Take Off - Visual Servoing - Cross The Gate - Land
Test info: {'Starting drone orientation': {'Roll': '0.0°', 'Pitch': '0.0°', 'Yaw': '90.0°'}, 'Relative angle': '45.0°', 'Sigma noise': '0.289 px', 'Take off height': '0.5 m'}

Time: 0.0s Position Orientation --- setpoint_z --- state_roll state_pitch --- state_x --- state_yaw — state_y **---** state_z Visual Servoing Take Off -2 Take Off Visual Servoing 150 Frame 150 Frame 250 300 100 200 250 300 50 img_0.png Velocity (body-fixed) **Angular Velocity** 0.8 --- setpoint_vx --- setpoint_wz 0.3 ___ state_roll_rate --- setpoint_vy 0.6 --- state_pitch_rate --- setpoint_vz 0.2 --- state_yaw_rate --- state_vx 0.4 --- state_vy --- state_vz -0.2-0.1--0.4-0.2−0.6 Visual Servoing Take Off Visual Servoing 150 Frame 150 Frame 250 200 300 100 200 250 300 100 50 50 IBVS error: nan 500 € — IBVS error 400-Norm of the error 200-200 100 150 250 300 Frame