On Problem of Parameters Identification of Dynamic Object

Kamil Aida-zade, and Cemal Ardil

Abstract—In this paper, some problem formulations of dynamic object parameters recovery described by non-autonomous system of ordinary differential equations with multipoint unshared edge conditions are investigated. Depending on the number of additional conditions the problem is reduced to an algebraic equations system or to a problem of quadratic programming. With this purpose the paper offers a new scheme of the edge conditions transfer method called by conditions shift. The method permits to get rid from differential links and multipoint unshared initially-edge conditions. The advantage of the proposed approach is concluded by capabilities of reduction of a parametric identification problem to essential simple problems of the solution of an algebraic system or quadratic programming.

Keywords—dynamic objects, ordinary differential equations, multipoint unshared edge conditions, quadratic programming, conditions shift

I. PROBLEM FORMULATION

Let’s consider a problem of parameters identification of a linear non-autonomous dynamic system:

\[ \dot{x}(t) = A(t)x(t) + B(t)p + C(t), \quad t \in [t_0, t_1], \]  

(1)

where \( x(t) \in E^s \) - phase state of system; \( p \in E^l \) - required parameters; \( A(t), B(t), C(t) \) - given matrixes with dimensions \((n \times n), (n \times l), (n \times 1)\) respectively, moreover \( A(t) \neq \text{const} \).

There are \( m \) initially-edge conditions of a system that can also depend on unknown parameters:

\[ \sum_{i=0}^{k} \alpha^i x(t_i) + \xi = \beta, \]  

(2)

where \( t_i, v, 0 \leq v \leq k \) - times moments from \( [t_0, t_1] \), \( t_k = t_0, t_i = t_j \), the matrixes \( \alpha^i, \xi, \beta \) with respective dimensions \((m \times n), (m \times 1), (m \times 1)\) are given.

Let’s mark a general problem of linear systems of differential equations with the multipoint unshared edge conditions. The problem (1), (2), generally speaking, concerns to this class of problems at fixed values of parameter \( P \). The problem is connected to the complexity of obtaining of constructive necessary and sufficient conditions of the solution existence of a boundary value problem such as (1), (2), that is studied by many scientists, starting from activities of Tamarkin, Valle-Poussin and other scientists ([1], [3]).

Let

\[ \text{rang } A(t) = n, \quad \text{rang } B(t) = \text{max}(n, l), \quad t \in [t_0, t_1], \]  

\[ \text{rang}[\alpha^0, ..., \alpha^k, \xi] = \text{rang}[\alpha^0, ..., \alpha^k, \xi, \beta] = m. \]

Depending on a ratio between values of matrixes ranks, participating in (1), (2), the following cases, corresponding to the different problem formulations, are possible.

Case A: \( m = n + l \). Then there is a single vector of parameters \( P \) and corresponding solution of a boundary value problem (1), (2) (problem A).

Case B: \( m < n + l \). Then the system vector of parameters, satisfying (1), (2), is not unique and there are additional conditions on system parameters and status in the form of equality with the number no more than \( n + l - m \) and inequality

\[ \sum_{j=0}^{k} e^j x(t_j) + \xi p(\xi) g, \]  

(3)

the total number which one let will be equal \( m \). In that case the choice of optimal parameter values can be performed according to any criterion. For example, as criterion of parameters optimization can be used the minimized functional:

\[ J(p) = \sigma_1 \text{tr}p^2 + \sum_{j=0}^{k} \sigma_2 \text{tr}x(t_j) - X^* \text{tr}x^* \]  

(4)

Here \( \sigma_1, \sigma_2, j = 0, 1, ..., k \) - positive weight coefficients; matrixes \( e^j, j = 0, ..., k, f, g \) with dimentions \((m \times n),(m \times l), (m \times 1)\) respectively; the time moments \( t_j \in [t_0, t_1], \ T_j \in [t_0, t_1] \) and desired system status \( X^* \) on moment \( t_j \), \( j = 0, 1, ..., k \) are given (problem B).

In case \( m > n + l \), i.e. the number of linearly - independent initially-edge conditions exceeds the number of conditionally free parameters of a dynamic system, generally, as is known, boundary value problem (1), (2) will not have the solution at any value of vector of parameters \( P \).

II. THE SOLUTION OF PROBLEM A

For a numerical solution of a problem \( A \) the following scheme of the transfer (shift) of multipoint unshared edge conditions (2), offered in [1,3], will be used.

