Fault Detection and Isolation for Linear Structured Systems

J. Jia, H. L. Trentelman and M. K. Camlibel

Bernoulli Institute for Mathematics, Computer Science and Artificial Intelligence, University of Groningen, The Netherlands

Benelux Meeting on Systems and Control, 2020



university of groningen

1 Introduction

- 2 Problem Formulation
- **3** Conditions for Solvability of The FDI Problem for (A, L, C)
- $[rac{1}{2}]$ Algebraic Conditions for Solvability of The FDI Problem for $(\mathcal{A},\mathcal{L},\mathcal{C})$
- Graph-theoretic Conditions for Solvability of The FDI Problem for (A, L, C)

6 Summary

•
$$\Sigma: \begin{cases} \dot{x} = Ax + Lf \\ y = Cx \end{cases}$$
, $x \in \mathbb{R}^n$, $f \in \mathbb{R}^q$, $y \in \mathbb{R}^p$. Denoted by (A, L, C) .

- (二)

•
$$\Sigma: \begin{cases} \dot{x} = Ax + Lf \\ y = Cx \end{cases}$$
, $x \in \mathbb{R}^n$, $f \in \mathbb{R}^q$, $y \in \mathbb{R}^p$. Denoted by (A, L, C) .

• The *i*th fault occurs if $f_i \neq 0$ (i.e., not identically equal to 0).

•
$$\Sigma: \begin{cases} \dot{x} = Ax + Lf \\ y = Cx \end{cases}$$
, $x \in \mathbb{R}^n$, $f \in \mathbb{R}^q$, $y \in \mathbb{R}^p$. Denoted by (A, L, C) .

- The *i*th fault occurs if $f_i \neq 0$ (i.e., not identically equal to 0).
- Ω : $\dot{\hat{x}} = (A + GC)\hat{x} Gy$, $G \in \mathbb{R}^{n \times p}$,

•
$$\Sigma: \begin{cases} \dot{x} = Ax + Lf \\ y = Cx \end{cases}$$
, $x \in \mathbb{R}^n$, $f \in \mathbb{R}^q$, $y \in \mathbb{R}^p$. Denoted by (A, L, C) .

- The *i*th fault occurs if $f_i \neq 0$ (i.e., not identically equal to 0).
- Ω : $\dot{\hat{x}} = (A + GC)\hat{x} Gy$, $G \in \mathbb{R}^{n \times p}$, such that $\{C\mathcal{V}_i\}_{i=1}^q$ are **independent**, i.e., $C\mathcal{V}_i \neq \{0\}$ and $C\mathcal{V}_i \cap C\mathcal{V}_j = \{0\} \ \forall i \neq j$, where \mathcal{V}_i is the smallest (A + GC)-invariant subspace containing im L_i .

•
$$\Sigma: \begin{cases} \dot{x} = Ax + Lf \\ y = Cx \end{cases}$$
, $x \in \mathbb{R}^n$, $f \in \mathbb{R}^q$, $y \in \mathbb{R}^p$. Denoted by (A, L, C) .

- The *i*th fault occurs if $f_i \neq 0$ (i.e., not identically equal to 0).
- Ω : $\dot{\hat{x}} = (A + GC)\hat{x} Gy$, $G \in \mathbb{R}^{n \times p}$, such that $\{C\mathcal{V}_i\}_{i=1}^q$ are **independent**, i.e., $C\mathcal{V}_i \neq \{0\}$ and $C\mathcal{V}_i \cap C\mathcal{V}_j = \{0\} \forall i \neq j$, where \mathcal{V}_i is the smallest (A + GC)-invariant subspace containing im L_i .



•
$$r := C\hat{x} - y$$
, $e := \hat{x} - x$

J. Jia (Rug JBI)

FDI for Linear Structured Systems

≣ ▶ < ≣ ▶ ≣ ∽ ९.० March 15, 2020 4 / 25

< 円

•
$$r := C\hat{x} - y$$
, $e := \hat{x} - x$
• $\begin{cases} \dot{e} = (A + GC)e - Lf, \\ r = Ce. \end{cases}$

- (二)

•
$$r := C\hat{x} - y$$
, $e := \hat{x} - x$
• $\begin{cases} \dot{e} = (A + GC)e - Lf, \\ r = Ce. \end{cases}$

• In this work, we do **not** require $e(t) \rightarrow 0$, and assume e(0) = 0.

•
$$r := C\hat{x} - y$$
, $e := \hat{x} - x$
• $\begin{cases} \dot{e} = (A + GC)e - Lf, \\ r = Ce. \end{cases}$

- In this work, we do **not** require $e(t) \rightarrow 0$, and assume e(0) = 0.
- $e(t) \in \mathcal{V}_1 + \mathcal{V}_2 + \ldots + \mathcal{V}_q$ and $r(t) \in C\mathcal{V}_1 + C\mathcal{V}_2 + \ldots + C\mathcal{V}_q$.

