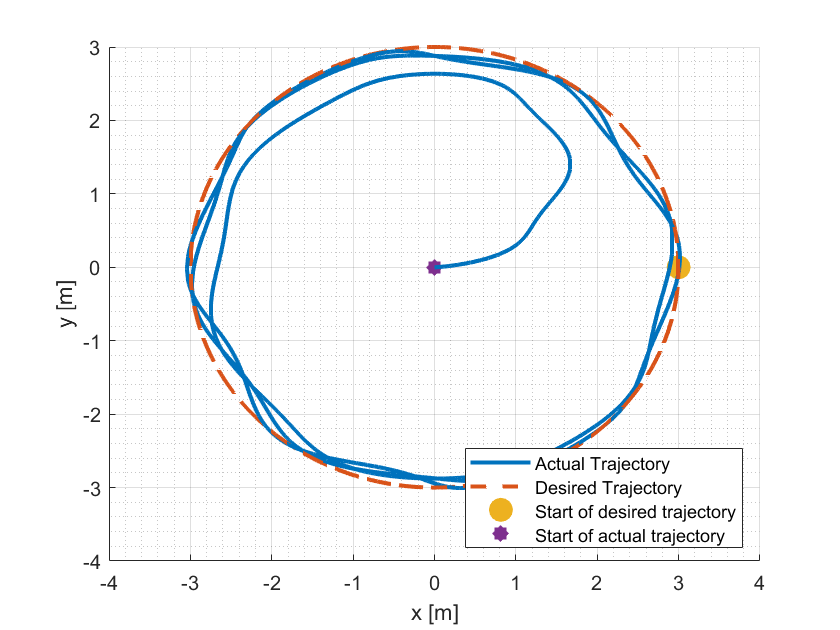
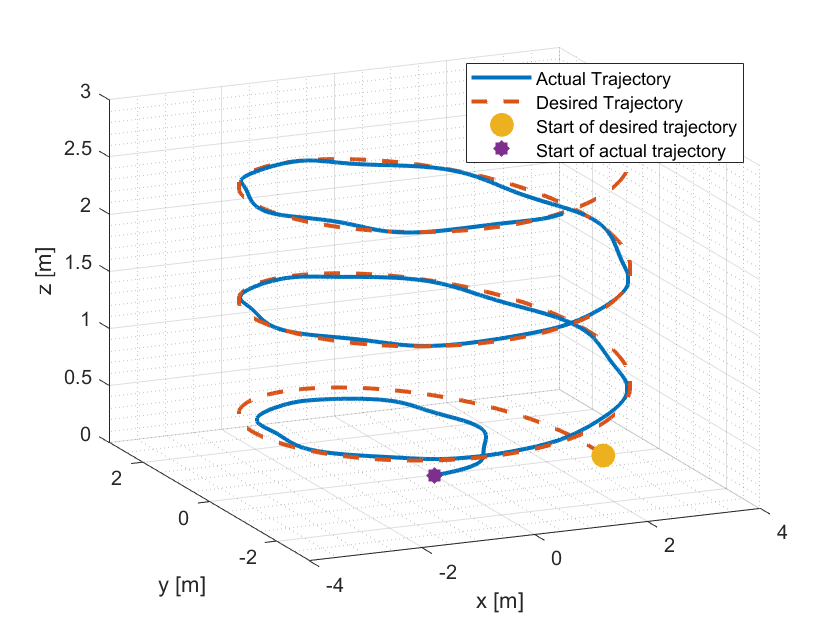
Desain Kontroler Quadcopter – Input (Hanya Posisi

