```
>> load('labsys_mpc_v1.2.mat')
>> stateOfMPC.signals.values(151,:)

ans =

   1.0e+04 *

  Columns 1 through 3

    0.0062    0.0031    1.1274

  Column 4

   -0.0000

>> initialState=stateOfMPC.signals.values(151,:)

initialState =

   1.0e+04 *

  Columns 1 through 3

    0.0062    0.0031    1.1274

  Column 4

   -0.0000

>> load('labsys_mpc_v0.5.mat')
>> mpcstate05=mpcstate(mpc_labsys05,initialState05(1),initialState05(2),initialState05↙
(3),initialState05(4))
Error using mpc_chkstate (line 24)
"State.Plant" must be a vector of 3 entries.

Error in mpcstate (line 123)
            mpc_chkstate('Plant',this.Plant,nxp,MPCData.xoff(1:nxp));
>> mpcstate05=mpcstate(mpc_labsys05,[163 81.5 11600],-0.858,0,1,zeros(3))
Error using mpc_chkstate (line 24)
"State.Noise" must be a vector of 0 entries.

Error in mpcstate (line 125)
            mpc_chkstate('Noise',this.Noise,nxnoise,MPCData.xoff(nxp+nxdist+1:↙
nxp+nxdist+nxnoise));
>> mpcstate05=mpcstate(mpc_labsys05,[163 81.5 11600],-0.858,[],1,zeros(3))
Error using mpcstate (line 130)
MPCSTATE expects the Covariance parameter to be a 4-by-4 matrix.  You supplied
a 3-by-3 matrix.

>> mpcstate05=mpcstate(mpc_labsys05,[163 81.5 11600],-0.858,[],1,zeros(4))
MPCSTATE object with fields
          Plant: [163 81.5000 11600]
    Disturbance: -0.8580
          Noise: [1×0 double]
       LastMove: 1
```

```
     Covariance: [4×4 double]

>>
```