Observer in original coordinates Measuring x6 1.0 x_1 System 10⁰ $\hat{x_1}$ Observer 0.5 T 10⁻² $^{1}_{1}$ 0.0 -0.5 10^{-4} -1.0 10^{0} x₂ System 0.5 ––– \hat{x}_2 Observer 10^{-2} 10 ELLO 2 2 10⁻⁴ 0.0 χ_2 -0.5 10^{-6} - x₂ Error -1.0 x_3 System 10⁰ 1 \hat{x}_3 Observer 2 10⁻² × 10⁻⁴ $\overset{\mathsf{x}}{\mathsf{x}}$ 0 -1x₃ Error 10^{-6} 0.5 10⁰ 0.0 x 10⁻⁵ _₹ -0.5 -1.0x₄ System 10^{-4} \hat{x}_4 Observer -1.5 10^{1} 5 ₽ 10⁻¹ χ_5 0 10^{-3} **-**5 \hat{x}_5 Observer 10 x₆ System 10^{1} \hat{x}_6 Observer 5 10⁻¹ 0 **-**5 10⁻³ x₆ Error -102 10 0 4 6 8 10 0 6 8 Time (s) Time (s)