1. Desain Kontroler Proportional (P)
   1. Lintasan 1 : Circular

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| Gain |  |  |  |  |  |  |
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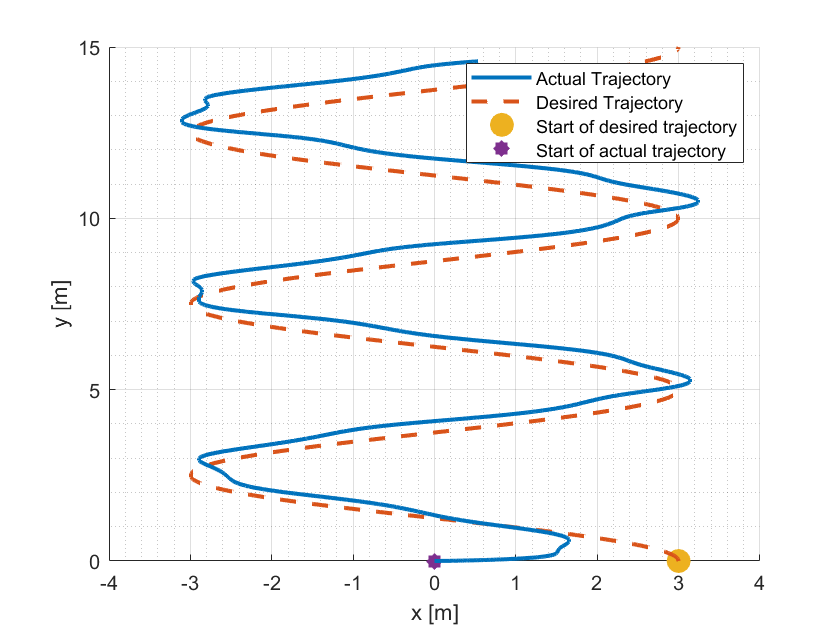
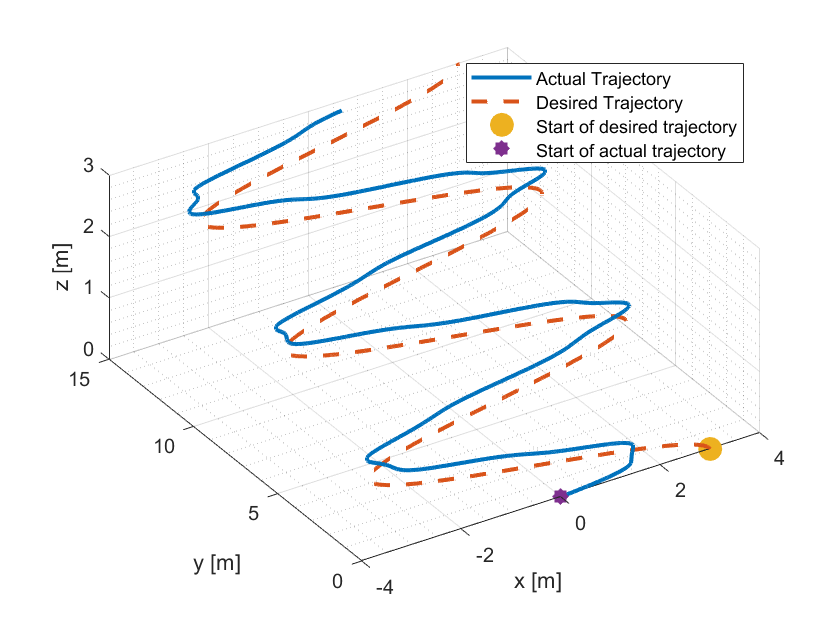


