Contoh: Motor DC terkendali jangkar

1 masukan: $u = e_a(t) \rightarrow m = 1$

2 keluaran $\left.\begin{array}{l} y_1 = i(t) \\ y_2 = \omega(t) \end{array}\right\} \rightarrow k = 2$

Dimensi: 2 peubah keadaan: $\left.\begin{array}{l} x_1 = i(t) \\ x_2 = \omega(t) \end{array}\right\} n = 2$

A: [2x2], B [2x1], C [2x2], D = [2x1]

$$\dot{x} = \underbrace{\begin{bmatrix} & \\ & \end{bmatrix}}_{A[2\times2]} x + \underbrace{\begin{bmatrix} \\ \end{bmatrix}}_{B[2\times1]} u$$

$$y = \underbrace{\begin{bmatrix} & \\ & \end{bmatrix}}_{C[2\times2]} x * \underbrace{\begin{bmatrix} \\ \end{bmatrix}}_{D[2\times1]} u$$