

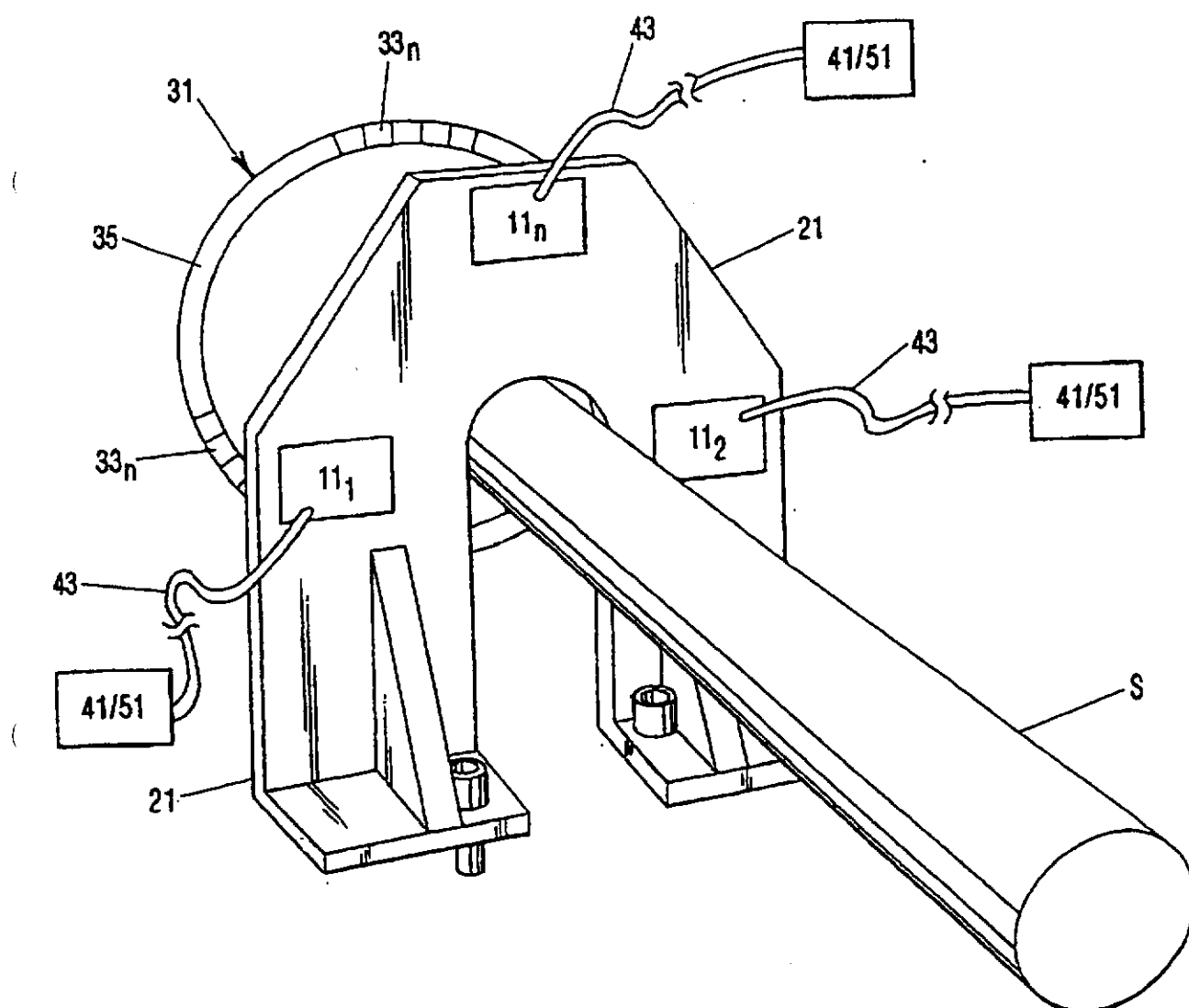


FIG-1

