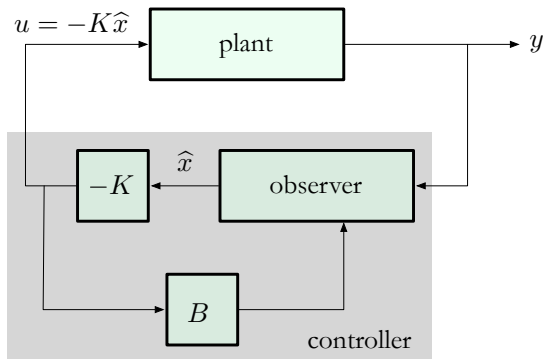


## Dynamic Output Feedback

$$\dot{\hat{x}} = (A - LC - BK)\hat{x} + Ly, \quad u = -K\hat{x}$$



Controller transfer function (from  $y$  to  $u$ ):

$$s\hat{X} = (A - LC - BK)\hat{X} + LY, \quad U = -K\hat{X}$$
$$U = \underbrace{-K(Is - A + LC + BK)^{-1}LY}_{=D(s)}$$