* 1. Lintasan 2 : Spiral

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| Gain |  |  |  |  |  |  |
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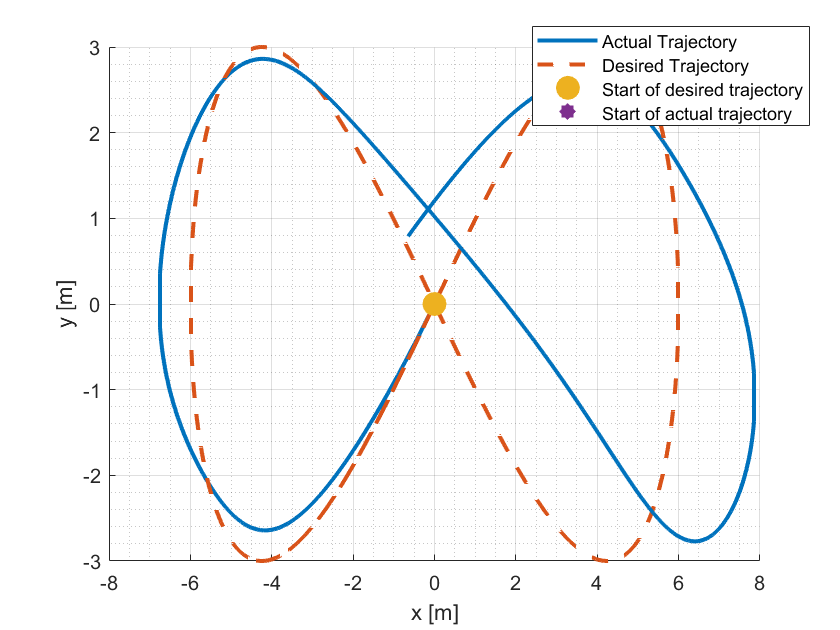
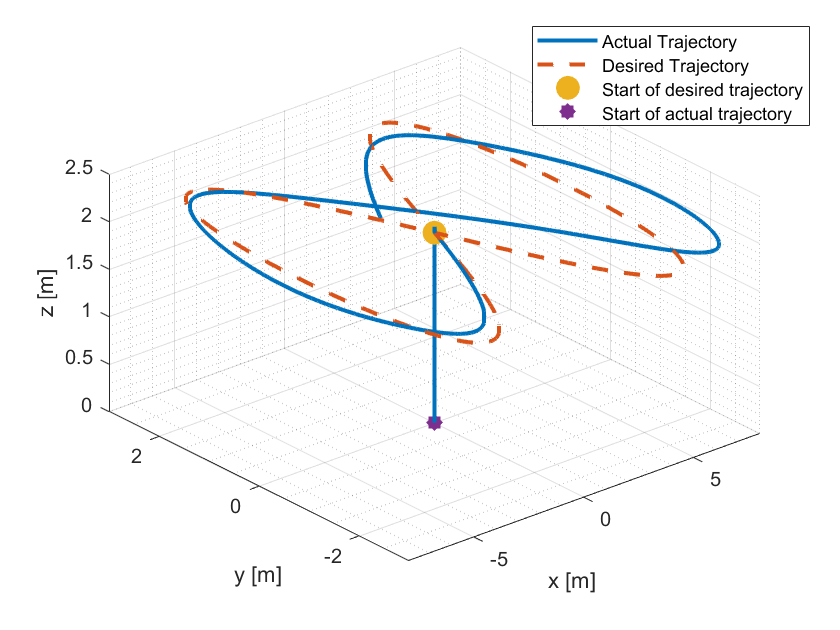


