

**Publicacions més rellevants de la línia de recerca:**  
**Geometria de les realitzacions parcials generalitzades  
i la seva relació amb el *cover problem*.**

**Referència:** F. Puerta, X. Puerta, I. Zaballa. On the parametrization of the controllability subspaces of a controllable pair. *Linear Algebra Appl.*, **401** (2005), pp. 429-444.

**Abstract:** Given a controllable linear control system defined by a pair of constant matrices  $(A, B)$ , the set of controllability subspaces is a stratified submanifold of the set of  $(A, B)$ -invariant subspaces. We parametrize each strata by means of coordinate charts. This parametrization has significant differences to that of  $(A, B)$ -invariant subspaces, showing a more complex geometric structure.

---

**Referència:** F. Puerta, X. Puerta, I. Zaballa, On the geometry of the solutions of the cover problem, *SIAM Journal of Control and Optimization* 45 (2) (2006), pp. 389-413.

**Abstract:** For a given system  $\Sigma(A, B)$  and a subspace  $\mathcal{S}$ , the cover problem consists of finding all  $(A, B)$ -invariant subspaces containing  $\mathcal{S}$ . For controllable systems, the set of these subspaces can be suitably stratified. In this paper, necessary and sufficient conditions are given for the cover problem to have a solution on a given strata. Then the geometry of these solutions is studied. In particular, the set of the solutions is provided with a differentiable structure and a parameterization of all solutions is obtained through a coordinate atlas of the corresponding smooth manifold.

---

**Referència:** Marta Peña, Ferran Puerta and Xavier Puerta. A sufficient condition for Lipschitz stability of controlled invariant subspaces *Mediterranean Journal of Mathematics*, **4 v6** (2009), pp. 475-485.

**Abstract:** Given a pair of matrices  $(A; B)$  we study the Lipschitz stability of its controlled invariant subspaces. A sufficient condition is derived from the geometry of the set formed by the quadruples  $(A; B; F; S)$  where  $S$  is an  $(A; B)$ -invariant subspace and  $F$  a corresponding feedback.