CORRECTION

유상하중의 불확실성을 고려한 쿼드로터의 모델 참조 적응제어 기법 설계
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Model Reference Adaptive Control of a Quadrotor Considering the Uncertainty of Payload
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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 Hychoong Bang, has been corrected as follows :

Equation (5) :
\[
l = \frac{dx}{\sqrt{2}} = \frac{dy}{\sqrt{2}}, \quad c_T = \frac{k_Q}{k_T}
\]
\[
T = k_T w_{motor}^2, \quad M = k_Q w_{motor}^2
\]

\[
\begin{bmatrix}
F_i \\
L \\
M \\
N
\end{bmatrix} = \begin{bmatrix}
-1 & -1 & -1 & -1 \\
-l & l & l & l \\
l & -l & -l & -l \\
c_T & -c_T & c_T & -c_T
\end{bmatrix}
\begin{bmatrix}
T_1 \\
T_2 \\
T_3 \\
T_4
\end{bmatrix}
\]

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