* 1. Lintasan 3 : Lemniscate / 8

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| --- | --- | --- | --- | --- | --- | --- |
| Gain |  |  |  |  |  |  |
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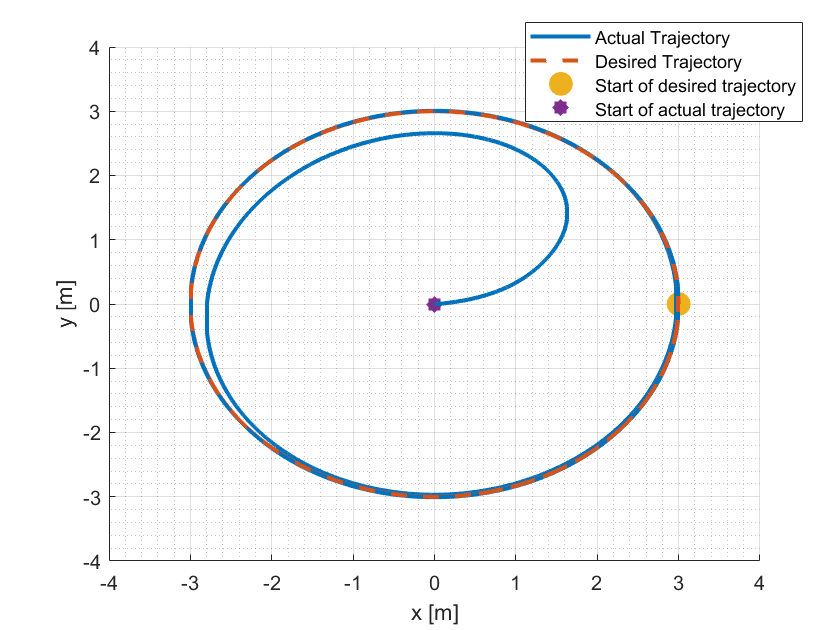
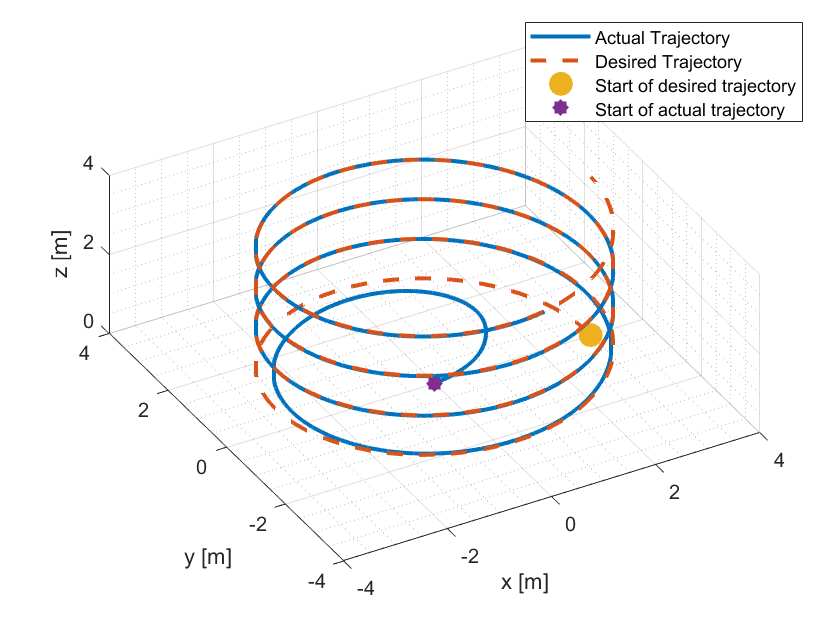


1. Desain Kontroler Proportional-Integral (PI)
   1. Lintasan 1 : Circular

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| --- | --- | --- | --- | --- | --- | --- |
| Gain |  |  |  |  |  |  |
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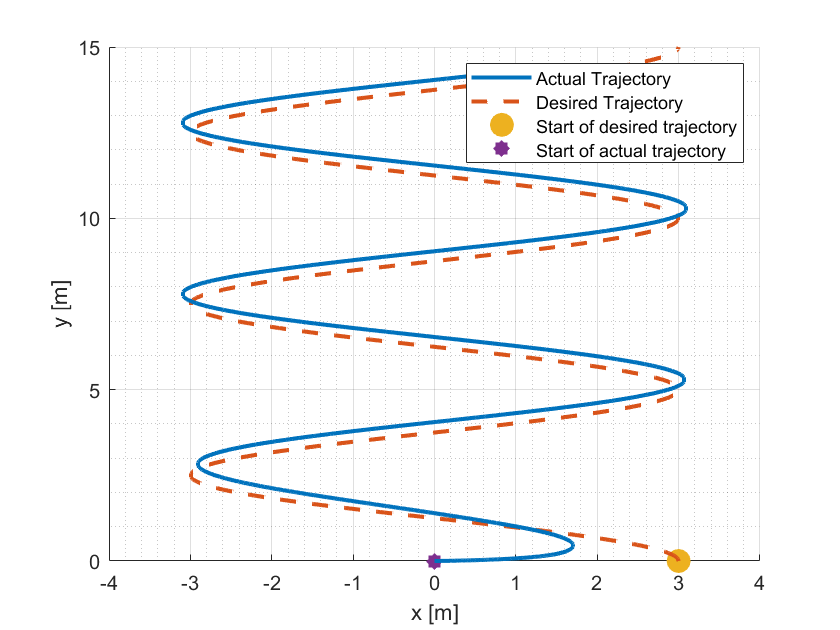
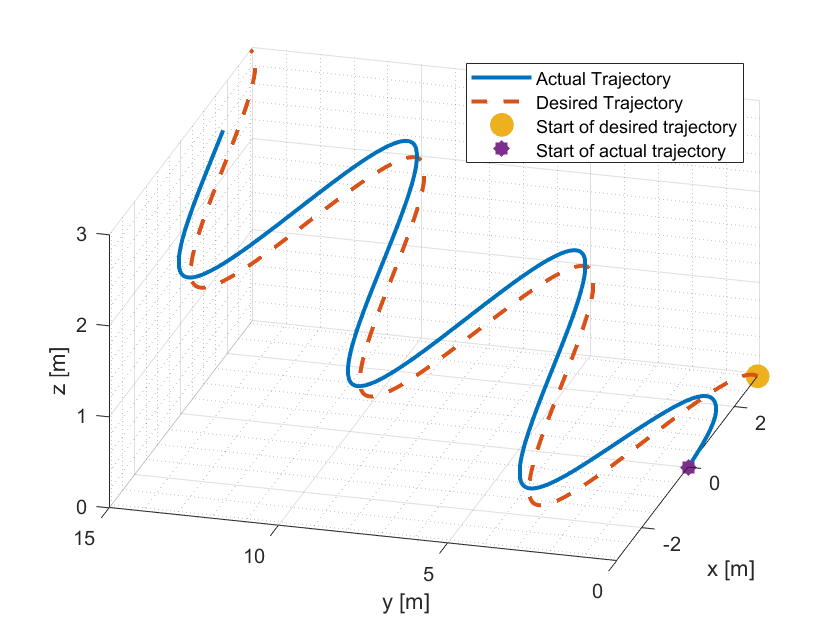


