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

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Potential competing interests: No potential competing interests to declare.

Good LR and topic! However, I have a few queries, which are listed below:

1. Page 10. Figure 4 or Figure 5?
2. Equation 14. Based on my study, Tphi and Ttheta suppose include all w since your design, as in fig 4 or fig 10, is referring to the X-configuration of the quadrotor, not the +-configuration. Please refer to other references during modelling and check + or x configuration on that part.
3. Regarding the results, as you haven't applied control techniques, I would recommend conducting simulations based on varying propeller speeds to observe the quadrotor's reactions. This involves testing the dynamics of the quadrotor without a controller. For instance, you can set all motors to rotate at the same high speed and plot a graph to showcase the quadrotor in a hover state. Then, by increasing the speeds of motors 2 and 4 relative to motors 1 and 3, you can observe potential lateral movements, such as the quadrotor shifting left or right. Similarly, you can explore the effects of different speed configurations for forward and reverse movements, as well as yaw rotations (right or left). My suggestion is based on your discussion in Chapter 3, specifically in the "Results and Discussion" section. I noticed that the details were not extensively covered, and I recommend providing more in-depth information in that particular part of your work.

Thanks