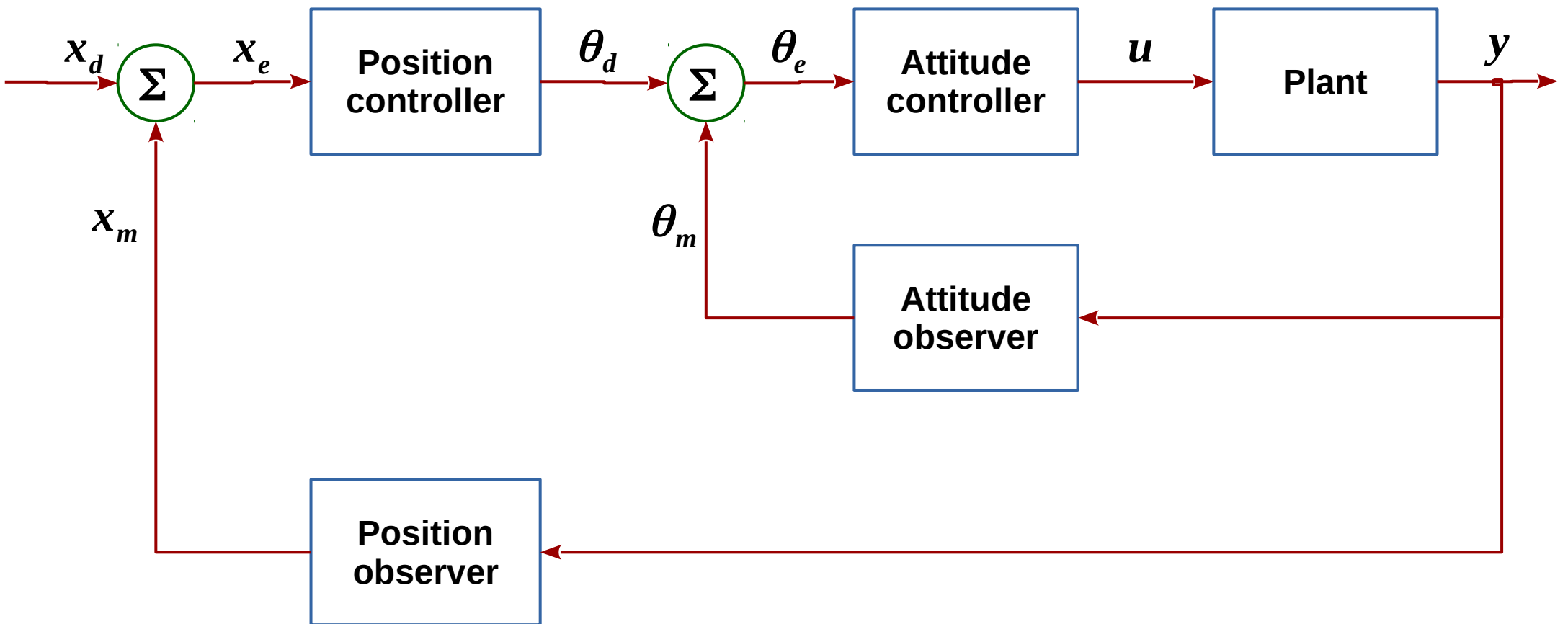


Quadrotor Angle-rate controller

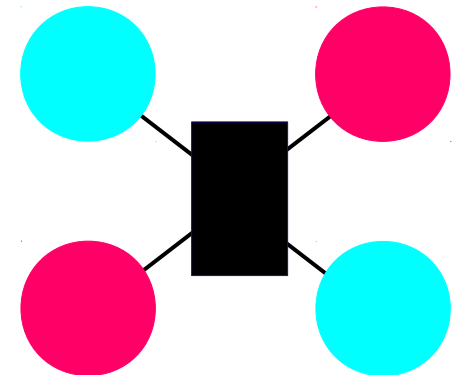


$$\mathbf{x}^{\text{def}} \{x, y, z, u, v, w\}$$

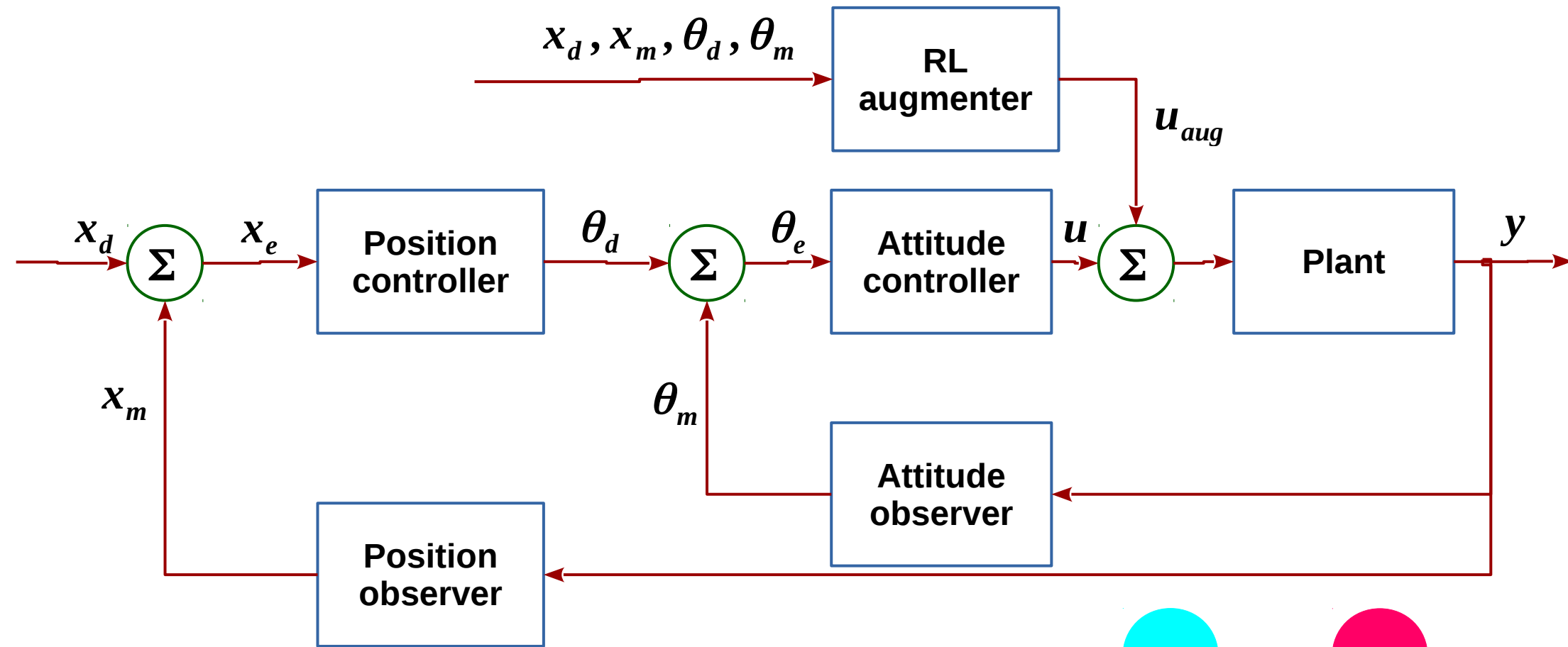
$$\boldsymbol{\theta}^{\text{def}} \{\theta, \phi, \psi, p, q, r\}$$

$$\mathbf{u}^{\text{def}} \{motor_1, motor_2, motor_3, motor_4\}$$

$$\mathbf{y}^{\text{def}} \{environment\}$$



Quadrotor RL-Augmented Angle-rate controller



$$\mathbf{x} \stackrel{\text{def}}{=} \{x, y, z, u, v, w\}$$

$$\boldsymbol{\theta} \stackrel{\text{def}}{=} \{\theta, \phi, \psi, p, q, r\}$$

$$\mathbf{u} \stackrel{\text{def}}{=} \{motor_1, motor_2, motor_3, motor_4\}$$

$$\mathbf{y} \stackrel{\text{def}}{=} \{environment\}$$

