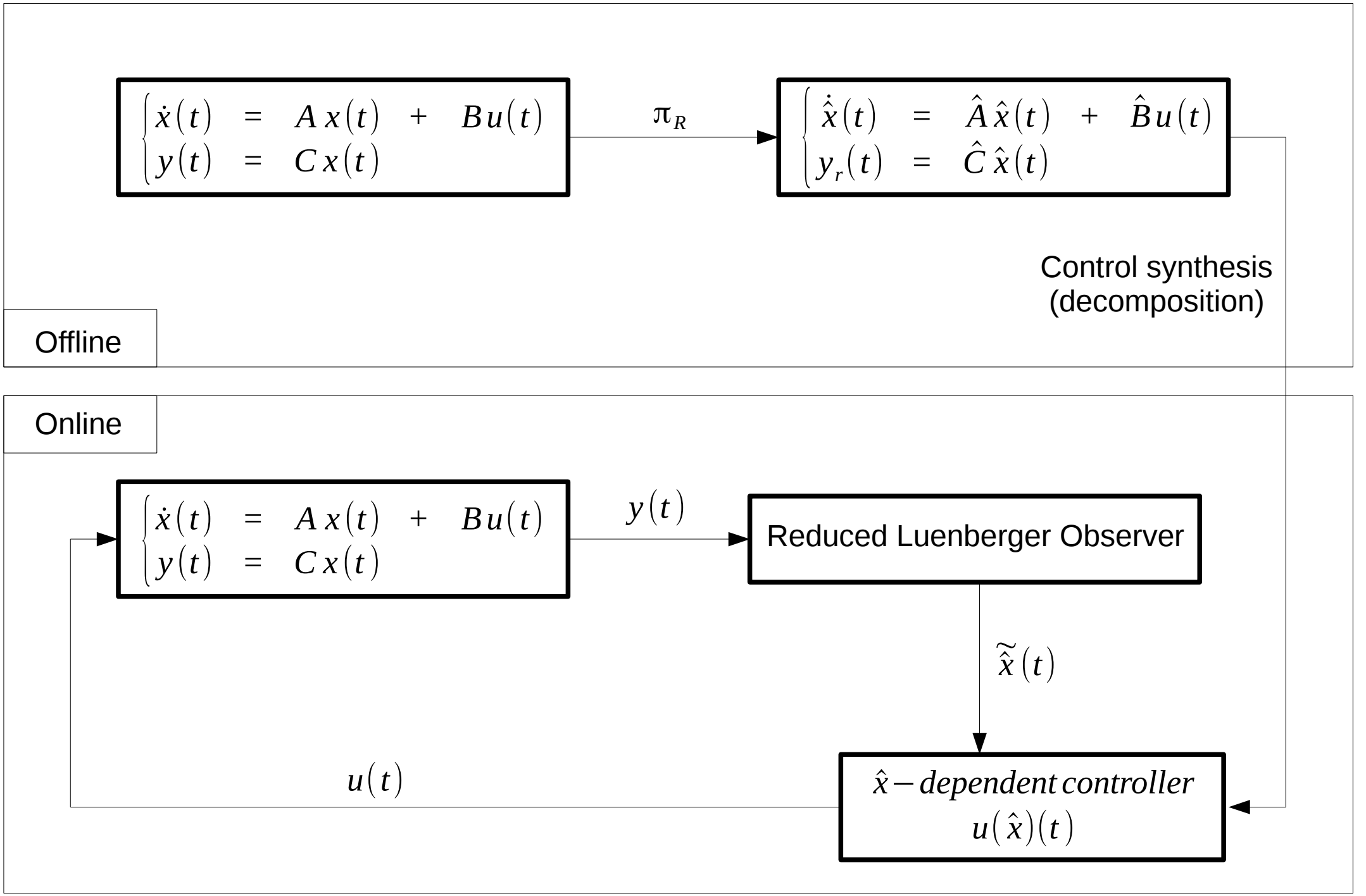
$\begin{cases} \dot{x}(t) = A\,x(t) + B\,u(t) \\ y(t) = C\,x(t) \end{cases}$
π_R
$\begin{cases} \dot{\hat{x}}(t) = \hat{A}\,\hat{x}(t) + \hat{B}\,u(t) \\ y_r(t) = \hat{C}\,\hat{x}(t) \end{cases}$
Control synthesis
(decomposition)
Offline
Online
$\begin{cases} \dot{x}(t) = A\,x(t) + B\,u(t) \\ y(t) = C\,x(t) \end{cases}$
$y(t)$
Reduced Luenberger Observer
$\tilde{\hat{x}}(t)$
$u(t)$
$\hat{x}-dependent\,controller$
$u(\hat{x})(t)$