•
$$r := C\hat{x} - y$$
, $e := \hat{x} - x$
• $\begin{cases} \dot{e} = (A + GC)e - Lf, \\ r = Ce. \end{cases}$

- In this work, we do **not** require $e(t) \rightarrow 0$, and assume e(0) = 0.
- $e(t) \in \mathcal{V}_1 + \mathcal{V}_2 + \ldots + \mathcal{V}_q$ and $r(t) \in C\mathcal{V}_1 + C\mathcal{V}_2 + \ldots + C\mathcal{V}_q$.
- Since $\{C\mathcal{V}_i\}_{i=1}^q$ are **independent**, r(t) can be written uniquely as $r(t) = r_1(t) + r_2(t) + \cdots + r_q(t)$ with $r_i(t) \in C\mathcal{V}_i$ for all t.

•
$$r := C\hat{x} - y$$
, $e := \hat{x} - x$
• $\begin{cases} \dot{e} = (A + GC)e - Lf, \\ r = Ce. \end{cases}$

- In this work, we do **not** require $e(t) \rightarrow 0$, and assume e(0) = 0.
- $e(t) \in \mathcal{V}_1 + \mathcal{V}_2 + \ldots + \mathcal{V}_q$ and $r(t) \in C\mathcal{V}_1 + C\mathcal{V}_2 + \ldots + C\mathcal{V}_q$.
- Since $\{C\mathcal{V}_i\}_{i=1}^q$ are **independent**, r(t) can be written uniquely as $r(t) = r_1(t) + r_2(t) + \cdots + r_q(t)$ with $r_i(t) \in C\mathcal{V}_i$ for all t.
- Indeed, r_i ≠ 0 only if f_i ≠ 0, i.e., r_i ≠ 0 implies that the *i*th fault occurs.

•
$$r := C\hat{x} - y$$
, $e := \hat{x} - x$
• $\begin{cases} \dot{e} = (A + GC)e - Lf, \\ r = Ce. \end{cases}$

- In this work, we do **not** require $e(t) \rightarrow 0$, and assume e(0) = 0.
- $e(t) \in \mathcal{V}_1 + \mathcal{V}_2 + \ldots + \mathcal{V}_q$ and $r(t) \in C\mathcal{V}_1 + C\mathcal{V}_2 + \ldots + C\mathcal{V}_q$.
- Since $\{C\mathcal{V}_i\}_{i=1}^q$ are **independent**, r(t) can be written uniquely as $r(t) = r_1(t) + r_2(t) + \cdots + r_q(t)$ with $r_i(t) \in C\mathcal{V}_i$ for all t.
- Indeed, r_i ≠ 0 only if f_i ≠ 0, i.e., r_i ≠ 0 implies that the *i*th fault occurs.
- The FDI problem is solvable for (A, L, C) if ∃G such that {CV_i}^q_{i=1} are independent.

The FDI Problem for Linear Structured Systems

The FDI problem is solvable for (A, L, C) if {CS_i^{*}}^q_{i=1} independent, where S_i^{*} is the smallest (C, A)-invariant subspace containing im L_i.¹

¹M. -A. Massoumnia (1986), 'A Geometric Approach to The Synthesis of Failure Detection Filters.'

The FDI Problem for Linear Structured Systems

- The FDI problem is solvable for (A, L, C) if {CS_i^{*}}^q_{i=1} independent, where S_i^{*} is the smallest (C, A)-invariant subspace containing im L_i.¹
- In many scenarios, the exact values of entries in *A*, *L* and *C* are not known, but some **patterns** of *A*, *L* and *C* are known exactly.

The FDI Problem for Linear Structured Systems

- The FDI problem is solvable for (A, L, C) if {CS_i^{*}}^q_{i=1} independent, where S_i^{*} is the smallest (C, A)-invariant subspace containing im L_i.¹
- In many scenarios, the exact values of entries in *A*, *L* and *C* are not known, but some **patterns** of *A*, *L* and *C* are known exactly.

For example:

$$A = \begin{bmatrix} c_1 & 0 & 0 & 0 & 0 \\ c_2 & \lambda_1 & 0 & \lambda_2 & 0 \\ 0 & c_3 & c_4 & \lambda_3 & 0 \\ c_5 & 0 & 0 & \lambda_4 & c_6 \\ 0 & 0 & c_7 & 0 & c_8 \end{bmatrix}, \quad L = \begin{bmatrix} c_9 & 0 \\ \lambda_5 & c_{10} \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad C = \begin{bmatrix} 0 & 0 & 0 & c_{11} & 0 \\ 0 & 0 & 0 & \lambda_6 & \lambda_7 \\ 0 & 0 & 0 & c_{12} & c_{13} \end{bmatrix},$$

where c_1, c_2, \ldots, c_{13} are nonzero real numbers, and $\lambda_1, \lambda_2, \ldots, \lambda_7$ are arbitrary real numbers.

Pattern Matrices and Pattern Classes

• Given a pattern matrix $\mathcal{M} \in \{0, *, ?\}^{p \times q}$, we define the *pattern class* of \mathcal{M} as ²

$$\mathcal{P}(\mathcal{M}) := \{ M \in \mathbb{R}^{p \times q} \mid M_{ij} = 0 \text{ if } \mathcal{M}_{ij} = 0, \\ M_{ij} \neq 0 \text{ if } \mathcal{M}_{ij} = *. \}$$

²J. Jia, H. J. van Waarde, H. L. Trentelman, M. K. Camlibel (2020), 'A Unifying Framework for Strong Structural Controllability'.

