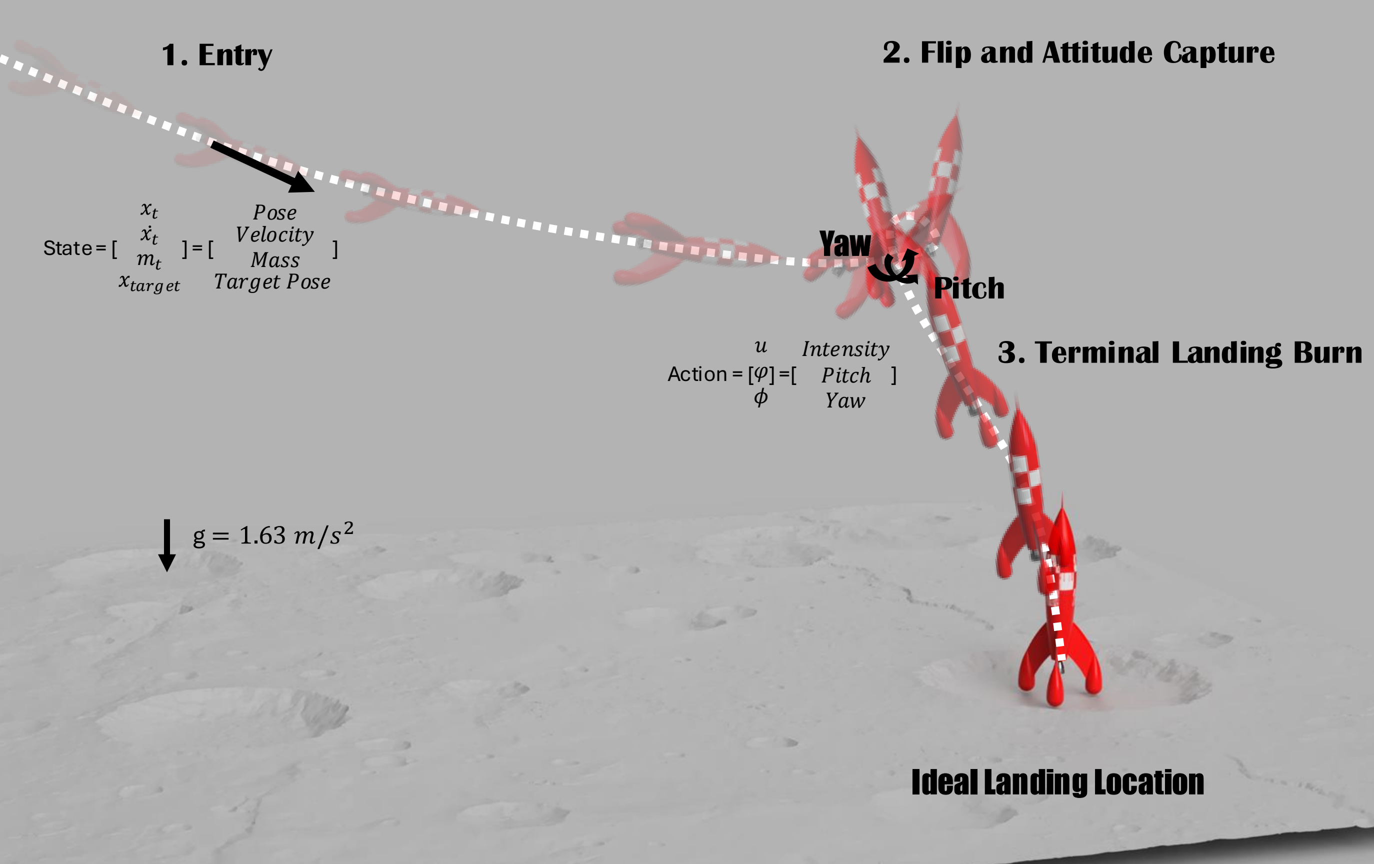
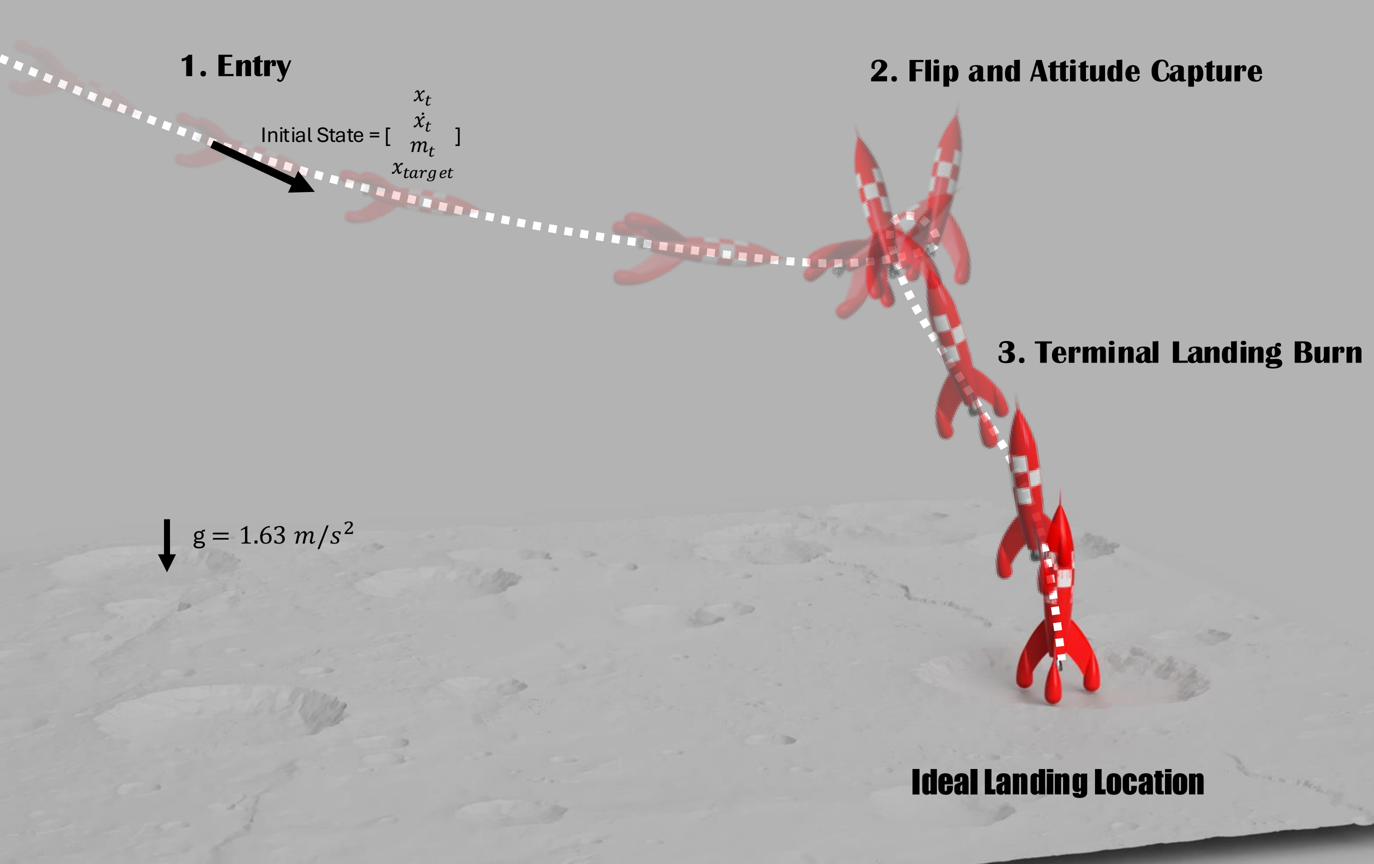