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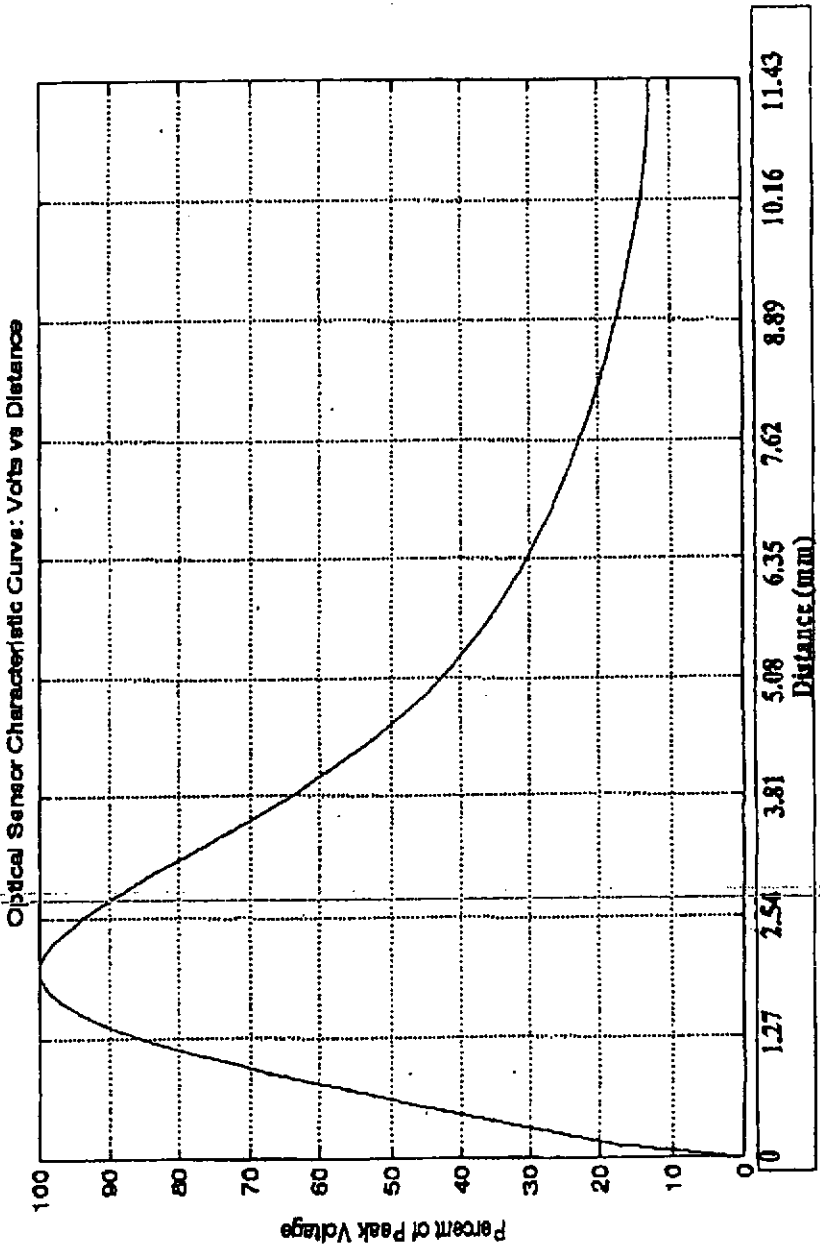


