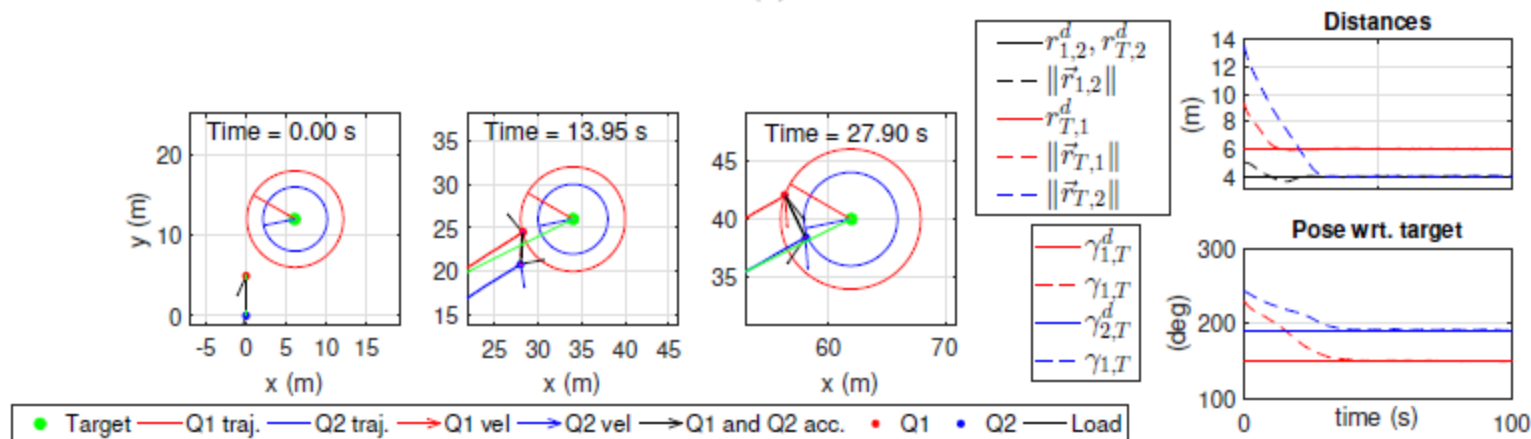


(a)



(b)

Fig. 15 Moving target; Quadrotor system performance; with wind and noise; $K_P = 0.3, K_D = 0.9, K_{D_r} = 0, K_{D_\alpha} = K_{D_{r_\alpha}} = 0.2, K_{P_\alpha} = 0.3$; Control: (a) 5.4, Table 5; $K_{P_r} = 0.05$, (b) 5.9, Table 5; $K_{P_r} = 0.1$.