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# An Interval Observer for Continuous-Time Persidskii Systems

Denis Efimov, Andrey Polyakov, Xubin Ping

**Abstract**—The paper deals with design of interval observers for a class of generalized Persidskii systems. The conditions of stability for the suggested nonlinear interval observer are formulated using linear matrix inequalities. The nonnegativity of this class of models is investigated for nonlinearities satisfying the incremental passivity conditions. The efficiency of the proposed observer is demonstrated on a Lotka-Volterra model.

## I. INTRODUCTION

There are many application domains, where estimation or control tasks have to be solved under presence of important nonlinearity and uncertainty of the process models. To give a few popular examples: systems biology and neuroscience, where identification of parameters and modeling are very complicated [1], or collaborative robotics, where presence of multiple agents (including humans) introduces a lot of uncertainty [2]. Moreover, finding a generic control or estimation solution in the nonlinear setting is difficult, and frequently various canonical models are considered, *e.g.*, linear parameter-varying systems, Lur'e models [3], [4], homogeneous dynamics.

Usually, a state observer contains a copy of the process dynamics, then in the presence of uncertain parameters or/and external disturbances, such an estimator design, which has to follow the ideal value of the state, can be realized under restrictive assumptions only [5]. However, an interval observation remains more feasible since this kind of estimators using input-output information calculates only a set of admissible values (interval) for the state at each instant of time [6], [7]. It is worth highlighting that the interval estimation is not a reduction of the original observation problem, in fact it is an improvement since the interval mean value can be utilized as the state pointwise estimate, while the interval bounds provide an evaluation of the observation accuracy for the assumed model uncertainty. There are several methods to design interval/set-membership estimators [8], [9], [10], and this work deals with a design based on the theory of nonnegative systems [11], [12], [13], [14]. In such a way the main difficulty for synthesis consists

in ensuring simultaneously the stability and nonnegativity of the interval estimation error dynamics by a proper design of the observer gains.

The objective of this paper is to propose an interval observer for a class of Persidskii systems. This class of nonlinear models was first introduced for stability analysis in [15], where a linear combination of the integrals of the nonlinearities was used as a Lyapunov function. Next, that result was extended in [16] by augmenting the Lyapunov function through a combination of the absolute values of the states. Further, this class of nonlinear systems was studied in the context of diagonal stability [17], [18], sliding mode control [19], [20], [21] and Lur'e systems [3], with applications to opinion dynamics [22], neural networks [23], [24], [25] and others [26]. Its main advantage consists in availability of a canonical form of Lyapunov function. Hence, to analyze stability of the suggested nonlinear observer the Lyapunov function method will be used, whose application results in verification of linear matrix inequalities (LMIs). The conditions of nonnegativity for the Persidskii systems are revisited. Finally, the utility of the developed theory is demonstrated on the problem of interval estimation for a population model supporting mutualistic interactions in the Lotka-Volterra form.

## Notation

- $\mathbb{R}_+ = \{x \in \mathbb{R} : x \geq 0\}$ , where  $\mathbb{R}$  is the set of real numbers.  $\mathbb{Z}$  is the set of integers,  $\mathbb{Z}_+ = \mathbb{Z} \cap \mathbb{R}_+$ .
- $|\cdot|$  denotes the absolute value in  $\mathbb{R}$ ,  $\|\cdot\|$  is used for the Euclidean norm on  $\mathbb{R}^n$ .
- For a measurable function  $d : \mathbb{R}_+ \rightarrow \mathbb{R}^m$  and  $[t_0, t_1) \subset \mathbb{R}_+$  define the norm  $\|d\|_{[t_0, t_1)} = \text{ess sup}_{t \in [t_0, t_1)} \|d(t)\|$ , then  $\|d\|_\infty = \|d\|_{[0, +\infty)}$  and the set of  $d$  with the property  $\|d\|_\infty < +\infty$  we further denote as  $\mathcal{L}_\infty^m$  (the set of essentially bounded measurable functions).
- A continuous function  $\alpha : \mathbb{R}_+ \rightarrow \mathbb{R}_+$  belongs to the class  $\mathcal{K}$  if  $\alpha(0) = 0$  and the function is strictly increasing. The function  $\alpha : \mathbb{R}_+ \rightarrow \mathbb{R}_+$  belongs to the class  $\mathcal{K}_\infty$  if  $\alpha \in \mathcal{K}$  and it is increasing to infinity.
- A finite series of integers  $1, 2, \dots, n$  is denoted by  $\overline{1, n}$ , and  $\{\overline{1, n}\} = \{1, 2, \dots, n\}$ .
- Denote the identity matrix of dimension  $n \times n$  by  $I_n$ , the vector of dimension  $n$  or the matrix of dimension  $n \times m$  with all elements equal 1 by  $\mathbf{1}_n$  and  $\mathbf{1}_{n \times m}$ , respectively. The canonical basis vectors in  $\mathbb{R}^n$  are denoted as  $\mathbf{e}_i =$