FIG 2

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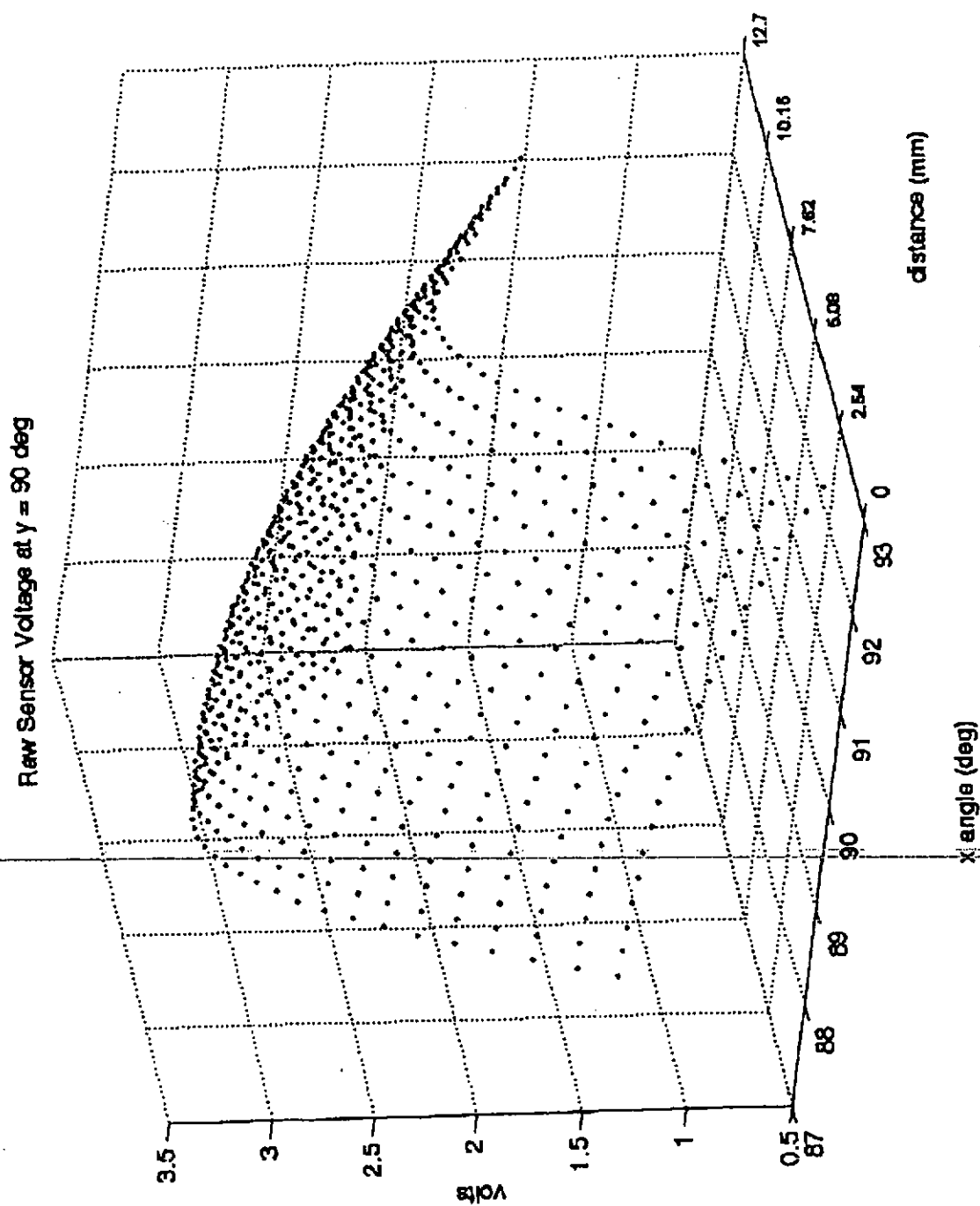


