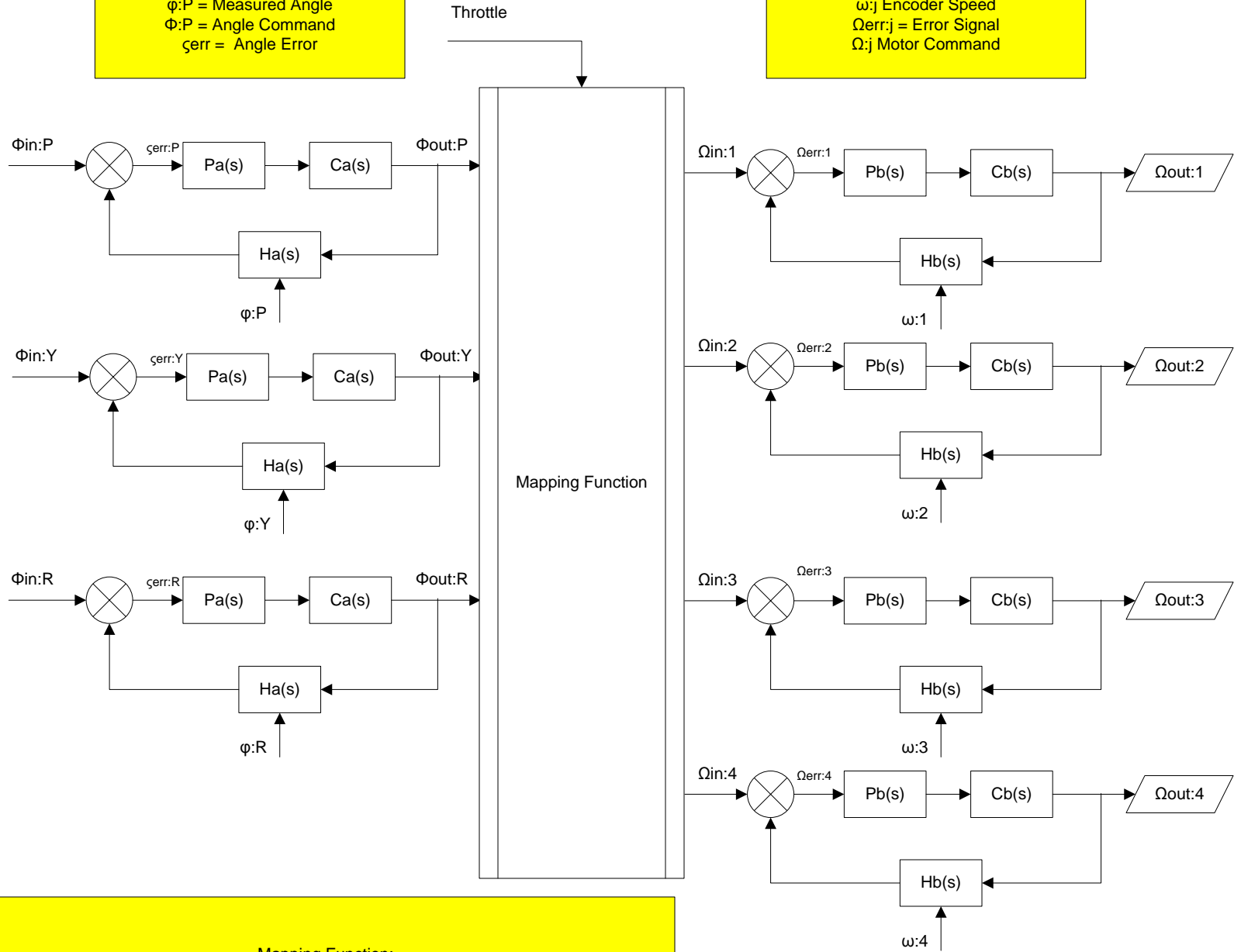


$Ca(s) = K_Pp + K_Pi*s + k_Pd/s$
 $Ha(s)$ = Sensor Gain
 $Pa(s)$ = Plant Transfer Function
 For j = Pitch,Yaw,Roll
 $\phi:P$ = Measured Angle
 $\Phi:P$ = Angle Command
 ζerr = Angle Error

$Cb(s) = K_{jp} + K_{ji}*s + K_{jd}/s$
 $Hb(s)$ = Sensor Gain
 $Pb(s)$ = Plant Transfer Function
 For j = Motors 1:4
 $\omega:j$ Encoder Speed
 $\Omega err:j$ = Error Signal
 $\Omega:j$ Motor Command



Mapping Function:
 Constants: MID_RANGE
 $\Omega_{in:1} = \Phi_{out:P}, \Phi_{out:Y}, \Phi_{out:R}, \text{Throttle}$