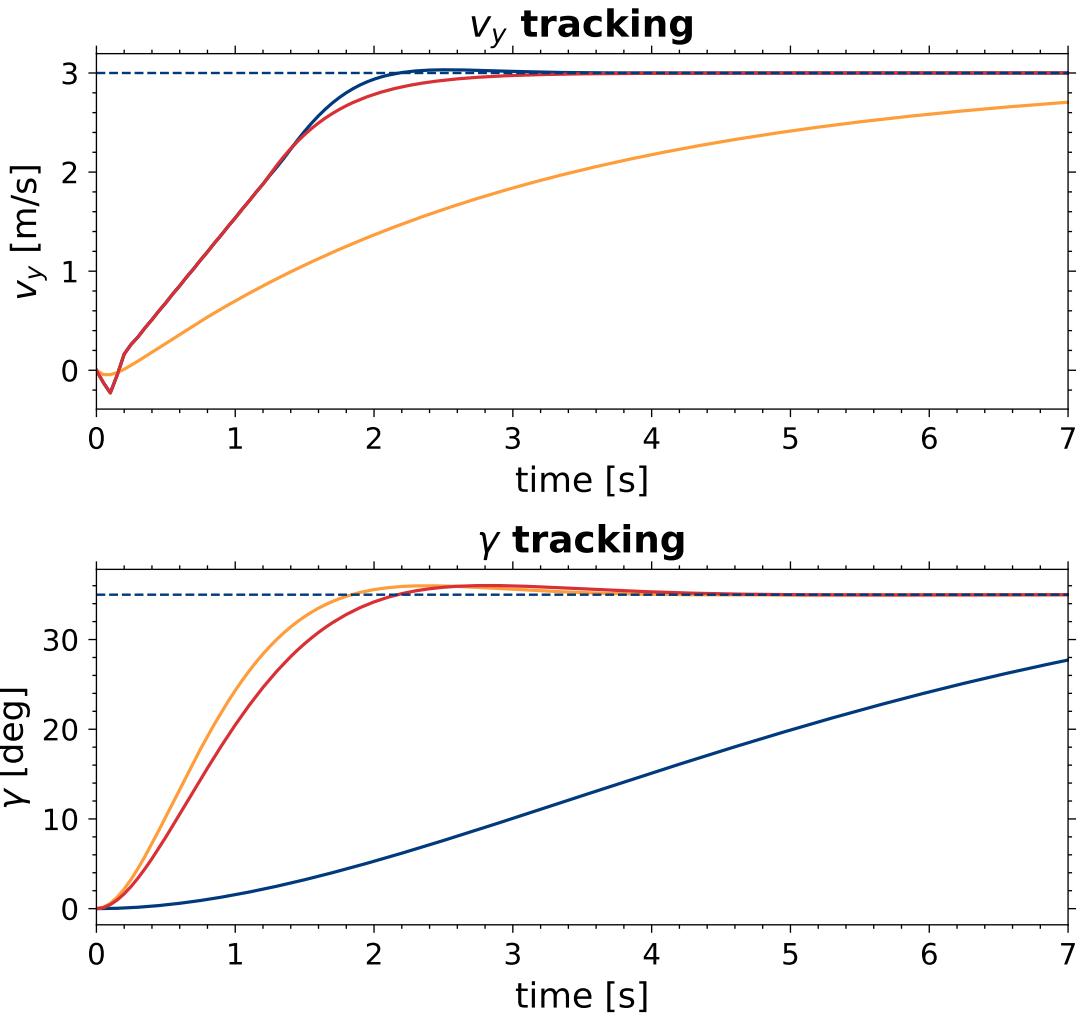
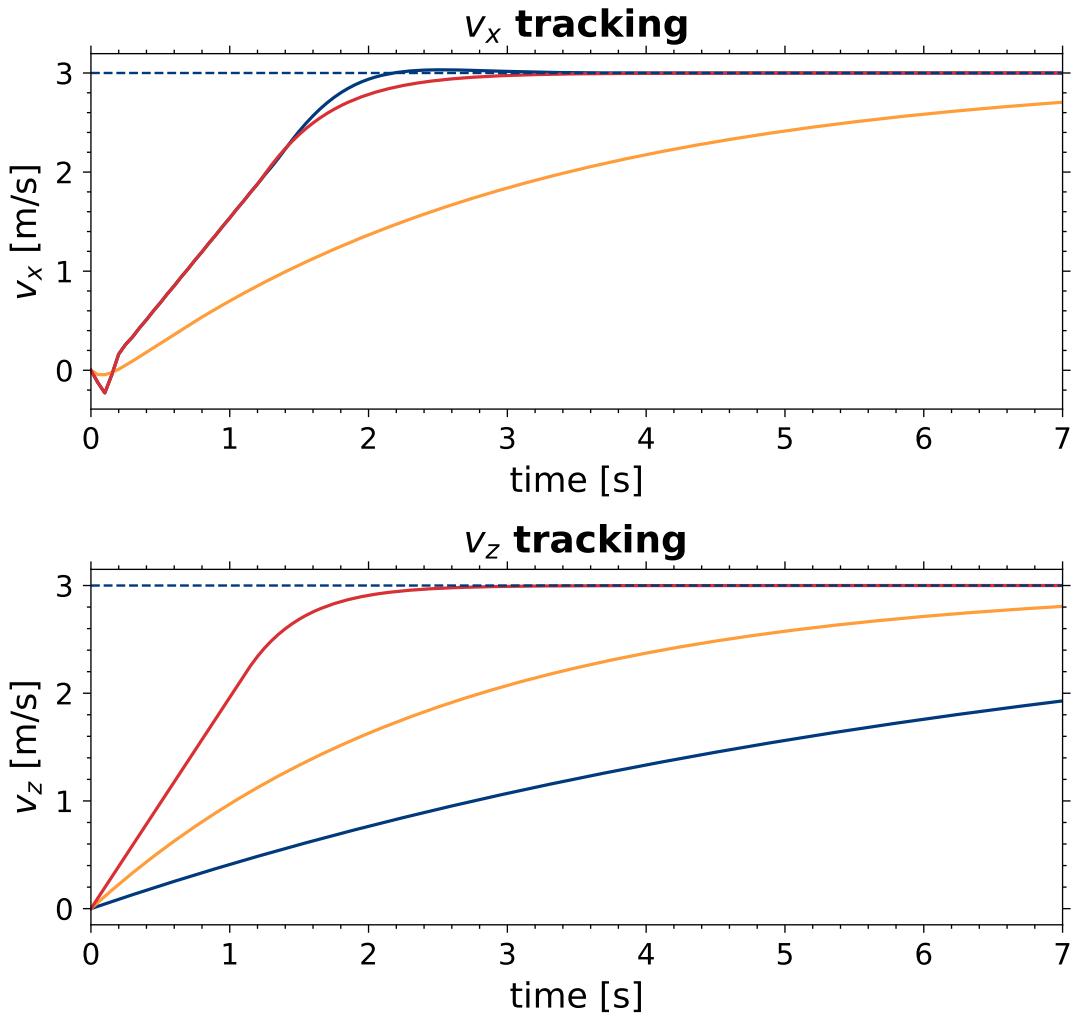


Closed-loop MPC tracking ($v_x, v_y, v_z = 3 \text{ m/s}$, roll = 35°)



$H = 5.0 \text{ s}, N = 100$

Identity $Q = I, R = I$

Heuristic $Q_{ii} = 1/x_{i,\max}^2, R_{ii} = 1/u_{i,\max}^2$

Final tuned