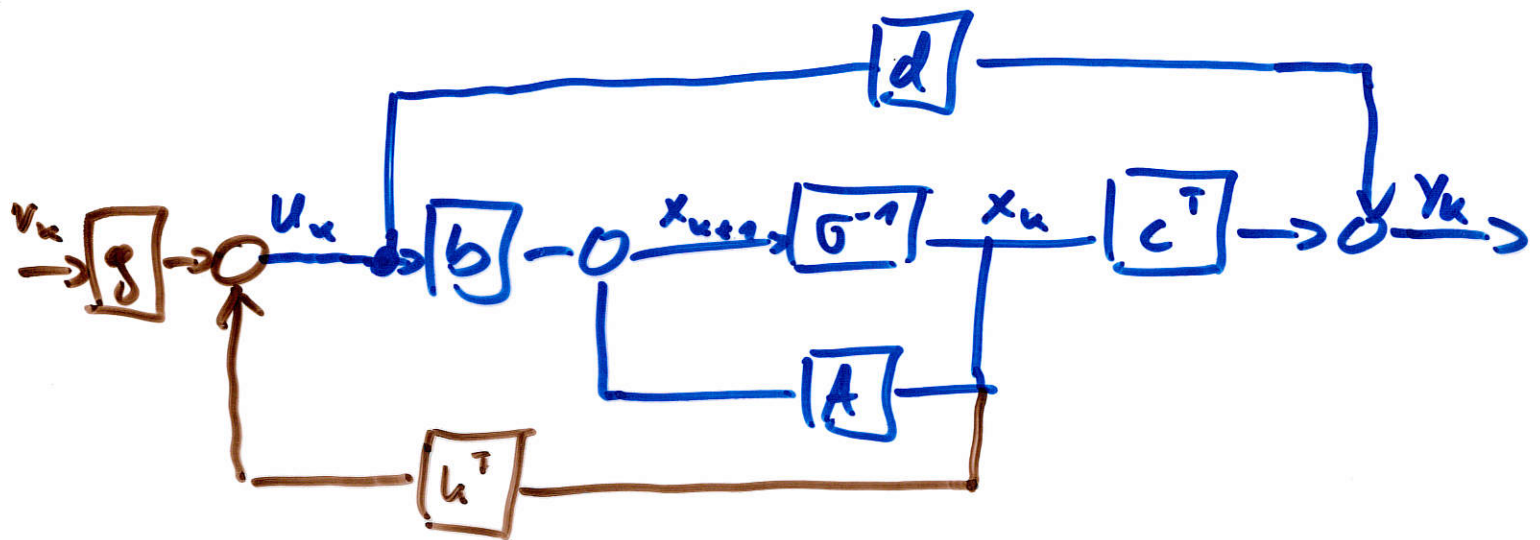


$$x_{k+1} = Ax_k + bu_k$$

$$y_k = c^T x_k + du_k$$



$$zR: u_k = k^T x_k + g v_k$$

Formel von Ackermann:

$$k^T = -e_v^T M_e^{-1} P_{wunsch}(A)$$

# Zustandsbeobachter

