

Sensor	Observation	Accuracy
IMU	β (drone heading)	3°
GNSS	Drone horizontal position	2 cm at twice the standard deviation (Bandini et al., 2017)
Radar	OD (range to water surface)	0.5 % of the actual range (Bandini et al., 2017)
Camera	Lw, Lh (offset between sonar and camera center along horizontal and vertical axis of the picture)	$\approx 3\%$ of the actual value