

**Table S1.** PID gains applied to attitude and altitude controls when the hexacopter is (a) at null and (b) with the fruit harvesting mechanism

	(a) at null			(b) with fruit harvesting mechanism		
	P	I	D	P	I	D
X	38	0.05	41.5	170	10	160
Y	38	0.05	41.5	180	15	150
Z	35	0	43	140	2	100
Attitude	81	0	20	130	0	30.2