



Erratum

Passivity-Based Attitude Control on the Special Orthogonal Group of Rigid-Body Rotations

James Richard Forbes

University of Michigan, Ann Arbor, Michigan 48109-2140

[*J. Guidance*, 36(6), pp. 1596–1605, 2013]

DOI: 10.2514/1.G00051010.2514/1.G000510; published online 21 April 2014.

The author of [1] acknowledges [2] for a clear and methodical exposition leading to their control law (20) and (21). A similar exposition in [1] leads to the controller (18). This addendum is intended to correct the omission of [2] from the bibliography in [1].

References

[1] Forbes, J. R., “Passivity-Based Attitude Control on the Special Orthogonal Group of Rigid-Body Rotations,” *Journal of Guidance, Control, and Dynamics*, Vol. 36, No. 6, 2013, pp. 1596–1605.
doi:10.2514/1.59270

[2] Khosravian, A., and Namvar, M., “Rigid Body Attitude Control Using a Single Vector Measurement and Gyro,” *IEEE Transactions on Automatic Control*, Vol. 57, No. 5, 2012, pp. 1273–1279.
doi:10.1109/TAC.2011.2174663

This article has been cited by:

1. Quan Hu, Xiao Feng, Xiangyuan Zeng, Jingrui Zhang Passivity Control with Practical Finite-time Convergence for Large Space Structures . [[Citation](#)] [[PDF](#)] [[PDF Plus](#)]