



Fig. 20 Circular motion of target; Quadrotor system performance; with wind and noise; $K_P = 0.5, K_{Pr} = 0.1, K_D = 2, K_{Pa} = 0.3, K_{Da} = K_{Dr} = 2$; Control: (a) 8.1, Table 8; $K_{Dr} = 0$, (b) 8.2, Table 8; $K_{Dr} = 1$, (c) 8.3, Table 8; $K_{Dr} = 0$.