* 1. Lintasan 2 : Spiral

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| --- | --- | --- | --- | --- | --- | --- |
| Gain |  |  |  |  |  |  |
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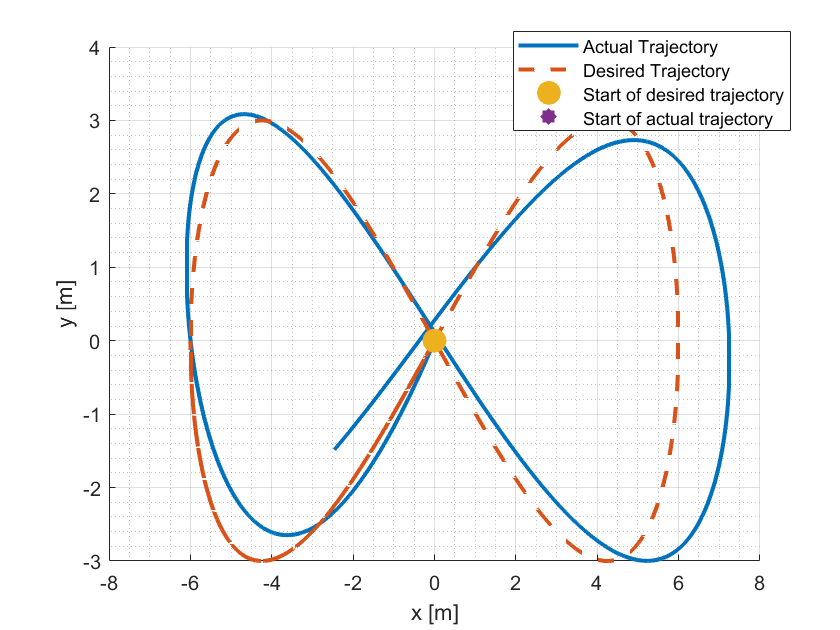
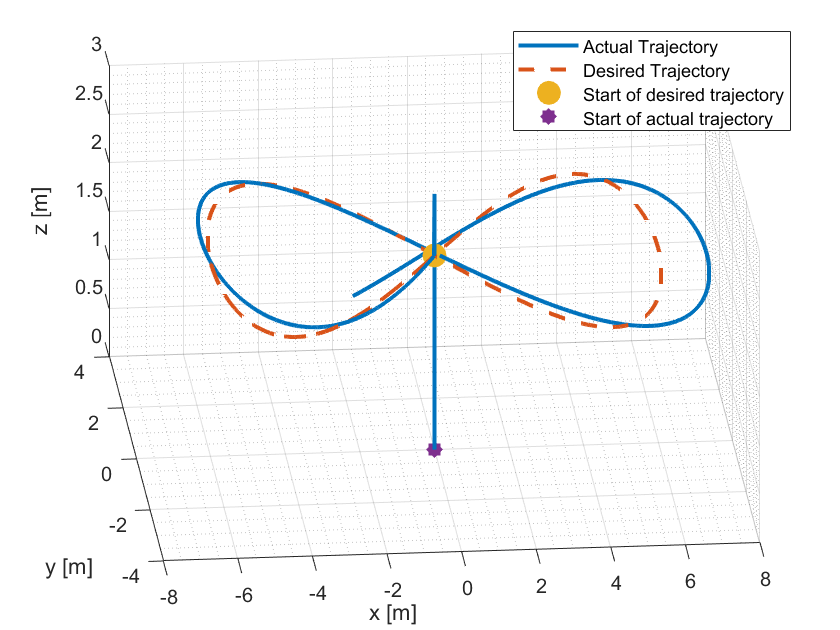