Let’s consider an expression at interval \([t_0, t_1]\) :

\[ \alpha^0(t)x(t) + \sum_{i=0}^{k} \alpha^i(t)x(t_i) + \xi(t)p = \beta(t), \]  

(5)

where \( x(t) \) is required solution of the boundary problem, the matrix functions \( \alpha^i(t), \xi(t), \beta(t) \) with dimensions \((m \times n),(m \times l), (m \times 1)\) are still arbitrary satisfying only conditions:

\[ \alpha^0(t_0) = \hat{\alpha^0}, \quad v = 0, ..., k, \quad \xi(t_0) = \hat{\xi}, \quad \beta(\alpha_0) = \hat{\beta}. \]  

(6)
The expression (5) at \( t = t_0 \) coincides with conditions (2). The matrix functions \( \alpha^0(t), \nu = 0, \ldots, k, \quad \zeta(t), \quad \beta(t) \), satisfying a ratio (5) at \( t \in [t_0, \hat{t}_1] \), are not unique. Let’s speak, such that \( \alpha^0(t) \) are determined by solution of a problem \( (1), (2) \), the right of edge conditions sequentially on subinterval \([t_{i-1}, t_i] \), \( i = 2, \ldots, k \) at the end we shall receive matrix \( \beta(t) \):

\[
\hat{\beta}(t) = S^0(t)\beta(t) + \alpha^0(t)C(t), \quad \beta(t_0) = \hat{\beta},
\]

\[
\alpha^0(t) = M(t)\hat{\alpha}, \quad \nu = 1, \ldots, k,
\]

where

\[
S^0(t) = (\alpha_0A\alpha_0^T + \alpha_0B\xi^T - \alpha_0C\beta^T)(\alpha_0\alpha_0^T + \xi\xi^T + \beta\beta^T)^{-1},
\]

\( T \) is the sign of matrix transposition, \( I \) is \( m \)-dimensional unit matrix. Then these matrix functions execute shift of conditions (2) to the right on an interval \( [t_0, \hat{t}_1] \), i.e. for them the (15), (7) is executed. Moreover, it takes place:

\[
\|f^0(t)\|^2 + \|\xi(t)\|^2 + \|\beta(t)\|^2 = \text{const}, \quad t \in [t_0, \hat{t}_1],
\]

whence follows the stability of a Cauchy problem (9) - (12).

**Proof.** Let for \( x(t) \), being solution of a problem (1), (2), the ratio takes place:

\[
\alpha^0(t)x(t) + \sum_{\nu=1}^m \hat{\alpha} x(t_{\nu}) + \hat{\xi}(t) p = \beta(t), \quad t \in [t_0, \hat{t}_1], \tag{15}
\]

where \( \alpha^0(t), \hat{\xi}(t), \beta(t) \) while arbitrary differentiable functions. Let’s differentiate (15) and take into account (1) (for short, argument \( t \) on functions is omitted):

\[
\hat{\alpha}^0 t x + \hat{\alpha} t x + \hat{\alpha} x + \alpha^0 Ax + \alpha^0 Bp + \alpha^0 C + \hat{\xi} p = \hat{\beta}.
\]

Let’s conduct a grouping:

\[
(\hat{\alpha}^0 + \alpha^0 A)x + (\hat{\xi} + \alpha^0 B)p + (\hat{\beta} + \alpha^0 C) = 0.
\]

Using apparently checked by direct permutation in a problem conditions:

\[
x(t) \equiv 0, \quad t \in [t_0, t_1], \quad p \equiv 0
\]

and arbitrary of functions \( \alpha^0(t), \hat{\xi}(t), \beta(t) \), we shall demand fulfillment of equaling to zero the expressions in brackets:

\[
\hat{\alpha}^0 = -\alpha^0 A, \quad \hat{\xi} = -\alpha^0 B, \quad \hat{\beta} = \alpha^0 C,
\]

provided that

\[
\alpha^0(t_0) = \hat{\alpha}^0, \quad \hat{\xi}(t_0) = \hat{\xi}, \quad \beta(t_0) = \hat{\beta}.
\]

Let’s multiply (15) by an arbitrary matrix function \( M(t) \) of dimension \((m \times m)\) such, that

\[
M(t_0) = I,
\]

\[
M(t)\alpha^0(t)x(t) + \sum_{\nu=1}^m M(t)\hat{\alpha} t x(t_{\nu}) + M(t)\hat{\xi}(t) p = M(t)\beta(t)
\]

