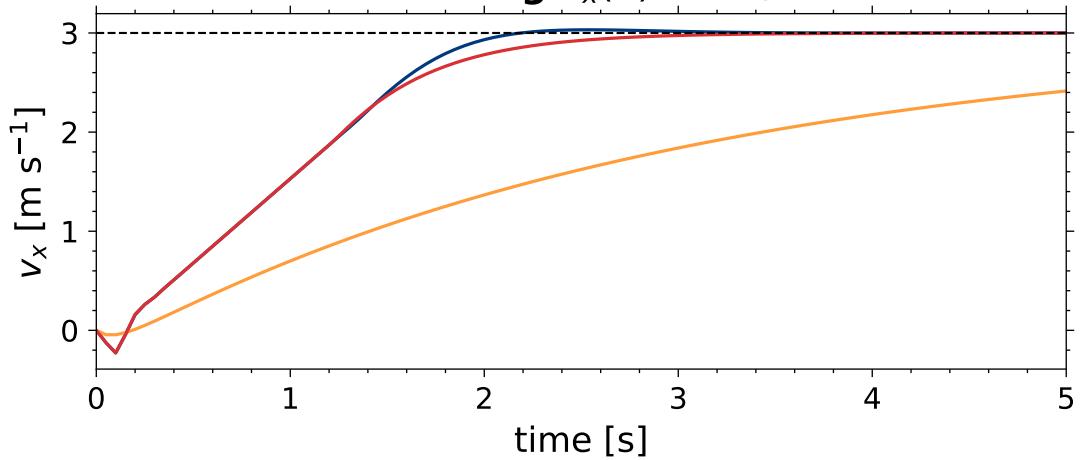
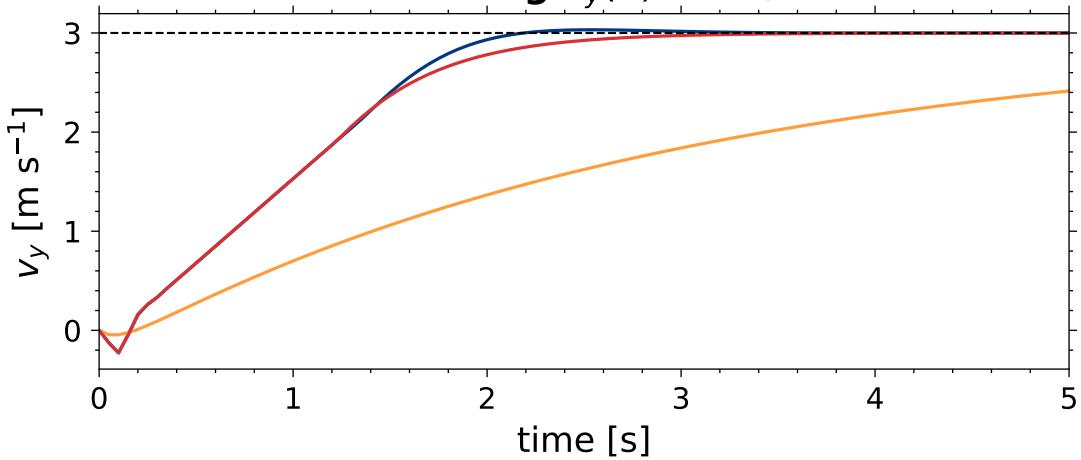


Open-loop MPC predictions for velocity and roll subsystems

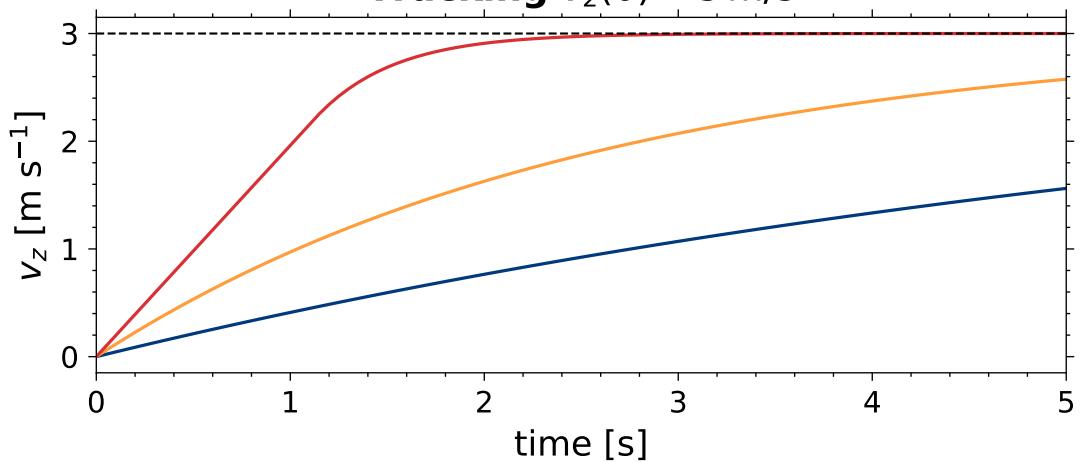
Tracking $v_x(0) = 3 \text{ m/s}$



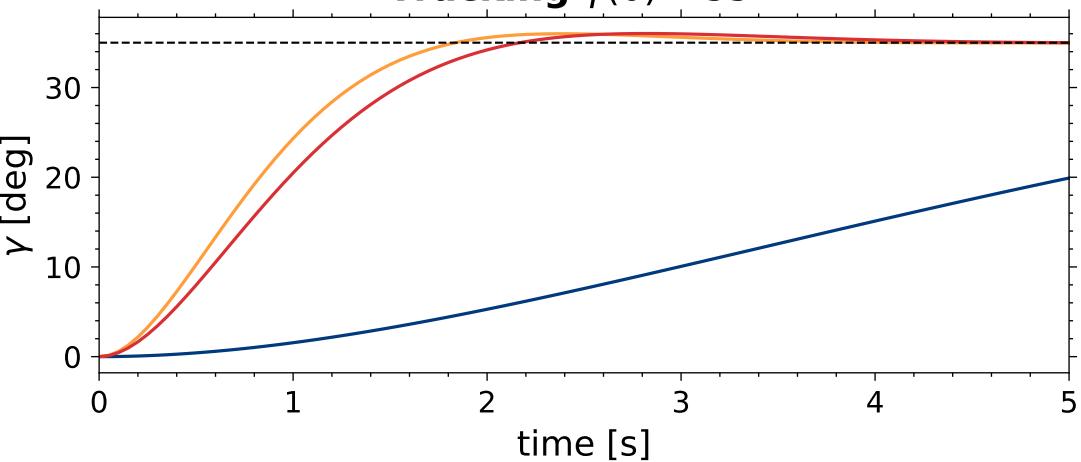
Tracking $v_y(0) = 3 \text{ m/s}$



Tracking $v_z(0) = 3 \text{ m/s}$



Tracking $\gamma(0) = 35^\circ$



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

Identity $Q = I, R = I$

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

Final tuned