* 1. Lintasan 3 : Lemniscate / 8

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| --- | --- | --- | --- | --- | --- | --- |
| Gain |  |  |  |  |  |  |
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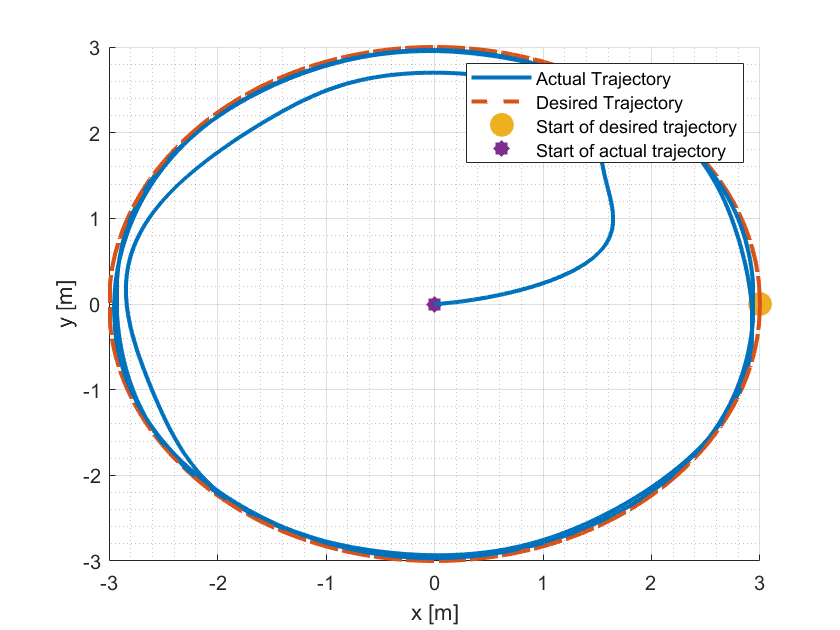
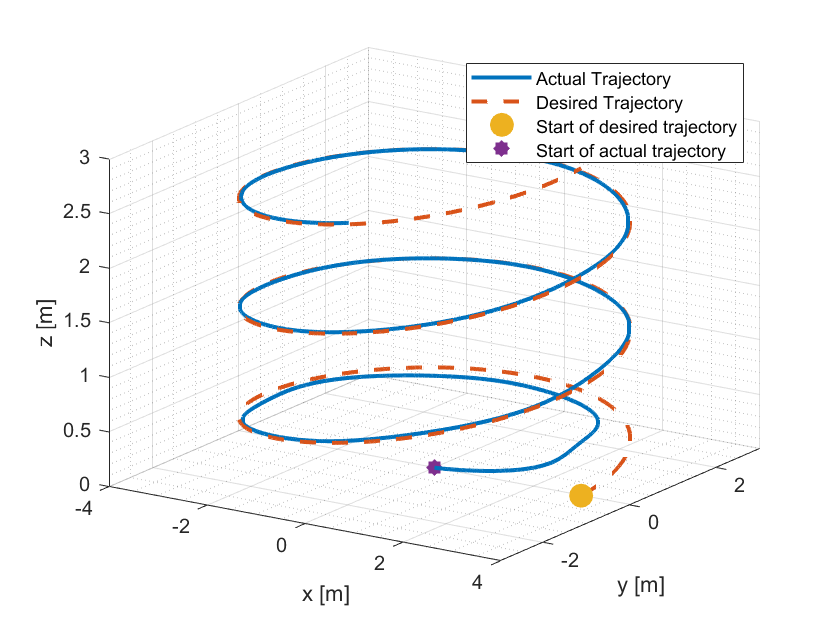


