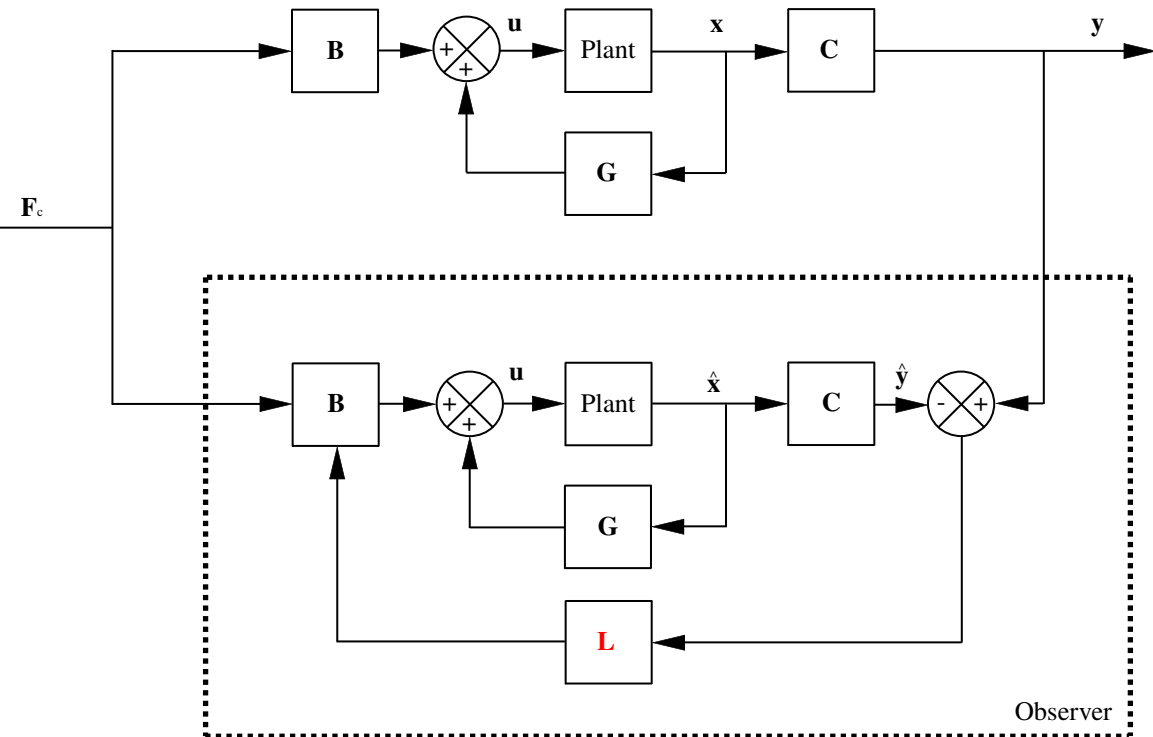


Codes:

LMIs for designing an FTS observer for the Epileptor Model

Observer approach for the Epileptor model using a fourth-order Runge-Kutta integrator



x States

\hat{x} Estimated states

y Measurable states

\hat{y} Measurable estimated states

B Input matrix

C Output matrix

G Gains of the controller

L Gains of the observer

F_c Input force

u Input vector