

# Active Acquisition of Information for Diagnosis and Supervisory Control of Discrete Event Systems

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In (Thorsley and Teneketzis 2007), Definition 1 is incomplete. The revised definition below states the additional necessary condition missing from Thorsley and Teneketzis (2007).

**Definition 1** An observation policy  $g := (g_0, \dots, g_{T-1})$  is a sequence of functions  $g_t : L_T \rightarrow 2^{\Sigma_{co}}$  such that for all  $t, t = 0, \dots, T - 1$ ,  $g_t$  is measurable with respect to the  $\sigma$ -field  $\mathcal{G}_t^g$ , defined below (in Definition 3).

Note that for all  $s' \in L_t$  and  $s, \hat{s} \in \chi_t(s')$ ,  $g_t(s) = g_t(\hat{s})$ . The statement “The functions  $\chi_t$  are used in the following definition,” found above Definition 1 in the text, should be ignored when reading the paper.

Definition 3 is unchanged, but we restate it here for convenience.

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**Definition 3** The filtration  $\{\mathcal{G}_t^g, t = 0 \dots T\}$  corresponding to  $g$  is

$$\sigma(\pi_t : \pi_t \in R_t^g), t = 0 \dots T. \quad (11)$$

Note that  $\mathcal{G}_t^g, t = 0 \dots T - 1$ , depends on  $g_0, g_1, \dots, g_{t-1}$ .

## References

Thorsley D, Teneketzis D (2007) Active acquisition of information for diagnosis and supervisory control of discrete event systems. *Discrete Event Dyn Syst: Theory and Applications* 17(4): 531–583