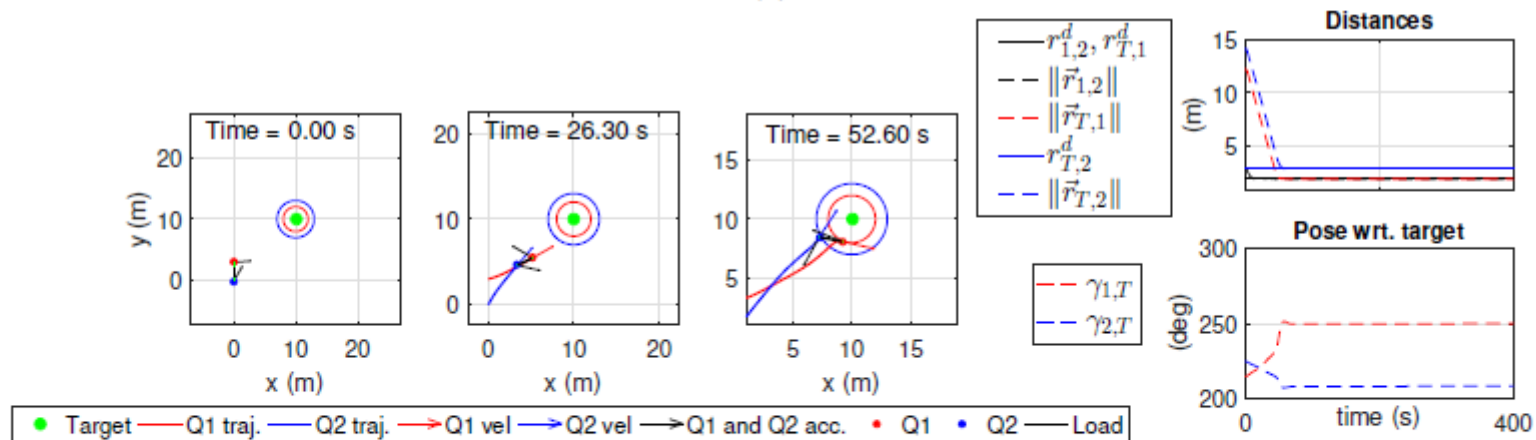


(a)



(b)

Fig. 10 Static target; NL model; Quadrotor system performance; Control: (a) 4.7, Table 4; $K_P = 0.05$, $K_{Pr} = 0.05$, $K_D = 0.9$, $K_{Dr} = 0$, (b) 4.10, Table 4; $K_P = 0.2$, $K_{Pr} = 0.1$, $K_D = 0.9$, $K_{Dr} = 0.5$.