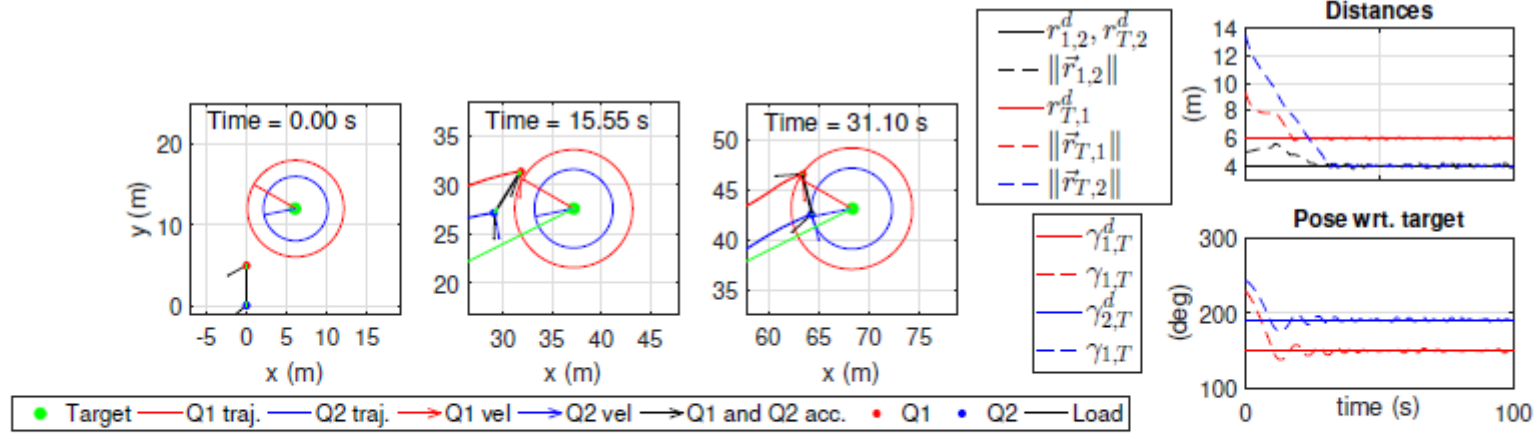


(a)



(b)

Fig. 16 Moving target (straight); Quadrotor system performance; with wind and noise; $K_P = 0.3, K_{P_r} = 0.05, K_D = 0.9, K_{D_\alpha} = K_{D_{r_\alpha}} = 0.2, K_{P_\alpha} = 0.3$; Control: (a) 6.5, Table 6; $K_{D_r} = 0$, (b) 6.6, Table 6; $K_{D_r} = 0.5$.