gyroAxesSwap Velocity xPosition x0.4Setpoint x0.2 0.2 Position x0.1  $\cdots$  Estimated x0 Velocity x-0.20 Estimated velocity x -0.40 Position yVelocity y0.4Velocity y0.2 ----- Estimated velocity y 0.2Setpoint y0.1 Position y0  $\cdots$  Estimated yVelocity zPosition zVelocity z0.4 ----- Estimated velocity z0.5Setpoint z0.2 Position zEstimated z 0 10 Acceleration x, y, zAttitude x, y, z**-** z 0.1**y** -20 10 -0.110 2 10 Gyro x, y, zz-range0.4 0.2z-range 0 2 2 10 6 10 Pixel count x, yKalman errors x, y, z1 5 0.5 0 -0.52 10 2 Motors control signals  $u_1$ Motors control signals  $u_2$  $\cdot 10^4$  $\cdot 10^{4}$ 6 6 4 2 2 **-** u<sub>1</sub>  $-u_2$ 0 10 Motors control signals  $u_3$ Motors control signals  $u_4$  $\cdot 10^{4}$ 6

2

 $---u_4$ 

**–** *u*<sub>3</sub>

10

2