

PAST

FUTURE

Output constraints

Measured output (y)

Present time

Set-point (Target)

Predicted output (\hat{y})

Control move (Δu)

Input constraints

$k-3$

k

$k+1$

$k+M$

$k+P$

Control Horizon (M)

Time

Manipulated input (u)

Prediction Horizon (P)

