

Erratum

Corrections to “Practical Fixed-Time Consensus Tracking for Multiple Euler–Lagrange Systems With Stochastic Packet Losses and Input/Output Constraints”

He Li , Cheng-Lin Liu , Ya Zhang , and Yang-Yang Chen , *Senior Member, IEEE*

In [1], several errors were introduced during the production process, which are corrected here.

The captions for Figs. 6, 7, 9, and 10 are incorrect. The correct versions are as follows:

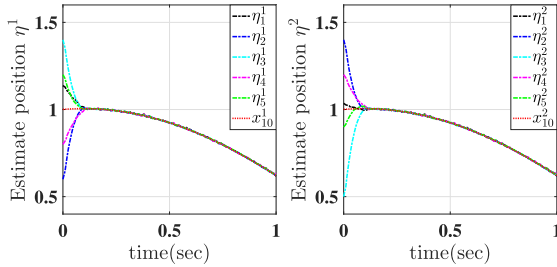


Fig. 6. Manipulators’ angular position estimation obtained by the FDO in this article Case (a) of initial values and 0.05 step size.

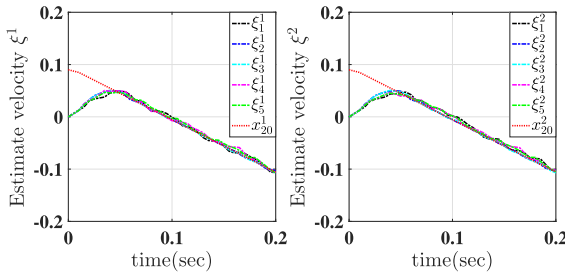


Fig. 7. Manipulators’ angular velocity estimation obtained by the FDO in this article. Case (a) of initial values and 0.05 step size.

The text citations for these figures are also incorrect and are as follows. In the paragraph preceding Remark 10, the text should be

Manuscript received November 4, 2021; accepted November 4, 2021. Date of current version March 24, 2022. This work was supported by the National Natural Science Foundation of China under Grants 61973139 and 61473138, and in part by the Fundamental Research Funds for the Central Universities under Grant JUSRP22014. (*Corresponding author: Cheng-Lin Liu.*)

He Li and Cheng-Lin Liu are with the Key Laboratory of Advanced Process Control for Light Industry, Ministry of Education, Institute of Automation, Jiangnan University, Wuxi 214122, China (e-mail: liheemail@stu.jiangnan.edu.cn; liucl@jiangnan.edu.cn).

Ya Zhang and Yang-Yang Chen are with the School of Automation, Southeast University, Nanjing 210096, China (e-mail: yazhang@seu.edu.cn; yychen@seu.edu.cn).

Digital Object Identifier 10.1109/JSYST.2021.3126187

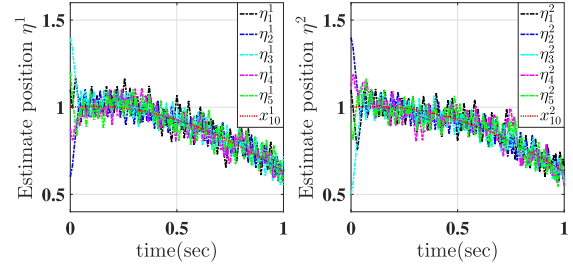


Fig. 9. Manipulators’ angular position estimation obtained by the FDO in [19]. Case (a) of initial values and 0.05 step size.

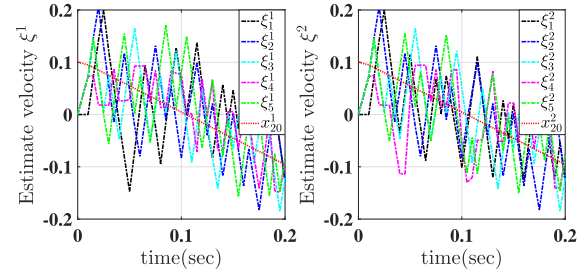


Fig. 10. Manipulators’ angular velocity estimation obtained by the FDO in [19]. Case (a) of initial values and 0.05 step size.

Comparing Figs. 6 and 7 with Figs. 9 and 10, we can see that the FDO proposed in this article can make more precise estimation of the leader’s states.

In the first paragraph following Remark 10, it should say After that, the FLSs based fixed-time tracking control is activated.

At the top of Figs. 8 and 11, it is found that the followers can track the leader’s trajectory within 0.55(s), and the settling time satisfies $T_{co} \leq 1.8101(s)$. The bottom of Figs. 8 and 11 shows us that the tracking errors converge rapidly to the compact set close to zero. According to the bottom of Fig. 8, it can also be found that the asymmetric constraints cannot be violated.

REFERENCE

- [1] H. Li, C.-L. Liu, Y. Zhang, and Y.-Y. Chen, “Practical fixed-time consensus tracking for multiple Euler–Lagrange systems with stochastic packet losses and input/output constraints,” *IEEE Syst. J.*, to be published, doi: 10.1109/JSYST.2021.3112720.