Necessary and Sufficient Conditions for Distinguishability of Linear Control Systems

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Abstract. Distinguishability takes a crucial rule in studying observability of hybrid system such as switched system. Recently, for two linear systems, Lou and Si gave a condition not only necessary but also sufficient to the distinguishability of linear systems. However, the condition is not easy enough to verify. This paper will give a new equivalent condition which is relatively easy to verify.

Key words and phrases. distinguishability, linear control systems, necessary and sufficient condition.

AMS subject classifications. 34H05, 93B99

1 Introduction

Consider a switched system composed by two time-invariant subsystems \((i = 1, 2)\):

\[
S_i : \begin{cases}
\frac{dx}{dt} = A_i x(t) + B_i u(t), \\
y(t) = C_i x(t) + G_i u(t),
\end{cases}
\]

(1.1)

where \(x(t) \in \mathbb{R}^n\), \(u(t) \in \mathbb{R}^m\) and \(y(t) \in \mathbb{R}^k\). Naturally,

\[
A_i \in \mathbb{R}^{n \times n}, \quad B_i \in \mathbb{R}^{n \times m}, \quad C_i \in \mathbb{R}^{k \times n}, \quad G_i \in \mathbb{R}^{k \times m}.
\]

(1.2)

Switched system is an important case of hybrid systems. When we consider the observability of switched system composed by time-invariant subsystems such as system (1.1), distinguishability takes a crucial rule (see [6], [8]). Among the references about observability/distinguishability of hybrid system, we would like to refer the readers to the papers [1], [2], [3], [4], [5], [7], [9], [10], [11], [13] and [14].

In [14], the authors got a necessary and sufficient condition for distinguishability of two linear automation systems (i.e. \(B_1 = B_2 = 0, G_1 = G_2 = 0\)). However, as pointed out by the authors

\*This work was supported in part by NSFC (No. 61074047 and 10831007), and 973 Program (No. 2011CB808002).

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of [14], for non-automation system, the input plays a crucial role and the distinguishability of two linear systems becomes very difficult. Recently, in [8], the authors gave a definition of distinguishability for linear non-automation systems (see Definition 1.1 below), and yielded a necessary and sufficient condition for distinguishability of two linear systems.

**Definition 1.1 (distinguishability)** Systems $S_1$ and $S_2$ are said to be distinguishable on $[0, T]$, if for any non-zero 

$$(x_{10}, x_{20}, u(\cdot)) \in \mathbb{R}^n \times \mathbb{R}^n \times L^1(0, T; \mathbb{R}^m),$$

the corresponding outputs $y_1(\cdot)$ and $y_2(\cdot)$ can not be identical to each other on $[0, T]$.

To study the distinguishability of two systems, some auxiliary concepts of distinguishability was also introduced in [8]:

**Definition 1.2** Given $T > 0$. Let $\mathcal{U} \subseteq L^1(0, T; \mathbb{R}^m)$ be a function space. We say that $S_1$ and $S_2$ are $\mathcal{U}$ input distinguishable on $[0, T]$ if for any non-zero 

$$(x_{10}, x_{20}, u(\cdot)) \in \mathbb{R}^n \times \mathbb{R}^n \times \mathcal{U},$$

the outputs $y_1(\cdot)$ and $y_2(\cdot)$ can not be identical to each other on $[0, T]$.

Especially, when $\mathcal{U}$ is the set of polynomial function class, the set of analytic function class and the set of smooth function class $C^\infty([0, T]; \mathbb{R}^m)$, then the corresponding distinguishability is called “polynomial input distinguishability”, “analytic input distinguishability” and “smooth input distinguishability”, etc.

Denote

$$A = \begin{pmatrix} A_1 & 0 \\ 0 & A_2 \end{pmatrix}, B = \begin{pmatrix} B_1 \\ B_2 \end{pmatrix}, C = (C_1 - C_2), G = G_1 - G_2$$

(1.3)

and

$$X_0 = \begin{pmatrix} x_{10} \\ x_{20} \end{pmatrix}, Y(\cdot) = y_1(\cdot) - y_2(\cdot).$$

(1.4)

Then the distinguishability of $S_1$ and $S_2$ on $[0, T]$ is equivalent to that for the following system:

$$S : \begin{cases} \frac{dX}{dt} = AX(t) + Bu(t), \\ X(0) = X_0; \\ Y(t) = CX(t) + Gu(t), \end{cases}$$

(1.5)

$(X_0, u(\cdot)) \neq 0$ implies $Y(\cdot) \neq 0$ on $[0, T]$.

