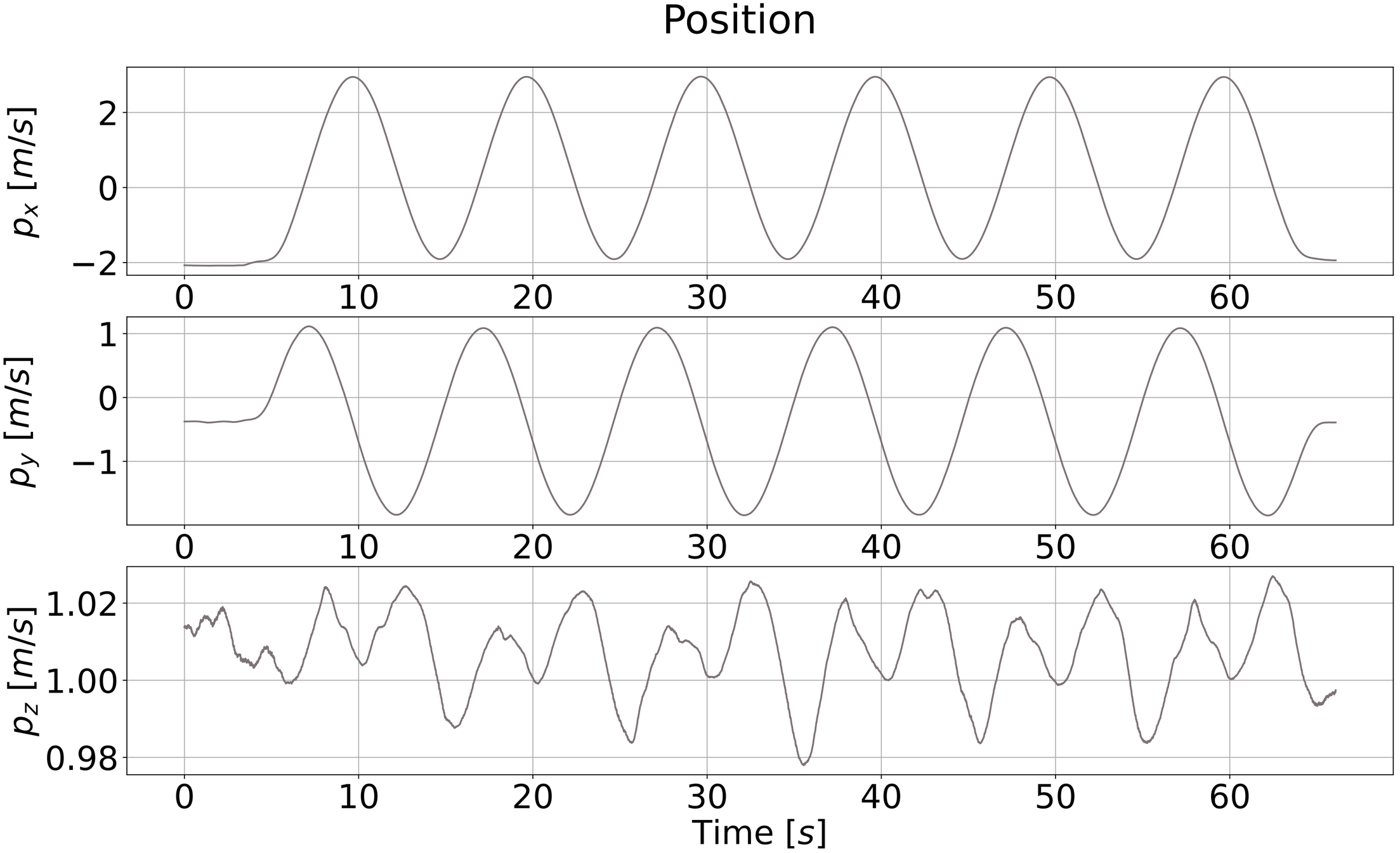
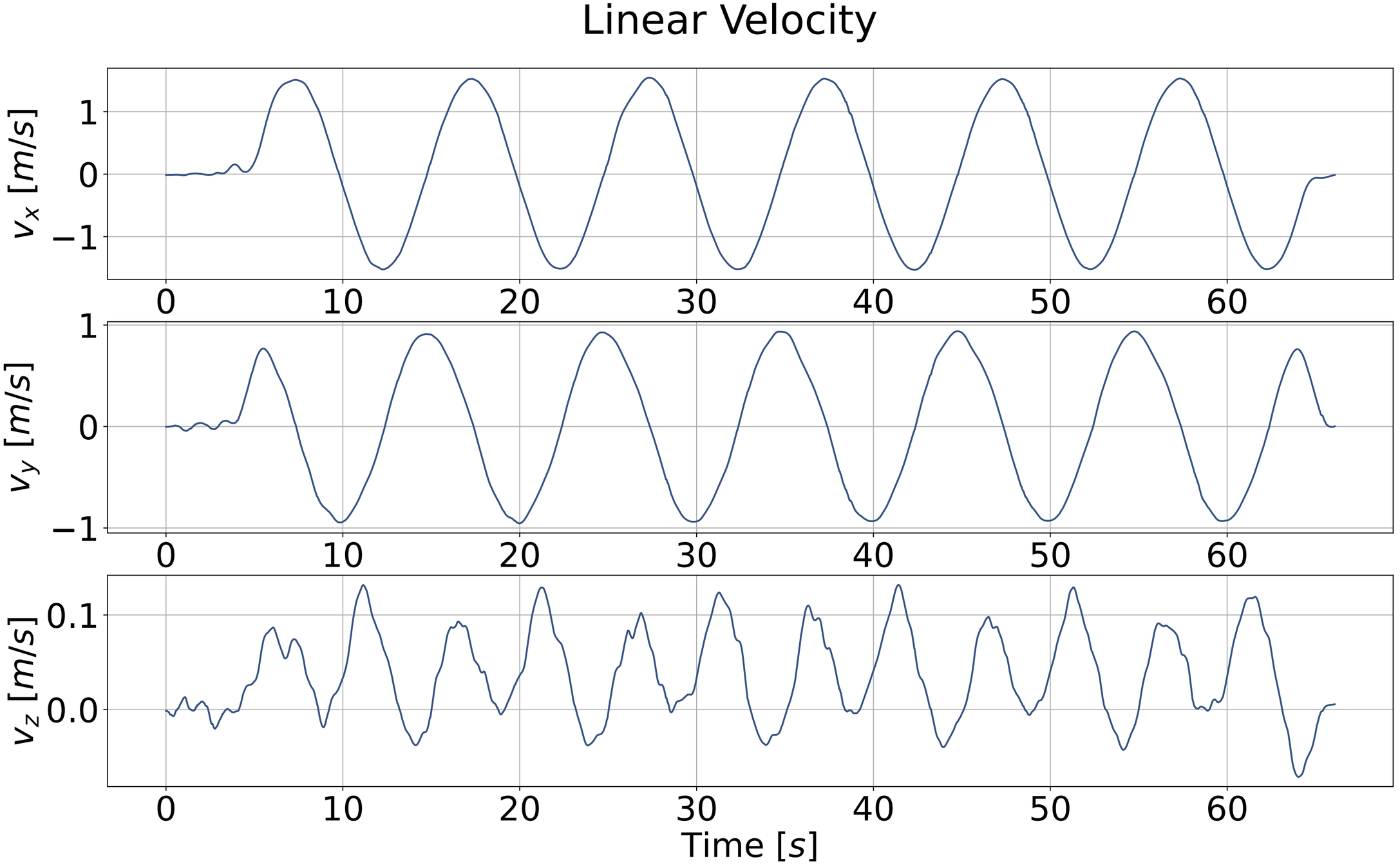
