Firefly, from RotorS, to track a desired trajectory. This mission depends on:

- a trajectory tracking controller
- a reference position trajectory to be tracked
- a yaw controller
- a yaw reference

<\p>

- PID Controller, with saturation on integral part

  <\p>

- **Circle trajectory** with **radius** in (m), and **speed** (linear velocity) in (m/s)<\p>

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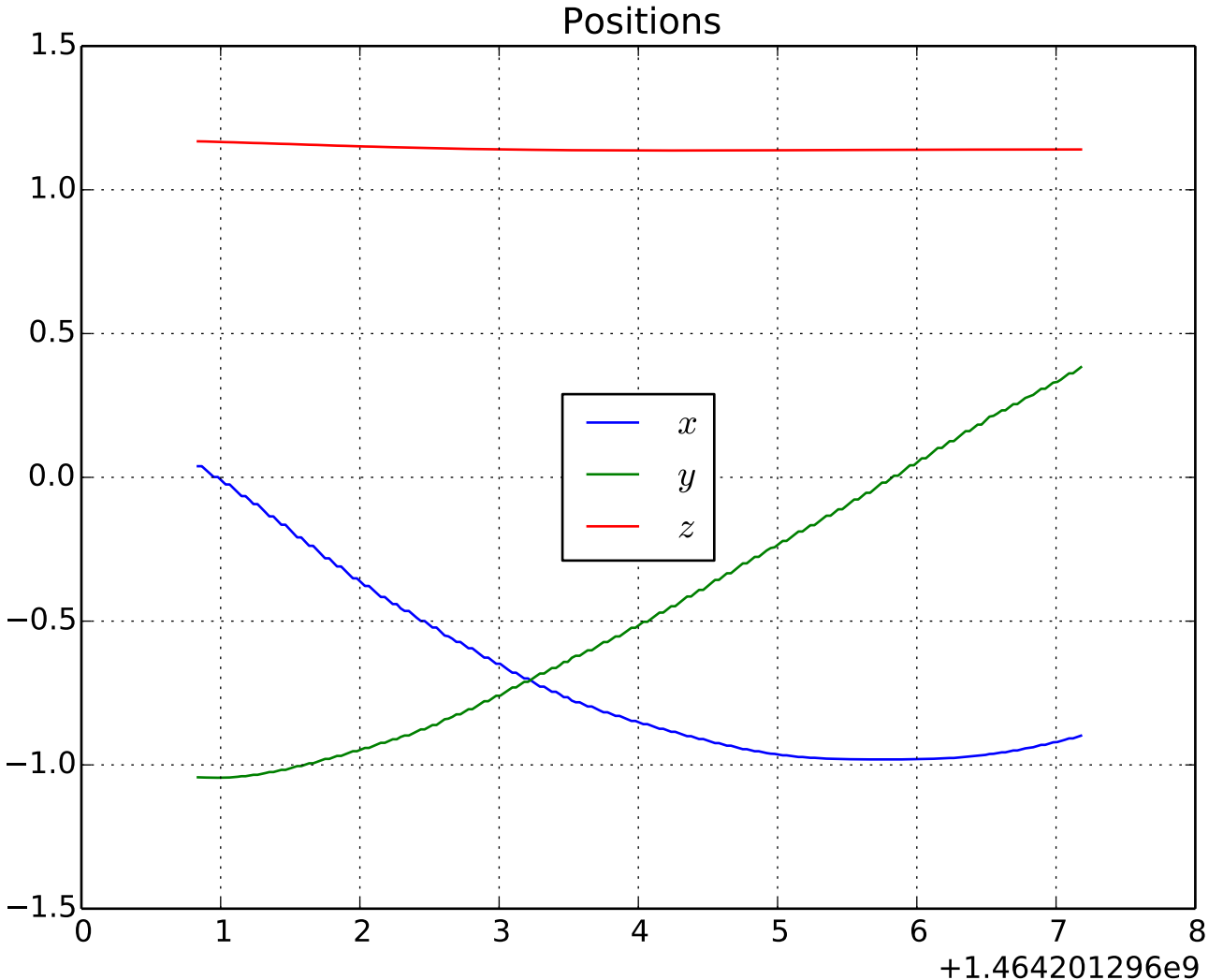
