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In Addition To The Conditions Given Above, We Must Assume That The Ordering Is Complete In The Sense That If A 6=B Then Either A  $^{\circ}b$  Or B  $^{\circ}a$ . So Assume We Have Such A Relation On Z N. Since [0] and [1] are Distinct Congugacy Classes In Z N, We Must Then Have Either [0]  $^{\circ}[1]$  Or [1]  $^{\circ}[0]$ . Assume [0]  $^{\circ}[1]$ . The Mar 3th, 2024

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See [Khalil Ch. 3] The Peaking Phenomenon Example: Controlled Linear System With Right-half Plane Ze Ro Feedback Can Change Location Of Poles But Not Location Of Zer O (unstable Pole-zero Cancellation Not Allowed). G Cl Dse! D S #1ew 2 O S2 #2w O S #w 2 O (1) A Step Response Will Reveal A Apr 3th, 2024

#### 5. NONLINEAR MODELS [1] Nonlinear (NL) Regression Models

5. NONLINEAR MODELS [1] Nonlinear (NL) Regression Models • General Form Of Nonlinear Or Linear Regression Models: Yt =  $H(xt \bullet, \beta) + \epsilon t$ ,  $\epsilon t$  lid  $N(0, \sigma 2)$ . • Assume That The Xt• And  $\epsilon t$  Stochastically Independent.  $\rightarrow$  This Assumption Implies That: Feb 2th. 2024

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Sometime Later Schmidt (Schmidt, 1993) Succeeded In Deriving An Approximate Algorithm Based On Daum's Original Theory, And Developed A Successful Numerical Implementation Of A Nonlinear Filter That Was A Significant Improvement To The Kalman And Extended Kalman Filters For The Type Of Tracking Problem Schmidt Was Interested In. Mar 1th. 2024

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