Review of: "Neuro-Fuzzy-Based Adaptive Control for Autonomous Drone Flight"

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Comments to the authors:

Te authors propose a design, development, and application of an intelligent adaptive hybrid controller to control and stabilise adrone.

They used Linear Quadratic Regulator (LQR) under white-noise disturbance to generate data for

training adaptive neuro-fuzzy inference systems (ANFIS.

The contribution of the paper is a collective ideas from the literature applied to drone.

The following comments are to make the paper clear and to improve it readability.

1. The authors mentioned before Figure 1 that "The whole process is depicted in Figure 1", while title is "Fig. 1. Fuzzy Inference System"

2. The authors should give in a separate figure the whole process and correct the mistake in comment 1 above.

3.In the paragraph after Equation (16), the second line authors wrote " the space state representation of the system is as stated below", but there is nothing below.

This typo mistake should be corrected.

4. The Black boxes around Figure 2 should be removed.

5. All the background of the Figures in the simulation should be white, with no black boxes.

6. There is a typo mistake in Equation (8).

7. There are many typo mistakes in page 5.

8. "in" is not used to represent the input.

9. Explain more the phrase after Equation (11), "... stability and control derivative". This is not a usual phrase to explain the variables.

10. There are some references not mentioned such as "Multi-Model Fuzzy Formation control of UAV quadrotors."