Denoting

\[
G_1(t) = M(t)\alpha^0(t), \quad G_2(t) = M(t)\hat{\xi}(t), \quad G_3(t) = M(t)\beta(t),
\]

\[
G_4(t) = M(t)\hat{\alpha}, \quad G_5(t) = \hat{\xi}, \quad G_6(t) = \hat{\beta},
\]

we obtain:

\[
G_1(t_0) = \hat{\alpha}^0, \quad G_2(t_0) = \hat{\xi}, \quad G_3(t_0) = \hat{\beta}, \quad G_4(t_0) = \hat{\alpha}, \quad v = 1, \ldots, k
\]

\[
\hat{\beta}(t) = S^0(t)\beta(t) + \alpha^0(t)C(t), \quad \beta(t_0) = \hat{\beta},
\]

\[
\alpha^0(t) = M(t)\hat{\alpha}, \quad \nu = 1, \ldots, k.
\]
Let $M(t)$ satisfy the equality:
\[
\|G_1(t)\|^2 + \|G_2(t)\|^2 = \text{const}.
\]
Then
\[
G_1 G_1^* + G_1 G_1^* + G_2 G_2^* + G_2 G_2^* + G_3 G_3^* + G_3 G_3^* = 0.
\]

(21)

Differentiating equation (19) and considering (16), we will receive:
\[
G_1 = M_a \alpha + M_a \alpha = MM^{-1} G_1 - M_a \alpha = G_1 - G_1 A,
\]
\[
G_2 = M_\varphi \varphi + M_\varphi \varphi = MM^{-1} G_1 - M_\varphi \varphi = G_1 - G_1 B,
\]
\[
G_3 = M_\beta + M_\beta = MM^{-1} G_1 + M_\alpha \varphi = MM^{-1} G_1 + G_1 C.
\]

(22)

(23)

(24)

Transposing (22)-(24), we will receive:
\[
G_1^* = G_1^* (M^{-1})^* M - A^* G_1^*,
\]
\[
G_2^* = G_2^* (M^{-1})^* M - B^* G_1^*,
\]
\[
G_3^* = G_3^* (M^{-1})^* M + C^* G_1^*.
\]

(25)

(26)

(27)

Allowing expressions (22) - (27) in (21), after simple transformations we will receive:
\[
\begin{align*}
&M M^{-1} G_1 G_1^* - G_1 A G_1^* + G_1 G_1^* (M^{-1}) Y M^* - G_1 A^* G_1^* +
&M M^{-1} G_1 G_1^* - G_1 B G_1^* + G_1 G_1^* (M^{-1}) Y M^* - G_1 B^* G_1^* +
&M M^{-1} G_1 G_1^* - G_1 C G_1^* + G_1 G_1^* (M^{-1}) Y M^* - G_1 C^* G_1^* +
&-G_2 B G_1^* + G_2 G_1^* + G_3 C G_1^*) = 0,
&-G_2 B G_1^* + G_2 G_1^* + G_3 C G_1^*) = 0
\end{align*}
\]

From independence and arbitrary of matrices $G_1, G_2, G_3$ for fulfillment of this equation it is enough to demand from $M(t)$, that the expressions in square brackets equals zero. Then
\[
M M^{-1} = (G_1 A G_1^* + G_1 B G_1^* - G_1 C G_1^*) (G_1 A G_1^* + G_1 B G_1^* + G_1 C G_1^*) = S_0.
\]

Here the notation of a right part of differential equation by $S_0$ is introduced. Then
\[
M = S_0 M.
\]

(28)

Differentiating equation (19) and considering (28), (16), we will receive:
\[
G_1 = M_a \alpha + M_a \alpha = S_0 M_a \alpha - M_a \alpha = S_0 G_1 - G_1 A,
\]
\[
G_2 = M_\varphi \varphi + M_\varphi \varphi = S_0 M_\varphi \varphi - M_\varphi \varphi = S_0 G_2 - G_1 B,
\]
\[
G_3 = M_\beta + M_\beta = S_0 M_\beta + M_\alpha \varphi = S_0 G_3 + G_1 C.
\]

(29)

(30)

(31)

Adding the condition (20), we will receive
\[
G_1(t_0) = \hat{\alpha}_0,
\]
\[
G_2(t_0) = \hat{\xi}_0,
\]
\[
G_3(t_0) = \hat{\beta}.
\]

(32)

Again having renamed matrix functions $G_i(t)$ through $\alpha^0(t)$, $G_i^*(t)$ through $\alpha^* (t)$, $G_i(t)$ through $\xi(t)$, and $G_i(t)$ through $\tilde{\beta}$, we shall receive functions, executing shift of conditions (2) to the right, about which one there is a speech in the theorem.