FIG 3

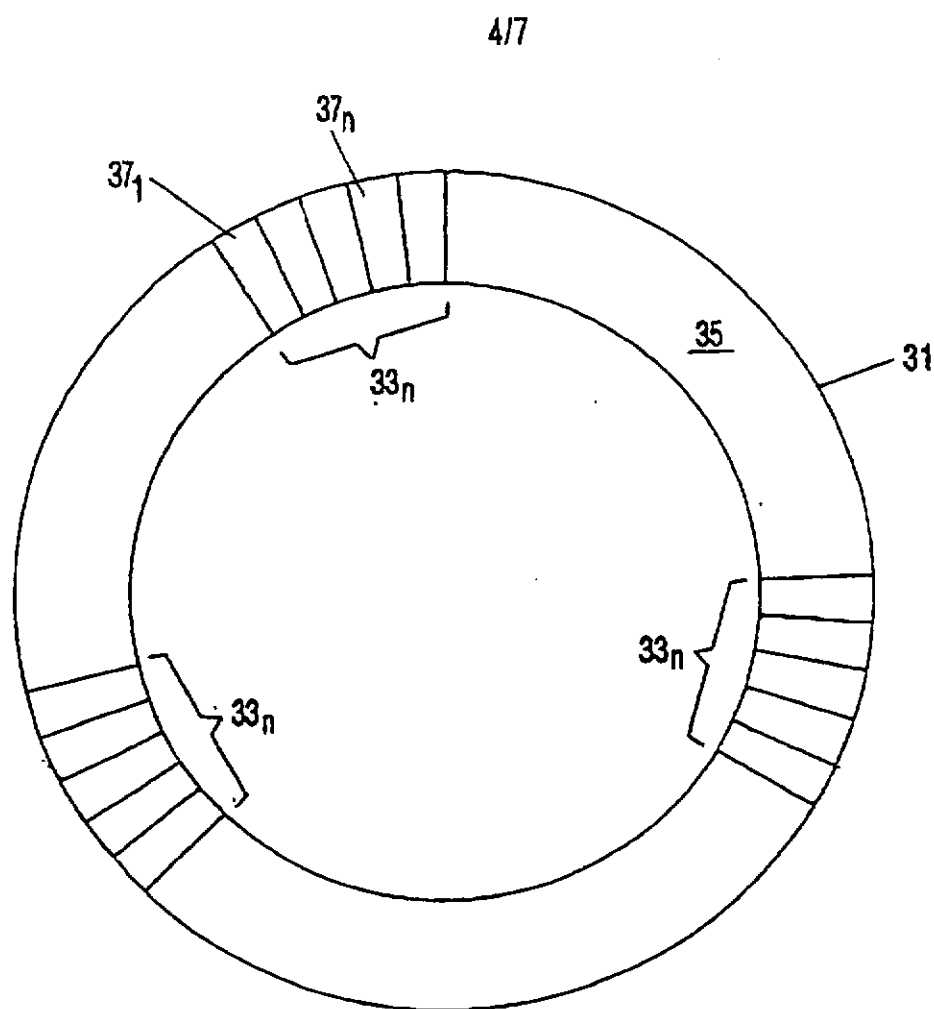


FIG-4a

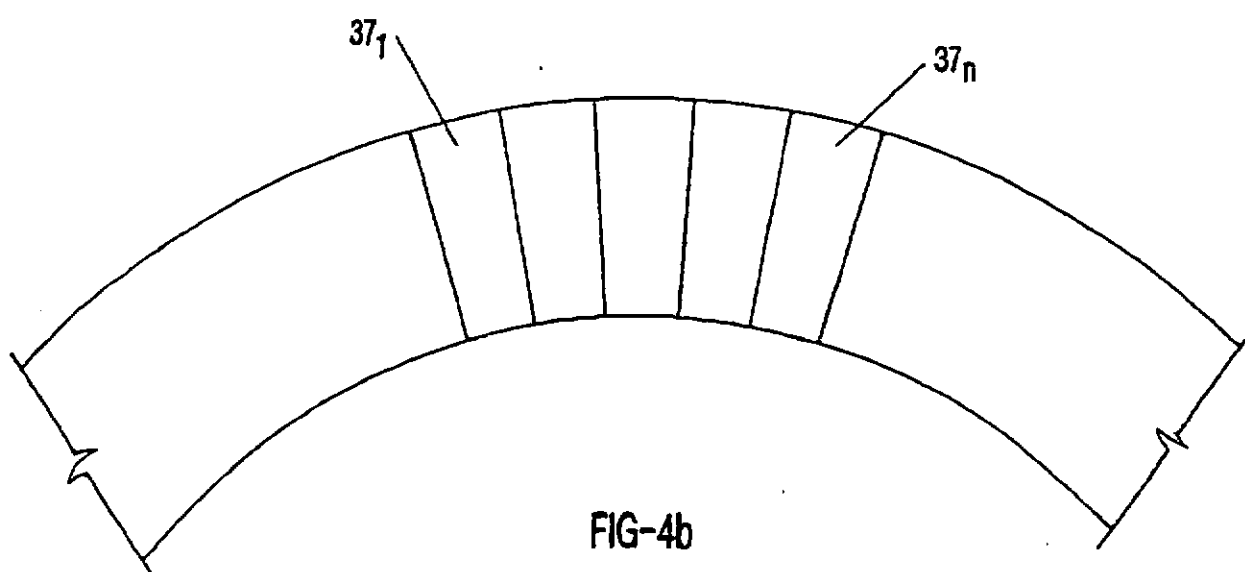