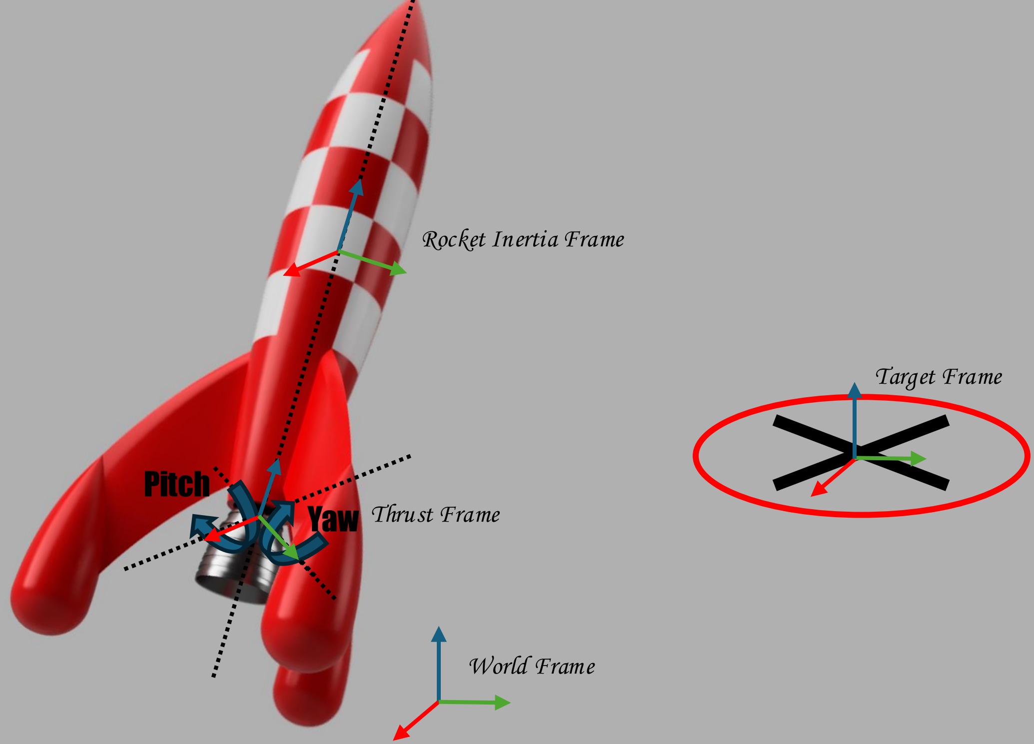