1. Desain Kontroler Proportional-Derivative (PD)
   1. Lintasan 1 : Circular

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| Gain |  |  |  |  |  |  |
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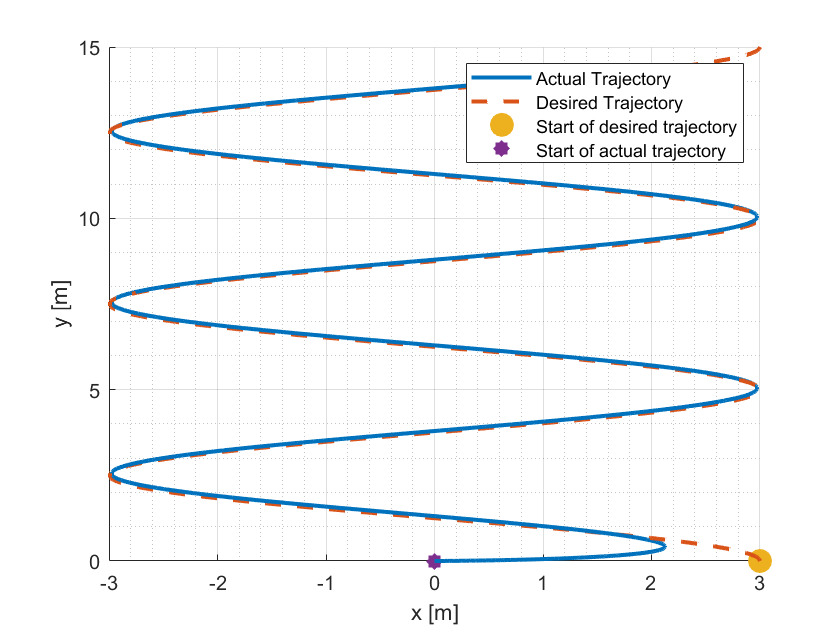
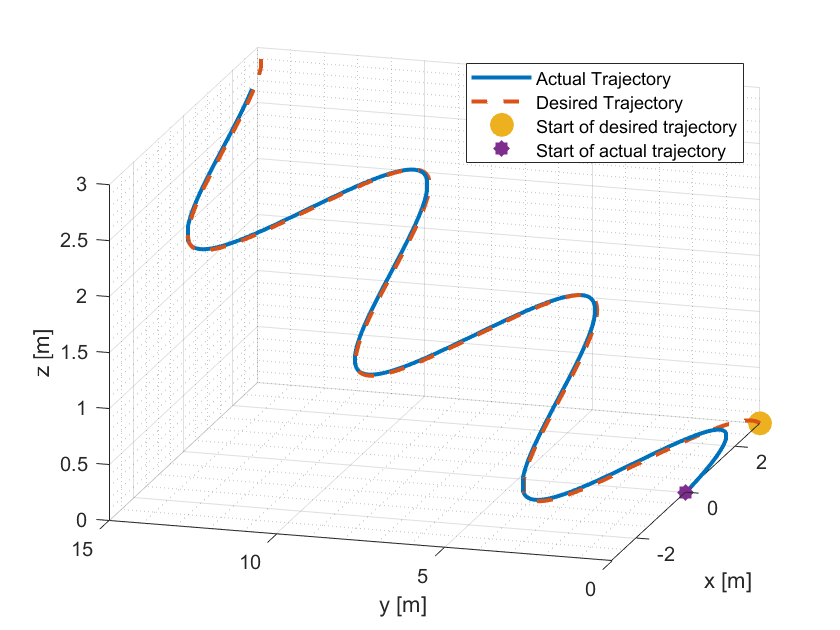