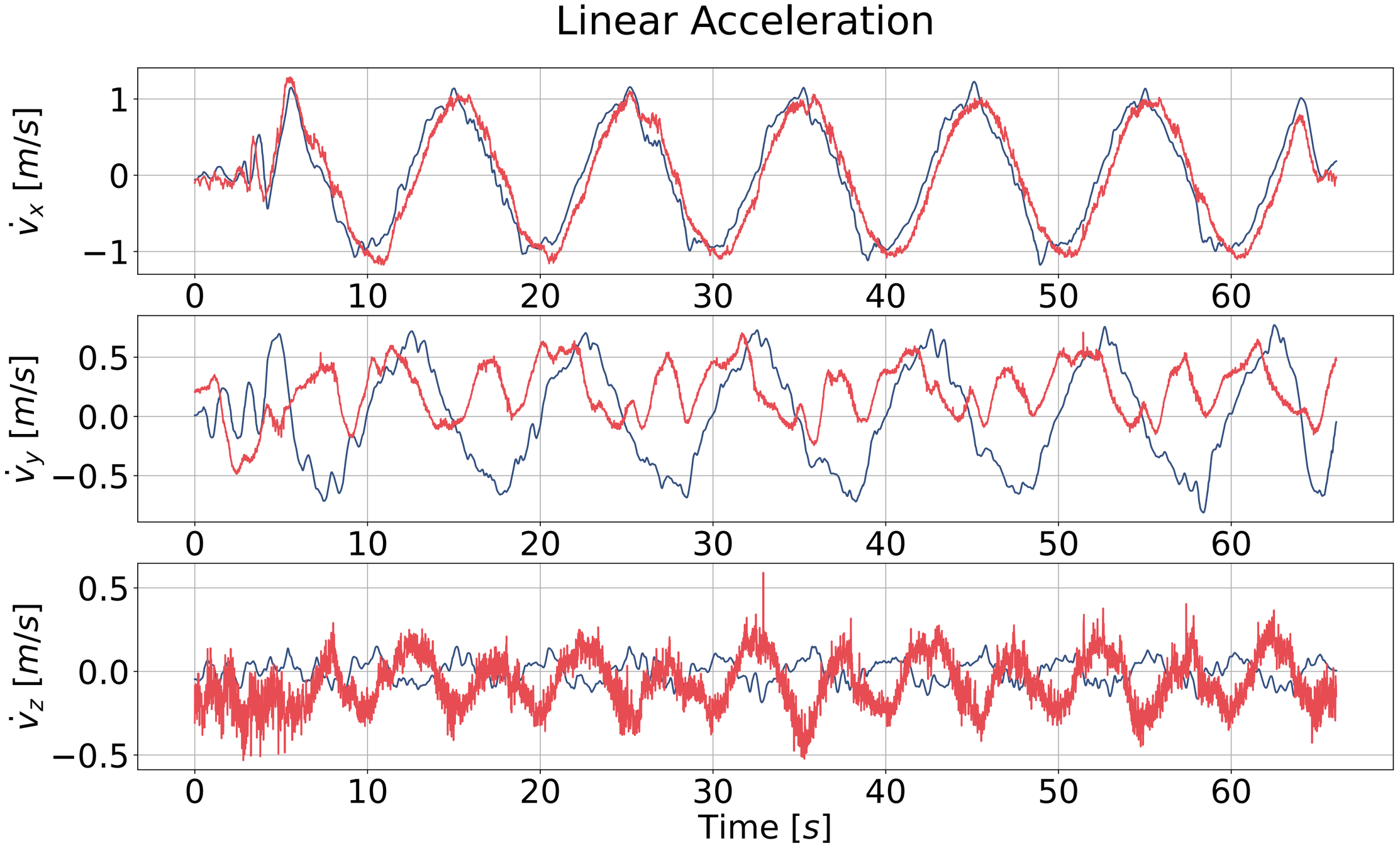