FIG-4b

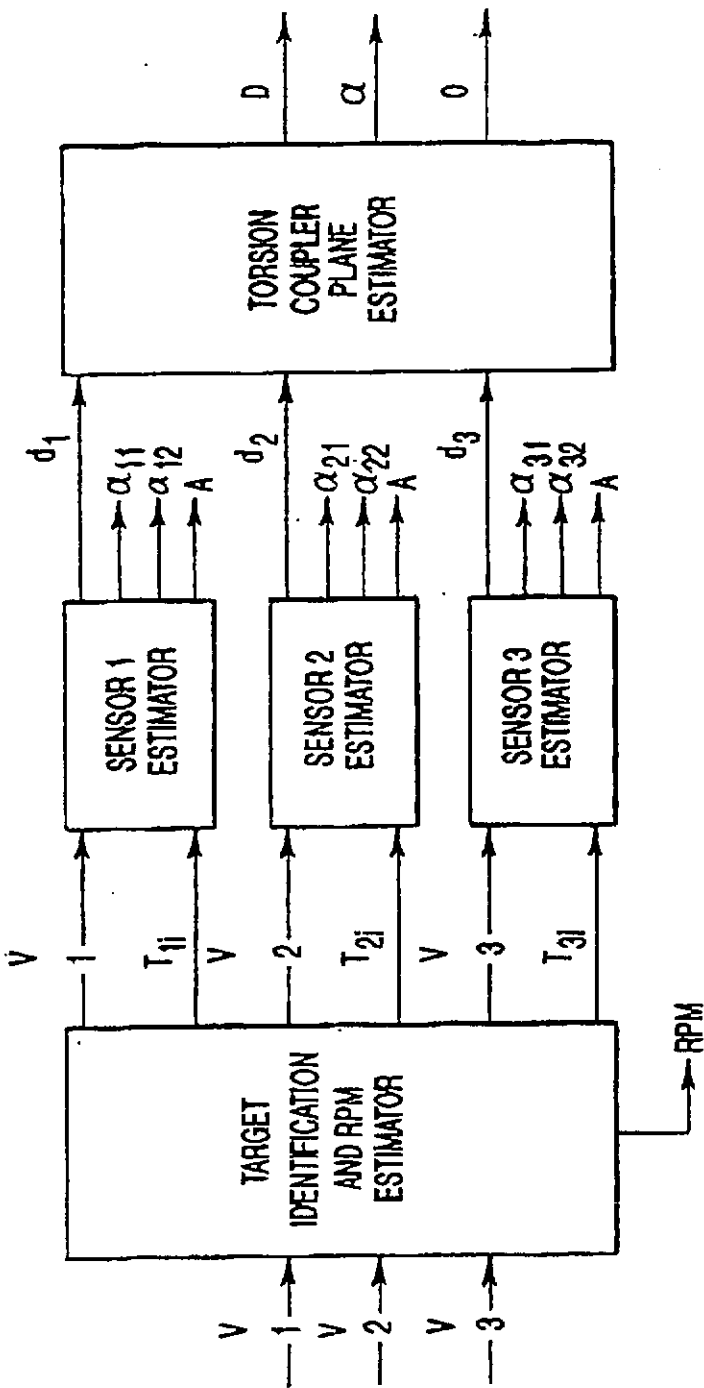
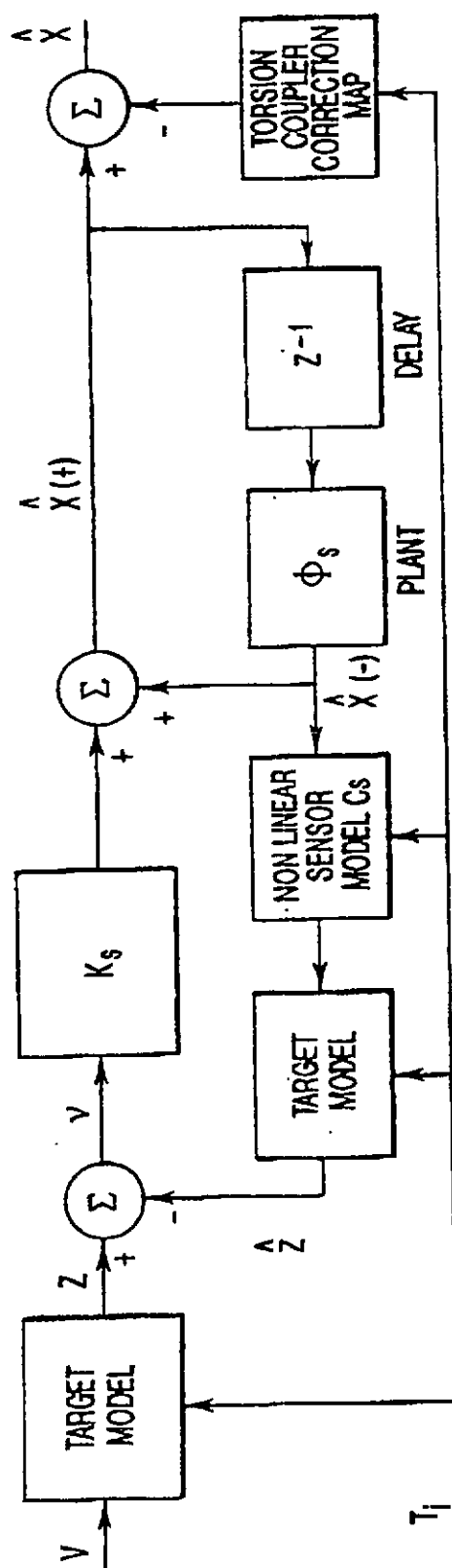


