Fig. 21 Lawnmower pattern; $K_P = 1, K_{Pr} = 1.5, K_D = 2, K_{Dr} = K_{Dr\alpha} = 2, K_{D\alpha} = 0.4, K_{P\alpha} = 0$; (a) Quadrotor system performance, (b) Control performance, (c) Quadrotor trajectories.