Pattern Matrices and Pattern Classes

• Given a pattern matrix $\mathcal{M} \in \{0,*,?\}^{p \times q},$ we define the pattern class of $\mathcal M$ as 2

$$\mathcal{P}(\mathcal{M}) := \{ M \in \mathbb{R}^{p imes q} \mid M_{ij} = 0 \text{ if } \mathcal{M}_{ij} = 0, \ M_{ij} \neq 0 \text{ if } \mathcal{M}_{ij} = *. \}$$

$$\mathcal{M} = egin{bmatrix} * & 0 & * \ 0 & 0 & * \ ? & * & * \end{bmatrix} \ \mathcal{M} \in \{0, *, ?\}^{3 imes 3}$$

• Given a pattern matrix $\mathcal{M} \in \{0,*,?\}^{p \times q},$ we define the pattern class of $\mathcal M$ as 2

$$\mathcal{P}(\mathcal{M}) := \{ M \in \mathbb{R}^{p imes q} \mid M_{ij} = 0 \text{ if } \mathcal{M}_{ij} = 0, \ M_{ij} \neq 0 \text{ if } \mathcal{M}_{ij} = *. \}$$

$$\mathcal{M} = \begin{bmatrix} * & 0 & * \\ 0 & 0 & * \\ ? & * & * \end{bmatrix} \qquad \begin{bmatrix} 1 & 0 & 2 \\ 0 & 0 & 2 \\ 1 & 1 & 3 \end{bmatrix} \in \mathcal{P}(\mathcal{M})$$
$$\mathcal{M} \in \{0, *, ?\}^{3 \times 3}$$

• Given a pattern matrix $\mathcal{M} \in \{0,*,?\}^{p \times q}$, we define the pattern class of \mathcal{M} as ²

$$\mathcal{P}(\mathcal{M}) := \{ M \in \mathbb{R}^{p \times q} \mid M_{ij} = 0 \text{ if } \mathcal{M}_{ij} = 0, \\ M_{ij} \neq 0 \text{ if } \mathcal{M}_{ij} = *. \}$$



Let $\mathcal{A} \in \{0, *, ?\}^{n \times n}$, $\mathcal{L} \in \{0, *, ?\}^{n \times q}$ and $\mathcal{C} \in \{0, *, ?\}^{p \times n}$. We call the family of systems of the form

$$\dot{x} = Ax + Lf y = Cx,$$
 (1)

where $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$, the linear structured system associated with \mathcal{A} , \mathcal{L} and \mathcal{C} , represented by $(\mathcal{A}, \mathcal{L}, \mathcal{C})$.

Let $\mathcal{A} \in \{0, *, ?\}^{n \times n}$, $\mathcal{L} \in \{0, *, ?\}^{n \times q}$ and $\mathcal{C} \in \{0, *, ?\}^{p \times n}$. We call the family of systems of the form

$$\dot{x} = Ax + Lf y = Cx,$$
 (1)

where $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$, the linear structured system associated with \mathcal{A} , \mathcal{L} and \mathcal{C} , represented by $(\mathcal{A}, \mathcal{L}, \mathcal{C})$. We say $(\mathcal{A}, \mathcal{L}, \mathcal{C}) \in (\mathcal{A}, \mathcal{L}, \mathcal{C})$ if $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$. Let $\mathcal{A} \in \{0, *, ?\}^{n \times n}$, $\mathcal{L} \in \{0, *, ?\}^{n \times q}$ and $\mathcal{C} \in \{0, *, ?\}^{p \times n}$. We call the family of systems of the form

$$\dot{x} = Ax + Lf y = Cx,$$
 (1)

where $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$, the linear structured system associated with \mathcal{A} , \mathcal{L} and \mathcal{C} , represented by $(\mathcal{A}, \mathcal{L}, \mathcal{C})$. We say $(\mathcal{A}, \mathcal{L}, \mathcal{C}) \in (\mathcal{A}, \mathcal{L}, \mathcal{C})$ if $\mathcal{A} \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $\mathcal{C} \in \mathcal{P}(\mathcal{C})$.

• Research directions of the FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$:

The FDI Problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$

Let $\mathcal{A} \in \{0, *, ?\}^{n \times n}$, $\mathcal{L} \in \{0, *, ?\}^{n \times q}$ and $\mathcal{C} \in \{0, *, ?\}^{p \times n}$. We call the family of systems of the form

$$\begin{aligned} \dot{x} &= Ax + Lf \\ y &= Cx, \end{aligned} \tag{1}$$

where $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$, the linear structured system associated with \mathcal{A} , \mathcal{L} and \mathcal{C} , represented by $(\mathcal{A}, \mathcal{L}, \mathcal{C})$. We say $(\mathcal{A}, \mathcal{L}, \mathcal{C}) \in (\mathcal{A}, \mathcal{L}, \mathcal{C})$ if $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$.

- Research directions of the FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$:
 - The FDI problem is solvable for at least one member of a given structured system.³

³C. Commault, J.M. Dion, O. Sename and R. Motyeian (2000), 'Fault Detection and Isolation of Structured Systems.'

The FDI Problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$

Let $\mathcal{A} \in \{0, *, ?\}^{n \times n}$, $\mathcal{L} \in \{0, *, ?\}^{n \times q}$ and $\mathcal{C} \in \{0, *, ?\}^{p \times n}$. We call the family of systems of the form

$$\begin{aligned} \dot{x} &= Ax + Lf \\ y &= Cx, \end{aligned} \tag{1}$$

where $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$, the linear structured system associated with \mathcal{A} , \mathcal{L} and \mathcal{C} , represented by $(\mathcal{A}, \mathcal{L}, \mathcal{C})$.

