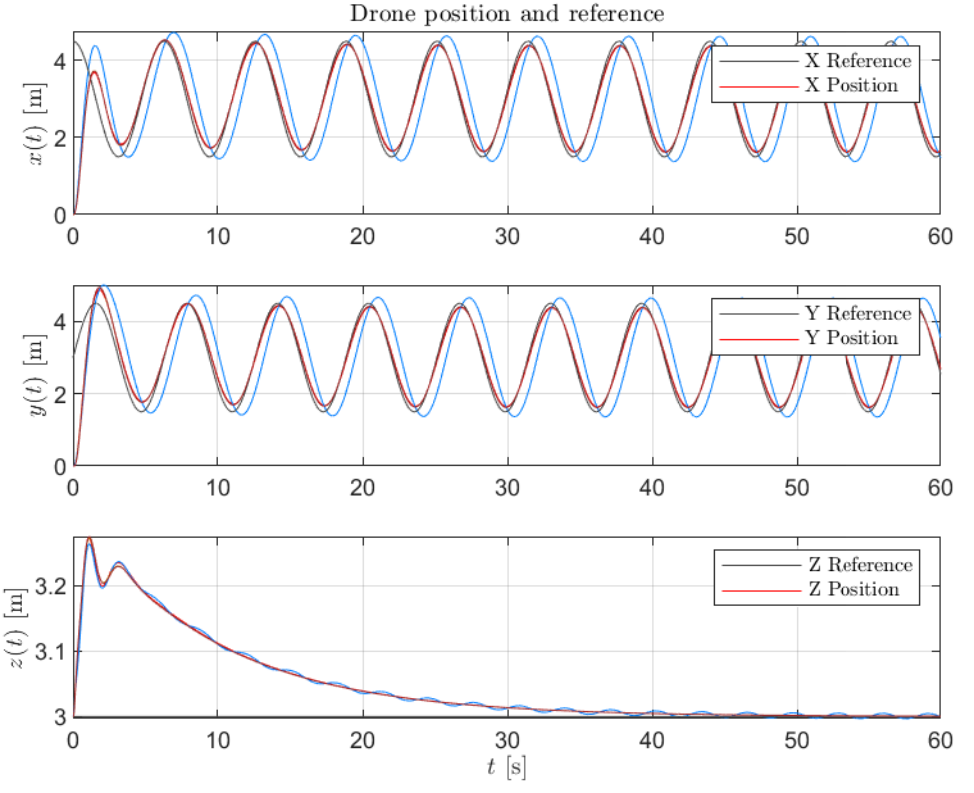
Drone position and reference
X Reference
X Position
$x(t)$ [m]
Y Reference
Y Position
$y(t)$ [m]
Z Reference
Z Position
$z(t)$ [m]
t [s]
0
10
20
30
40
50
60
0
2
4
3
3.1
3.2