It was proved in [8] that
Theorem 1.3  The distinguishability of $S_1$ and $S_2$ on $[0, T]$ is equivalent to that $S_1$ and $S_2$ are analytic input distinguishable. Moreover, it is equivalent to that the infinite dimensional equation

$$\mathcal{M} \beta \equiv \begin{pmatrix} C & G & 0 & 0 & 0 & \cdots \\ CA & CB & G & 0 & 0 & \cdots \\ CA^2 & CAB & CB & G & 0 & \cdots \\ CA^3 & CA^2B & CAB & CB & G & \cdots \\ \vdots & \vdots & \vdots & \vdots & \vdots & \ddots \end{pmatrix} \begin{pmatrix} \beta_1 \\ \beta_2 \\ \beta_3 \\ \beta_4 \\ \beta_5 \\ \vdots \end{pmatrix} = 0.$$  

admits only trivial solution. Consequently, it is independent of $T$.

The disadvantage of Theorem 1.3 is that whether equation (1.6) admitting only trivial solution is not easy to verify. In this paper, we will seek for an equivalent condition which can be verified easier.

2 Properties of Differential Operator $D$ and Laplace Transform $\mathcal{L}$

We recall the notions of differential operator $D$ and Laplace transform $\mathcal{L}$ and list some useful properties of them. For the cause of notation simplicity, in this section, matrices $A, B, C, G$ and integers $n, m, k$ and etc., can be different from that in other sections.

Denote by $\mathbb{C}$ the space of complex numbers. Let

$$P(\lambda) = a_n\lambda^n + a_{n-1}\lambda^{n-1} + \ldots + a_1\lambda + a_0$$

be a polynomial, where $a_k \in \mathbb{C}$ and $\lambda \in \mathbb{C}$. For smooth vector valued function $f : [0, T] \to \mathbb{C}^k$, define

$$P(D)f(t) = a_n \frac{d^n f(t)}{dt^n} + a_{n-1} \frac{d^{n-1} f(t)}{dt^{n-1}} + \ldots + a_1 f'(t) + a_0 f(t).$$  

(2.1)

It is well known that

Lemma 2.1  Let $f, g : [0, T] \to \mathbb{C}^n$ be two smooth vector valued functions on $[0, T]$, $P(\cdot), Q(\cdot)$ are two polynomials, $\alpha, \beta \in \mathbb{C}$ and $\lambda \in \mathbb{C}$ are two complex constants. Then

$$\left(\alpha P(D) + \beta Q(D)\right)f(t) = \alpha P(D)f(t) + \beta Q(D)f(t),$$  

(2.2)

$$P(D)\left(\alpha f(t) + \beta g(t)\right) = \alpha P(D)f(t) + \beta P(D)g(t),$$  

(2.3)

$$\left(P(D)Q(D)\right)f(t) = P(D)\left(Q(D)f(t)\right) = Q(D)\left(P(D)f(t)\right),$$  

(2.4)

$$P(D)\left(e^{\lambda t}f(t)\right) = e^{\lambda t}P(D + \lambda)f(t).$$  

(2.5)
For a function \( f(\cdot) \in L^1_{loc}[0, +\infty) \), the Laplace transform of \( f(\cdot) \) is defined by

\[
F(s) \equiv \mathcal{L}(f(\cdot))(s) \triangleq \int_0^{+\infty} e^{-st} f(t) \, dt, \quad s > 0.
\]

It is well known that Laplace transform can be defined for many functions and even for generalized functions such as \( \delta \) function. If there exist \( M_1, M_2 > 0 \) such that

\[
|f(t)| \leq M_1 e^{M_2 t}, \quad \forall \ t > 0,
\]

then \( \mathcal{L}(f(\cdot))(s) \) is well defined for \( s \in (M_2, +\infty) \). Moreover, \( f(\cdot) \) has the form

\[
f(t) = e^{\lambda_1 t} P_1(t) + e^{\lambda_2 t} P_2(t) + \ldots + e^{\lambda_n t} P_n(t)
\]

with \( \lambda_k \in \mathbb{C} \) and \( P_k(\cdot) \) being polynomial \( (k = 1, 2, \ldots) \) if and only if \( \mathcal{L}(f) \) is a proper rational function.