Remark.
It is important to note following. As it was indicated above, matrix functions executing shift of conditions (2), are not determined uniquely. For example, the functions defined by linear Cauchy problems (16), formally meet definition (15) of shifting to the right of initially-edge conditions (2), but as is known [1] one of linear problems
\[
x = Ax + f(t),
\]
\[
x(t_0) = x_0,
\]
\[
\alpha^* = -A \alpha^0,
\]
\[
\alpha^* (t_0) = \hat{\alpha}^0,
\]
or both simultaneously depending on eigenvalues of a matrix $A$ are unstable. The fulfillment of a condition (14) provides that the auxiliary Cauchy problems (9) - (12) will have stable solution and it is very important at realization of practical calculations.

The proof method of the theorem can easily be applied to particular cases of condition (14):
\[
\| \alpha(t) \|^2 = \| \hat{\alpha}^0 \|^2 = \text{const},
\]
\[
\| \alpha^* (t) \|^2 = \| \hat{\alpha}^0 \|^2 + \| \hat{\beta} \|^2 = \text{const},
\]
\[
\| \alpha^* (t) \|^2 + \| \xi(t) \|^2 = \| \hat{\alpha}^0 \|^2 + \| \hat{\beta} \|^2 = \text{const},
\]

under which the condition of the theorem will differ only by kind of a function $S_0(t)$.

At definite specificity of conditions (2), for example, when a part $m_l$ from conditions (2) ($m_l < m$) have local nature and are determined on the left-hand end of an interval at $t = t_0$:
\[
\Omega x(t_0) + \xi \varphi = \varphi,
\]

(33)

where $\varphi$, $\xi$, $\varphi$ are given matrices of dimension $(m_0 \times n)\), (m_0 \times l), (m_0 \times 1)$ respectively, more effective is the implementation of a left-shift of conditions (2), beginning from an interval $[\hat{t}_l, \hat{t}_l]$, the number which one is in this case equal $m = n - m_l + 1$. In this case instead of (5) we’ll consider a ratio on a section $[\hat{t}_l, \hat{t}_l]$
\[
\alpha^l(t)x(t) + \sum_{l=0}^{k-1} \alpha^l(t) x(\hat{t}_l) + \xi(t) p = \beta(t),
\]

(34)

where $x(t)$ is the solution of a boundary value problem; \[\alpha^l(t), \xi(t), \beta(t)\] are arbitrary matrices of dimension $(m \times n), (m \times l), (m \times 1),$ $v = 0...k,$ obeying:
\[
\alpha^l(\hat{t}_l) = \hat{\alpha}^l, \quad \xi(t) = \hat{\xi}(t), \quad \beta(\hat{t}_l) = \hat{\beta}, \quad v = 0...k.
\]

(35)

Let’s speak, that the matrix functions execute shift of conditions (2) to the left, since from (34) at $t = t_{l-1}$ we will receive:
\[
\sum_{l=0}^{k-1} \alpha^l(t) x(\hat{t}_l) + \hat{\xi} \hat{p} = \hat{\beta},
\]

(36)

here following redesignations are used:
\[
\alpha^{k-1} = \alpha^l(\hat{t}_l-1) + \alpha^{l-1}(\hat{t}_l-1),
\]
\[
\hat{\alpha}^l = \alpha^{l}(\hat{t}_l-1), \quad v = 0,...,k - 2,
\]
\[
\hat{\xi} = \xi(\hat{t}_l-1).
\]

(37)

The conditions (36) and (2) are equivalent, but in (36) the value of a required function in the most right point $x(\hat{t}_l)$ does not participate. Further, repeating a left-shift of conditions on series time frames $[\hat{t}_{l-1}, \hat{t}_l]$, $s = k -1, k - 2, ..., 1$, in the end we shall receive locally given condition on the left-hand end:
\[ \hat{\alpha}^2 x(t_0) + \hat{\xi} p = \hat{\beta} \] (37)

From \((n+1)\) conditions (33), (37) it is possible to define \((n+1)\) of unknowns \(x_i = x(t_i) \in E^i\) and \(p \in E^p\), then to solve a Cauchy problem concerning (1) with the obtained initial conditions \(x(t_i)\) and already known values of parameters vector \(p\) of (1).

