



$$x = [T_{e1} \ T_{e2} \ T_i \ T_f \ T_2]^T$$

$$u = [T_a \ T_g \ T_p \ \langle \bar{T}_{iw} \rangle \ Q_{sol,e} \ Q_{tot} \ Q_{cool}]^T$$

$$\theta = [R_{e1} \ R_{e2} \ R_{e3} \ R_{i1} \ R_{i2} \ R_{f1} \ R_{f2} \ R_w \ R_c \dots \\ \dots C_{e1} \ C_{e2} \ C_i \ C_f \ C_2]^T$$