We say $(A, L, C) \in (\mathcal{A}, \mathcal{L}, \mathcal{C})$ if $A \in \mathcal{P}(\mathcal{A})$, $L \in \mathcal{P}(\mathcal{L})$ and $C \in \mathcal{P}(\mathcal{C})$.

- Research directions of the FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$:
 - The FDI problem is solvable for at least one member of a given structured system.³
 - The FDI problem is solvable for all members of a given structured system.⁴

⁴P. Rapisarda, A. R. F. Everts and M. K. Camlibel (2015), 'Fault Detection and Isolation for Systems Defined over Graphs.'

Introduction

- 2 Problem Formulation
 - 3 Conditions for Solvability of The FDI Problem for (A, L, C)
- $[\Phi]$ Algebraic Conditions for Solvability of The FDI Problem for $(\mathcal{A},\mathcal{L},\mathcal{C})$
- 5 Graph-theoretic Conditions for Solvability of The FDI Problem for (A, L, C)

6 Summary

Define the FDI problem for (A, L, C) to be solvable if the FDI problem is solvable for every (A, L, C) ∈ (A, L, C).

- Define the FDI problem for (A, L, C) to be solvable if the FDI problem is solvable for every (A, L, C) ∈ (A, L, C).
- For general A ∈ {0, *, ?}^{n×n}, L ∈ {0, *, ?}^{n×q} and C ∈ {0, *, ?}^{p×n}, the conditions for solvability of the FDI problem for (A, L, C) are still absent.

- Define the FDI problem for (A, L, C) to be solvable if the FDI problem is solvable for every (A, L, C) ∈ (A, L, C).
- For general A ∈ {0, *, ?}^{n×n}, L ∈ {0, *, ?}^{n×q} and C ∈ {0, *, ?}^{p×n}, the conditions for solvability of the FDI problem for (A, L, C) are still absent.
- **Problem:** Given (A, L, C), find conditions under which the FDI problem for (A, L, C) is solvable.

Introduction

- 2 Problem Formulation
- **③** Conditions for Solvability of The FDI Problem for (A, L, C)
- $[\Phi]$ Algebraic Conditions for Solvability of The FDI Problem for $(\mathcal{A},\mathcal{L},\mathcal{C})$
- 5 Graph-theoretic Conditions for Solvability of The FDI Problem for (A, L, C)

6 Summary

J. Jia (Rug JBI)

A Necessary and Sufficient Condition for Solvability of The FDI Problem for (A, L, C)

Let d_i be a positive integer such that

$$CA^{j}L_{i} = 0$$
 for $j = 0, 1, ..., d_{i} - 2$ and $CA^{d_{i}-1}L_{i} \neq 0$.

If this d_i exists, we then call it the **index** of (A, L_i, C) .

A Necessary and Sufficient Condition for Solvability of The FDI Problem for (A, L, C)

Let d_i be a positive integer such that

$$CA^{j}L_{i} = 0$$
 for $j = 0, 1, ..., d_{i} - 2$ and $CA^{d_{i}-1}L_{i} \neq 0$.

If this d_i exists, we then call it the **index** of (A, L_i, C) .

Theorem 1

Consider the system (A, L, C) of the form (1). The FDI problem for (A, L, C) is solvable if and only if the index d_i exists for i = 1, 2, ..., q, and the matrix R has full column rank, where R is defined by

$$R := \begin{bmatrix} CA^{d_1-1}L_1 & CA^{d_2-1}L_2 & \cdots & CA^{d_q-1}L_q \end{bmatrix}.$$
(2)

Algebraic Conditions for Solvability of The FDI Problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$

- Introduction
- 2 Problem Formulation
- 3 Conditions for Solvability of The FDI Problem for (A, L, C)
- ${f 9}$ Algebraic Conditions for Solvability of The FDI Problem for $({\cal A},{\cal L},{\cal C})$
- 5 Graph-theoretic Conditions for Solvability of The FDI Problem for (A, L, C)
- Summary

Table: Addition and multiplication within the set $\{0, *, ?\}$.⁵



⁵B. Shali (2019), 'Strong Structural Properties of Structured Linear Systems.'

Table: Addition and multiplication within the set $\{0, *, ?\}$. ⁵



Let $\mathcal{M} \in \{0, *, ?\}^{r \times s}$ and $\mathcal{N} \in \{0, *, ?\}^{s \times t}$. Define $\mathcal{MN} \in \{0, *, ?\}^{r \times t}$ by

$$(\mathcal{MN})_{ij} := \sum_{k=1}^{q} (\mathcal{M}_{ik} \cdot \mathcal{N}_{kj}) \quad i = 1, 2, \ldots, r, \quad j = 1, 2, \ldots, t.$$

J. Jia (Rug JBI)
Table: Addition and multiplication within the set $\{0, *, ?\}$. ⁵



Let $\mathcal{M} \in \{0, *, ?\}^{r \times s}$ and $\mathcal{N} \in \{0, *, ?\}^{s \times t}$. Define $\mathcal{MN} \in \{0, *, ?\}^{r \times t}$ by

$$(\mathcal{MN})_{ij} := \sum_{k=1}^{q} (\mathcal{M}_{ik} \cdot \mathcal{N}_{kj}) \quad i = 1, 2, \dots, r, \quad j = 1, 2, \dots, t.$$

If r = s, we call \mathcal{M} a square pattern matrix. Define the *k*th power \mathcal{M}^k recursively by $\mathcal{M}^0 = \mathcal{I}$, $\mathcal{M}^i = \mathcal{M}^{i-1}\mathcal{M}$, i = 1, 2, ..., k.