### 3 Main Results

Now we consider the necessary and sufficient conditions for distinguishability. Let \( A, B, C, G \) be defined as in §1. By the discussions of [8], we know that if \( S_1 \) and \( S_2 \) are not distinguishable, then they are not analytic input distinguishable. More precisely, there exists a pair \((X_0, u(\cdot))\) such that

\[
(X_0, u(\cdot)) \neq 0, \quad (3.1)
\]

\[
Ce^{At} x_0 + C \int_0^t e^{A(t-s)} Bu(s) \, ds + Gu(t) = 0, \quad \forall \ t \geq 0, \quad (3.2)
\]

and

\[
u(t) = \sum_{j=0}^{\infty} \frac{\alpha_j}{j!} t^j, \quad t \in [0, +\infty), \quad (3.3)
\]

with

\[
|\alpha_j| \leq M^{j+1}, \quad \forall \ j = 0, 1, \ldots \quad (3.4)
\]

for some \( M > 0 \).

One can see that if \( u(\cdot) \) satisfies (3.3)–(3.4), then

\[
|u(t)| \leq Me^{Mt}, \quad \forall \ t \geq 0
\]

and therefore \( \mathcal{L}(u(\cdot))(s) \) can be defined for any \( s > M \).

A crucial property we will prove in the following is that

**Lemma 3.1** If \( S_1 \) and \( S_2 \) are not distinguishable, then we can find a pair \((X_0, \bar{u}(\cdot))\) satisfying (3.3)–(3.4) with

\[
\bar{u}(\cdot) = e^{\lambda_1 t} P_1(t) + e^{\lambda_2 t} P_2(t) + \ldots + e^{\lambda_q t} P_q(t), \quad (3.5)
\]

where \( \lambda_i \in \mathbb{C} \) and \( P_i(\cdot) \) are vector-valued polynomials \( (i = 1, 2, \ldots, q) \).
Proof. Since $S_1$ and $S_2$ are not distinguishable, by the results of [8], there exists a pair $(X_0, u(\cdot))$ satisfies (3.1)—(3.4). Denote

$$\Phi(s) = \mathcal{L}\left(Ce^{A_1}\right)(s), \quad \Psi(s) = \Phi(s)B, \quad U(s) = \mathcal{L}\left(u(\cdot)\right)(s).$$

Then every element in matrices $\Phi$ and $\Psi + G$ are rational functions.

Consider the Laplace transform of (3.2), we have

$$\Phi(s)X_0 + \left(\Psi(s) + G\right)U(s) = 0. \quad (3.6)$$

Let

$$r = \text{rank} \left(\Psi(s_0) + G\right) = \max_{s \in [0, +\infty)} \text{rank} \left(\Psi(s) + G\right).$$

**Case 1:** $r = m$. There exist $1 \leq j_1 < j_2 < \ldots < j_r \leq k$ such that the matrix $\tilde{\Psi}(s)$ composed by $j_i$-th rows ($i = 1, 2, \ldots, r$) of $\Psi(s) + G$ is invertible at $s = s_0$. Then since every element in $\tilde{\Psi}(\cdot)$ are rational functions, the determinant of $\tilde{\Psi}(\cdot)$ is a rational function and is not identical to zero. Consequently, $\tilde{\Psi}(s)$ is invertible on $[0, +\infty)$ except for finite points. Let $\tilde{\Phi}(s)$ be the matrix composed by $j_i$-th ($i = 1, 2, \ldots, r$) rows of $\Phi(s)$. Then

$$U(s) = \tilde{\Psi}(s)^{-1}\Phi(s)X_0, \quad s \in [0, +\infty).$$

Thus, every element in $U(s)$ are rational functions. Moreover, noting that the inverse Laplace transform of a (non-zero) polynomial is the linear combination of $\delta$ function and its derivatives, elements in $U(s)$ must be proper rational functions since $u(\cdot)$ is analytic. Thus, $u(\cdot)$ has the form (3.3). Therefore, in this case, we can get our result by choosing $X_0 = X_0$ and $\bar{u}(\cdot) = u(\cdot)$.

