

**Predefined  
trajectory**

$x^{ref}$

**MPC**

$u$

**Thrust  
allocation**

$\omega$



**DF-GP**

$\min \sum \eta_i ||\mu_{gpi} - \Delta||^2$

$\mu_{gp1}(x, u, \lambda_1)$

$\mu_{gp2}(x, u, \lambda_2)$

$\mu_{gp3}(x, u, \lambda_3)$

$\vdots$

$\mu_{gpN}(x, u, \lambda_N)$

$x$