

Errata in *Real-Time Tube MPC Applied to a 10-State Quadrotor Model*

1. Wrong ODEs in the quadrotor model

The last two ODEs (pitch and roll) in the 10D quadrotor model (5) in our paper, unfortunately, contain a typo. The correct model should be

$$\dot{x}(t) = \underbrace{\begin{pmatrix} x_4(t) + w_1(t) \\ x_5(t) + w_2(t) \\ x_6(t) + w_3(t) \\ g \tan(x_7(t)) \\ g \tan(x_8(t)) \\ -g \\ -d_1 x_7(t) + x_9(t) \\ -d_1 x_8(t) + x_{10}(t) \\ -d_0 x_7(t) \\ -d_0 x_8(t) \end{pmatrix}}_{f(x(t), w(t))} + \underbrace{\begin{pmatrix} 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & k_T \\ 0 & 0 & 0 \\ 0 & 0 & 0 \\ n_0 & 0 & 0 \\ 0 & n_0 & 0 \end{pmatrix}}_G u(t)$$

Courtesy: Matthias Müller and Johannes Köhler.