

Errata

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23	Table 2.2 100 - 500, should be 100 - 350.
35	Q and V are not defined, V is volume of the settler, and Q the flow.
45, 48	h is not defined, it is the sampling interval.
48	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.
53	k is not defined, it is the prediction horizon.
81	$K_L a(u)(y_{set}-y)$ should be $K_L a(u)(y_{sat} - y)$.
110	Remark 4. An alternative approach using an extended Kalman filter is presented in Appendix D.
124,127,145	? should be Robinson (1990).
125	? should be Olsson and Piani (1992).
126	? should be Khalil (1996).
143	? should be Söderström (1996).
160	wrong dimension on G and G_d , the last row is lost. They should be
	$G = \begin{bmatrix} -0.2920 & 0.2985 & -0.1922 \\ -0.2377 & 0.1682 & 0.1077 \\ -0.1155 & 0.1119 & 0.0705 \\ 0.1660 & -0.0347 & 0.0494 \end{bmatrix}$
	$G_d = \begin{bmatrix} -0.4531 & -0.00267 & -0.0066 \\ -1.7515 & 0.00510 & -0.0236 \\ -1.4949 & 0.00324 & -0.0352 \\ -0.5509 & -0.00205 & -0.0056 \end{bmatrix}$
165	eq. (6.42) should be Δu instead of u .
169	eq. (6.42) should be squared.