ose
ocity]
ose
Yaw
Pitch
u Thrust In
Action = [φ] =[Thrust
ϕ Thrust
3. T



1. Entry
2. Flip and Attitude Capture
Yaw
Pitch
3. Terminal Landing Burn
State = [x_t $\dot{x}_t$ m_t x_{target}] = [Pose Velocity Mass Target Pose]
Action = [u φ ϕ] = [Intensity Pitch Yaw]
$g = 1.63\ m/s^2$
Ideal Landing Location



1. Entry
Initial State = [x_t $\dot{x}_t$ m_t x_{target}]
2. Flip and Attitude Capture
3. Terminal Landing Burn
$g = 1.63\ m/s^2$
Ideal Landing Location

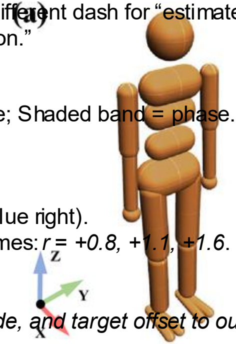

Rocket Inertia Frame
Target Frame
Pitch
Yaw
Thrust Frame
World Frame

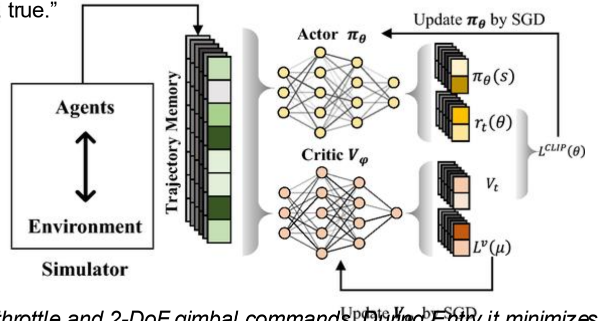
with a hairline offset in a different dash for “estimated vs. true.”
), with text “policy dispersion.”

nbaled thrust; Bar = throttle; Shaded band = phase.

t glow on plume.
yaw sign (e.g., cyan left, blue right).
c callouts) at 3 anchor frames: *r* = *+0.8, +1.1, +1.6*.

es attitude, velocity, altitude, and target offset to output throttle and 2-DoF gimbal commands. During Entry it minimizes lateral velocity and fuel; F





arameter count (e.g., “~0.8M params”).
andomization: mass ±10%, g ±5%, sensor noise.”
k (SVG labels, throttle bar, gimbal cones, legend) sized to your canvas so you can drop them directly onto the render.