Fig. 23 Lawnmower pattern; with wind and noise; Control: 8.1, Table 8; $K_P = 0.2, K_{Pr} = 0.05, K_D = 2, K_{Dr} = 0, K_{Dr\alpha} = 2, K_{D\alpha} = 0.4, K_{P\alpha} = 0.1$; (a) Quadrotor system performance, (b) Control performance, (c) Quadrotor trajectories.