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$[0 \dots 0 \ 1 \ \dots 0]^\top$  for  $i = \overline{1, n}$ , where 1 appears in the  $i^{\text{th}}$  position.

- $\text{diag}\{g\} \in \mathbb{D}_+^n$  represents a diagonal matrix of dimension  $n \times n$  with a vector  $g \in \mathbb{R}_+^n$  on the main diagonal, where  $\mathbb{D}_+^n \subset \mathbb{R}^{n \times n}$  is the set of nonnegative diagonal matrices.
- For a matrix  $A \in \mathbb{R}^{n \times n}$  the vector of its eigenvalues is denoted by  $\lambda(A)$ , its  $i^{\text{th}}$  row and column by  $A^{(i)}$  and  $A^{[i]}$ , respectively, for  $i = \overline{1, n}$ ;  $\|A\|_{\max} = \max_{i,j=\overline{1,n}} |A_{i,j}|$  (the elementwise maximum norm, it is not sub-multiplicative) and  $\|A\|_2 = \sqrt{\max_{i=\overline{1,n}} \lambda_i(A^\top A)}$  (the induced matrix norm), the relations  $\|A\|_{\max} \leq \|A\|_2 \leq n\|A\|_{\max}$  are satisfied between these norms.
- The relation  $P \prec 0$  ( $P \succ 0$ ) means that a symmetric matrix  $P \in \mathbb{R}^{n \times n}$  is negative (positive) definite.

## II. PRELIMINARIES

The used standard stability notions and their definitions can be found in [27].

In this paper, it is assumed that if the upper limit of a summation or a sequence is smaller than the lower one, then the corresponding terms (conditions) have to be omitted.

### A. Interval arithmetic

For two vectors  $x_1, x_2 \in \mathbb{R}^n$  or matrices  $A_1, A_2 \in \mathbb{R}^{n \times n}$ , the relations  $x_1 \leq x_2$  and  $A_1 \leq A_2$  are understood elementwise.

Given a matrix  $A \in \mathbb{R}^{m \times n}$ , define  $A^+ = \max\{0, A\}$ ,  $A^- = A^+ - A$  (similarly for vectors) and denote the matrix of absolute values of all elements by  $|A| = A^+ + A^-$ .

**Lemma 1.** [28] *Let  $x \in \mathbb{R}^n$  be a vector variable,  $\underline{x} \leq x \leq \bar{x}$  for some  $\underline{x}, \bar{x} \in \mathbb{R}^n$ . If  $A \in \mathbb{R}^{m \times n}$  is a constant matrix, then*

$$A^+ \underline{x} - A^- \bar{x} \leq Ax \leq A^+ \bar{x} - A^- \underline{x}. \quad (1)$$

### B. Nonnegative systems

A matrix  $A \in \mathbb{R}^{n \times n}$  is called *Hurwitz* if all its eigenvalues have negative real parts, it is called *Metzler* if all its elements outside the main diagonal are nonnegative.

Any solution of the linear system

$$\dot{x}(t) = Ax(t) + B\omega(t), \quad t \geq 0, \quad (2)$$

with  $x(t) \in \mathbb{R}^n$  and a Metzler matrix  $A \in \mathbb{R}^{n \times n}$ , is elementwise nonnegative for all  $t \geq 0$  provided that  $x(0) \geq 0$ ,  $\omega : \mathbb{R}_+ \rightarrow \mathbb{R}_+^q$  and  $B \in \mathbb{R}_+^{n \times q}$  [29], [30]. The dynamical systems are called *nonnegative* if for initial conditions in  $\mathbb{R}_+^n$  the nonnegativity of the solutions is guaranteed [30].