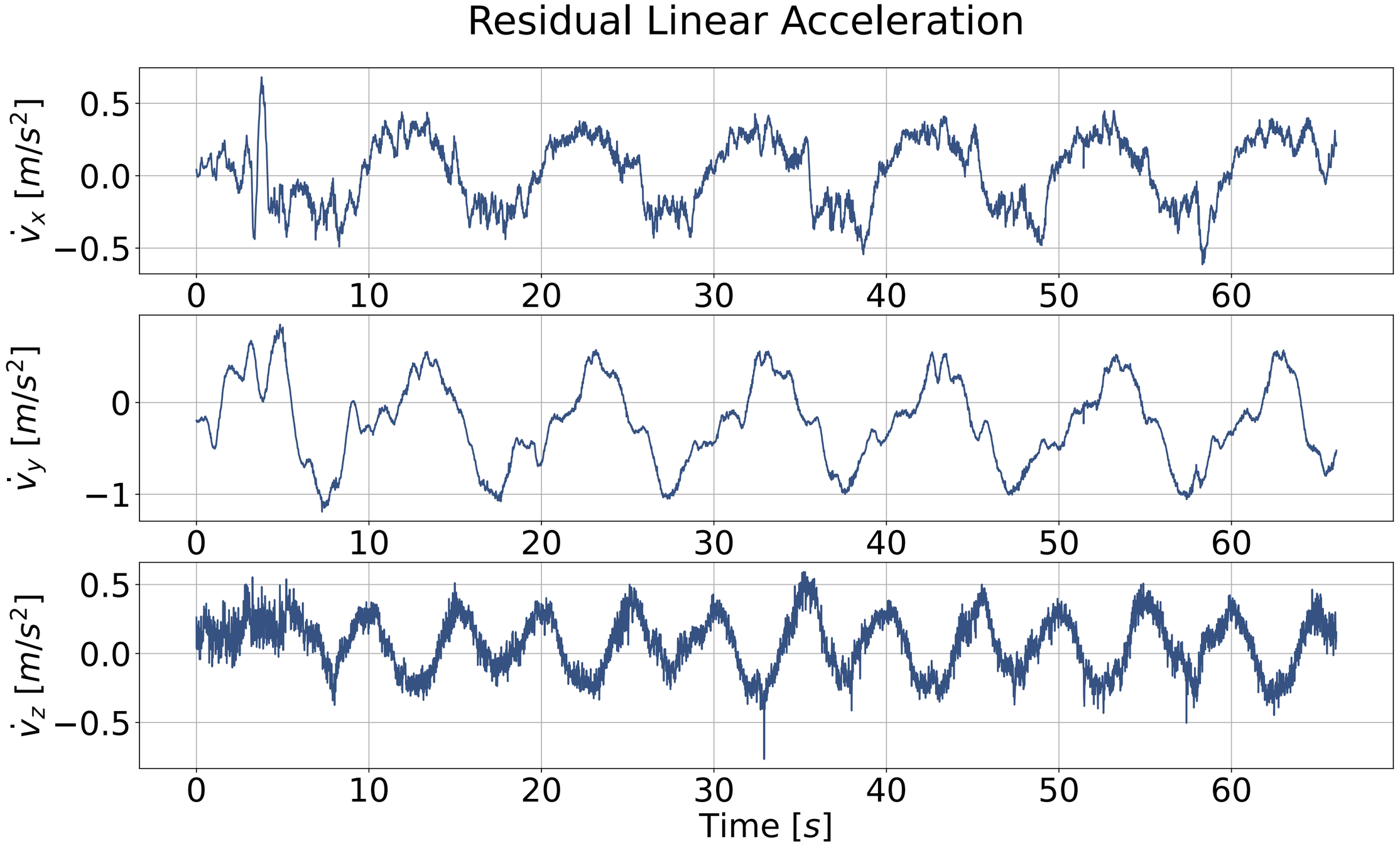
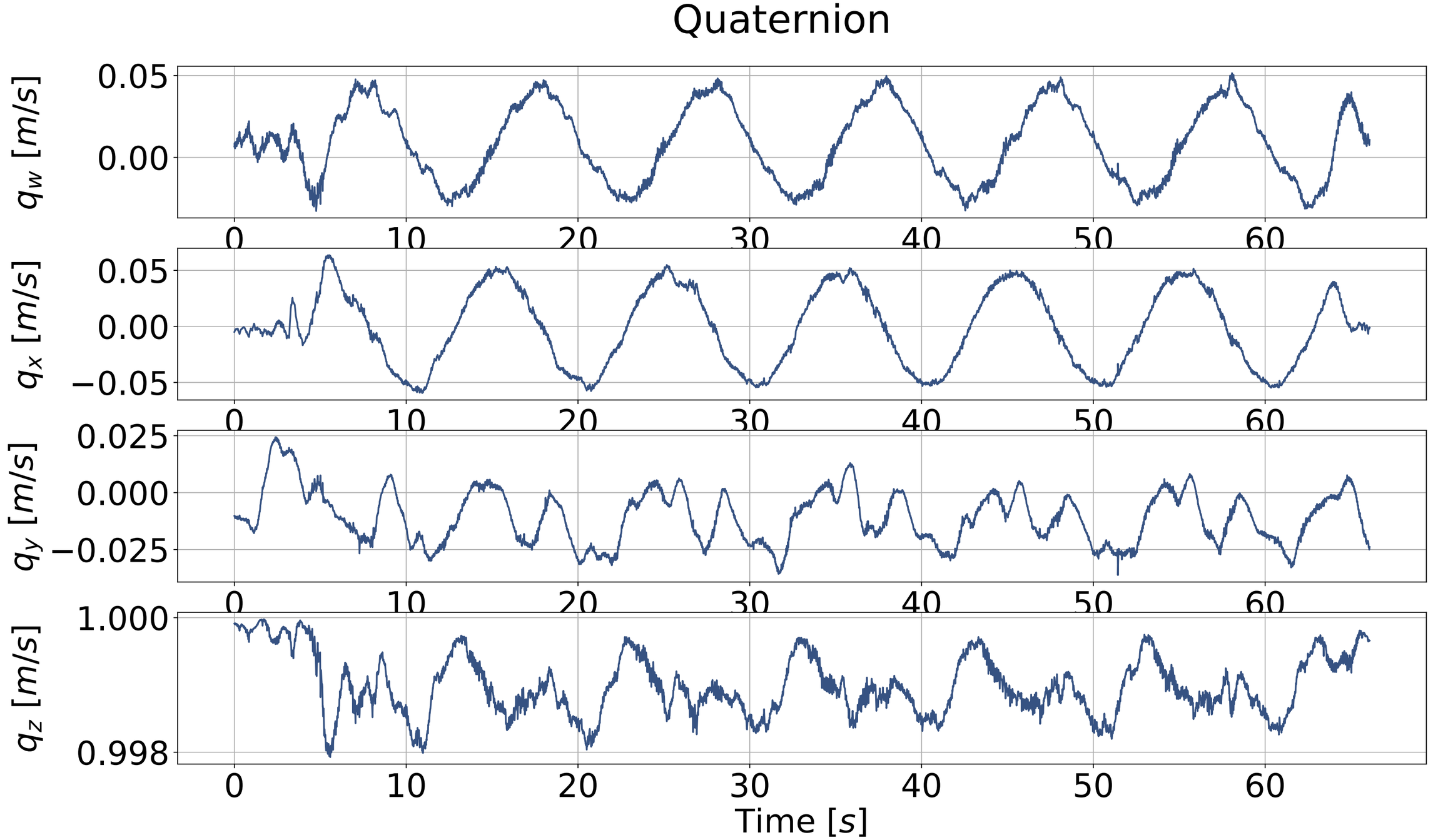
