Review of: "Modelling of Quadcopter for Precision Agriculture and Surveillance Purposes"

Eduardo Suárez[1]

1 Universidad de Vigo

Potential competing interests: No potential competing interests to declare.

This article seems to me an interesting contribution; however, as a scientific dissemination focusing on the utilization of UAVs in agriculture, I believe that it falls short of delivering tangible and pertinent contributions. Moreover, it lacks the requisite depth and rigor in elucidating the methodologies, presenting results, and engaging in discussions. Therefore, it needs improvement to be seen as a scientific article with the impact or relevance required.

The objective defined in the abstract is not sufficiently clear and specific. In section 2.1, a geometric model is described, which is either generic or at least not referenced or justified in terms of dimensions used, contradicting what is stated previously in the abstract: "Subsequently, the quadcopter was physically fabricated in accordance with the computer model." It is unclear.

In general, the mathematical model described is not adequately referenced, and I cannot find the novelty. If a known model is simply used, it should be specified. If modifications are made or a new effect is implemented, it should be specified and explained more clearly. I cannot locate the contribution in this section, similar to the supposed control system.

The discussion of results presented does not seem to correspond to the results previously shown. It is essential to explain in detail the conditions that have been modeled and the results that have been achieved to justify the modification decisions, whose results are supposedly shown in Figure 10.

Some minor errors:

- On page 10, the cross-reference to Figure 4 is incorrect. I understand that it refers to Figure 5, not Figure 4.
- Equation 9 has a repeated sine function.
- There is no reference in the text to Figure 8.
- Figure 8 does not match the figure caption, and if it does, the image does not contribute much, as there is no trajectory shown.