



$$x = \begin{bmatrix} T_{e_1} & T_{e_2} & T_i^o & T_f & T_g \end{bmatrix}^T$$

$$u = \begin{bmatrix} T_a & T_g & T_p & \bar{T}_{iw} & Q_{gol,e} & Q_{tot} & Q_{cool} \end{bmatrix}^T$$

$$\Theta = \begin{bmatrix} R_{e_1} & R_{e_2} & R_{e_3} & R_{i1}^o & R_{i2}^o & R_{f1} & R_{f2} & R_w & R_c & \dots \\ \dots & C_{e_1} & C_{e_2} & C_i^o & C_f & C_z \end{bmatrix}^T$$