Let η_i be a positive integer such that $C\mathcal{A}^j\mathcal{L}_i = \mathcal{O}$ for $j = 0, 1, ..., \eta_i - 2$ and $C\mathcal{A}^{\eta_i-1}\mathcal{L}_i \neq \mathcal{O}$. If η_i exists, then we call it the **index** of $(\mathcal{A}, \mathcal{L}_i, \mathcal{C})$.

The relationship between the index of (A, L_i, C) and that of $(A, L_i, C) \in (A, L_i, C)$.

The relationship between the index of $(\mathcal{A}, \mathcal{L}_i, \mathcal{C})$ and that of $(\mathcal{A}, \mathcal{L}_i, \mathcal{C}) \in (\mathcal{A}, \mathcal{L}_i, \mathcal{C})$.

Lemma 2

Consider the pattern matrix triple $(\mathcal{A}, \mathcal{L}_i, \mathcal{C})$. Then the following holds:

- Let $(A, L_i, C) \in (\mathcal{A}, \mathcal{L}_i, \mathcal{C})$. If both the index η_i of $(\mathcal{A}, \mathcal{L}_i, \mathcal{C})$ and the index d_i of (A, L_i, C) exist, then $\mathbf{d}_i \ge \eta_i$.
- Suppose that the index η_i of (A, L_i, C) exists, and suppose further that at least one entry of CA^{η_i-1}L_i is equal to *. Let (A, L_i, C) ∈ (A, L_i, C). Then, the index d_i of (A, L_i, C) exists and d_i = η_i.
- **(a)** If the index of $(\mathcal{A}, \mathcal{L}_i, \mathcal{C})$ does not exist, then the index of $(\mathcal{A}, \mathcal{L}_i, \mathcal{C})$ does not exist for any $(\mathcal{A}, \mathcal{L}_i, \mathcal{C}) \in (\mathcal{A}, \mathcal{L}_i, \mathcal{C})$.

э

A B A B A B A
 A B A
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 B
 A
 A
 A

$$\mathcal{A} = \begin{bmatrix} 0 & 0 & 0 \\ * & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}, \ \mathcal{L} = \begin{bmatrix} * & 0 & 0 \\ 0 & * & 0 \\ 0 & * & * \end{bmatrix}, \ \mathcal{C} = \begin{bmatrix} ? & * & 0 \\ 0 & * & 0 \end{bmatrix}.$$
(3)

March 15, 2020 15 / 2

э

$$\mathcal{A} = \begin{bmatrix} 0 & 0 & 0 \\ * & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}, \ \mathcal{L} = \begin{bmatrix} * & 0 & 0 \\ 0 & * & 0 \\ 0 & * & * \end{bmatrix}, \ \mathcal{C} = \begin{bmatrix} ? & * & 0 \\ 0 & * & 0 \end{bmatrix}.$$
(3)
$$\mathcal{C}\mathcal{L}_1 = \begin{bmatrix} ? \\ 0 \end{bmatrix} \neq \mathcal{O}, \mathcal{C}\mathcal{L}_2 = \begin{bmatrix} * \\ * \end{bmatrix} \neq \mathcal{O},$$
$$\mathcal{C}\mathcal{A}^k\mathcal{L}_3 = \mathcal{O} \text{ for } k = 0, 1, 2, \dots.$$

This implies that $\eta_1 = \eta_2 = 1$ and the index of $(\mathcal{A}, \mathcal{L}_3, \mathcal{C})$ not exists.

э

$$A = \begin{bmatrix} 0 & 0 & 0 \\ c1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}, \ L = \begin{bmatrix} c_2 & 0 & 0 \\ 0 & c_3 & 0 \\ 0 & c_4 & c_5 \end{bmatrix}, \ C = \begin{bmatrix} \lambda_1 & c_6 & 0 \\ 0 & c_7 & 0 \end{bmatrix},$$

March 15, 2020 15 / 2

イロト イポト イヨト イヨト

3

$$A = \begin{bmatrix} 0 & 0 & 0 \\ c1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}, \ L = \begin{bmatrix} c_2 & 0 & 0 \\ 0 & c_3 & 0 \\ 0 & c_4 & c_5 \end{bmatrix}, \ C = \begin{bmatrix} \lambda_1 & c_6 & 0 \\ 0 & c_7 & 0 \end{bmatrix},$$
$$\begin{bmatrix} CL_1 & CL_2 \end{bmatrix} = \begin{bmatrix} \lambda_1 c_2 & c_3 c_6 \\ 0 & c_3 c_9 \end{bmatrix}, \ CAL_1 = \begin{bmatrix} c_1 c_2 c_6 \\ c_1 c_2 c_7 \end{bmatrix}.$$

 $CA^{k}L_{3} = 0$ for k = 0, 1, ...

