Observer in original coordinates Measuring x6 10¹ 1.0 T 10⁻¹ 0.5 $\stackrel{\mathsf{X}}{\sim}$ 0.0 x_1 System -0.5 $\hat{x_1}$ Observer x_1 Error -1.0x₂ System 0.5 10^{-1} \hat{x}_2 Observer 0.0 **X**₂ -0.5x₂ Error -1.0 10^{1} 1 ₽ 10⁻¹ $\overset{\mathsf{x}}{\mathsf{x}}$ 0 x₃ System 10⁻³ -1 \hat{x}_3 Observer 0.5 x₄ System 10⁰ \hat{x}_4 Observer 0.0 X 44 10-5 ×[₹] −0.5 -1.0 10^{-4} x₄ Error -1.5 10^{1} 5 x 10⁻¹ χ_5 0 10-3 -5 \hat{x}_5 Observer x₅ Error 10 x₆ System \hat{x}_6 Observer 10^{0} 5 -10⁻² 0 10^{-4} x₆ Error -102 10 0 4 6 8 10 0 6 8

Time (s)

Time (s)