Problem 1: 1D Quadrotor Controller
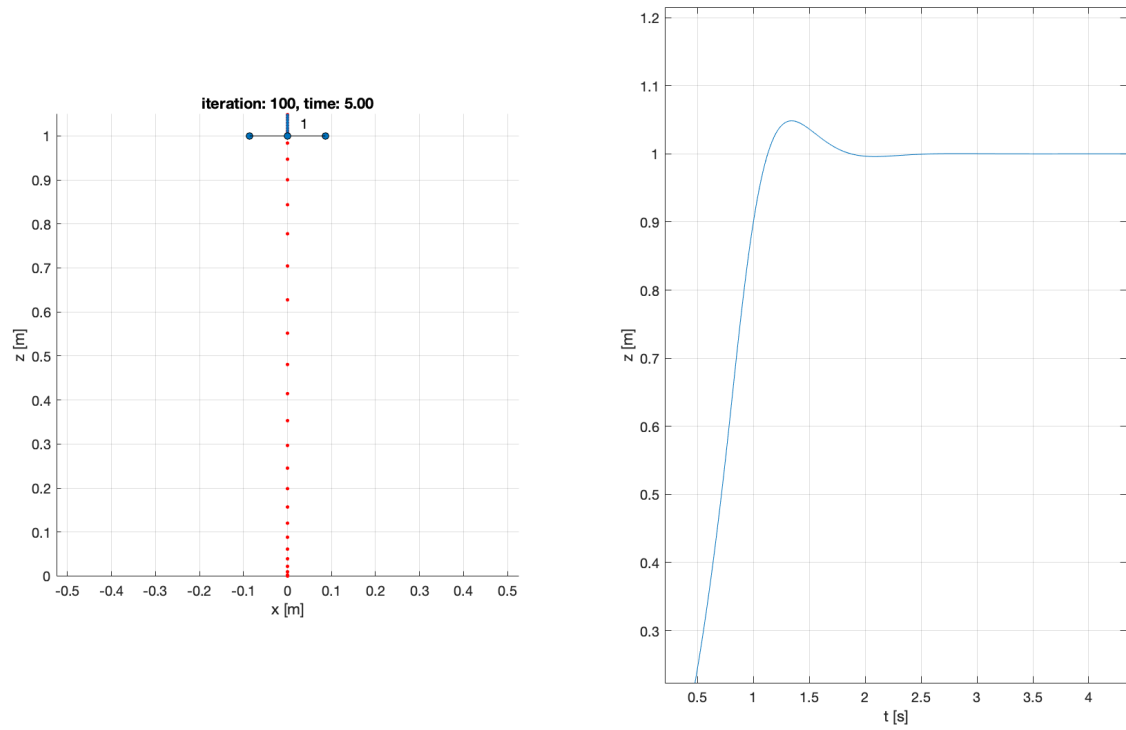

Figure 1: 1D quadrotor trajectory (rise time = 1s, max overshoot = 4.8%)

See `AMR_HW4_1/controller.m` for implementation.
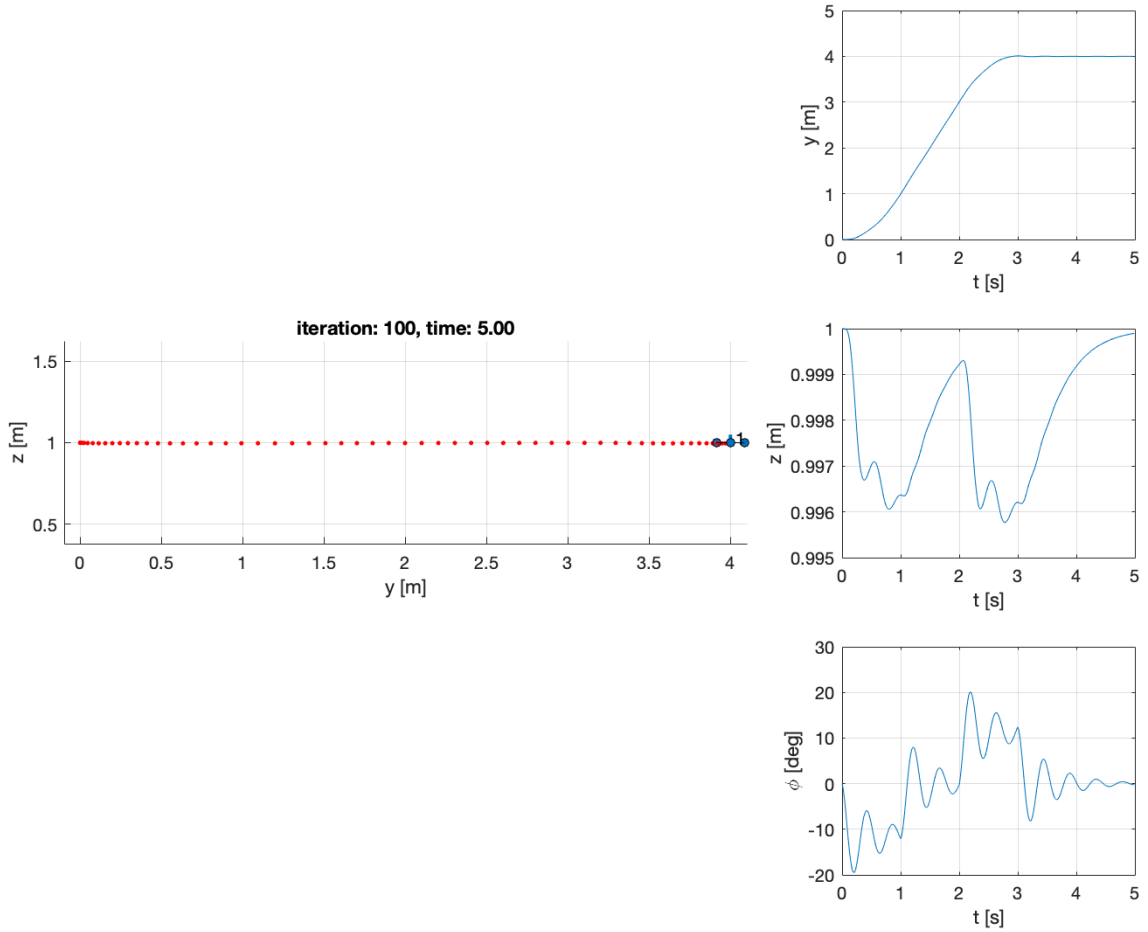
1 Problem 2: 2D Quadrotor Controller