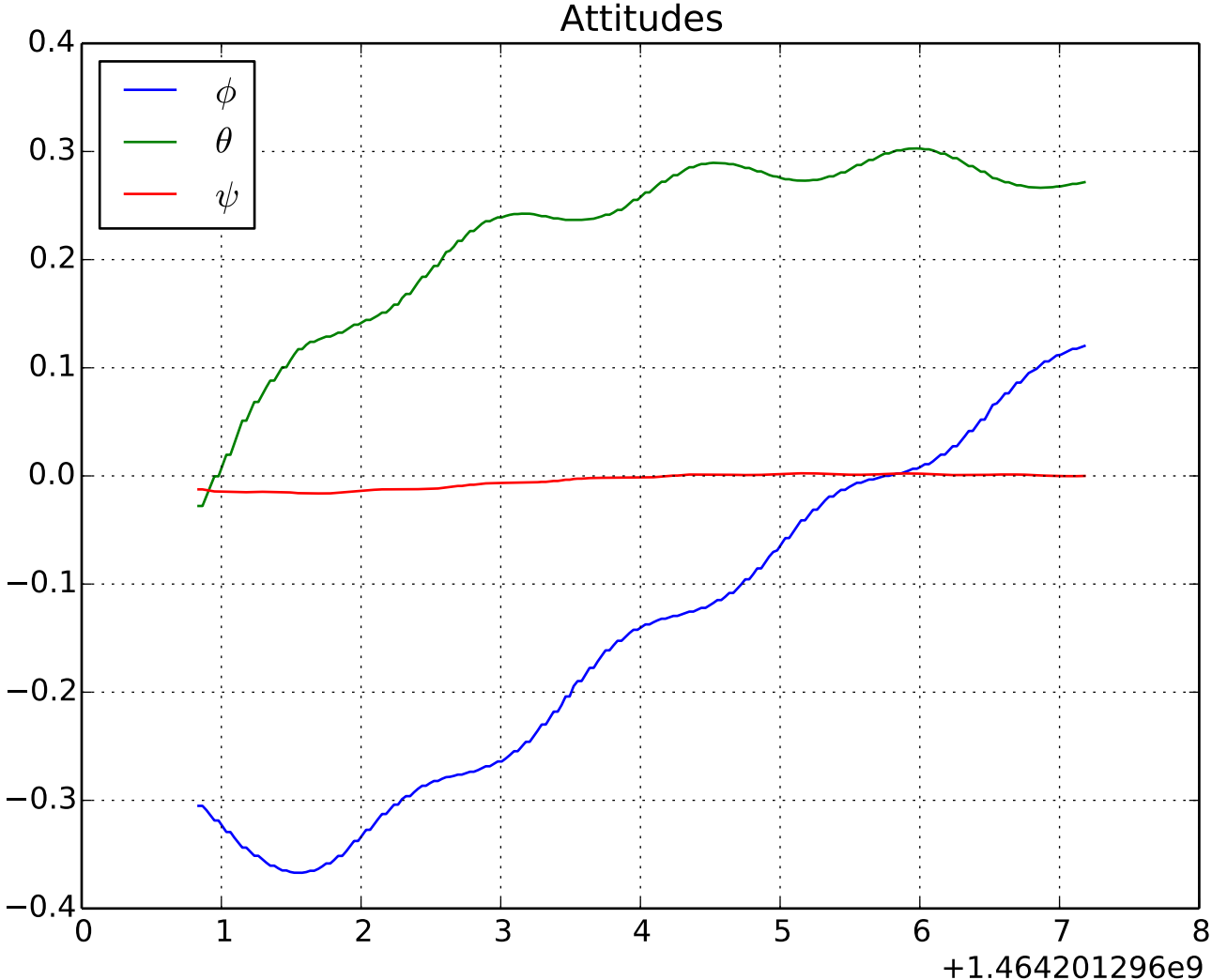
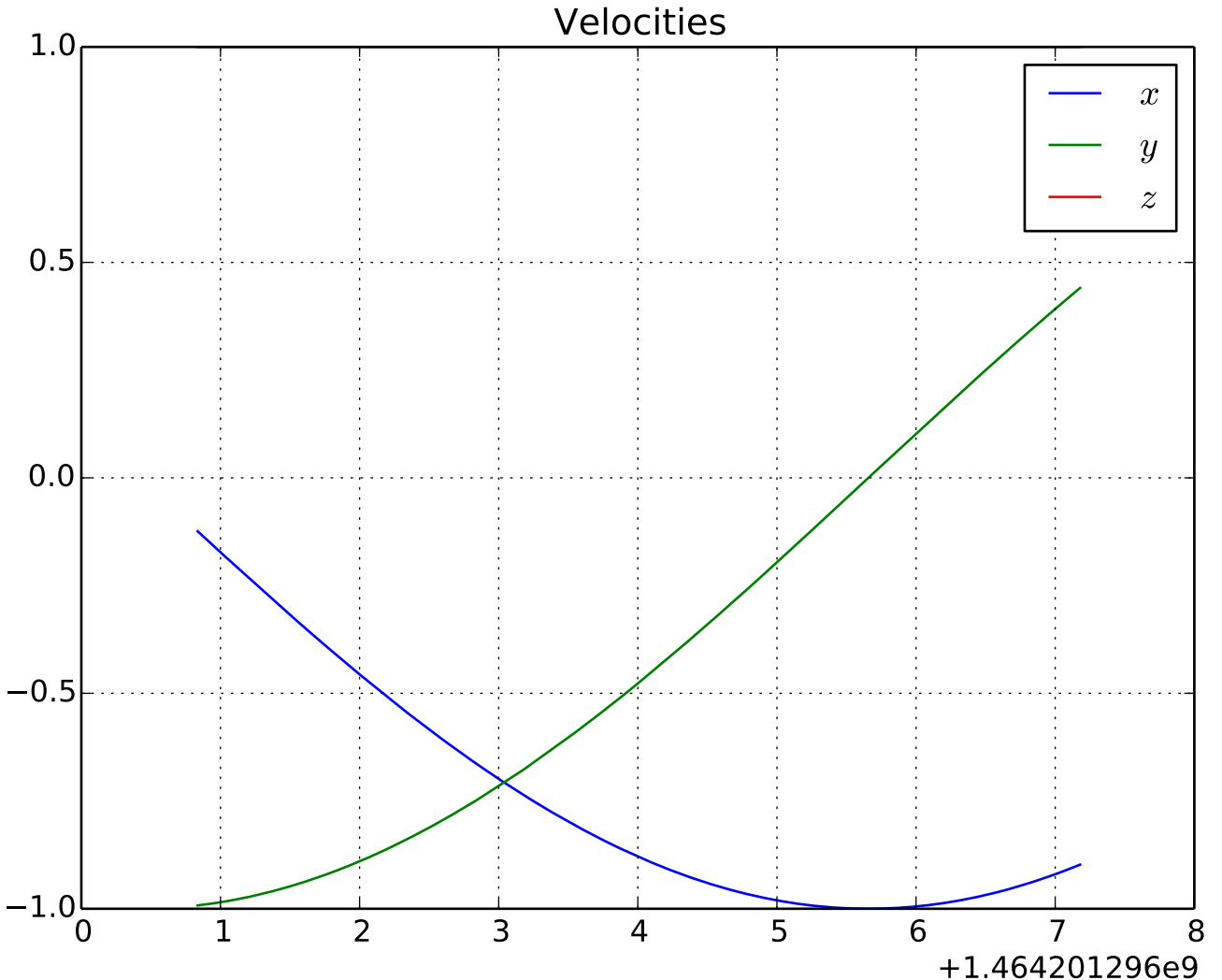
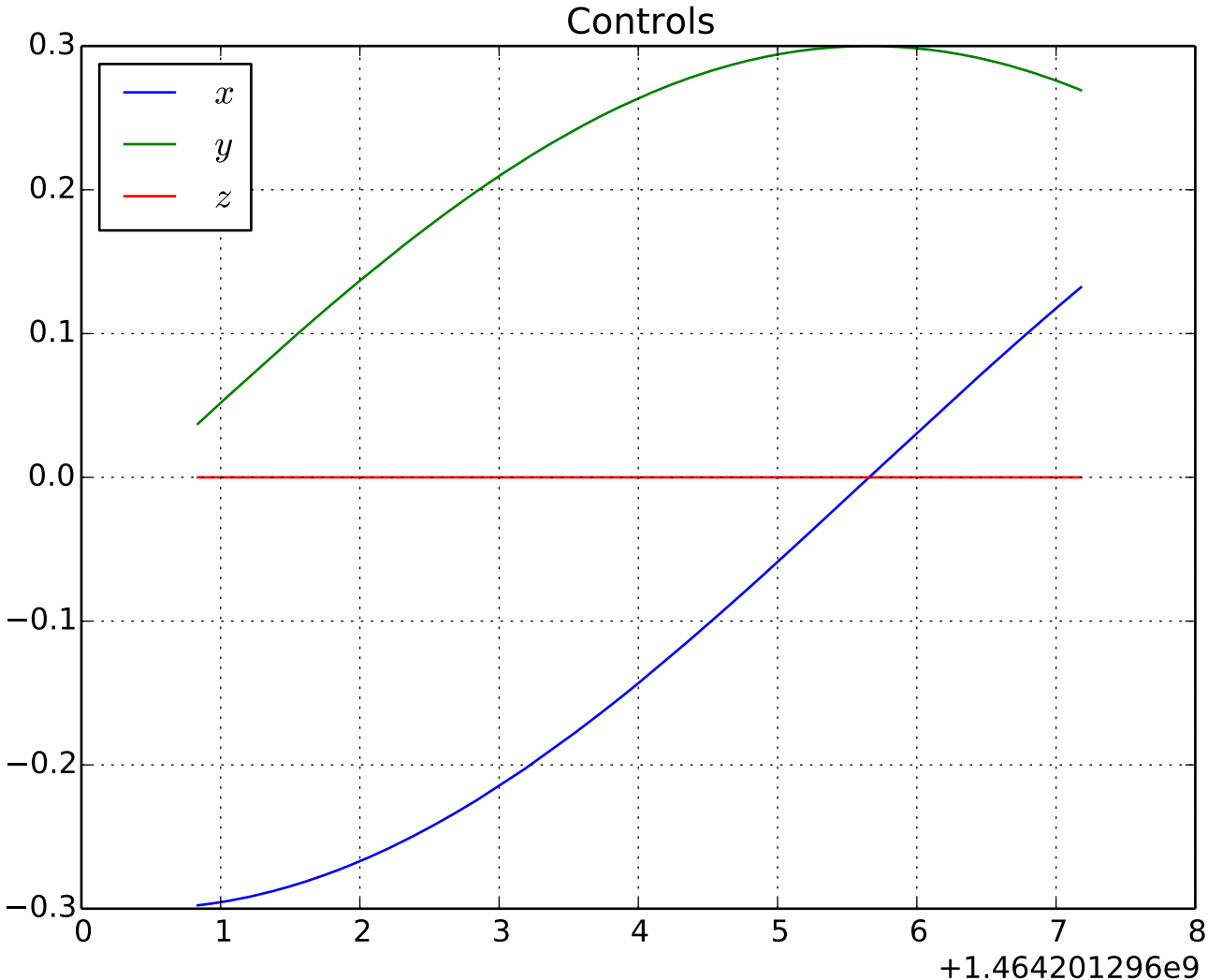
rt <\p> Circle trajectory with radius in (m), and


