There are separate Drone Files created for each question, and a modified *quadcopter_script.m* is used to run the tasks in each question.

The submitted drone files are named as follows:

- *Drone_q1*
- *Drone_q2*
- *Drone_q3a*
- *Drone_q3b*
- *Drone_q3c*

An additional function file is submitted called *dlinearise.m* which linearises the non-linear model around the equilibrium point. This function file also discretises the linearised model created.

To run the scripts for each question please change the name of the class called in *quadcopter_script.m* as shown in figure A1.

```
70      %instantiate a drone object, input the axis and arena limits
71      drones = [];
72      for i = 1:num_drones
73          % Please change the name of the class here to reflect the appropriate
74          % version of quadcopter simulation to run according to question.
75          drones = [drones Drone_q1(ax1, ax2, ax3, spaceDim, num_drones)];
76      end
```

Figure A1 – changing quadcopter_script.m to run the respective tasks from each question

The simulation will start with figures for quadcopter simulation, position and orientation being plotted on top of one another. Please move the windows accordingly to show all plots as required.