

Corrigendum to “Cascaded incremental nonlinear dynamic inversion control for MAV disturbance rejection”[Journal of Control Engineering Practice 73 (2018) 79–90, (S0967066118300030), (10.1016/j.conengprac.2018.01.003)]

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Important note

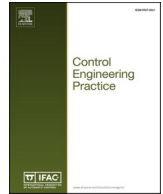
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Corrigendum

Corrigendum to “Cascaded incremental nonlinear dynamic inversion control for MAV disturbance rejection” [Journal of Control Engineering Practice 73 (2018) 79–90]

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The authors regret to inform that an incorrect transfer function was included in Eq. (12). The correct transfer function is:

$$TF_{\eta_{\text{ref}} \rightarrow \eta} = \frac{K_{\eta} K_{\Omega} \alpha T_s^2 z^2}{z^3 + (K_{\Omega} \alpha T_s + K_{\eta} K_{\Omega} \alpha T_s^2 + \alpha - 3) z^2 + (3 - 2\alpha - K_{\Omega} \alpha T_s) z - 1 + \alpha} \quad (12)$$

The selected gains were $K_{\Omega} = 28.0$ and $K_{\eta} = 21.4$. This leads to a real pole at 0.964 and two complex poles at $0.965 \pm 0.0445i$. The difference of the model compared to the measured step response has now reduced, the largest difference being 4.8% of the final step value at 0.14 s. The mistake does not influence any of the conclusions drawn in the paper.

The authors would like to apologize for any inconvenience caused.

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