

Contents

Preface	v
1 Notion of state observers	1
2 Observability	5
2.1 Observability, identifiability, observability and identifiability criteria	5
2.2 Transfer function and canonical forms	16
2.2.1 Canonical forms for scalar systems	17
2.2.2 Canonical forms for vector systems	21
2.3 Canonical representation with the isolation of zero dynamics	26
2.3.1 Zero dynamics of scalar systems	26
2.3.2 Zero dynamics of vector systems	30
2.4 Nonstationary linear systems	35
Conclusion	37
3 Observers of full-phase vector for fully determined linear systems	38
3.1 Full-dimensional observers	38
3.1.1 Algorithms of the synthesis of observers with the use of different canonical forms	43
3.1.2 Synthesis of observers with the use of the first canonical representation of vector systems	44
3.1.3 Synthesis with the use of the Luenberger form	45
3.1.4 Synthesis of observers with the reconstructible pair $\{C, A\}$	46
3.2 Lowered order Luenberger observers	50
Conclusion	55
4 Functional observers for fully determined linear systems	56
4.1 Problem statement. Luenberger type functional observers	56
4.2 Reconstruction of scalar functionals	59
4.3 Reconstruction of vector functionals	69
4.4 Method of scalar observers	70
4.4.1 The case of multiple roots	77

4.4.2	The case of complex roots	83
4.5	Systems with vector output	84
4.6	Analysis of properties of solutions of linear systems of special type . .	90
4.7	Minimal functional observers with a defined spectrum	103
	Conclusion	129
5	Asymptotic observers for linear systems with uncertainty	131
5.1	Hyperoutput systems	132
5.2	Functional observers	138
5.3	Synthesis of observers by the method of pseudoinputs	139
5.4	Classical methods of synthesis of observers under the uncertainty conditions	144
5.4.1	Removal of disturbance from the equation of estimation error .	144
5.4.2	The method of removal of disturbance from the equation of the system	146
5.4.3	Methods based on the reduction of a system to a special canonical form	147
5.4.4	Method of pseudoinputs	149
5.4.5	Methods of synthesis of observers with control	149
5.5	Static and unstatic methods of estimation under the conditions of uncertainty	150
5.5.1	Observers for square systems with uncertainty	150
5.5.2	Observers for systems with arbitrary relative order $r > 1$. . .	163
	Conclusion	164
6	Observers for bilinear systems	165
6.1	Asymptotic observers of bilinear systems in the plane	165
6.2	Asymptotic observers for certain classes of n -dimensional bilinear systems	177
6.2.1	Problem statement	177
6.2.2	Systems with a scalar output and a degenerate matrix of bilinearity	179
6.2.3	Systems with a vector output and degenerate matrix of bilinearity	184
6.2.4	Systems with vector output and known input	186
6.2.5	Asymptotic observers on the basis of the decomposition method	188
	Conclusion	190
7	Observers for discrete systems	191
7.1	Mathematical models of discrete objects	191
7.2	Discrete observability and observers. Canonical forms	193
7.3	Method of pseudoinputs in the problem of synthesis of functional observers	204

7.3.1	Scalar system, scalar functional	204
7.3.2	Scalar observations, vector functional	208
7.4	Method of scalar observers in the problem of synthesis of a minimal order functional observer	213
7.4.1	Scalar functional, scalar observation	214
7.4.2	Scalar observations, vector functional	216
7.5	Synthesis of observers under the conditions of uncertainty	217
7.5.1	Square systems	218
7.5.2	Hyperoutput systems	219
7.5.3	Method of pseudoinputs in the synthesis of state observer . . .	223
7.5.4	Some classical methods of synthesis of state observers under the conditions of uncertainty	225
7.5.5	Method of exclusion of perturbation from the equation for the estimation error	226
7.5.6	Method of exclusion of perturbation from the equation of the system	228
7.5.7	Methods based on special canonical forms	230
	Conclusion	231
	Bibliography	233
	Index	241