J. Jia (Rug JBI)

FDI for Linear Structured Systems

March 15, 2020 15 / 25

э

$$A = \begin{bmatrix} 0 & 0 & 0 \\ c1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}, \ L = \begin{bmatrix} c_2 & 0 & 0 \\ 0 & c_3 & 0 \\ 0 & c_4 & c_5 \end{bmatrix}, \ C = \begin{bmatrix} \lambda_1 & c_6 & 0 \\ 0 & c_7 & 0 \end{bmatrix},$$
$$\begin{bmatrix} CL_1 & CL_2 \end{bmatrix} = \begin{bmatrix} \lambda_1 c_2 & c_3 c_6 \\ 0 & c_3 c_9 \end{bmatrix}, \ CAL_1 = \begin{bmatrix} c_1 c_2 c_6 \\ c_1 c_2 c_7 \end{bmatrix}.$$

• $d_1 \ge \eta_1$: If $\lambda_1 = 0$ then $d_1 = 2 > \eta_1$ and otherwise $d_1 = 1 = \eta_1$;

 $CA^{k}L_{3} = 0$ for k = 0, 1, ...

$$A = \begin{bmatrix} 0 & 0 & 0 \\ c1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}, \ L = \begin{bmatrix} c_2 & 0 & 0 \\ 0 & c_3 & 0 \\ 0 & c_4 & c_5 \end{bmatrix}, \ C = \begin{bmatrix} \lambda_1 & c_6 & 0 \\ 0 & c_7 & 0 \end{bmatrix},$$

$$\begin{bmatrix} CL_1 & CL_2 \end{bmatrix} = \begin{bmatrix} \lambda_1 c_2 & c_3 c_6 \\ 0 & c_3 c_9 \end{bmatrix}, \quad CAL_1 = \begin{bmatrix} c_1 c_2 c_6 \\ c_1 c_2 c_7 \end{bmatrix}$$

 $CA^{k}L_{3} = 0$ for k = 0, 1, ...

• $d_1 \ge \eta_1$: If $\lambda_1 = 0$ then $d_1 = 2 > \eta_1$ and otherwise $d_1 = 1 = \eta_1$; • $d_2 = 1 = \eta_2$;

$$A = \begin{bmatrix} 0 & 0 & 0 \\ c1 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}, \ L = \begin{bmatrix} c_2 & 0 & 0 \\ 0 & c_3 & 0 \\ 0 & c_4 & c_5 \end{bmatrix}, \ C = \begin{bmatrix} \lambda_1 & c_6 & 0 \\ 0 & c_7 & 0 \end{bmatrix},$$

$$\begin{bmatrix} CL_1 & CL_2 \end{bmatrix} = \begin{bmatrix} \lambda_1 c_2 & c_3 c_6 \\ 0 & c_3 c_9 \end{bmatrix}, \quad CAL_1 = \begin{bmatrix} c_1 c_2 c_6 \\ c_1 c_2 c_7 \end{bmatrix}$$

 $CA^{k}L_{3} = 0$ for k = 0, 1, ...

• $d_1 \geqslant \eta_1$: If $\lambda_1 = 0$ then $d_1 = 2 > \eta_1$ and otherwise $d_1 = 1 = \eta_1$;

- $d_2 = 1 = \eta_2;$
- The index of (A, L_3, C) does not exist.

٠

A necessary condition for solvability of the FDI problem:

Theorem 3

Consider the system $(\mathcal{A}, \mathcal{L}, \mathcal{C})$. Suppose that the FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$ is solvable. Then, the index η_i of $(\mathcal{A}, \mathcal{L}_i, \mathcal{C})$ exists for all i = 1, 2, ..., q.

In the sequel, we will assume that for all *i* = 1, 2, ... *q* the indices η_i exist.

- In the sequel, we will assume that for all *i* = 1, 2, ... *q* the indices η_i exist.
- Define the following pattern matrix associated with $(\mathcal{A}, \mathcal{L}, \mathcal{C})$:

$$\mathcal{R} := \begin{bmatrix} \mathcal{C}\mathcal{A}^{\eta_1 - 1}\mathcal{L}_1 & \mathcal{C}\mathcal{A}^{\eta_2 - 1}\mathcal{L}_2 & \cdots & \mathcal{C}\mathcal{A}^{\eta_q - 1}\mathcal{L}_q \end{bmatrix}.$$
(4)

- In the sequel, we will assume that for all *i* = 1, 2, ... *q* the indices η_i exist.
- Define the following pattern matrix associated with $(\mathcal{A}, \mathcal{L}, \mathcal{C})$:

$$\mathcal{R} := \begin{bmatrix} \mathcal{C}\mathcal{A}^{\eta_1 - 1}\mathcal{L}_1 & \mathcal{C}\mathcal{A}^{\eta_2 - 1}\mathcal{L}_2 & \cdots & \mathcal{C}\mathcal{A}^{\eta_q - 1}\mathcal{L}_q \end{bmatrix}.$$
(4)

We say that R has full column rank if all the matrices in the pattern class P(R) have full column rank.