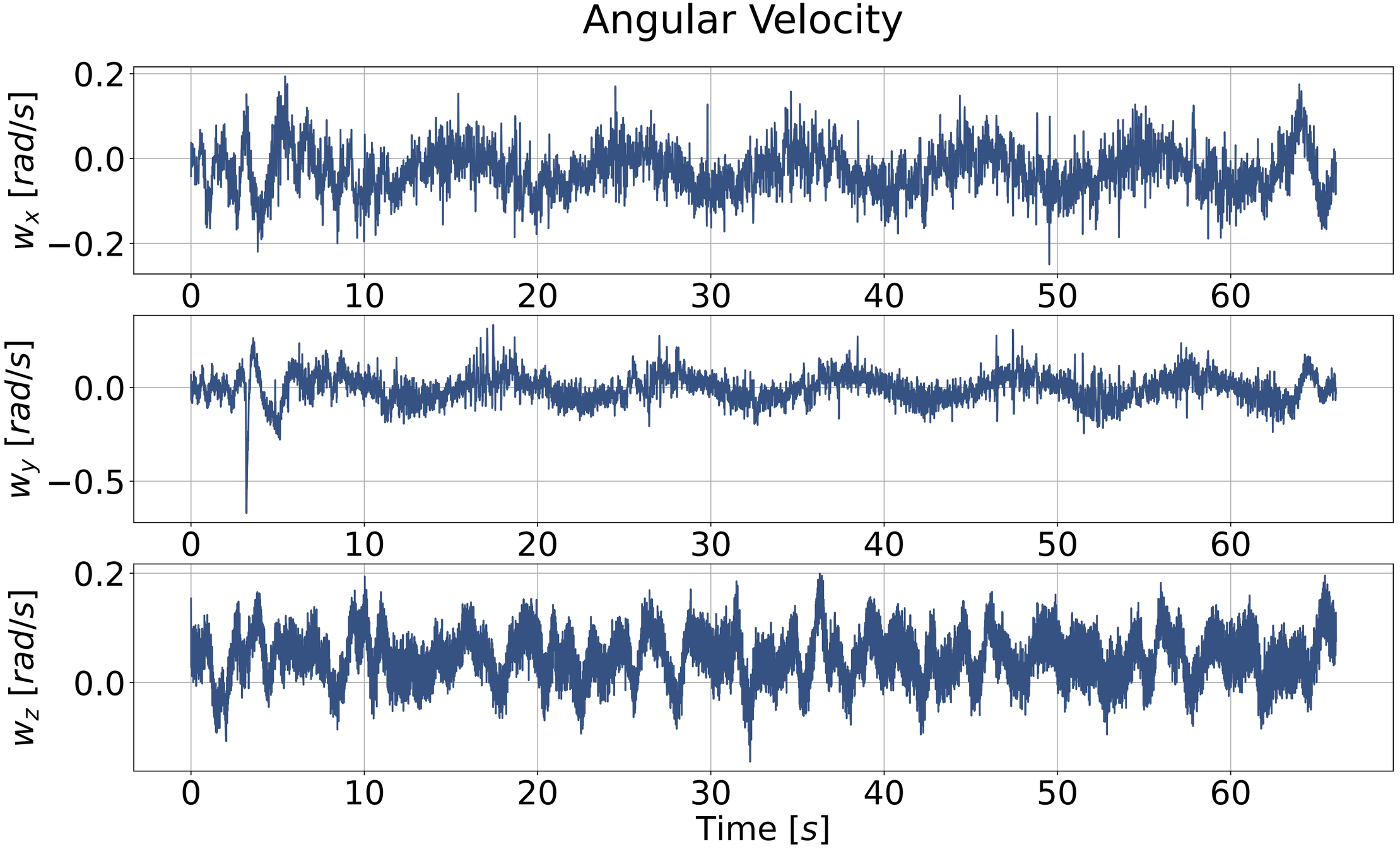

