Corrigendum for: R. Kamalapurkar, H. T. Dinh, S. Bhasin, and W. E. Dixon, "Approximate optimal trajectory tracking for continuous-time nonlinear systems," *Automatica*, vol. 51, pp. 40–48, 2015. DOI: 10.1016/j.automatica.2014.10.103

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Correction: In the sentence after Equation (5), it is claimed that $F(0) = 0$ for the class of desired trajectories that satisfy Assumption 2. This is incorrect. For this claim to be true, the class of desired trajectories needs to be further restricted to those that satisfy $h_d(0) = 0$.

Further explanation: The property $F(0) = 0$ is only used to establish the bound $\|F(\zeta)\| \leq L_F \|\zeta\|$, which is further simplified as $\|F(\zeta)\| \leq L_F \|e\| + L_F \|x_d\|$, and eventually, $\|F(\zeta)\| \leq L_F \|e\| + L_F \bar{d}$. Since a similar bound of the form $\|F(\zeta)\| \leq a\|e\| + b\bar{d}$ can be arrived at using local Lipschitz continuity of F and continuity of h_d,[1] the added restriction $h_d(0) = 0$ and the property $F(0) = 0$ are not needed to derive the main results of the paper.

[1] To arrive at the claimed bound, express F as $F_1 + F_2$ where F_1 is made of the first n rows of F and n zeros, and F_2 is made of n zeros and the last n rows of F. Since x_d is bounded and h_d is continuous, F_2 is bounded. The function F_1 is locally Lipschitz continuous and Assumption 2 leads to $F_1(0) = 0$. As a result, $\|F_1(\zeta)\| \leq L_{F1} \|\zeta\|$ and from there, $\|F_1(\zeta)\| \leq L_{F1}(\|e\| + \|x_d\|)$ and the claimed bound follows.