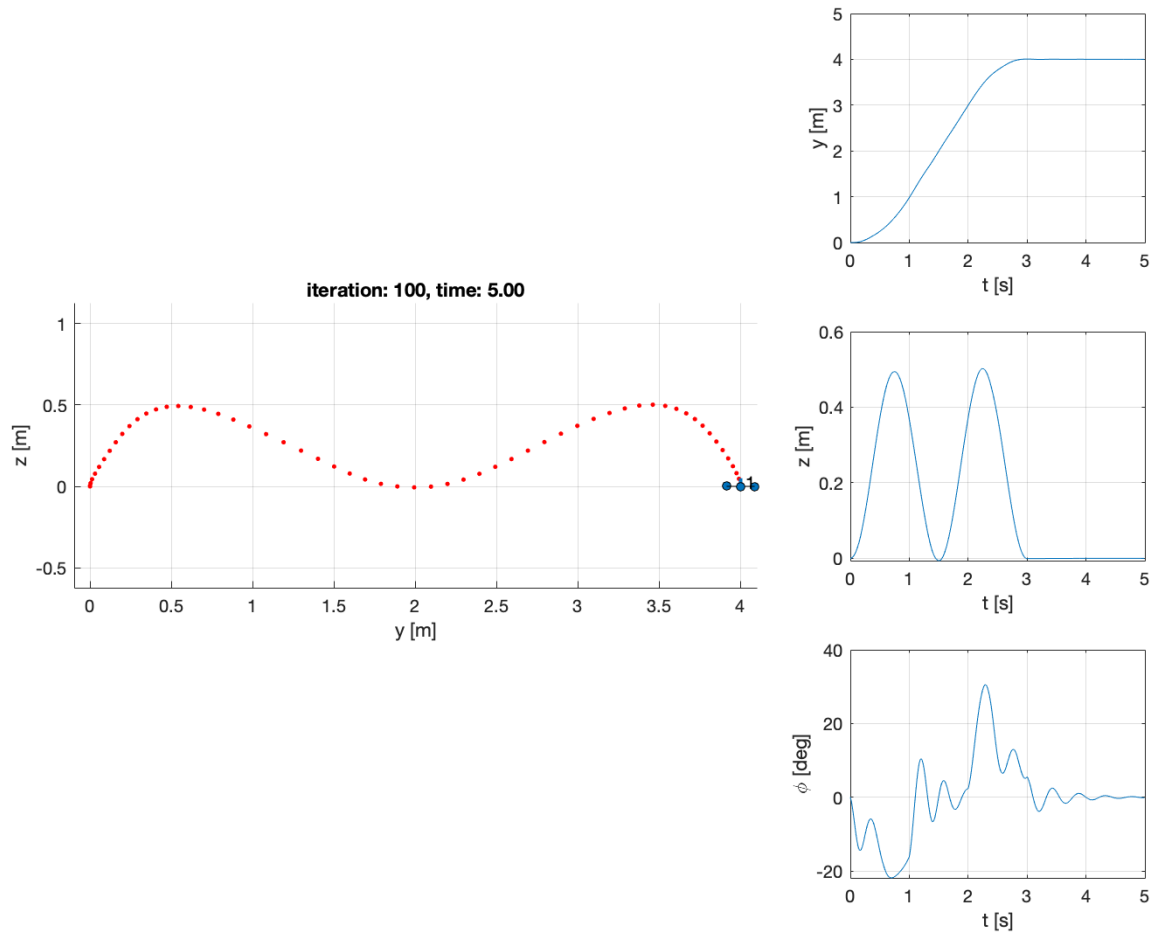Figure 2: 2D quadrotor trajectory (straight line)

Figure 3: 2D quadrotor trajectory (sine curve)

See `AMR_HW4_2/controller.m` for implementation.