```
>> modelToMPC=setmpcsignals(tf20,'MeasuredDisturbances',1,'Manipulated',[2 3])

modelToMPC =

  From input "t_e" to output "t_i":
                 0.0004579 z^-1
  z^(-1) * ----------------------------
           1 - 1.892 z^-1 + 0.8924 z^-2

  From input "RadiatorValve" to output "t_i":
               0.2329
  z^(-1) * ---------------
           1 - 0.9939 z^-1

  From input "FloorValve" to output "t_i":
               0.2582
  z^(-1) * --------------
           1 - 0.992 z^-1

Input groups:
       Name        Channels
     Measured         1
    Manipulated      2,3

Output groups:
      Name      Channels
    Measured       1

Name: tf20
Sample time: 1800 seconds
Discrete-time identified transfer function.

Parameterization:
   Number of poles: [2 1 1]   Number of zeros: [1 0 0]
   Number of free coefficients: 7
   Use "tfdata", "getpvec", "getcov" for parameters and their uncertainties.

Status:
Model modified after estimation.
>> newMPC=mpc(modelToMPC,1800)
-->Converting linear model from System Identification Toolbox to state-space.
-->The "PredictionHorizon" property of "mpc" object is empty. Trying PredictionHorizon↙
= 10.
-->The "ControlHorizon" property of the "mpc" object is empty. Assuming 2.
-->The "Weights.ManipulatedVariables" property of "mpc" object is empty. Assuming↙
default 0.00000.
-->The "Weights.ManipulatedVariablesRate" property of "mpc" object is empty. Assuming↙
default 0.10000.
-->The "Weights.OutputVariables" property of "mpc" object is empty. Assuming default↙
1.00000.

MPC object (created on 01-Dec-2018 21:41:04):
---------------------------------------------
Sampling time:      1800 (seconds)
Prediction Horizon: 10
```

```
Control Horizon:    2

Plant Model:        (max I/O delay = 1)
                                        --------------
      2  manipulated variable(s)   -->|  4 states  |
                                       |            |-->  1 measured output(s)
      1  measured disturbance(s)   -->|  3 inputs  |
                                       |            |-->  0 unmeasured output(s)
      0  unmeasured disturbance(s) -->|  1 outputs |
                                        --------------
Indices:
  (input vector)    Manipulated variables: [2 3 ]
                    Measured disturbances: [1 ]
  (output vector)        Measured outputs: [1 ]

Disturbance and Noise Models:
        Output disturbance model: default (type "getoutdist(newMPC)" for details)
         Measurement noise model: default (unity gain after scaling)

Weights:
        ManipulatedVariables: [0 0]
    ManipulatedVariablesRate: [0.1000 0.1000]
             OutputVariables: 1
                         ECR: 100000

State Estimation:  Default Kalman Filter (type "getEstimator(newMPC)" for details)

Unconstrained
>>
```