The template functions \(\alpha^* (t), \nu = 0, \ldots, k, \xi(t), \beta(t)\) executing shift of conditions (2) to the left are not unique, the following theorem takes place.

**Theorem 2.** Functions \(\alpha^* (t), \nu = 0, \ldots, k, \xi(t), \beta(t)\) defined by the solution of following non-linear Cauchy problems:

\[ \hat{\alpha}^4 (t) = S^4 (t) \alpha^4 (t) - \alpha^4 (t) M(t), \quad \alpha^4 (t_0) = \hat{\alpha}^4, \]

\[ M(t) = S^4 (t) M(t), \quad M(\hat{t}_i) = I, \]

\[ \hat{\xi}(t) = S^4 (t) \xi(t) - \alpha^4 (t) B(t), \quad \hat{\beta}(t) = S^4 (t) \beta(t) + \alpha^4 (t) C(t), \]

\[ \alpha^* (t) = M(t) \alpha^* (t), \quad \nu = 0, \ldots, k - 1, \]

\[ S^4 (t) = (\alpha^4 A \alpha^4 + \alpha^4 B \alpha^4 - \alpha^4 C \beta^* \alpha^4 + \xi^2 \alpha^4 + \beta^4 \alpha^4)\gamma, \]

execute shift of conditions (2) to the left on a section \([\tilde{t}_j, \tilde{t}_i], \) and takes place

\[ \|\alpha^4 (t)\| + \|\xi(t)\| + \|\beta(t)\| = \text{const}, \quad t \in [\tilde{t}_j, \tilde{t}_i]. \]

**III. THE SOLUTION OF PROBLEM B**

For the solution of problem B it is basically used the procedure of conditions shift (2), described above, permitting to get rid from differential links (1) and to reduce a problem of parameters optimization to a problem of quadratic programming.

Let’s introduce new variables:

\[ z^i_0 = x(\tilde{t}_i), \quad \nu = 0, \ldots, k, \quad z^i_1 = x(\tilde{t}_i), \quad j = 0, \ldots, k_1, \]

\[ z^i_0 = x(\tilde{t}_i), \quad i = 0, \ldots, k_2, \]

\[ Z = (z_1^i, z_2^i, z_3^i) \in E^N, \quad N = (k + k_1 + k_2 + 3) m. \] (38)

It is clear that executing series shift to the right of conditions (2) at intervals \([\tilde{t}_j, \tilde{t}_i], j = 1, \ldots, k, \) i.e. solving Cauchy problems (9) - (12) and determining values of matrix functions in time moments \(i_j, i_j, j = 0, \ldots, k_1, i = 0, \ldots, k_2\) in addition to \((k + 1) m\) relations of a kind (7):

\[ \sum_{v=0}^{k} \alpha^{*v} (\tilde{t}_j) z^v_0 + \xi(\tilde{t}_j)p = \beta(\tilde{t}_j), \quad j = 0, \ldots, k, \] (39)

we receive the \((k_1 + 1) m\) and \((k_2 + 1) m\) relations:

\[ \alpha^{*v} (\tilde{t}_j) z^v_0 + \sum_{v=0}^{k} \alpha^{*v} (\tilde{t}_j) z^v_0 + \xi(\tilde{t}_j) p = \beta(\tilde{t}_j), \quad j = 0, \ldots, k_1, \] (40)

\[ \alpha^{*v} (\tilde{t}_j) z^v_0 + \sum_{v=0}^{k} \alpha^{*v} (\tilde{t}_j) z^v_0 + \xi(\tilde{t}_j) p = \beta(\tilde{t}_j), \quad i = 0, \ldots, k_2, \] (41)

where \(\mu_j, \chi_i\) are the numbers of subintervals, keeping instantly accordingly \(\tilde{t}_j\) and \(\tilde{t}_i\), i.e.

\[ \tilde{t}_j \in [\tilde{t}_{j-1}, \tilde{t}_{j}], \quad \tilde{t}_i \in [\tilde{t}_{i-1}, \tilde{t}_{i}], \quad j = 0, \ldots, k_1, \quad i = 0, \ldots, k_2 \]

It is clear, that the number of restrictions as equalities in (39) - (36) equals \(M = (k + k_1 + k_2 + 3)m\).