### C. Persidskii systems

Consider the following class of systems [31], [32]:

$$\dot{x}(t) = A_0 x(t) + \sum_{j=1}^M A_j f^j(H_j x(t)) + Bu(t) + d(t), \quad (3)$$

$$y(t) = \begin{bmatrix} C_0 x(t) \\ C_1 f^1(H_1 x(t)) \\ \vdots \\ C_M f^M(H_M x(t)) \end{bmatrix} + v(t), \quad t \geq 0,$$

where  $x(t) = [x_1(t) \dots x_n(t)]^\top \in \mathbb{R}^n$  is the state vector,  $x(0) \in \mathbb{R}^n$ ;  $u(t) \in \mathbb{R}^m$  is the known input,  $u \in \mathcal{L}_\infty^m$ ;  $y(t) \in \mathbb{R}^p$  is the output signal,  $p = \sum_{k=0}^M p_k$  and  $C_g \in \mathbb{R}^{p_g \times k_g}$  for  $g = \overline{0, M}$ , which is available for measurements and containing the perturbation  $v(t) \in \mathbb{R}^p$ ,  $v \in \mathcal{L}_\infty^p$ ; and  $d(t) \in \mathbb{R}^n$  is the external disturbance,  $d \in \mathcal{L}_\infty^n$ ;  $f^j : \mathbb{R}^{k_j} \rightarrow \mathbb{R}^{k_j}$  with diagonal structure  $f^j(s) = [f_1^j(s_1) \dots f_{k_j}^j(s_{k_j})]^\top$ ,  $j = \overline{1, M}$  are the continuous functions ensuring existence and uniqueness of solutions in (3) for  $t \geq 0$ , the matrices  $A_g \in \mathbb{R}^{n \times k_g}$  and  $H_g \in \mathbb{R}^{k_g \times n}$  for  $g = \overline{0, M}$ , where for brevity we use the convention  $k_0 = n$  and  $H_0 = I_n$  with  $f^0(x) = x$ .

The model (3) belongs to the class of *Persidskii system* [16], [17] under the following *passivity* (or *sector*) condition imposed on  $f^j$ : for any  $j = \overline{1, M}$  and  $i = \overline{1, k_j}$ :

$$s f_i^j(s) > 0 \quad \forall s \in \mathbb{R} \setminus \{0\}.$$

In the property above it is stated that all nonlinearities belong to a sector and may take zero values at zero only. If  $H_1 = I_n$  and  $A_r = 0$  for all  $r = \overline{2, M}$ , then we recover the system studied by Persidskii in [16]. In the case of  $M = 1$ , (3) belongs also to the class of Lur'e systems widely investigated in the absolute stability theory [4]. In this work we will need a more strong *incremental passivity* (or *monotonicity*) property ensured by the following assumption:

**Assumption 1.** *For any  $j = \overline{1, M}$  and  $i = \overline{1, k_j}$ :*

$$(s_1 - s_2) \left( f_i^j(s_1) - f_i^j(s_2) \right) > 0 \quad \forall s_1, s_2 \in \mathbb{R}, \quad s_1 \neq s_2.$$

Taking  $s_2 = 0$ , and since  $f_i^j(0) = 0$ , Assumption 1 implies the sector condition, while additionally asking certain monotonicity of the nonlinearities (it is also called *incremental passivity* of  $f_i^j$ ).

After a proper re-indexing and decomposition of  $f^j$ , there exists  $\nu \in \{0, M\}$  such that for all  $z = \overline{1, \nu}$  and  $i = \overline{1, k_z}$ :

$$\lim_{s \rightarrow \pm\infty} f_i^z(s) = \pm\infty;$$

and due to Assumption 1 for all  $j = \overline{1, M}$  and  $i = \overline{1, k_j}$ :

$$\lim_{s \rightarrow \pm\infty} \int_0^s f_i^j(\sigma) d\sigma = +\infty.$$

Thus, some of the nonlinearities are radially unbounded, and  $\nu = 0$  corresponds to the case when all nonlinearities are bounded (at least for negative or positive argument).

### III. PROBLEM STATEMENT

Consider the system (3). The following assumptions will be used in this work.

