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CONCLUSION Geometric state space theory is a powerful and now well-established methodology for the treatment of qualitative problems of structural analysis and synthesis in linear multivariable control. It is likely that the approach will also succeed in further exploring recent problem areas like hierarchical and decentralized control.

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In control engineering, a state-space representation is a mathematical model of a physical system as a set of input, output and state variables related by first-order differential equations or difference equations. State variables are variables whose values evolve over time in a way that depends on the values they have at any given time and on the externally imposed values of input variables.

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State-space approaches for SISO system can also be found in the literature. Although the state-space representation is a very convenient description for multi-variable systems, only few times it...

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The state space approach has introduced an effective and systematic method for the design of a controller for a multivariable system. Description of a multivariable system by a set of first order simultaneous differential equations is called a state space representation which had been used by Lyapunov for stability analysis.

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## **The Role of Poles and Zeros in Multivariable Feedback Theory**

In state-determined systems, the state variables may always be taken as the outputs of integrator blocks. A system of order  $n$  has  $n$  integrators in its block diagram.

## **2.14 Analysis and Design of Feedback Control Systems State**

...

First and obviously, the setting is linear state space and the mathematics chiefly linear algebra in abstract (geometrie) style. The basic ideas are the familiar system concepts of controllability and observability, thought of as geometrie properties of distinguished state subspaces. ... while the usual linear multivariable control theory ...

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[ $A_{bar}, B_{bar}, C_{bar}, T, k$ ] =  $obsvf(A, B, C)$  decomposes the state-space system with matrices  $A$ ,  $B$ , and  $C$  into the observability staircase form  $A_{bar}$ ,  $B_{bar}$ , and  $C_{bar}$ , as described above.  $T$  is the similarity transformation matrix and  $k$  is a vector of length  $n$ , where  $n$  is the number of states in  $A$ .

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