**Case 2:** $r < m$. Let $X_0 = 0$. We will prove that there exists a $\bar{u}(\cdot) \neq 0$ such that $(X_0, \bar{u}(\cdot))$ satisfies (3.2) and (3.3).

Let $1 \leq j_1 < j_2 < \ldots < j_r \leq k$ satisfy that the matrix $\tilde{\Psi}(s)$ composed by $j_i$-th rows ($i = 1, 2, \ldots, r$) of $\Psi(s) + G$ has full row rank when $s = s_0$. Then $\tilde{\Psi}(s)$ has full row rank except for finite points. Moreover, the equation

$$\left(\Psi(s) + G\right)V(s) = 0 \quad (3.7)$$

is equivalent to

$$\tilde{\Psi}(s)V(s) = 0. \quad (3.8)$$

Without loss of generality, suppose that

$$\tilde{\Psi}(s) = \begin{pmatrix} \tilde{\Psi}_1(s) & \tilde{\Psi}_2(s) \end{pmatrix},$$
where $\tilde{\Psi}_1(s)$ is an $r \times r$ matrix-valued function such that $\tilde{\Psi}_1(s)$ is invertible at $s = s_0$. Then since elements in $\tilde{\Psi}_1(s)$ are rational functions, $\tilde{\Psi}_1(s)$ is invertible except for finite points. Consequently, it is easy to see that (3.8) admits a solution $V_1(\cdot)$ with

$$V_1(s) = \begin{pmatrix} Q_1(s) \\ \vdots \\ Q_r(s) \\ 1 \\ \vdots \\ 1 \end{pmatrix},$$

where $Q_j(s)$ ($j = 1, \ldots, r$) are rational functions. Choosing $J$ large enough and letting

$$V(s) = \frac{V_1(s)}{s^J},$$

we get a nontrivial solution $V(\cdot)$ of (3.8) (or (3.7), equivalently) such that every element of $V(\cdot)$ are proper rational functions. Consequently,

$$\bar{u}(\cdot) = \mathcal{L}^{-1}(V(\cdot)) \neq 0$$

is well-defined and $\bar{u}(\cdot)$ has the form (3.3). Moreover,

$$C \int_0^t e^{A(t-s)} B\bar{u}(s) ds + G\bar{u}(t) = 0, \quad \forall \ t \geq 0.$$

That is $(\bar{X}_0, \bar{u}(\cdot))$ satisfies (3.2).

We get the proof. \qed

Using the properties of the differential operator $D$, we can go further.

**Lemma 3.2** If $S_1$ and $S_2$ are not distinguishable, then we can find a pair $(\bar{X}_0, \bar{u}(\cdot)) \neq 0$ satisfying (3.2) and

$$\bar{u}(\cdot) = e^{\lambda t} \xi,$$

where $\lambda \in \mathbb{C}$ and $\xi \in \mathbb{C}^m$.

**Proof.** By Lemma 3.1, there exists a pair $(\bar{X}_0, \bar{u}(\cdot))$ satisfying (3.1)—(3.2) and (3.5).

**Case 1:** $\bar{u}(\cdot) \equiv 0$. Then let $\tilde{u}(\cdot) = \bar{u}(\cdot)$, we get the conclusion.

**Case 2:** $\bar{u}(\cdot) \neq 0$. Then

$$\bar{u}(t) = e^{\lambda_1 t} P_1(t) + \cdots + e^{\lambda_q t} P_q(t),$$

where

$$P_i(t) = \xi_{p_i, 1} t^{p_i} + \xi_{p_i-1, 1} t^{p_i-1} + \cdots + \xi_{1, 1} t + \xi_{0, 1}, \quad i = 1, \ldots, q.$$
\[ p_i \geq 0, \quad \xi_{p_i, i} \neq 0, \]

and

\[ \lambda_i \neq \lambda_j, \quad i \neq j. \]

Let \((X(\cdot), Y(\cdot))\) be the solution of \((1.5)\) corresponding to \((\overline{X}_0, \overline{u}(\cdot))\). Then

\[ Y(t) \equiv CX(t) + G\overline{u}(t) \equiv 0 \]

since \((\overline{X}_0, \overline{u}(\cdot))\) satisfies \((3.2)\).