**Assumption 2.** Let  $x(0) \in [\underline{x}_0, \bar{x}_0]$  for known  $\underline{x}_0, \bar{x}_0 \in \mathbb{R}^n$ .

**Assumption 3.** There exists known signals  $\underline{d}, \bar{d} \in \mathcal{L}_\infty^n$  and a constant  $V > 0$  such that  $\underline{d}(t) \leq d(t) \leq \bar{d}(t)$  and  $-V\mathbf{1}_p \leq v(t) \leq V\mathbf{1}_p$  for all  $t \geq 0$ .

Assumptions 2 and 3 represent standard hypotheses for the interval estimation [6], [7].

The objective of this work is to design an *interval observer* for the system (3), which is a dynamical system that utilizes the properties stated in assumptions 1–3 (i.e., takes the information on the initial conditions  $[\underline{x}_0, \bar{x}_0]$ , the admissible bounds on the values of the exogenous input  $[\underline{d}(t), \bar{d}(t)]$ , the upper bound on the measurement noise  $V$ ), the information about the system matrices  $A_k, H_k, B$  and  $C_k$  for  $k = \overline{0, M}$ , and generates interval estimates  $\underline{x}(t), \bar{x}(t) \in \mathbb{R}^n$  such that  $\bar{x} - \underline{x} \in \mathcal{L}_\infty^n$  and

$$\underline{x}(t) \leq x(t) \leq \bar{x}(t) \quad \forall t \geq 0. \quad (4)$$

Further, we design an interval observer for the system (3) under an additional assumption given in Section V.

### IV. NONNEGATIVITY IN PERSIDSKII SYSTEMS

In the simplest disturbance-free case of (3) with  $M = 1$  and  $H_1 = I_n$  (the conventional form of Persidskii systems):

$$\dot{x}(t) = A_0 x(t) + A_1 f^1(x(t)) + Bu(t),$$

the nonnegativity conditions can be similar to the ones for (2) [16], [33]: the matrices  $A_0$  and  $A_1$  are Metzler and  $Bu(t) \in \mathbb{R}_+^m$  for all  $t \geq 0$ . However, for  $H_1 \neq I_n$  the conditions become more sophisticated:

**Lemma 2.** For any  $x(0) \in \mathbb{R}_+^n$ , the special case of (3),

$$\dot{x}(t) = A_1 f^1(H_1 x(t)),$$

satisfying Assumption 1, has  $x(t) \geq 0$  for all  $t \geq 0$ , provided that for all  $i = \overline{1, k_1}$  one of the following properties is verified:

- i)  $H_1^{(i)} \geq 0$  and  $A_1^{[i]} \geq 0$ ,
- ii)  $H_1^{(i)} \leq 0$  and  $A_1^{[i]} \leq 0$ .

Moreover, if  $H_1^{(i)} = \kappa \mathbf{e}_r^\top$  for some  $\kappa \in \mathbb{R}$ ,  $i \in \{\overline{1, k_1}\}$  and  $r \in \{\overline{1, n}\}$ , then  $(A_1)_{r,i}$  can be arbitrary.

All proofs are skipped due to space limitations.

The conditions given in Lemma 2 generalize the previous ones: it is easy to check that if  $H_1 = I_n$ , then  $A_1$  can be chosen Metzler according to Lemma 2.

Since the proposed nonnegativity conditions depend on the pair of matrices  $A_1$  and  $H_1$ , then further we will say that

$$(A_1, H_1) \in \mathcal{N}$$

if the restrictions formulated in Lemma 2 are verified (hence, the property  $(A_0, H_0) = (A_0, I_n) \in \mathcal{N}$  implies that  $A_0$  is Metzler).

**Corollary 1.** Under Assumption 1 the system (3) is nonnegative if  $(A_k, H_k) \in \mathcal{N}$  for all  $k = \overline{0, M}$  and  $Bu(t) + d(t) \geq 0$  for all  $t \geq 0$ .

Similarly can be formulated conditions for nonnegativity of discrepancy between two solutions of (3) with different initial conditions:

**Corollary 2.** Under Assumption 1, consider a copy of (3):

$$\dot{\xi}(t) = A_0 \xi(t) + \sum_{j=1}^M A_j f^j(H_j \xi(t)) + Bu(t) + d(t),$$

with the same inputs  $u, d$  and  $\xi(0) \in \mathbb{R}^n$  verifying  $x(0) \geq \xi(0)$ , then  $x(t) \geq \xi(t)$  for all  $t \geq 0$  provided that  $(A_k, H_k) \in \mathcal{N}$  for all  $k = \overline{0, M}$ .

