

Errata corrige for the paper:

A. Piazzzi, M. Romano and C. Guarino Lo Bianco, “G<sup>3</sup>-splines for path planning of wheeled mobile robots”, *Proceedings of the 2003 European Control Conference*, Cambridge (UK), 1—4 September 2003.

In the above paper the G<sup>3</sup>-splines coefficients contain two typos involving the mix-up of the  $\eta_4$  and  $\eta_5$  parameters. Therefore expressions (20) and (23) should be replaced by:

$$\begin{aligned}\beta_4 = & 35(y_B - y_A) - \left(20\eta_1 + 5\eta_3 + \frac{2}{3}\eta_5\right)\sin\theta_A \\ & - \left(5\eta_1^2\kappa_A + \frac{2}{3}\eta_1^3\dot{\kappa}_A + 2\eta_1\eta_3\kappa_A\right)\cos\theta_A \\ & - \left(15\eta_2 - \frac{5}{2}\eta_4 + \frac{1}{6}\eta_6\right)\sin\theta_B \\ & + \left(\frac{5}{2}\eta_2^2\kappa_B - \frac{1}{6}\eta_2^3\dot{\kappa}_B - \frac{1}{2}\eta_2\eta_4\kappa_B\right)\cos\theta_B\end{aligned}$$

$$\begin{aligned}\beta_7 = & -20(y_B - y_A) + \left(10\eta_1 + 2\eta_3 + \frac{1}{6}\eta_5\right)\sin\theta_A \\ & + \left(2\eta_1^2\kappa_A + \frac{1}{6}\eta_1^3\dot{\kappa}_A + \frac{1}{2}\eta_1\eta_3\kappa_A\right)\cos\theta_A \\ & + \left(10\eta_2 - 2\eta_4 + \frac{1}{6}\eta_6\right)\sin\theta_B \\ & - \left(2\eta_2^2\kappa_B - \frac{1}{6}\eta_2^3\dot{\kappa}_B - \frac{1}{2}\eta_2\eta_4\kappa_B\right)\cos\theta_B\end{aligned}$$