Let

\[ Q(\lambda) = (\lambda - \lambda_1)^{p_1}(\lambda - \lambda_2)^{p_2+1} \cdots (\lambda - \lambda_q)^{p_q+1}, \]

\[ \tilde{u}(t) = Q(D)\overline{u}(t) \]

and

\[ \tilde{X}(t) = Q(D)X(t), \quad \tilde{Y}(t) = Q(D)Y(t). \]

We have \(\tilde{Y} \equiv 0\),

\[ \frac{d\tilde{X}}{dt} = AX(t) + B\tilde{u}(t), \]

and

\[ \tilde{Y}(t) = C\tilde{X}(t) + G\tilde{u}(t). \]

That is, \((\tilde{X}(\cdot), \tilde{Y}(\cdot))\) is the solution of \((1.5)\) corresponding to \((\tilde{X}_0, \tilde{u}(\cdot))\) for some \(\tilde{X}_0 \in \mathbb{R}^{2n}\). In other words, \((\tilde{X}_0, \tilde{u}(\cdot))\) satisfies \((3.2)\).

Finally, \((3.1)\) follows from

\[ \tilde{u}(t) = Q(D)\overline{u}(t) \]

\[ = \sum_{i=1}^{q} e^{\lambda_i t} Q(D + \lambda_i)P_i(t) \]

\[ = e^{\lambda_1 t} Q(D + \lambda_1)P_1(t) \]

\[ = e^{\lambda_1 t}(D + \lambda_1 - \lambda_2)^{p_2+1} \cdots (D + \lambda_1 - \lambda_q)^{p_q+1} D^{p_1} P_1(t) \]

\[ = (p_1)!(\lambda_1 - \lambda_2)^{p_2+1} \cdots (\lambda_1 - \lambda_q)^{p_q+1} e^{\lambda_1 t} \xi_{p_1, 1} \]

\[ \neq 0. \]

\[ \square \]

**Corollary 3.3** If \(S_1\) and \(S_2\) are 0-th polynomial input distinguishable, then they are polynomial input distinguishable.
Proof. Subsystems $S_1$ and $S_2$ are 0-th polynomial input distinguishable means that for any $(x_{10}, x_{20}, u(\cdot)) \in \mathbb{R}^n \times \mathbb{R}^n \times \mathcal{U}$ with $u(\cdot) \equiv \xi \in \mathbb{R}^m$, the outputs $y_1(\cdot)$ and $y_2(\cdot)$ can not be identical to each other on $[0, T]$.

If $S_1$ and $S_2$ are not polynomial input distinguishable, then there exists $(X_0, u(\cdot)) \neq 0$ such that (3.2) holds with $u(\cdot)$ being a polynomial. Then using the method we constructed $\tilde{u}(\cdot)$ from $\hat{u}(\cdot)$ in the proof of Lemma 3.2, we can construct a pair $(\tilde{X}_0, \tilde{u}(\cdot)) \neq 0$ satisfying (3.2) with $\tilde{u}(\cdot)$ being a constant vector. This means $S_1$ and $S_2$ are not 0-th polynomial input distinguishable.

By Corollary 3.3, the necessary and sufficient condition for 0-th polynomial input distinguishable and that for $k$-th polynomial input distinguishable are equivalent. Thus, by Theorem 3.1 of [8], we can see that for any $p \geq 0$, the matrix

$$
\begin{pmatrix}
C & G & 0 & \ldots & 0 \\
CA & CB & G & \ldots & 0 \\
\vdots & \vdots & \vdots & \ddots & \vdots \\
CA^{p+2} & CA^{p+1}B & CA^pB & \ldots & G \\
\vdots & \vdots & \vdots & \ddots & \vdots \\
CA^{2n} & CA^{2n-1}B \\
\end{pmatrix}
$$

has full column rank if and only if

$$
\begin{pmatrix}
C & G \\
CA & CB \\
CA^2 & CAB \\
\vdots & \vdots \\
CA^{2n} & CA^{2n-1}B \\
\end{pmatrix}
$$

has full column rank. Thus, it follows from Cayley-Hamilton’s theorem, they are both equivalent to that

$$
\begin{pmatrix}
C & G \\
CA & CB \\
CA^2 & CAB \\
\vdots & \vdots \\
CA^{2n} & CA^{2n-1}B \\
\end{pmatrix}
$$

has full column rank.