Using notations (38), limitations (3) and target functionals (4) we’ll write as:

\[ \sum_{j=0}^{k} e^v_0 z^v_0 + f p(\hat{z}), \] (42)

\[ J(Z, p) = \sigma_1 \|p\|_2^2 + \sum_{j=0}^{k} \sigma_2 \|z-j\|_2^2 - X^t (y), \] (43)

The problem (39) - (43) is a problem of quadratic programming with optimized vector \((Z, p)\) of dimension \(N+1\) and the number of limitations as equalities (39) - (41) is \(M\) and mixed type (37) is \(m\), generally can be presented at:

\[ RZ + Fp(\hat{z}) = \mu, \]

\[ J(Z, p) = \sigma_1 \|p\|_2^2 + \sigma_2 \|Z - Q\|_2^2, \]

where the matrices \(R, F\) and vectors \(T, Q\) are formed by limitations (39) - (42) with considering notation (38).

Thus, for a numerical solution of a problem B it is necessary to execute following. Using the numerical methods to solve Cauchy problems (9) - (12), to store values of matrix functions in all instants, participating in a formulation of problem B, namely:

\[ \tilde{t}_j, \tilde{t}_i, \tilde{t}_v, j = 0, \ldots, k_1, \quad i = 0, \ldots, k_2, \quad \nu = 0, \ldots, k_2. \]

Then it’s necessary to form matrices \(R, F\), vector \(T\) for the reference to the standard programs of the solution of a quadratic programming problem. Having received values of vector \(p\) and \(x(t_0) = x(\tilde{t}_0)\), it is possible numerically to decide a Cauchy problem concerning a system (1) and to receive values \(x(t)\) on all interval \(t \in [t_i, t_j]\) and to complete the solution of a problem B .

As example, we shall consider outcomes of parameters recovery in a following problem:

\[ x_1 = 3x_1 + t^2 p_1 + 3p_2 + 4t, \quad t \in [0; 2], \]

\[ x_2 = t x_1 - 2t^2 x_2 - p_1 - 2t^2 p_2 - 2t - 1, \]

with multipoint boundary conditions

\[ x_1(0) = x_1(0) + x_2(2) - 2p_1 = 6, \]

\[ x_1(0) + x_2(2) - p_1 + p_2 = 12, \]

with minimized criteria of quality:

\[ J_{x}(p) = \sigma_1 (p_1^2 + p_2^2) + (x_1(1)^2 + x_2(1))^2. \]

In the table 1 the problem solution results at different values of parameter \(\sigma\) are adduced. Let’s mark, that the precise solution of a problem at \(\sigma = 0\), as is simply to verify, is reached at value of parameters \(p^* = (-3; 1)\), at which \(x_1(t) = 2t^2 - 1, x_2(t) = t - 1\). The numerical solution of Cauchy
problems was conducted single-precision by the fourth order Runge-Kutta method at number of splittings equal 100.

<table>
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<th>( p_2^* )</th>
<th>( J_\sigma (p^*) )</th>
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</table>

In a problem of quadratic programming obtained after series two shifts in edge conditions to the right, the vector \( Z = (x(1), x(2), \rho) \in E^k \) is unknown and there are four limitations as equalising: two of them are obtained after the first shift:

\[
\hat{\alpha}^1 x(1) + \hat{\alpha}^2 x(2) + \hat{\xi} \rho = \hat{\beta},
\]

and two after the second shift:

\[
\hat{\alpha}^1 x(2) + \hat{\xi} \rho = \hat{\beta}.
\]

Four problems of quadratic programming with the same limitations, but different target functions at the expense of values of \( \sigma \) were decided. As a whole on all variants of calculation on IBM the Pentium-I was required 7 seconds.

IV. CONCLUSION

With the application of the approach, offered in paper, the plenty of numerical experiments concerning solving the problem \( A, B \) is conducted.

With usage of a method of a linearization offered by Pshenichnyi B.N. [4], the stated technique utilised also for a numerical solution of a non-linear problem of a dynamic system parameters recovery:

\[
\dot{x}(t) = f(x(t), \rho), \quad t \in [t_i, t_j],
\]

\[
g_j(x(t_i), x(t_i), ..., x(t_j), \rho) = 0, \quad j = 1, ..., n + 1.
\]

It is necessary to mark convenience of application of the offered approach. Its programmatic implementation does not produce problems, as basically the standard procedures, solving of Cauchy problem, system of algebraic equations and problems of quadratic programming, available, in particular, in software package Matlab, will be used.

REFERENCES