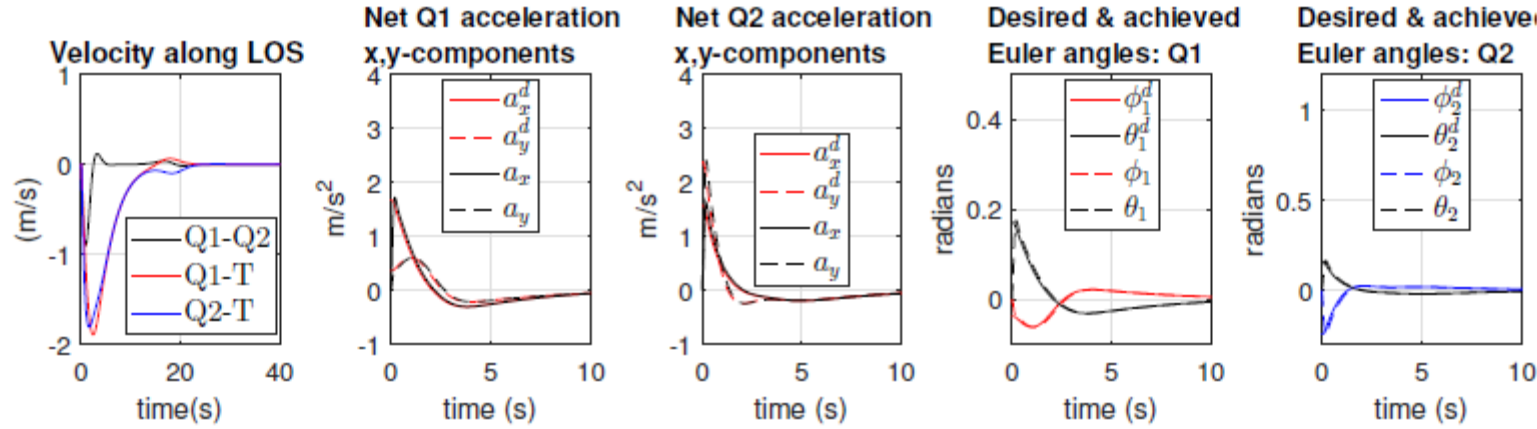


(a)



(b)

Fig. 8 Static target; Nonlinear (NL) model; $K_P = 0.2, K_{Pr} = 0.8, K_D = 0.9, K_{Dr} = 0.5$; (a) Quadrotor system performance, and (b) Control performance.