Positions
1.5
1.0
0.5
0.0
−0.5
−1.0
−1.5
0
1
2
3
4
5
6
7
8
+1.464201296e9
x
y
z


Attitudes
ϕ
θ
ψ
0.4
0.3
0.2
0.1
0.0
−0.1
−0.2
−0.3
−0.4
0
1
2
3
4
5
6
7
8
+1.464201296e9


Velocities
1.0
0.5
0.0
−0.5
−1.0
0
1
2
3
4
5
6
7
8
+1.464201296e9
x
y
z


Controls
x
y
z
0.3
0.2
0.1
0.0
−0.1
−0.2
−0.3
0
1
2
3
4
5
6
7
8
+1.464201296e9

Firefly, from RotorS, to track a desired trajectory. This mission depends on:

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- a yaw controller
- a yaw reference

<\p>

- PID Controller, with saturation on integral part

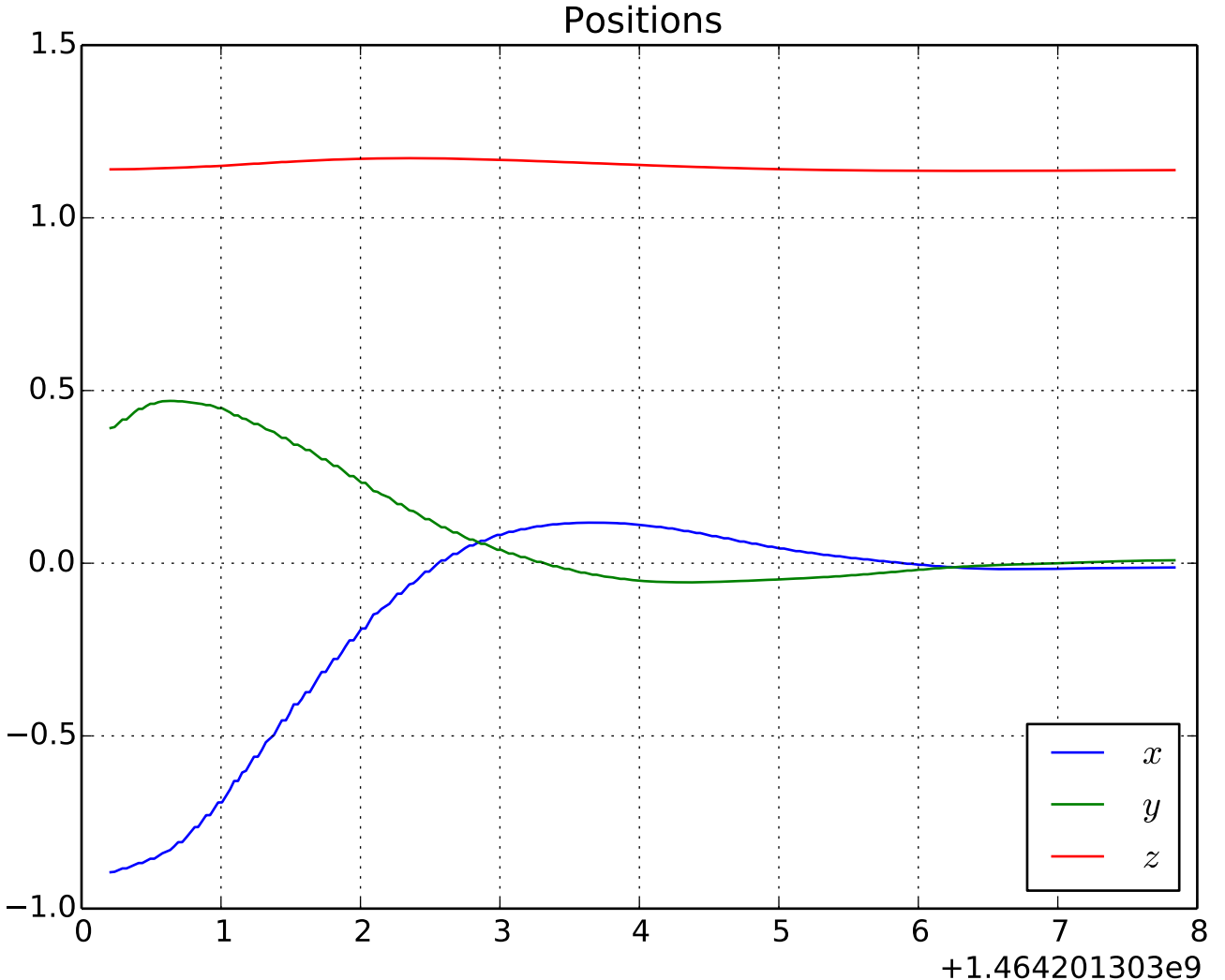
  <\p>

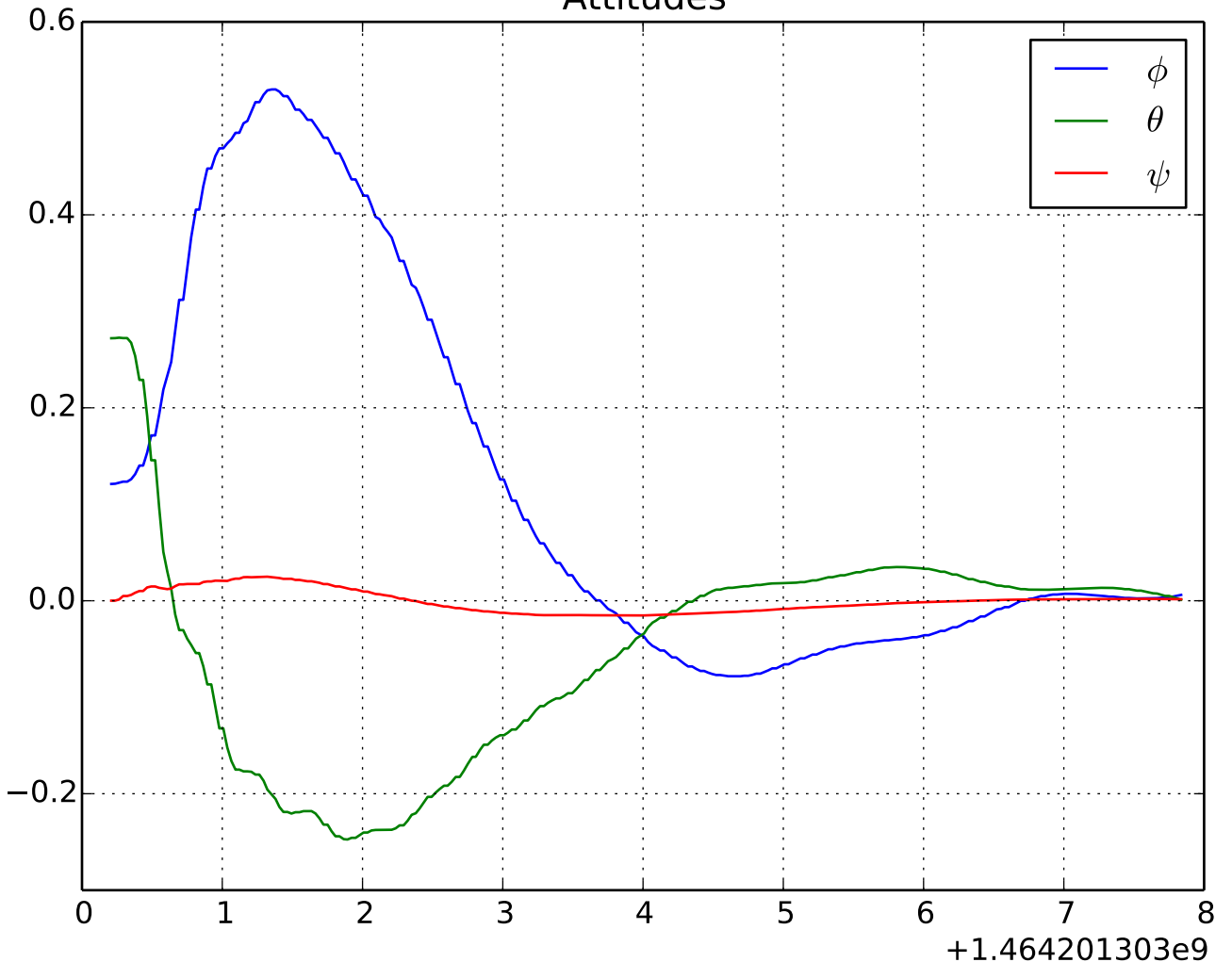
- **Stay at rest at speficied point**<\p>

