CORRECTION

유상하중의 불확실성을 고려한 쿼드로터의 모델 참조 적응제어 기법 설계

이동우[1], 김남수[2], 장광우[3], 이성헌[4], 방효충[5]

Model Reference Adaptive Control of a Quadrotor Considering the Uncertainty of Payload

Dongwoo Lee[1], Lamsu Kim[2], Kwangwoo Jang[3], Seongheon Lee[4] and Hyochoong Bang[5]
Korea Advanced Institute of Science and Technology

Correction to :
Journal of The Korean Society for Aeronautical and Space Sciences
Vol. 49, No. 9, pp. 749~757
DOI : 10.5139/JKSAS.2021.49.9.749

With the author(s)' decision, the article "Model Reference Adaptive Control of a Quadrotor Considering the Uncertainty of Payload", written by Dongwoo Lee, Lamsu Kim, Kwangwoo Jang, Seongheon Lee and Hyochoong Bang, has been corrected as follows :

Equation (5) :

$$l = \frac{dx}{\sqrt{2}} = \frac{dy}{\sqrt{2}}, c_T = \frac{k_Q}{k_T}$$

$$T = k_T w_{motor}^2, M = k_Q w_{motor}^2$$

$$\begin{bmatrix} F_z \\ L \\ M \\ N \end{bmatrix} = \begin{bmatrix} -1 & -1 & -1 & -1 \\ -l & l & l & -l \\ l & l & -l & -l \\ c_T & -c_T & c_T & -c_T \end{bmatrix} \begin{bmatrix} T_1 \\ T_2 \\ T_3 \\ T_4 \end{bmatrix}$$

The original article can be found online at https://doi.org/10.5139/JKSAS.2021.49.9.749.