- In the sequel, we will assume that for all *i* = 1, 2, ... *q* the indices η_i exist.
- Define the following pattern matrix associated with $(\mathcal{A}, \mathcal{L}, \mathcal{C})$:

$$\mathcal{R} := \begin{bmatrix} \mathcal{C} \mathcal{A}^{\eta_1 - 1} \mathcal{L}_1 & \mathcal{C} \mathcal{A}^{\eta_2 - 1} \mathcal{L}_2 & \cdots & \mathcal{C} \mathcal{A}^{\eta_q - 1} \mathcal{L}_q \end{bmatrix}.$$
(4)

We say that R has full column rank if all the matrices in the pattern class P(R) have full column rank.

Theorem 4

Consider the system $(\mathcal{A}, \mathcal{L}, \mathcal{C})$. Let \mathcal{R} be the pattern matrix given by (4). The FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$ is solvable if \mathcal{R} has full column rank.

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}.$$

March 15, 2020 17 / 25

э.

3

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}.$$

$$\begin{bmatrix} \mathcal{C}\mathcal{L}_1 & \mathcal{C}\mathcal{A}\mathcal{L}_1 \end{bmatrix} = \begin{bmatrix} 0 & * \\ 0 & ? \\ 0 & * \end{bmatrix},$$
$$\begin{bmatrix} \mathcal{C}\mathcal{L}_2 & \mathcal{C}\mathcal{A}\mathcal{L}_2 & \mathcal{C}\mathcal{A}^2\mathcal{L}_2 \end{bmatrix} = \begin{bmatrix} 0 & 0 & 0 \\ 0 & 0 & ? \\ 0 & 0 & * \end{bmatrix}$$

-

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}.$$

$$\mathcal{R} = \begin{bmatrix} \mathcal{C}\mathcal{A}\mathcal{L}_1 & \mathcal{C}\mathcal{A}^2\mathcal{L}_2 \end{bmatrix}$$
$$= \begin{bmatrix} * & 0 \\ ? & ? \\ * & * \end{bmatrix}.$$

< E

Image: A mathematical states and a mathem

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}.$$

< E

Image: A mathematical states and a mathem

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}$$

$$\mathcal{R} = \begin{bmatrix} \mathcal{C}\mathcal{A}\mathcal{L}_1 & \mathcal{C}\mathcal{A}^2\mathcal{L}_2 \end{bmatrix}$$
$$= \begin{bmatrix} * & 0 \\ ? & ? \\ * & * \end{bmatrix}.$$

$$R = egin{bmatrix} c_1 & 0 \ \lambda_1 & \lambda_2 \ c_2 & c_3 \end{bmatrix} \in \mathcal{P}(\mathcal{R})$$

R has full column rank for all choices c_i and λ_j .

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}$$

Therefore, the FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$ is solvable.

- Introduction
- 2 Problem Formulation
- 3 Conditions for Solvability of The FDI Problem for (A, L, C)
- $[\Phi]$ Algebraic Conditions for Solvability of The FDI Problem for $(\mathcal{A},\mathcal{L},\mathcal{C})$
- Graph-theoretic Conditions for Solvability of The FDI Problem for (A, L, C)
- Summary

Associated Graphs of Pattern Matrices

- Given a pattern matrix $\mathcal{M} \in \{0, *, ?\}^{p \times q}$ $(p \leq q)$, we define the associated graph $G(\mathcal{M}) = (V, E)$ as follows:
- Node set $V = \{1, 2, ..., q\}.$
- Edge set $E = E_* \cup E_?$, where $E_* = \{(i, j) \in V \times V \mid \mathcal{M}_{ji} = *\}$ and $E_? = \{(i, j) \in V \times V \mid \mathcal{M}_{ji} = ?\}.$

Associated Graphs of Pattern Matrices

- Given a pattern matrix $\mathcal{M} \in \{0, *, ?\}^{p \times q}$ $(p \leq q)$, we define the associated graph $G(\mathcal{M}) = (V, E)$ as follows:
- Node set $V = \{1, 2, ..., q\}.$
- Edge set $E = E_* \cup E_?$, where $E_* = \{(i, j) \in V \times V \mid \mathcal{M}_{ji} = *\}$ and $E_? = \{(i, j) \in V \times V \mid \mathcal{M}_{ji} = ?\}.$



$$\mathcal{M} = \begin{bmatrix} * & ? & * \\ 0 & ? & * \end{bmatrix}$$

Figure: The graph $G(\mathcal{M})$.

- Consider a graph $G(\mathcal{M})$ with $\mathcal{M} \in \{0, *, ?\}^{p \times q}$ $(p \leq q)$.
 - 1. Initially, color all nodes of $G(\mathcal{M})$ white.
 - 2. If a node $i \in V$ (of any color) has
 - exactly one white out-neighbor j and
 - $(i,j) \in E_*$,

- 3. Repeat the Step 2 until no more color changes are possible.
- The $G(\mathcal{M})$ is called **colorable** if all the nodes in $\{1, 2, ..., p\}$ are colored black finally.

