

**Düzeltilme**

Dergimizin 2005 yılı 2. sayısında yayımlanan “**Structured Robust Stability Analysis of an Inverted Pendulum System With a Fixed Feedback**“ başlıklı makaledeki hatalardan dolayı özür diliyoruz. Söz konusu hatalı bağıntıların doğruları aşağıdadır.

**Sayfa 57**

$$\begin{aligned}
 \dot{x}_1 &= x_2 \\
 \dot{x}_2 &= \frac{-bx_2 + M_p l \sin(x_3) x_4^2 - M_p g \sin(x_3) \cos(x_3) + u}{M_c + M_p - M_p \cos^2(x_3)} \\
 \dot{x}_3 &= x_4 \\
 \dot{x}_4 &= \frac{(bx_2 - u - M_p l \sin(x_3) x_4^2) \cos(x_3) + (M_c + M_p) g \sin(x_3)}{l(M_c + M_p - M_p \cos^2(x_3))}
 \end{aligned} \tag{1}$$

$$x_1 := x, \quad x_2 := \dot{x}, \quad x_3 := \theta, \quad x_4 := \dot{\theta}$$

**Sayfa 58**

$$\begin{aligned}
 \dot{x}_1 &= x_2 \\
 \dot{x}_2 &= -\frac{M_p g}{M_c} x_3 - \frac{b}{M_c} x_2 + \frac{1}{M_c} u \\
 \dot{x}_3 &= x_4 \\
 \dot{x}_4 &= \frac{(M_c + M_p) g}{M_c l} x_3 + \frac{b}{M_c l} x_2 - \frac{1}{M_c l} u
 \end{aligned} \tag{2}$$

$$\begin{aligned}
 \dot{X} &= AX + Bu \\
 y &= CX
 \end{aligned} \tag{3}$$

**Sayfa 59**

$$\begin{aligned}
 \dot{e} &= Ae + Bu \\
 y &= Ce + r
 \end{aligned} \tag{5}$$

Sayfa 63

$$\begin{aligned}\dot{X} &= (A - BK)X + BKx_d \\ y &= Cx\end{aligned}\tag{15}$$

$$\dot{X} = \begin{bmatrix} 0 & 1 & 0 & 0 \\ \frac{k_1}{M_c} & \frac{b+k_2}{M_c} & \frac{M_p g+k_3}{M_c} & \frac{k_4}{M_c} \\ 0 & 0 & 0 & 1 \\ \frac{k_1}{M_c l} & \frac{b+k_2}{M_c l} & \frac{(M_c+M_p)g+k_3}{M_c l} & \frac{k_4}{M_c l} \end{bmatrix} X + \begin{bmatrix} 0 \\ \frac{k_1}{M_c} \\ 0 \\ \frac{k_1}{M_c l} \end{bmatrix} r\tag{16}$$

$y = x_1$ .