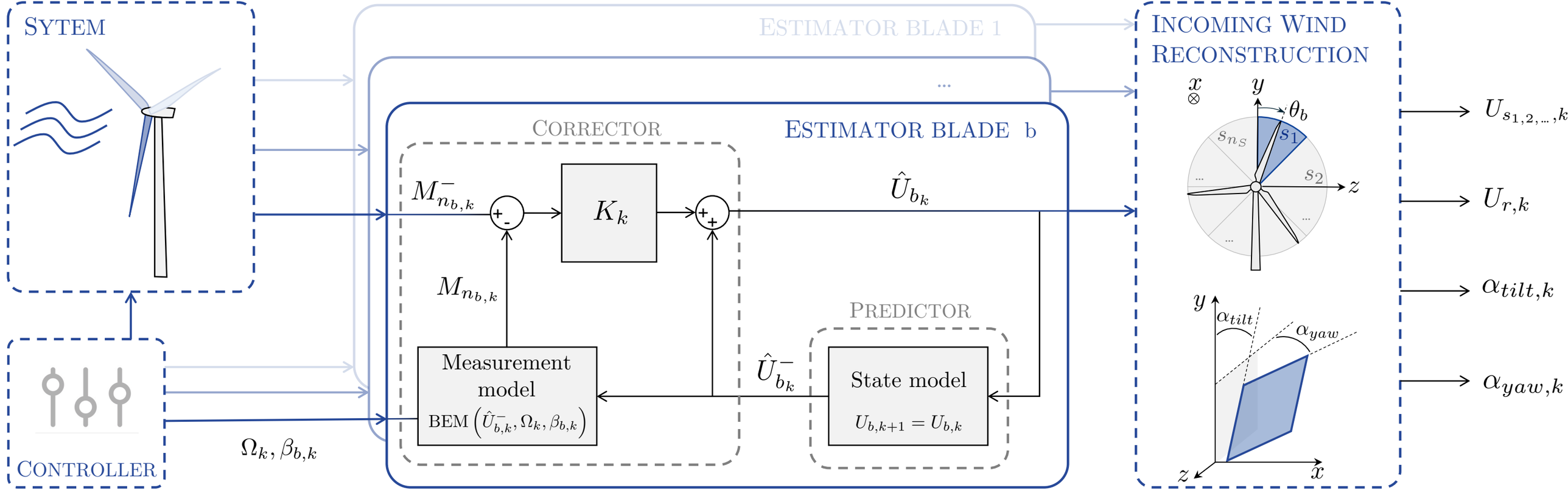
SYTEM
ESTIMATOR BLADE 1
...
CORRECTOR
ESTIMATOR BLADE b
$M^-_{n_{b,k}}$
K_k
$\hat{U}_{b_k}$
$M_{n_{b,k}}$
PREDICTOR
Measurement model
BEM $\left(\hat{U}^-_{b,k}, \Omega_k, \beta_{b,k}\right)$
$\hat{U}^-_{b_k}$
State model
$U_{b,k+1} = U_{b,k}$
CONTROLLER
$\Omega_k, \beta_{b,k}$
INCOMING WIND RECONSTRUCTION
x
y
θ_b
s_{n_S}
s_1
s_2
z
α_{tilt}
α_{yaw}
$U_{s_{1,2,\ldots},k}$
$U_{r,k}$
$\alpha_{tilt,k}$
$\alpha_{yaw,k}$