- Consider a graph $G(\mathcal{M})$ with $\mathcal{M} \in \{0, *, ?\}^{p \times q}$ $(p \leq q)$.
 - 1. Initially, color all nodes of $G(\mathcal{M})$ white.
 - 2. If a node $i \in V$ (of any color) has
 - exactly one white out-neighbor j and
 - $(i,j) \in E_*$,

- 3. Repeat the Step 2 until no more color changes are possible.
- The $G(\mathcal{M})$ is called **colorable** if all the nodes in $\{1, 2, ..., p\}$ are colored black finally.

$$\mathcal{M} = \begin{bmatrix} * & ? & * \\ 0 & ? & * \end{bmatrix}$$



- Consider a graph $G(\mathcal{M})$ with $\mathcal{M} \in \{0, *, ?\}^{p \times q}$ $(p \leq q)$.
 - 1. Initially, color all nodes of $G(\mathcal{M})$ white.
 - 2. If a node $i \in V$ (of any color) has
 - exactly one white out-neighbor j and
 - $(i,j) \in E_*$,

- 3. Repeat the Step 2 until no more color changes are possible.
- The $G(\mathcal{M})$ is called **colorable** if all the nodes in $\{1, 2, ..., p\}$ are colored black finally.

$$\mathcal{M} = \begin{bmatrix} * & ? & * \\ 0 & ? & * \end{bmatrix}$$



- Consider a graph $G(\mathcal{M})$ with $\mathcal{M} \in \{0, *, ?\}^{p \times q}$ $(p \leq q)$.
 - 1. Initially, color all nodes of $G(\mathcal{M})$ white.
 - 2. If a node $i \in V$ (of any color) has
 - exactly one white out-neighbor j and
 - $(i,j) \in E_*$,

- 3. Repeat the Step 2 until no more color changes are possible.
- The $G(\mathcal{M})$ is called **colorable** if all the nodes in $\{1, 2, ..., p\}$ are colored black finally.

$$\mathcal{M} = \begin{bmatrix} * & ? & * \\ 0 & ? & * \end{bmatrix}$$



A Graph-theoretic Condition for Solvability of The FDI Problem

Define the **transpose** of \mathcal{R} as the pattern matrix $\mathcal{R}^{\top} \in \{0, *, ?\}^{s \times r}$ with $(\mathcal{R}^{\top})_{ij} = \mathcal{R}_{ji}$ for i = 1, 2, ..., s and j = 1, 2, ..., r.

A Graph-theoretic Condition for Solvability of The FDI Problem

Define the **transpose** of \mathcal{R} as the pattern matrix $\mathcal{R}^{\top} \in \{0, *, ?\}^{s \times r}$ with $(\mathcal{R}^{\top})_{ij} = \mathcal{R}_{ji}$ for i = 1, 2, ..., s and j = 1, 2, ..., r.

Theorem 5

Consider the system $(\mathcal{A}, \mathcal{L}, \mathcal{C})$. Suppose that the indices η_i exists for i = 1, 2, ..., q. Let \mathcal{R} be the pattern matrix given by (4). Then, the FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$ is solvable if $G(\mathcal{R}^{\top})$ is colorable.

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}.$$

J. Jia (Rug JBI)

FDI for Linear Structured Systems

March 15, 2020 22

▶ < ∃ >

Image: A mathematical states and a mathem

3

$$\mathcal{A} = \begin{bmatrix} * & 0 & 0 & 0 & 0 \\ * & ? & 0 & ? & 0 \\ 0 & * & * & ? & 0 \\ * & 0 & 0 & ? & * \\ 0 & 0 & * & 0 & * \end{bmatrix}, \quad \mathcal{L} = \begin{bmatrix} * & 0 \\ ? & * \\ 0 & 0 \\ 0 & 0 \\ 0 & 0 \end{bmatrix}, \quad \mathcal{C} = \begin{bmatrix} 0 & 0 & 0 & * & 0 \\ 0 & 0 & 0 & ? & ? \\ 0 & 0 & 0 & * & * \end{bmatrix}.$$
$$\mathcal{R}^{\top} = \begin{bmatrix} * & ? & * \\ 0 & ? & * \\ 0 & ? & * \end{bmatrix}.$$



Figure: The graph $G(\mathcal{R}^{\top})$ is colorable.



Figure: The graph $G(\mathcal{R}^{\top})$ is colorable.

The FDI problem for $(\mathcal{A}, \mathcal{L}, \mathcal{C})$ is solvable.

22 / 25

• Formalize the solvability of the FDI problem for linear structured systems.

-

э
- Formalize the solvability of the FDI problem for linear structured systems.
- Establish a necessary and sufficient condition for solvability of the FDI problem for a given particular LTI system.

- Formalize the solvability of the FDI problem for linear structured systems.
- Establish a necessary and sufficient condition for solvability of the FDI problem for a given particular LTI system.
- Establish a sufficient condition for solvability of the FDI problem in terms of a rank test on a pattern matrix associated with the structured system.

- Formalize the solvability of the FDI problem for linear structured systems.
- Establish a necessary and sufficient condition for solvability of the FDI problem for a given particular LTI system.
- Establish a sufficient condition for solvability of the FDI problem in terms of a rank test on a pattern matrix associated with the structured system.
- Establish a graph-theoretic condition for solvability of the FDI problem using the concept of colorability of a graph.



📎 J. Jia, H. L. Trentelman and M. K. Camlibel (2020). Fault Detection and Isolation for Linear Structured Systems. https://arxiv.org/abs/2003.01502

J. Jia (Rug JBI)

FDI for Linear Structured Systems

March 15, 2020 24 / 25

Thank You for Your Attention! The End

J. Jia (Rug JBI)

FDI for Linear Structured Systems

March 15, 2020 25 / 25