Adaptive Control of Systems with Actuator and Sensor Nonlinearities
(**Gang Tao** and **Petar V. Kokotović**, John Wiley & Sons, 1996; ISBN 0-471-15654-X)

Errata

- On page 18, in line 2, replace "output" with "output $u(t)$".

- On page 23, Figure 2.19 should be modified. (?)

- On page 32, in (3.6), replace "$\widehat{\omega}_l(t)^T$" with "$\widehat{\omega}_l(t))^T$".

- On page 32, in line 1 of Proposition 3.1, replace "the dead-zone inverse $d_d(t)$ has" with "the dead-zone inverse, $d_d(t)$, has".

- On page 35, in (3.14), replace "$\widehat{g}t,t)$" with "$\widehat{g}(t,t)$".

- On page 42, in (3.37), replace "u_b" with "u_d".

- On page 82, after (4.122), replace "(4.155)" with "(4.112)".

- On page 153, after (7.24) and before (7.25), replace $\tilde{\theta}(t)$ by $\tilde{\theta}_N^*$, $\theta_j(t)$ by $\theta_{Nj}(t)$, and θ_j^* by θ_{Nj}^* and

- On page 252, after (A.4), replace "$a(D) = (1, s, \cdots, s^{n-2})^T$"
  with "$a(D) = (1, D, \cdots, D^{n-2})^T$".

- On page 256, in (A.24), replace "z" by "z_1".

- On page 257, after (A.27), replace "Filtering both sides of the first equality of (A.10) through" by "Filtering both sides of (A.10) through".

- On page 259, in (A.42), replace "$\rho(t)$" with "$\rho(t+n^*)$".

- On page 259, after (A.42), replace "where $\|\cdot\|_2$ is the Euclidean (l^2) vector norm" with "where $\|\cdot\|_2$ is the Euclidean (l^2) vector or induced matrix norm".

- On page 270, in (C.13), replace "$\rho(t)$" with "$\rho(t+n^*)$".

- On page 271, line 3, replace "$R^{(2n-1)\times(2n-1)}$" with "$C^{(2n-1)\times(2n-1)}$".

- On page 271, before (C.18), replace "recalling the estimation error expression" with "recalling the tracking error expression (7.39),".

- On page 271, replace (C.18) with

$$e(t) = k_p(\theta(t-n^*) - \theta^*)^T \omega(t-n^*) + d(t),$$

- On page 271, in (C.19), replace "$F_1(t)$" with "$k_p F_1(t)$".