

Parameter estimation

ϕ

(a)

Trim flights

(\mathbf{n}^*, ϵ)

(b)

e_{pz}

Altitude controller

Horizontal
Translational
Controller

(e_{px}, e_{py})

\mathbf{n}^d

Attitude controller

$f_{m,i}$

ω

IMU

Dynamics

R_b^w

\otimes
 p^d

Real Time
Low-pass filter

p