Closed-loop MPC responses for velocity and roll subsystems

$v_x(0) = 5\,\text{m/s}$

$v_y(0) = 5\,\text{m/s}$

$v_z(0) = 5\,\text{m/s}$

$\gamma(0) = 30°$
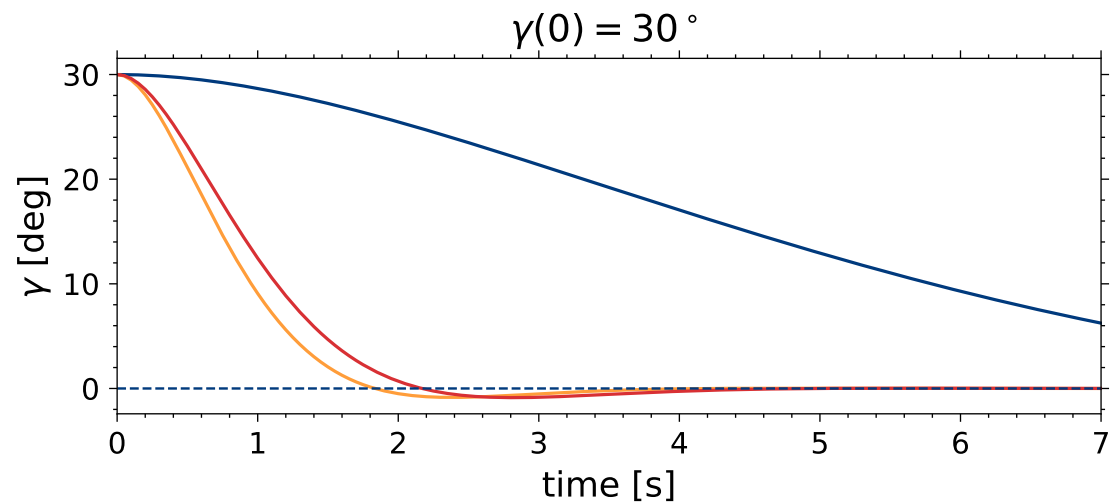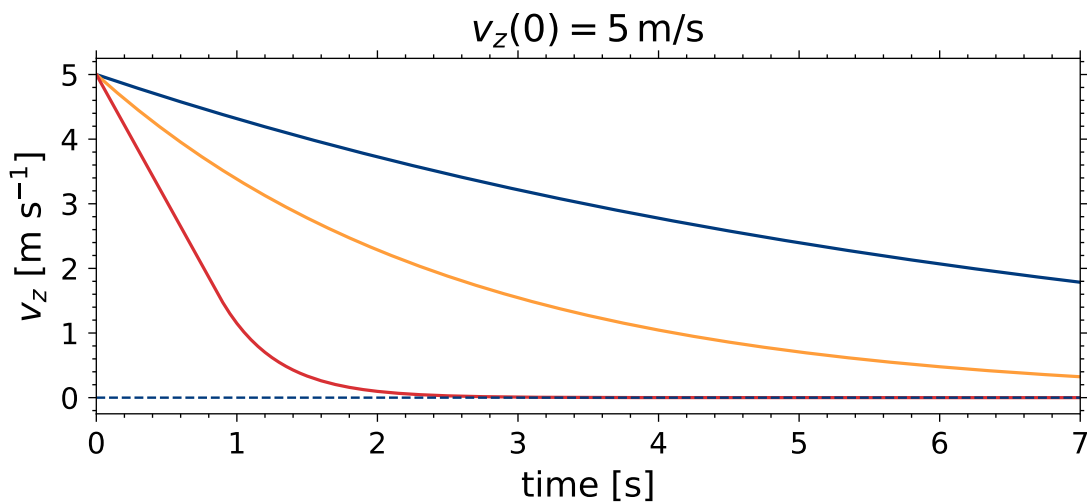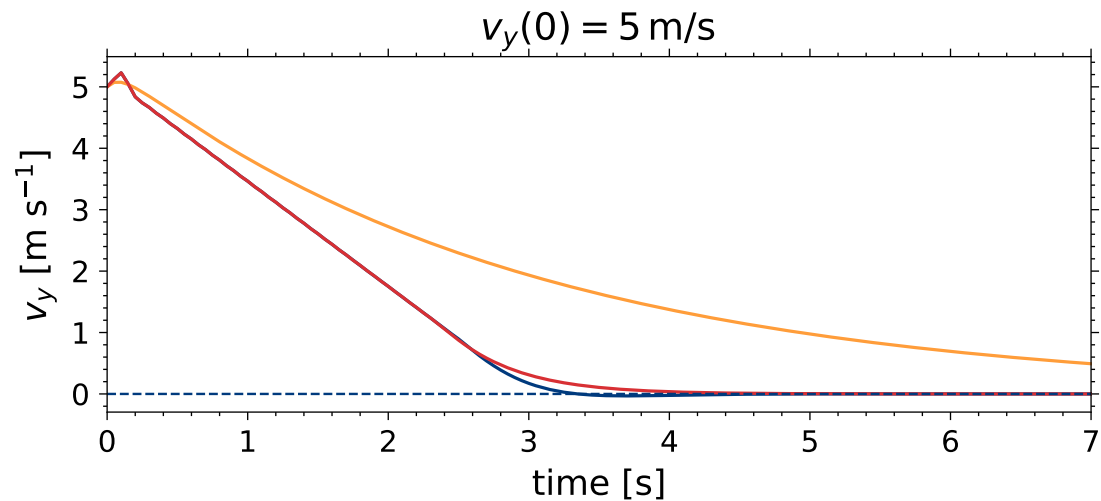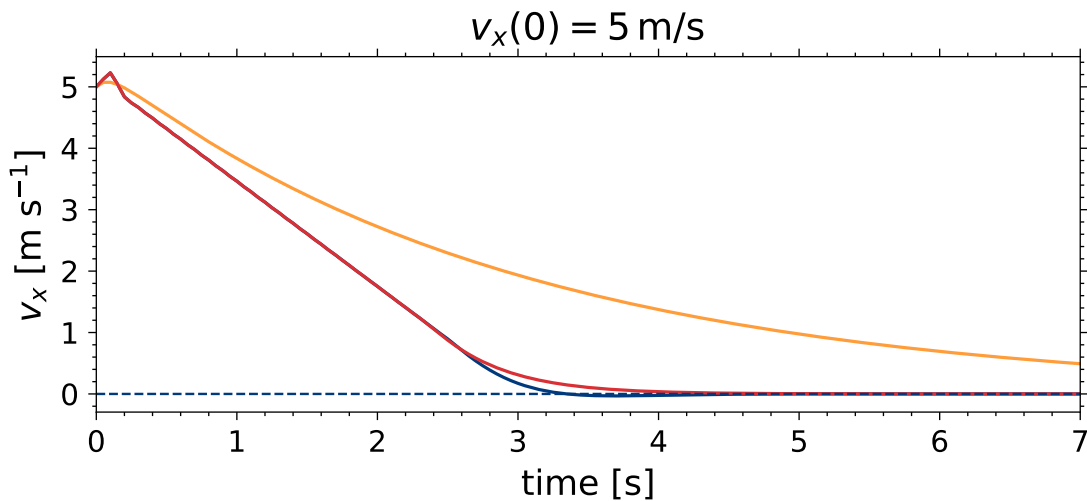
$H = 5.0\,\text{s},\ N = 100$

— Identity $Q = I, R = I$ — Heuristic $Q_{ii} = 1/x_{i,\max}^2,\ R_{ii} = 1/u_{i,\max}^2$ — Final tuned