Closed-loop MPC tracking + angle constraints

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

Subplots:
- **vx** — vx [m/s] vs time [s]
- **vy** — vy [m/s] vs time [s]
- **vz** — vz [m/s] vs time [s]
- **roll gamma** — gamma [deg] vs time [s]
- **alpha constraint** — alpha [deg] vs time [s]
- **beta constraint** — beta [deg] vs time [s]