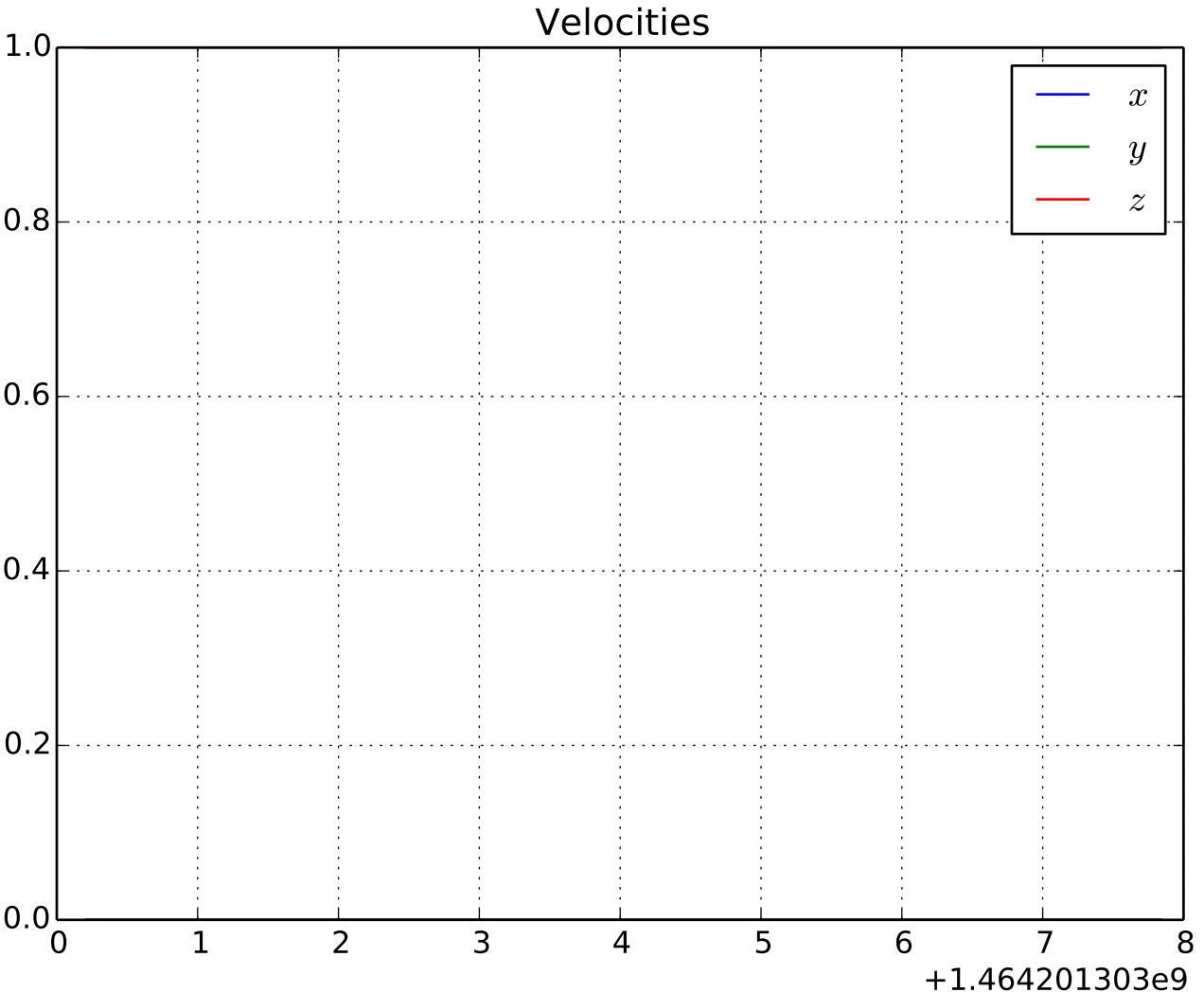
Firefly, from RotorS, to track a desired trajectory. This mission depends on:

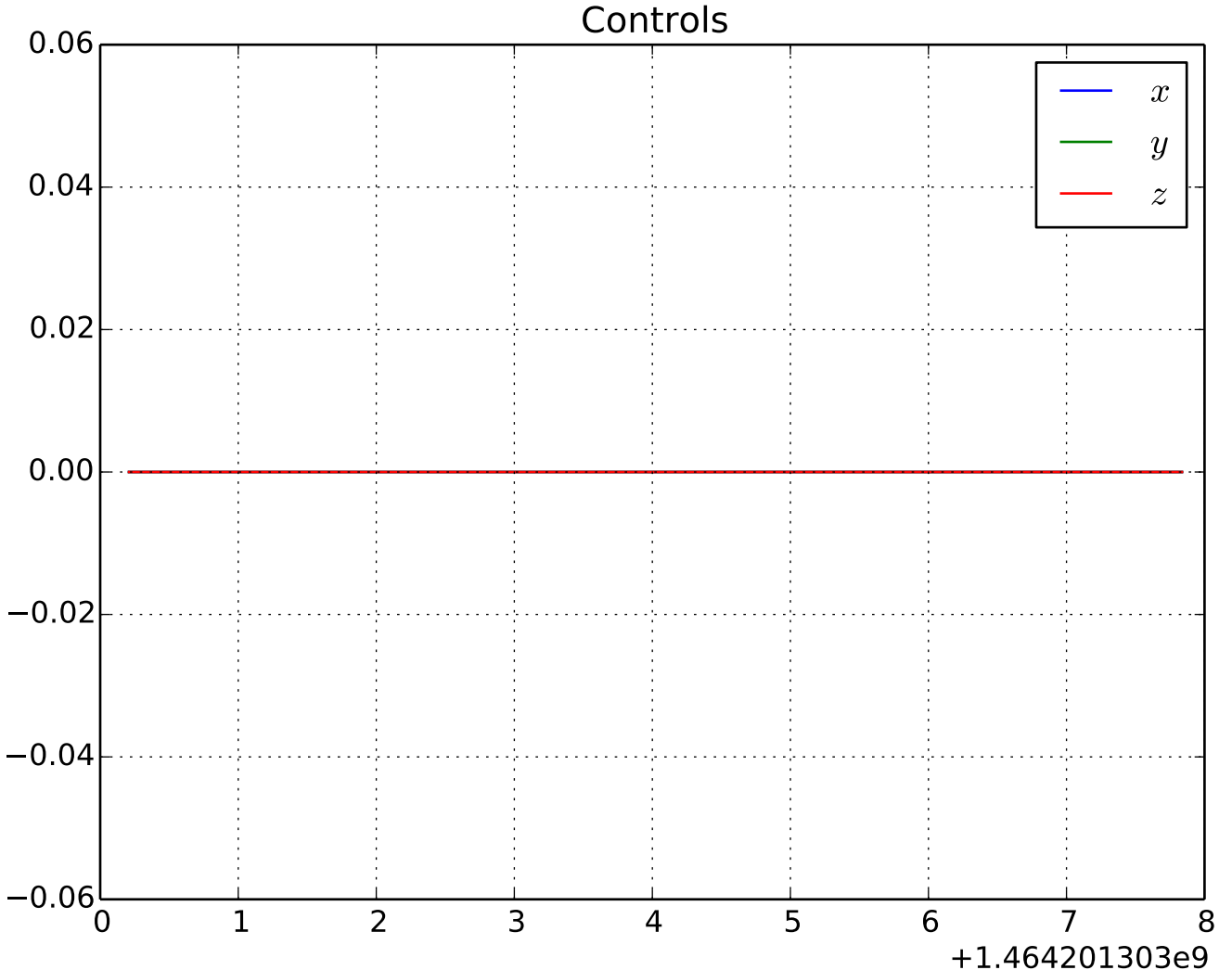
a trajectory tracking controller
a reference position trajectory to be tracked
a yaw controller
a yaw reference

with saturation on integral part <\p> Stay at rest at speficied


Positions
1.5
1.0
0.5
0.0
−0.5
−1.0
0
1
2
3
4
5
6
7
8
+1.464201303e9
x
y
z


Attitudes
0.6
0.4
0.2
0.0
−0.2
0
1
2
3
4
5
6
7
8
+1.464201303e9
ϕ
θ
ψ


Velocities
1.0
0.8
0.6
0.4
0.2
0.0
0
1
2
3
4
5
6
7
8
+1.464201303e9
x
y
z


Controls
0.06
0.04
0.02
0.00
−0.02
−0.04
−0.06
0
1
2
3
4
5
6
7
8
+1.464201303e9
x
y
z