The conditions of corollaries 1 and 2 will be used later in the design of interval observer.

*Remark 1.* As in the case of (2), if  $(A_k, H_k) \notin \mathcal{N}$ , then a transformation of coordinates can be considered. Indeed, the transformation  $z = Sx$  with an invertible matrix  $S \in \mathbb{R}^{n \times n}$  keeps the Persidskii form of (3) in the new coordinates and [13] can be used to derive  $S$ . However, to find such a  $S$  providing Metzler property to the matrix  $\tilde{A}_0 = SA_0S^{-1}$  and simultaneously  $(A_j, H_j) \in \mathcal{N}$  for all  $j = \overline{1, M}$  can be difficult. If all matrices  $A_j$  are sufficiently close to each other, then the result of [34] can be adapted to derive  $S$ .

However, if such a transformation  $S$  cannot be found, then interval inclusion of the nonlinearities can be utilized for design of interval observers. Such an inclusion is well developed in the theory of the bounding decomposition functions for mixed monotone mappings [35], which in our case has a simple realization:

**Lemma 3.** Let  $s, \underline{s}, \bar{s} \in \mathbb{R}^{k_1}$  and  $f^1 : \mathbb{R}^{k_1} \rightarrow \mathbb{R}^{k_1}$  verify Assumption 1, then

$$\underline{s} \leq s \leq \bar{s} \Leftrightarrow f^1(\underline{s}) \leq f^1(s) \leq f^1(\bar{s}).$$

If  $\underline{x} \leq x \leq \bar{x}$  for some  $x, \underline{x}, \bar{x} \in \mathbb{R}^n$ ,  $H_1 \in \mathbb{R}^{k_1 \times n}$  and  $f^1 : \mathbb{R}^{k_1} \rightarrow \mathbb{R}^{k_1}$  verifies Assumption 1, then  $\underline{s} = H_1^+ \underline{x} - H_1^- \bar{x} \leq s = H_1 x \leq H_1^+ \bar{x} - H_1^- \underline{x} = \bar{s}$  due to (1), and using Lemma 3 we obtain:

$$f^1(H_1^+ \underline{x} - H_1^- \bar{x}) \leq f^1(H_1 x) \leq f^1(H_1^+ \bar{x} - H_1^- \underline{x}). \quad (5)$$

### V. INTERVAL OBSERVER DESIGN

The system (3) can be equivalently presented as follows:

$$\begin{aligned} \dot{x}(t) = & (A_0 - L_0 C_0)x(t) + \sum_{j=1}^M (A_j - L_j C_j) f^j(H_j x(t)) \\ & + L(y(t) - v(t)) + Bu(t) + d(t), \end{aligned}$$

where  $L = [L_0 \ L_1 \ \dots \ L_M] \in \mathbb{R}^{n \times p}$ , with  $L_k \in \mathbb{R}^{n \times p_k}$  for  $k = \overline{0, M}$ , is an observer gain to be properly chosen next. As



$$\begin{aligned}\underline{\delta}(t) &= TBu(t) + Ly(t) + N\dot{y}_0(t) - \sum_{r=0}^{\ell} \kappa_r(\underline{x}(t)) \\ &\quad - |L|V + T^+ \underline{d}(t) - T^- \bar{d}(t), \\ \bar{\delta}(t) &= TBu(t) + Ly(t) + N\dot{y}_0(t) + \sum_{r=0}^{\ell} \bar{\kappa}_r(\bar{x}(t)) \\ &\quad + |L|V + T^+ \bar{d}(t) - T^- \underline{d}(t).\end{aligned}$$

Following [32], [37], the input-to-output stability property [38] of the system (7) is established by using a Lyapunov function:

$$W(X) = X^\top P X + 2 \sum_{j=1}^M \sum_{i=1}^{2k_j} \Lambda_i^j \int_0^{\mathcal{H}_j^{(i)} X} F_i^j(s) ds,$$

where  $P = P_1 + \Gamma^\top P_2 \Gamma$  and  $\Lambda^j = \text{diag}[\Lambda_1^j \dots \Lambda_{2k_j}^j]$ .