Position
p_x [m/s]
2
0
−2
0
10
20
30
40
50
60
p_y [m/s]
1
0
−1
0
10
20
30
40
50
60
p_z [m/s]
1.02
1.00
0.98
0
10
20
30
40
50
60
Time [s]

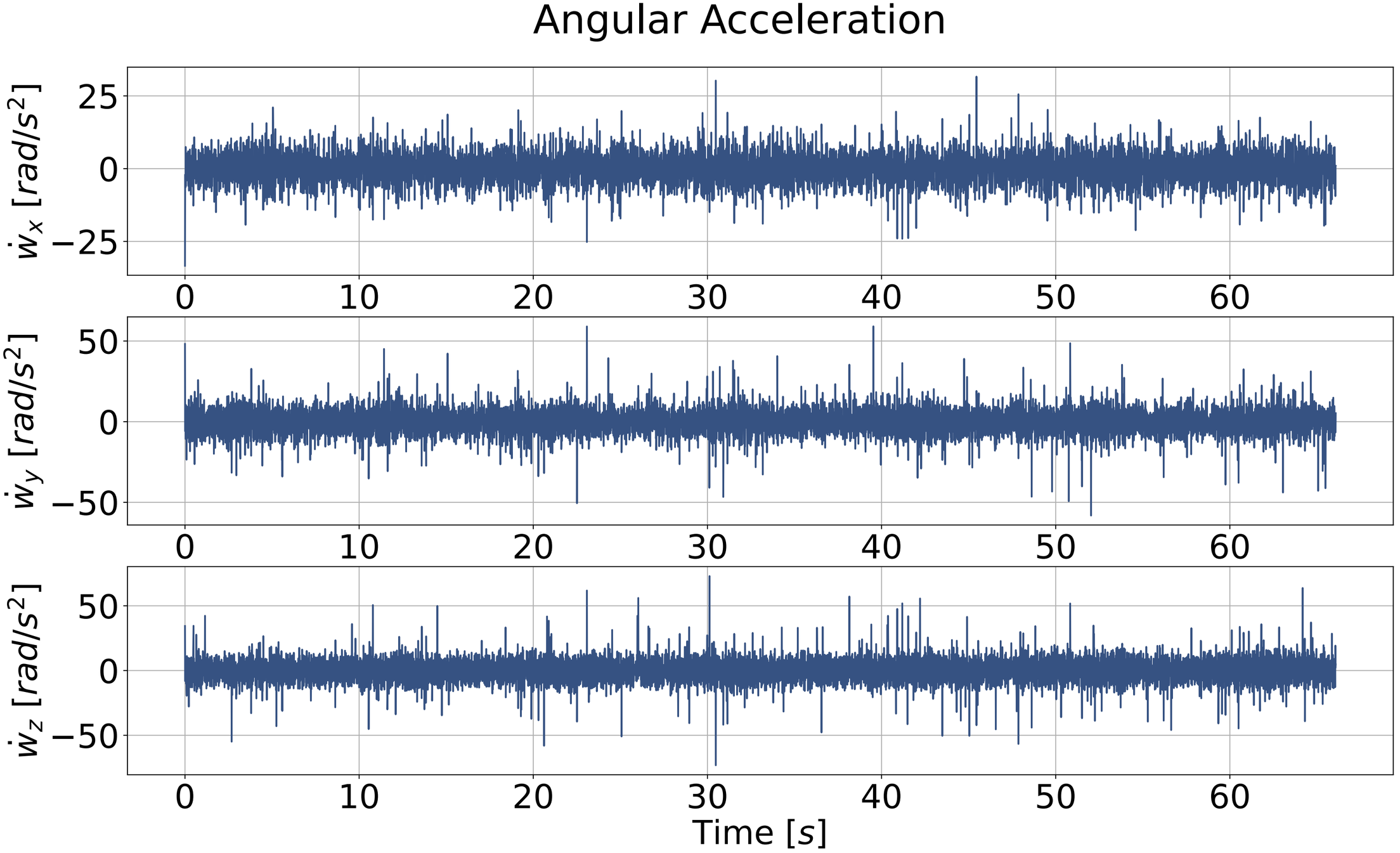

Linear Velocity
v_x [m/s]
1
0
−1
0
10
20
30
40
50
60
v_y [m/s]
1
0
−1
0
10
20
30
40
50
60
v_z [m/s]
0.1
0.0
0
10
20
30
40
50
60
Time [s]

