observer in original coordinates Measuring ['phi1fot, phi2dot'] 1.0 x_1 system $\hat{x_1}$ observer 0.5 10⁻² $\overset{\mathsf{X}}{\mathsf{^{1}}}$ 0.0 -0.5 10^{-4} x_1 Error -1.0x₂ system 0.5 $---\hat{x}_2$ observer 10^{-2} x₂ Error 0.0 χ_2 -0.5x₂ Error -1.0 x_3 system 1 10^{-1} | × 10⁻³ ×3 0 -10.5 x_4 system 10^{-1} \hat{x}_4 observer 0.0 10⁻³ [₹] −0.5 -1.0 10^{-5} x₄ Error -1.510 10⁰ 5 д 25 10-2 0 **-**5 10^{-4} \hat{x}_5 observer -10x₆ Error 10^{1} x₆ system 20 \hat{x}_6 observer 2 10⁻¹ 0 10⁻³ -20 5 0 5 10 15 20 25 30 0 10 15 20 25 30 Time (s) Time (s)