FIG-5

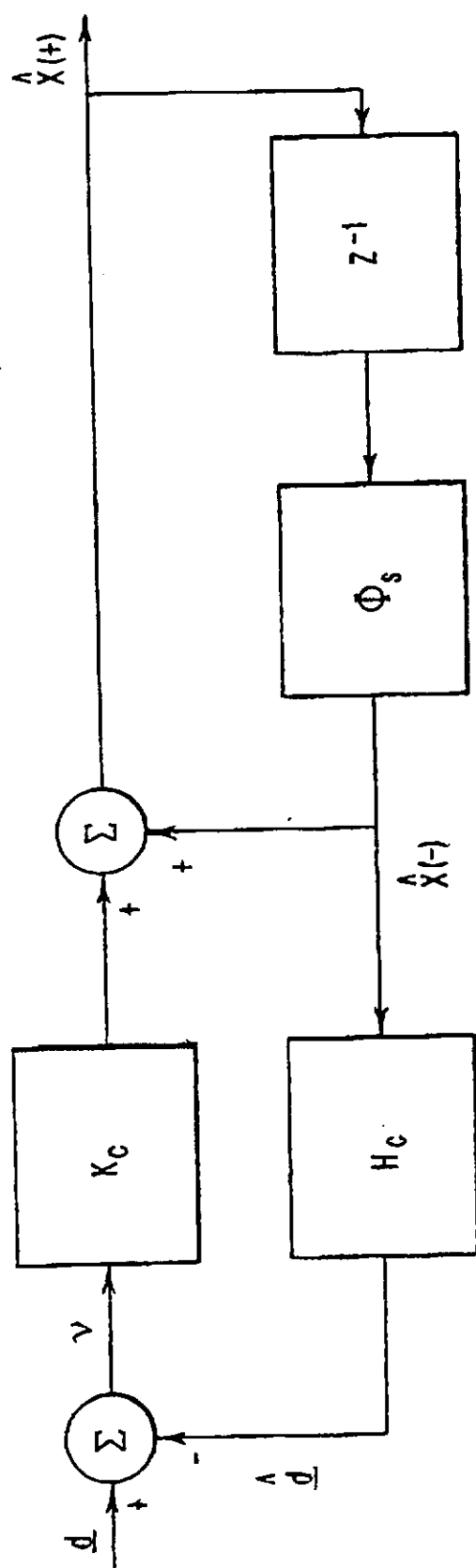

$$\lambda X(-) = \phi_s X(+)$$

Z = TARGET MODEL (T_i, V)

 $\hat{Z}$ - TARGET MODEL (T; NL SENSOR MODEL (X (-), Cs))
$$v = z - z^A$$
$$\hat{X}(+) = \hat{X}(-) + K_S v$$
$$\hat{X}^A = \hat{X}^{A(-)} - \text{COUPLER CORRECTION MAP}(T_i)$$

FIG-6

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$$\begin{aligned}\hat{X}(-) &= \Phi_s \hat{X}(+) \\ \bar{d} &= H_C \hat{X}(-) \\ v &= \bar{d} - \bar{d} \\ \hat{X}(+) &= \hat{X}(-) + K_C v\end{aligned}$$

FIG-7