Now, we state our main result.

Theorem 3.4 Systems $S_1$ and $S_2$ are distinguishable if and only for any $\lambda \in \mathbb{C}$,

$$
\mathcal{M}_\lambda = \begin{pmatrix}
C & G \\
C(A - \lambda I) & CB \\
C(A - \lambda I)^2 & C(A - \lambda I)B \\
\vdots & \vdots \\
C(A - \lambda I)^{2n} & C(A - \lambda I)^{2n-1}B \\
\end{pmatrix}
$$

(3.10)

has full column rank.
Proof. (i) Suppose that $S_1$ and $S_2$ are distinguishable. Let $\lambda \in \mathbb{C}$. Consider

\[
\begin{cases}
\frac{d\tilde{X}(t)}{dt} = (A - \lambda I)\tilde{X}(t) + B\tilde{u}(t), \\
\tilde{X}(0) = \tilde{X}_0, \\
\tilde{Y}(t) = C\tilde{X}(t) + G\tilde{u}(t). 
\end{cases}
\]

(3.11)

We claim for any $\tilde{x} \in \mathbb{C}^{2n}$ and $\xi \in \mathbb{C}^m$, $(\tilde{X}_0, \xi) \neq 0$, the solution of (3.11) corresponding to $\tilde{X}_0$ and

\[\tilde{u}(t) = \xi\]

satisfies

\[\tilde{Y}(t) \neq 0, \quad \text{on } [0, +\infty).\]

In other words, $(A_1 - \lambda I, B_1, C_1, G_1)$ and $(A_2 - \lambda I, B_2, C_2, G_2)$ are 0-th polynomial input distinguishable.

If it is not the case, then we have $(\tilde{X}_0, \xi) \neq 0$ such that the corresponding $\tilde{Y}(\cdot)$ equals to zero identically.

Let

\[X(t) = e^{\lambda t}\tilde{X}(t), \quad Y(t) = e^{\lambda t}\tilde{Y}(t),\]

Then $(X(\cdot), Y(\cdot))$ solves (1.5) with

\[X_0 = \tilde{X}_0, \quad u(\cdot) = e^{\lambda \cdot}\tilde{u}(t).\]

Since

\[Y(t) = e^{\lambda t}\tilde{Y}(t) = 0,\]

by considering the real part or imaginary part of $X_0, u(\cdot), X(\cdot)$ and $Y(\cdot)$, one can easily see that $S_1$ and $S_2$ are not distinguishable. This is a contradiction.

Similar to Theorem 3.1 of [8], we can get that the 0-th polynomial input distinguishable of $(A_1 - \lambda I, B_1, C_1, G_1)$ and $(A_2 - \lambda I, B_2, C_2, G_2)$ (in complex variable sense) implies that $\mathcal{M}$ has full column rank.

(ii) Suppose that $S_1$ and $S_2$ are not distinguishable. Then, Lemma 3.2 shows that there is a pair $(X_0, u(\cdot)) \neq 0$ satisfying (3.12) and

\[u(\cdot) = e^{\lambda t}\xi,\]

(3.12)

for some $\lambda \in \mathbb{C}$. This implies that $(A_1 - \lambda I, B_1, C_1, G_1)$ and $(A_2 - \lambda I, B_2, C_2, G_2)$ are not 0-th polynomial input distinguishable. Consequently, $\mathcal{M}_\lambda$ has not full column rank. □

\[\text{[1]}\text{Here variables are complex, but this can be treated similarly to the case of that only real variables are concerned.}\]
4 Generalization

In §1, the state variables are taken values in $\mathbb{R}^n$. In fact, we can consider more general cases. That is, for subsystem $S_i$ of (1.1), suppose that

$$A_i \in \mathbb{R}^{n_i \times n_i}, \quad B_i \in \mathbb{R}^{n_i \times m}, \quad C_i \in \mathbb{R}^{k \times n_i}, \quad G_i \in \mathbb{R}^{k \times m}, \quad i = 1, 2,$$

where $n_1, n_2, k, m \geq 1$.

