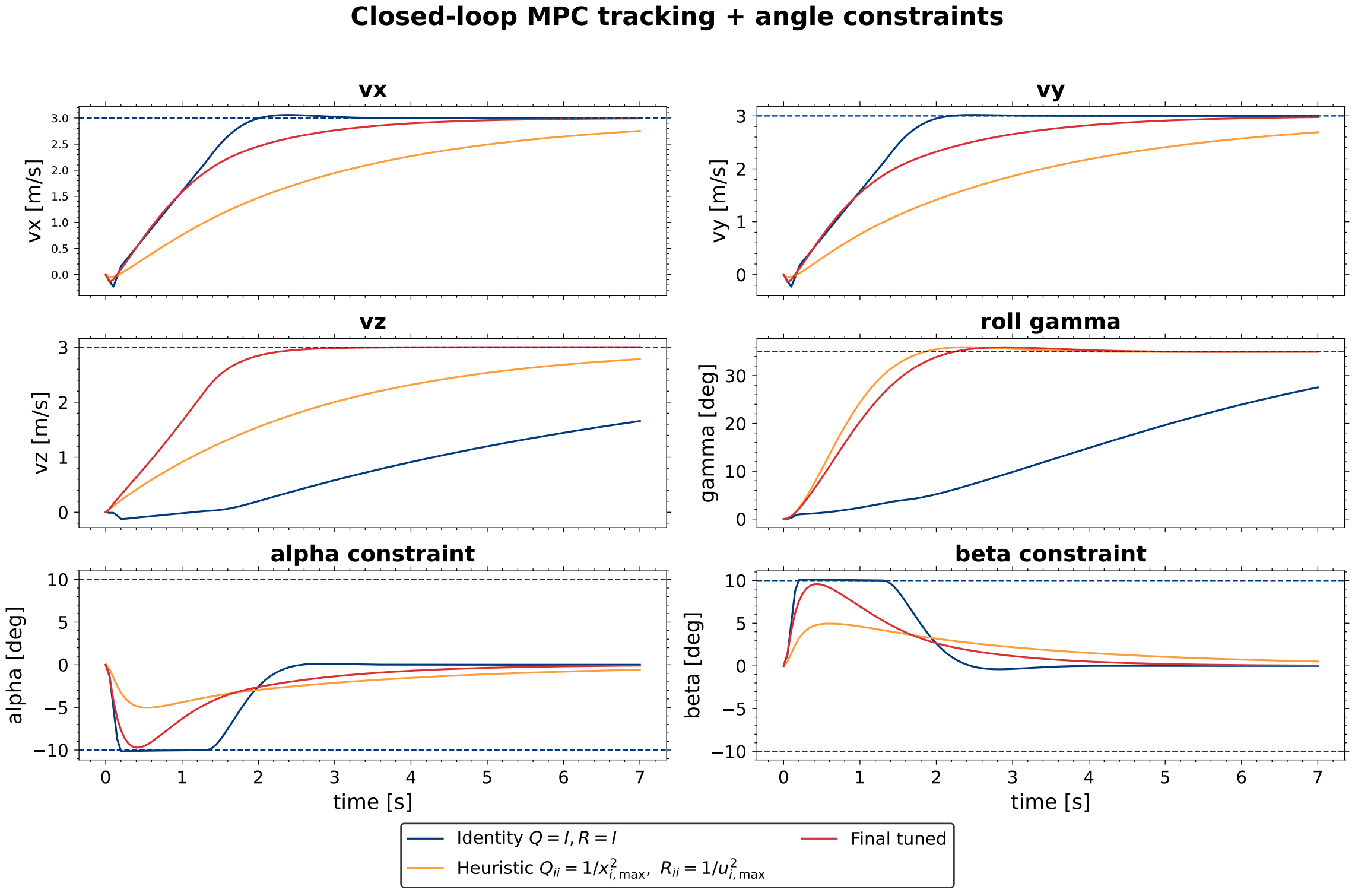
Closed-loop MPC tracking + angle constraints
vx
vx [m/s]
vy
vy [m/s]
vz
vz [m/s]
roll gamma
gamma [deg]
alpha constraint
alpha [deg]
beta constraint
beta [deg]
time [s]
time [s]
Identity $Q = I, R = I$
Final tuned
Heuristic $Q_{ii} = 1/x_{i,\max}^2$, $R_{ii} = 1/u_{i,\max}^2$