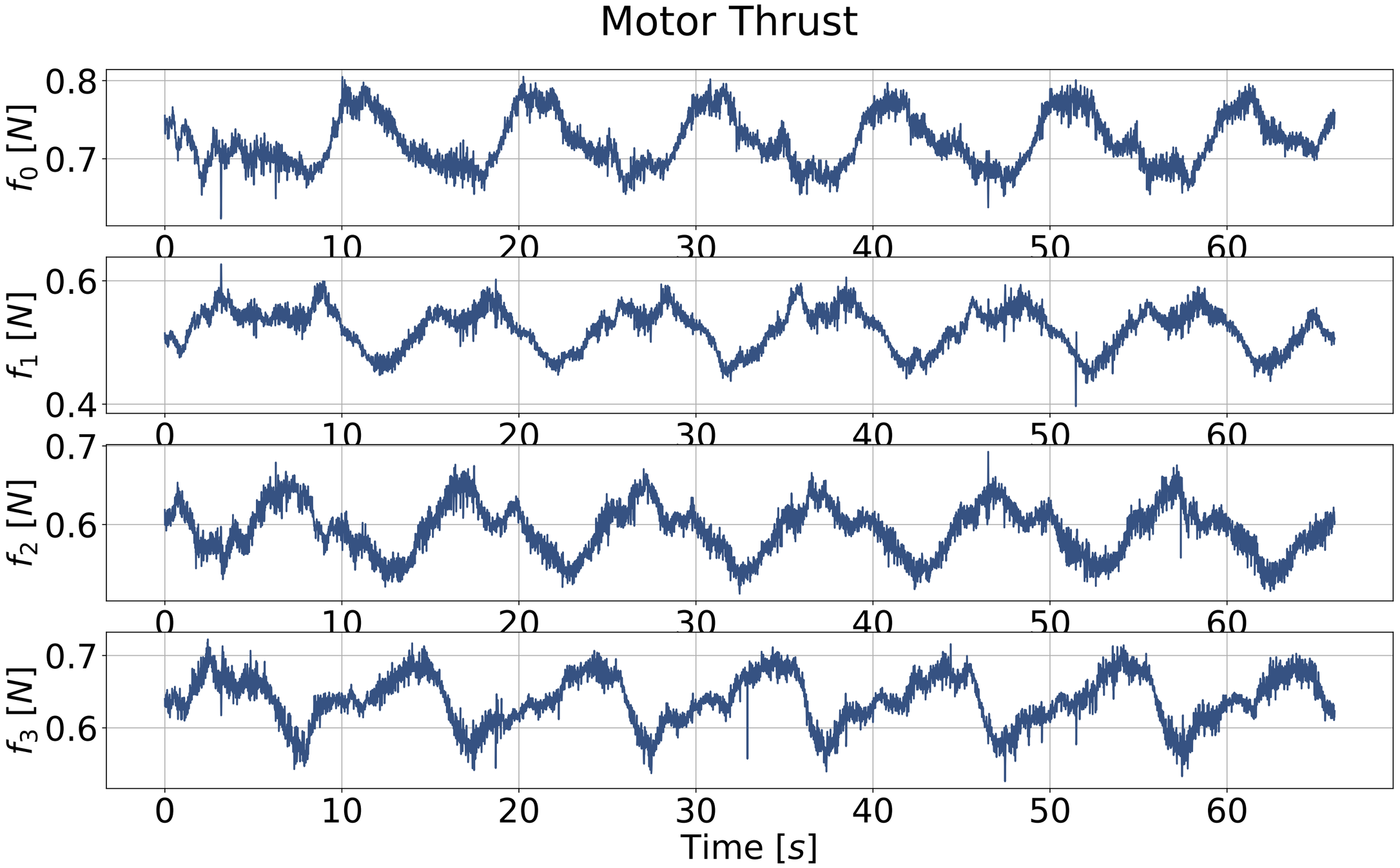

Linear Acceleration
$\dot{v}_x$ [m/s]
$\dot{v}_y$ [m/s]
$\dot{v}_z$ [m/s]
Time [s]
1
0
−1
0.5
0.0
−0.5
0
10
20
30
40
50
60