A necessary condition for feasibility of LMIs given in the formulation of Theorem 1 is that all matrices on the main diagonal of  $Q$  are nonnegative definite, *i.e.*,  $\Omega_g^\top \mathcal{D}_g + \mathcal{D}_g^\top \Omega_g \preceq 0$  for  $g = \underline{0}, \bar{M}$  with some  $\Omega_g \in \mathbb{R}^{2n \times 2k_g}$ , which can be easily checked. The result of this theorem also allows the asymptotic gain, for the estimation accuracy  $Y = \bar{x} - \underline{x}$  from the uncertainty collected in  $\delta$ , be evaluated.

## VI. INTERVAL ESTIMATION FOR A LOTKA-VOLTERRA MODEL

Consider the problem of interval state estimation for a generalized Lotka–Volterra model with a support of mutualistic interactions [39], [40]:

$$\dot{x}(t) = \text{diag}\{x(t)\} (d(t) + A_1 x(t) + A_2 \varphi(x(t))), \quad t \geq 0,$$

where  $x(t) \in \mathbb{R}_+^n$  is the vector of the populations of  $n$  biological species,  $x(0) \in \mathbb{R}_+^n$ ;  $d(t) \in \mathbb{R}^n$  corresponds to the intrinsic time-varying birth or death rates of the species,  $A_1 \in \mathbb{R}^{n \times n}$  is the community matrix, and  $A_2 \in \mathbb{R}^{n \times n}$  is the mutualistic interaction strength between the species;  $\varphi(x(t)) = [\varphi_1(x_1) \dots \varphi_n(x_n)]^\top = [\frac{x_1}{r_1 + x_1} \dots \frac{x_n}{r_n + x_n}]^\top$  is the vector of Michaelis-Menten functions with  $r = [r_1 \dots r_n]^\top \in \mathbb{R}_+^n$  being the half-saturation constants. We assume that the coupling matrices  $A_1$  and  $A_2$  are known, but the rates in  $d$  are known with an interval error, *i.e.*, there are  $\underline{d}(t), \bar{d}(t) \in \mathcal{L}_\infty^n$  such that

$$\underline{d}(t) \leq d(t) \leq \bar{d}(t), \quad \forall t \geq 0.$$

Without losing generality assume that the levels of the first  $\eta > 0$  populations can be measured:

$$\tilde{y}(t) = Cx(t), \quad C = [I_\eta \ 0].$$

Lotka–Volterra model is a highly nonlinear dynamical system, which is not in the form of (3), but it can be brought to it by a transformation of coordinates  $z = \ln(x)$  (where logarithm is applied elementwise) with

$$\begin{aligned}\dot{z}(t) &= A_1 f^1(z(t)) + A_2 f^2(z(t)) + u + d(t), \\ y(t) &= [y_0(t)^\top \ y_1(t)^\top \ y_2(t)^\top]^\top, \\ y_0(t) &= Cz(t), \quad y_1(t) = C f^1(z(t)), \quad y_2(t) = C f^2(z(t)),\end{aligned}$$

where

$$\begin{aligned}f^1(z) &= e^z - \mathbf{1}_n, \quad f^2(z) = \varphi(e^z) - c, \quad u = A_1 \mathbf{1}_n + A_2 c, \\ c &= [c_1 \dots c_n]^\top, \quad c_i = \frac{1}{1 + r_i}, \quad i = \overline{1, n},\end{aligned}$$

and Assumption 1 is satisfied for such a choice of  $f^1$  and  $f^2$ , the variable  $u \in \mathbb{R}^n$  represents the known input. The values of the output  $y(t)$  can be calculated from the measured signal  $\tilde{y}(t)$  (*i.e.*,  $\tilde{y}(t) = C e^{z(t)}$ , then  $\ln \tilde{y}(t) = Cz(t) = y_0(t)$  and so on). By assuming that  $x(0) \in [\underline{x}_0, \bar{x}_0]$  for some known  $\underline{x}_0, \bar{x}_0 \in \mathbb{R}_+^n$ , we get  $z(0) \in [\ln(\underline{x}_0), \ln(\bar{x}_0)] = [\underline{z}_0, \bar{z}_0]$  and assumptions 2 and 3 are also verified with  $V = 0$ . To guarantee the fulfillment of Assumption 4 we need to select the observer design gains  $L$  and  $N$  for given  $A_1$  and  $A_2$  with  $A_0 = 0$ , which we assume to be successfully done with  $\ell = 2$ . Hence, the interval observer takes the form (6), and if  $N = 0$  in the original coordinates:

$$\begin{aligned}\dot{\underline{x}}(t) &= \text{diag}\{\underline{x}(t)\} [-L_0 C \ln(\underline{x}(t)) + (A_1 - L_1 C) \underline{x}(t) \\ &\quad + (A_2 - L_2 C) \varphi(\underline{x}(t)) + L_0 \ln(\tilde{y}(t)) \\ &\quad + L_1 \tilde{y}(t) + L_2 \varphi(\tilde{y}(t)) + \underline{d}(t)], \\ \dot{\bar{x}}(t) &= \text{diag}\{\bar{x}(t)\} [-L_0 C \ln(\bar{x}(t)) + (A_1 - L_1 C) \bar{x}(t) \\ &\quad + (A_2 - L_2 C) \varphi(\bar{x}(t)) + L_0 \ln(\tilde{y}(t)) \\ &\quad + L_1 \tilde{y}(t) + L_2 \varphi(\tilde{y}(t)) + \bar{d}(t)],\end{aligned}$$

where it is worth to highlight the presence of nonlinear output injection terms.

**Example.** In Fig. 1, the results of simulation are shown (solid lines correspond to the trajectories of the system, dot and dash curves represent the lower and upper interval estimates, respectively) for

$$\begin{aligned}n &= 3, \quad \eta = 1, \\ A_1 &= \begin{bmatrix} -2.68 & 0.50 & 0.16 \\ -0.23 & -2.80 & 0.75 \\ 0.56 & 0.42 & -2.63 \end{bmatrix}, \quad A_2 = \begin{bmatrix} -1.98 & 0.62 & 0.72 \\ -0.05 & -1.46 & 0.09 \\ 0.24 & 0.65 & -1.12 \end{bmatrix}, \\ r &= [1.05 \ 1.81 \ 1.52]^\top, \quad d(t) = \sin(t) + [0.13 \ 0.15 \ 0.36]^\top,\end{aligned}$$

with the bounds

$$\begin{aligned}\underline{x}_0 &= [0.62 \ 0.19 \ 0.48]^\top, \quad \bar{x}_0 = [0.76 \ 0.23 \ 0.59]^\top, \\ \underline{d}(t) &= \sin(t) + [0.07 \ 0.08 \ 0.27]^\top, \quad \bar{d}(t) = \sin(t) + [0.20 \ 0.21 \ 0.45]^\top,\end{aligned}$$

and the observer gains:

$$\begin{aligned}L_0 &= [2 \ 0 \ 0]^\top, \quad L_1 = [-0.01 \ -0.29 \ -0.17]^\top, \\ L_2 &= [-0.92 \ -0.06 \ -0.58]^\top.\end{aligned}$$

For these values all assumptions are satisfied. As we can see the proposed interval observer generates very reasonable and bounded estimates for a highly nonlinear uncertain system.

## VII. CONCLUSION

The paper addressed the issue of design of interval observers for a class of generalized Persidskii systems. The conditions of nonnegativity in this class of models were established. A possible structure of the interval observer was given, together with respective stability conditions. All conditions are formulated in terms of LMIs. To illustrate the

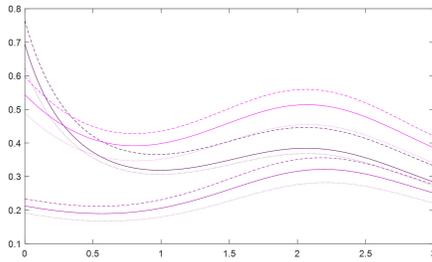


Figure 1. The results of interval estimation by (6) for a Lotka-Volterra model:  $x(t)$ ,  $\underline{x}(t)$ ,  $\bar{x}(t)$  versus time  $t$

efficiency of the proposed interval observer, it was applied to a Lotka-Volterra model. Development of these results to interval prediction and model predictive control design as in [41], [42] can be considered as a direction for future research.

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