Similar to Definition 1.1, we define

**Definition 4.1** Systems $S_1$ and $S_2$ are said to be distinguishable on $[0, T]$, if for any non-zero

$$(x_{10}, x_{20}, u(\cdot)) \in \mathbb{R}^{n_1} \times \mathbb{R}^{n_2} \times L^1(0, T; \mathbb{R}^m),$$

the corresponding output $y_1(\cdot; x_{10}, u(\cdot))$ of $S_1$ (satisfying the initial condition $x(0) = x_{10}$) and $y_1(\cdot; x_{20}, u(\cdot))$ of $S_2$ (satisfying the initial condition $x(0) = x_{20}$) are not identical to each other on $[0, T]$.

We have

**Theorem 4.2** Subsystems $S_1$ and $S_2$ are distinguishable if and only if for any $\lambda \in \mathbb{C}$, the matrix

$$\mathcal{M}_\lambda \equiv \left( \begin{array}{cc} C & G \\ C(A - \lambda I) & CB \\ C(A - \lambda I)^2 & C(A - \lambda I)B \\ \vdots & \vdots \\ C(A - \lambda I)^{n_1 + n_2} & C(A - \lambda I)^{(n_1 + n_2 - 1)}B \end{array} \right) \quad \text{(4.1)}$$

has full column rank, where

$$A = \begin{pmatrix} A_1 & 0 \\ 0 & A_2 \end{pmatrix} \in \mathbb{R}^{(n_1 + n_2) \times (n_1 + n_2)}, \quad B = \begin{pmatrix} B_1 \\ B_2 \end{pmatrix} \in \mathbb{R}^{(n_1 + n_2) \times m}, \quad C = (C_1 \quad -C_2) \in \mathbb{R}^{k \times (n_1 + n_2)}, \quad G = G_1 - G_2 \in \mathbb{R}^{k \times m}.$$

At the end of the paper, we prove the following equivalent result.

**Theorem 4.3** Let $\mathcal{M}_\lambda$ be defined by (4.1). Then $\mathcal{M}_\lambda$ has full column rank or any $\lambda \in \mathbb{C}$ if and only if for any $\lambda \in \mathbb{C}$

$$\left( \begin{array}{cc} C & G \\ A - \lambda I & B \end{array} \right)$$

has full column rank.
Proof. Let \( \tilde{\mathcal{C}} = (C \ G) \), \( \tilde{A}_\lambda = \begin{pmatrix} A - \lambda I & B \\ 0 & 0 \end{pmatrix} \). Then it is well known that for any \( \lambda \in \mathbb{C} \),

\[
\begin{pmatrix}
\tilde{\mathcal{C}} \\
\tilde{\mathcal{C}} \tilde{A}_\lambda \\
\vdots \\
\tilde{\mathcal{C}} \tilde{A}_\lambda^{n_1+n_2+m-1}
\end{pmatrix}
\]

has full column rank if and only if for any \( \lambda, \mu \in \mathbb{C} \), \( \begin{pmatrix} \tilde{\mathcal{C}} \\ \tilde{A}_\lambda - \mu I \end{pmatrix} \) has full column rank (see [12] for example).

Thus, using Cayley-Hamilton’s Theorem, for any \( \lambda \in \mathbb{C} \), \( \mathcal{M}_\lambda \) has full column rank if and only if for any \( \lambda, \mu \in \mathbb{C} \),

\[
\begin{pmatrix}
C & G \\
A - \lambda I & B \\
0 & -\mu I
\end{pmatrix}
\]

has full column rank. While the later is equivalent to that for any \( \lambda \in \mathbb{C} \), \( \begin{pmatrix} C \\ A - \lambda I \end{pmatrix} \) has full column rank. We get the proof. \( \square \)

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