

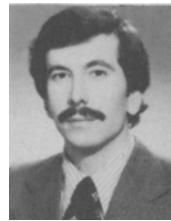
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Authors' biographies



Richard Kaplan received the BS degree in Engineering Science from the University of Miami at Coral Gables, Florida, USA and is currently working toward the MD degree in the same school. Presently he is employed by Artificial Hearing Systems Inc., Miami, as a design engineer for an ABR-based automated hearing testing system. Previously, he worked for four years as a microcomputer programmer. His primary interests are microprocessor-based medical instrumentation and computer applications in medicine. He has also published articles on microcomputer graphics and programming techniques.



Özcan Özdamar received his BS (1971) in Electrical Engineering from Middle East Technical University in Ankara, Turkey. He obtained the MS (1973) and Ph.D. (1976) in Biomedical Engineering from Northwestern University, Evanston, Illinois, USA. He has held academic appointments in Turkey and the USA and is currently an Associate Professor of Biomedical Engineering at the University of Miami, Coral Gables, Florida, USA, with a secondary appointment in the Department of Pediatrics of the School of Medicine there. His primary interests are neurosensory systems and computer applications in medicine, and he has been active in auditory modelling, neurophysiology and evoked potentials.

Errata

Medical & Biological Engineering & Computing, Vol. 25, No. 3, May 1987, 269–276.

'Dynamic model of the short-term regulation of arterial pressure in the cat'

On page 274, the final line of the penultimate paragraph should have read

holds: $\omega_n = \omega_r \sqrt{1 - 2\zeta^2}$, with $0 < \zeta < 1/\sqrt{2}$.

Medical & Biological Engineering & Computing, Vol. 25, No. 3, May 1987, 277–283.

'Dynamics of the short-term regulation of arterial pressure: frequency dependence and role of arterial compliance'

Eqns. 15–19, on page 279, should have read as follows:

$$\begin{cases} \left(s + \frac{1}{\tau_1} \right) X_1(s) - \frac{Q_0}{\tau_1} X_2(s) = \frac{U(s)}{C} \\ sX_2(s) - X_3(s) = 0 \\ G_R \omega_n^2 X_1(s) + \omega_n^2 X_2(s) \\ + (s + 2\zeta\omega_n) X_3(s) = -G_R R_c \omega_n^2 U(s) \end{cases} \quad (15)$$

$$Y(s) = X_1(s) + R_c U(s) \quad (16)$$

The element $X_1(s)$ of the vector $X(s)$ can be obtained by solution of the simultaneous set of state equations (eqn. 15) using the determinants (Cramer's rule)

$$X_1 = \frac{\Delta_1}{\Delta} \quad (17)$$

where

$$\Delta = |sI - A| = \begin{vmatrix} s + \frac{1}{\tau_1} & -\frac{Q_0}{\tau_1} & 0 \\ 0 & s & -1 \\ G_R \omega_n^2 & \omega_n^2 & s + 2\zeta\omega_n \end{vmatrix} \quad (18)$$

and Δ_1 is obtained from the matrix $[sI - A]$ by substituting $BU(s)$ for the first column. Therefore

$$X_1(s) = \frac{1}{\Delta} \begin{vmatrix} \frac{1}{C} & -\frac{Q_0}{\tau_1} & 0 \\ 0 & s & -1 \\ -G_R R_c \omega_n^2 & \omega_n^2 & s + 2\zeta\omega_n \end{vmatrix} U(s) \quad (19)$$

Eqn. 26, on page 281, should have read as follows:

$$\Delta P_o(t) = -G_o [1 - K_1 \exp(-\omega_1 t) + K_2 \times \exp(-\zeta\omega_n t) \sin(\omega_n \sqrt{1 - \zeta^2} t - \Phi)] \quad (26)$$