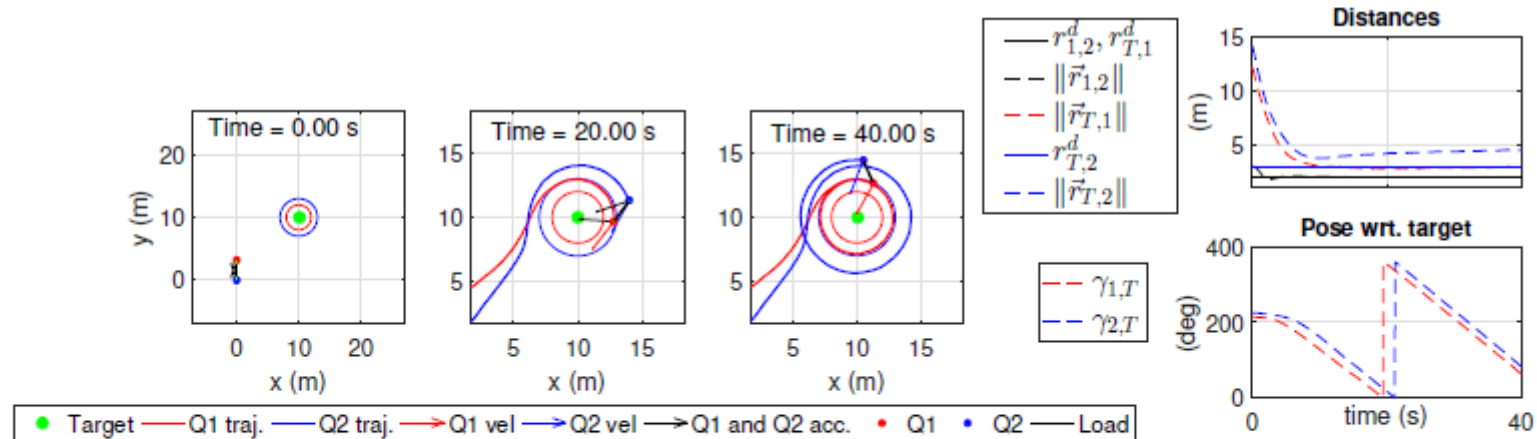Fig. 9 Static target; NL model; $K_P = 0.2, K_{Pr} = 0.8, K_D = 0.9, K_{Dr} = 0.5$; Quadrotor system performance (a) with sensor noise (b) with sensor noise and wind.