# Errata

<table>
<thead>
<tr>
<th>page</th>
<th></th>
</tr>
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<tbody>
<tr>
<td>23</td>
<td>Table 2.2 100 - 500, should be 100 - 350.</td>
</tr>
<tr>
<td>35</td>
<td>$Q$ and $V$ are not defined, $V$ is volume of the settler, and $Q$ the flow.</td>
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<tr>
<td>45, 48</td>
<td>$h$ is not defined, it is the sampling interval.</td>
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<td>48</td>
<td>$p$ is not defined, it is filter pole, chosen by the designer to make the controller less noise sensitive. This definition of $p$ is only used here.</td>
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<tr>
<td>53</td>
<td>$k$ is not defined, it is the prediction horizon.</td>
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<tr>
<td>81</td>
<td>$K_La(u)(y_{sat} - y)$ should be $K_La(u)(y_{sat} - y)$.</td>
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<tr>
<td>110</td>
<td>Remark 4. An alternative approach using an extended Kalman filter is presented in Appendix D.</td>
</tr>
<tr>
<td>125</td>
<td>? should be Olsson and Piani (1992).</td>
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<tr>
<td>126</td>
<td>? should be Khalil (1996).</td>
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<tr>
<td>143</td>
<td>? should be Söderström (1996).</td>
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<td>160</td>
<td>wrong dimension on $G$ and $G_d$, the last row is lost. They should be $G = \begin{bmatrix} -0.2920 &amp; 0.2985 &amp; -0.1922 \ -0.2377 &amp; 0.1682 &amp; 0.1077 \ -0.1155 &amp; 0.1119 &amp; 0.0705 \ -0.1660 &amp; -0.0347 &amp; 0.0494 \end{bmatrix}$ $G_d = \begin{bmatrix} -0.4531 &amp; -0.00267 &amp; -0.0066 \ -1.7515 &amp; 0.00510 &amp; -0.0236 \ -1.4949 &amp; 0.00324 &amp; -0.0352 \ -0.5509 &amp; -0.00205 &amp; -0.0056 \end{bmatrix}$ eq. (6.42) should be $\Delta u$ instead of $u$.</td>
</tr>
<tr>
<td>169</td>
<td>eq. (6.42) should be squared.</td>
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