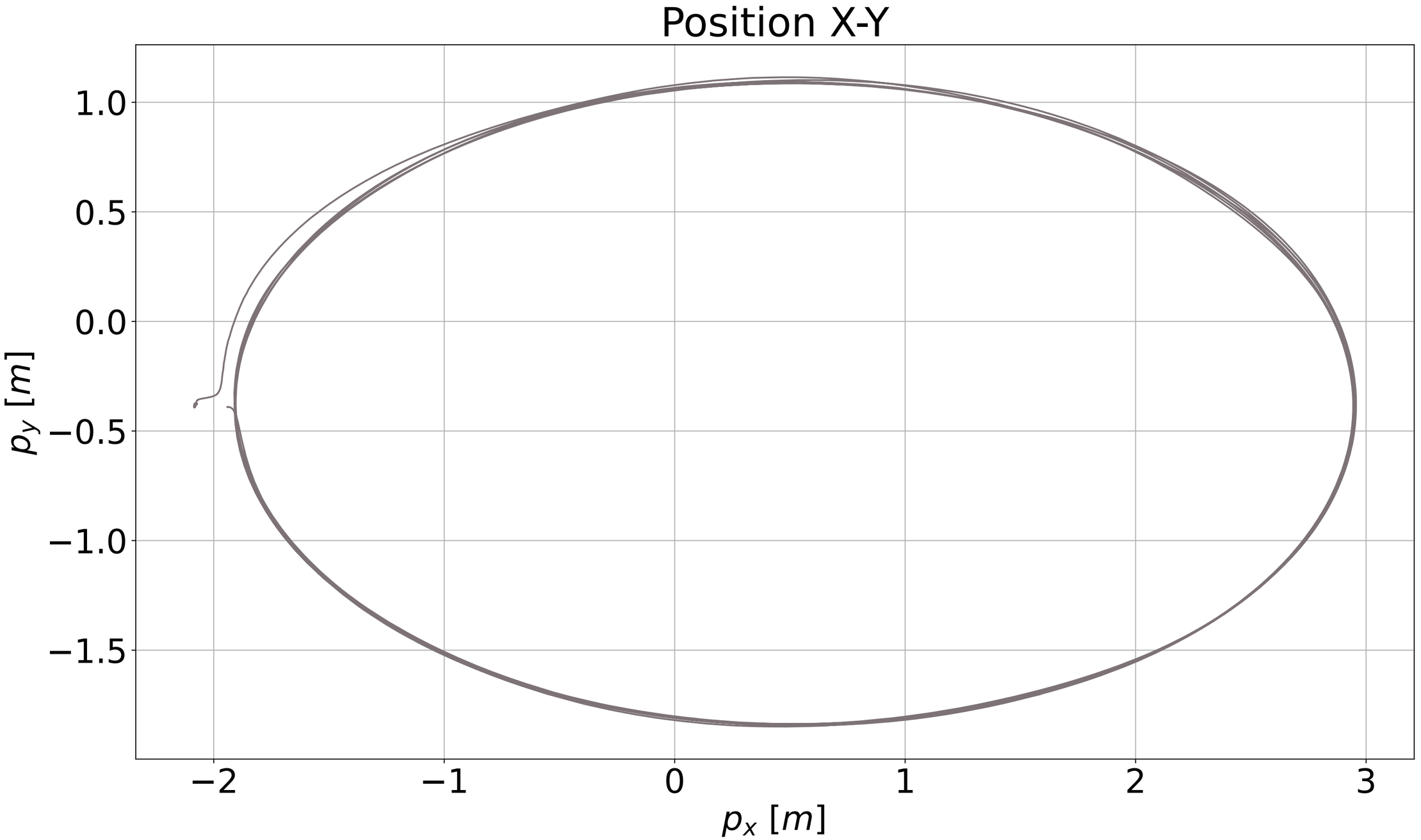

Residual Linear Acceleration
$\dot{v}_x$ $[m/s^2]$
0.5
0.0
−0.5
0
10
20
30
40
50
60
$\dot{v}_y$ $[m/s^2]$
0
−1
$\dot{v}_z$ $[m/s^2]$
Time $[s]$

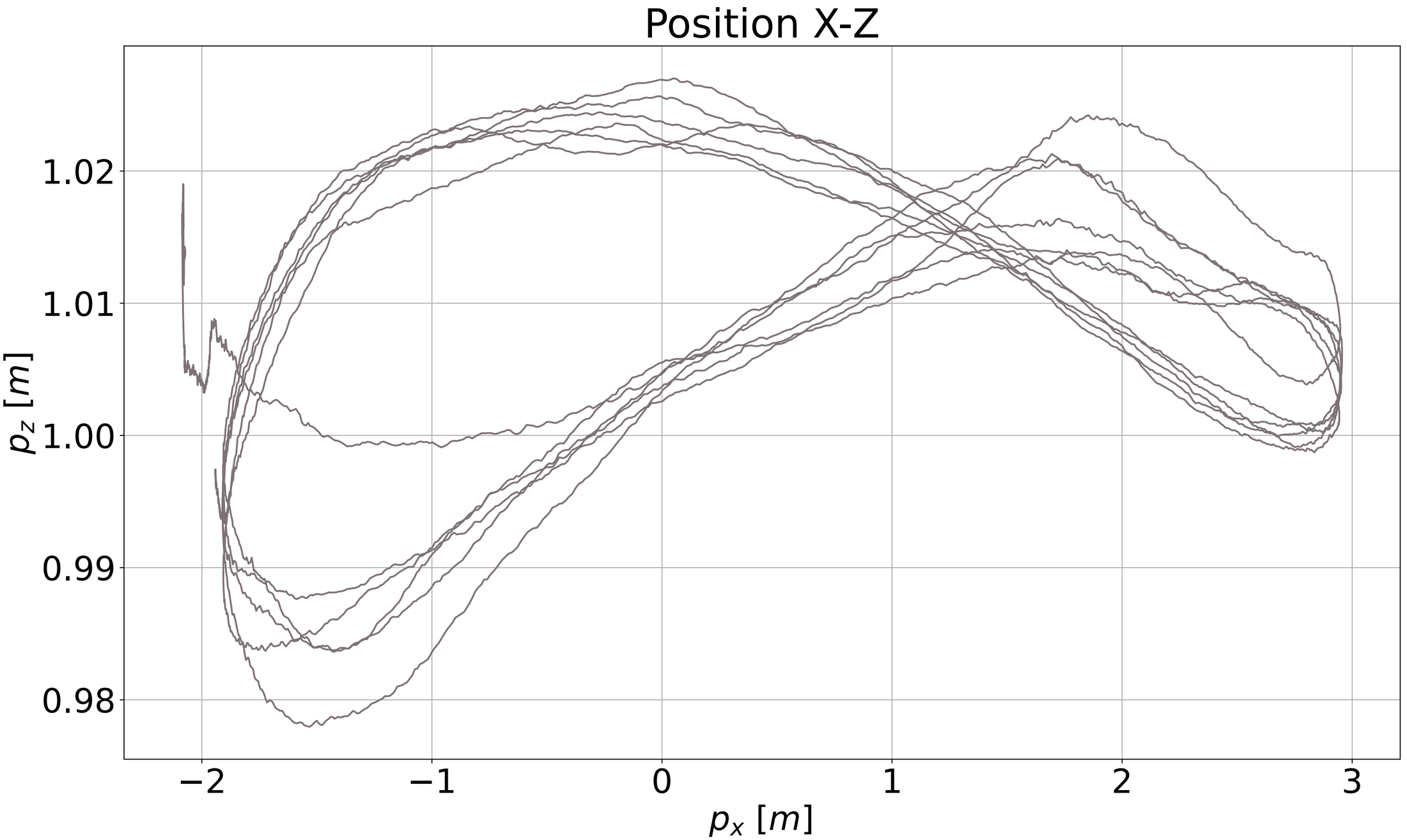

Quaternion
q_w [m/s]
0.05
0.00
q_x [m/s]
0.05
0.00
−0.05
q_y [m/s]
0.025
0.000
−0.025
q_z [m/s]
1.000
0.998
0
10
20
30
40
50
60
Time [s]