* 1. Lintasan 2 : Spiral

|  |  |  |  |  |  |  |
| --- | --- | --- | --- | --- | --- | --- |
| Gain |  |  |  |  |  |  |
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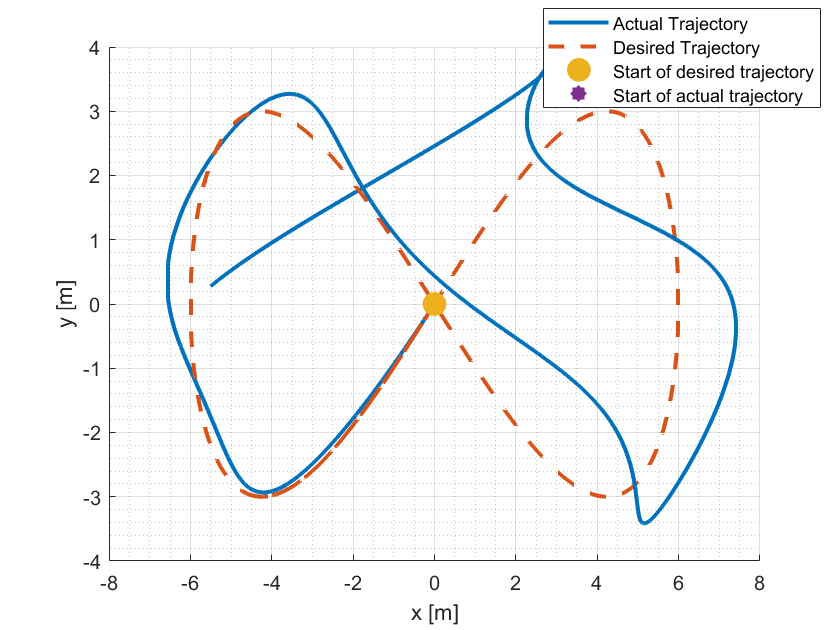
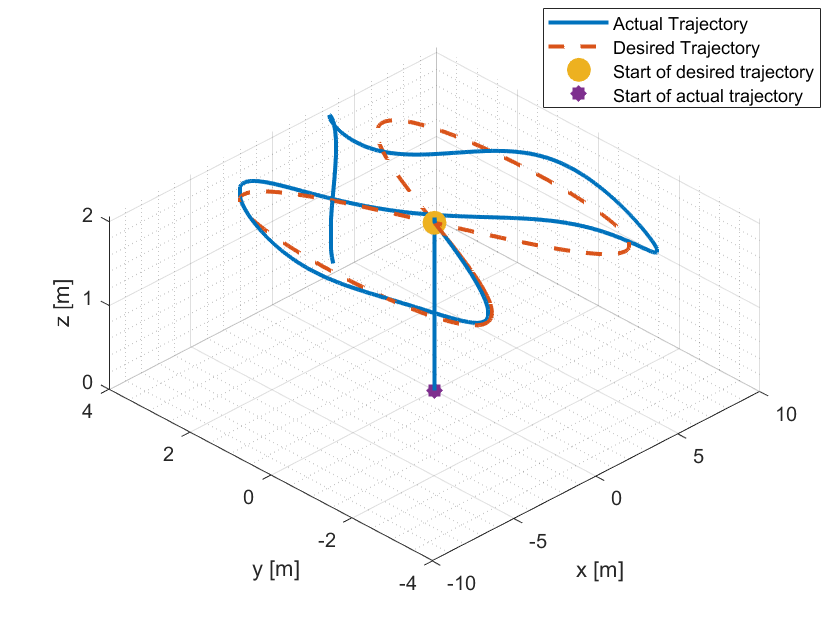


* 1. Lintasan 3 : Lemniscate / 8

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| Gain |  |  |  |  |  |  |
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1. Desain Kontroler Feedback Linearization
   1. Lintasan 1 : Circular