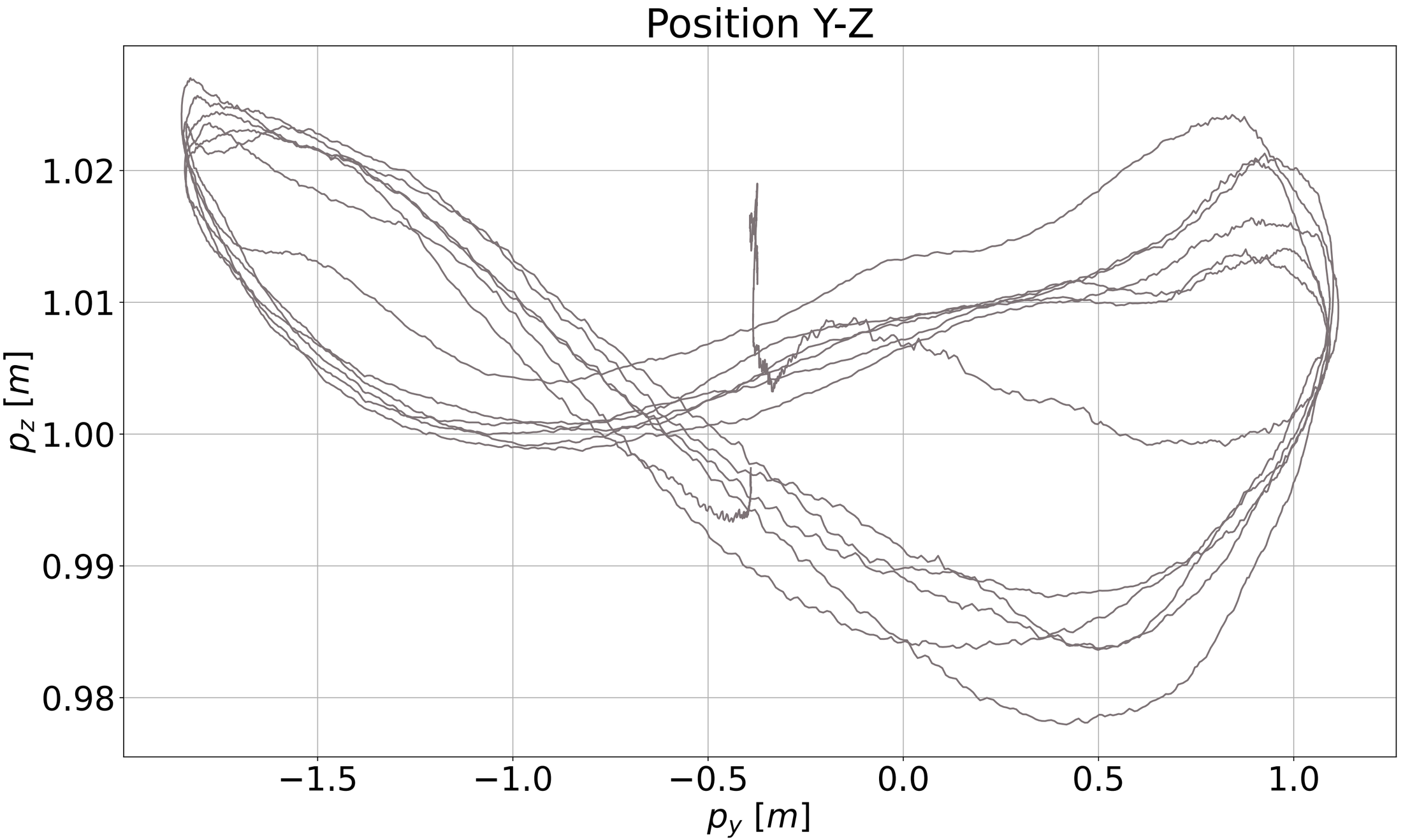

Angular Velocity
w_x [rad/s]
0.2
0.0
−0.2
0
10
20
30
40
50
60
w_y [rad/s]
0.0
−0.5
w_z [rad/s]
Time [s]


Angular Acceleration
$\dot{w}_x$ [rad/s^2]
25
0
−25
0
10
20
30
40
50
60
$\dot{w}_y$ [rad/s^2]
50
0
−50
0
10
20
30
40
50
60
$\dot{w}_z$ [rad/s^2]
50
0
−50
0
10
20
30
40
50
60
Time [s]


Motor Thrust
f_0 [N]
0.8
0.7
f_1 [N]
0.6
0.4
f_2 [N]
0.7
0.6
f_3 [N]
0.7
0.6
0
10
20
30
40
50
60
Time [s]


Position X-Y
1.0
0.5
0.0
−0.5
−1.0
−1.5
p_y [m]
−2
−1
0
1
2
3
p_x [m]


Position X-Z
1.02
1.01
1.00
0.99
0.98
$p_z\ [m]$
−2
−1
0
1
2
3
$p_x\ [m]$


Position Y-Z
1.02
1.01
1.00
0.99
0.98
$p_z\ [m]$
−1.5
−1.0
−0.5
0.0
0.5
1.0
$p_y\ [m]$