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The nonlinear dynamic equation for a pendulum is given by  $m\ddot{\theta} = -m\dot{\theta}^2 - k\theta$ , where  $l > 0$  is the length of the pendulum,  $m > 0$  is the mass,  $k > 0$  is a friction parameter and  $\theta$  is the angle subtended by the rod and the vertical axis through the pivot point, see Figure 1.1. PSfrag replacements  $\theta$  Figure 1.1 The pendulum in Exercise 1.1

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Exercises in Nonlinear Control Systems

Acces PDF Slotine Nonlinear Control Solution Exercise Slotine Nonlinear Control Solution Exercise Slotine, J.-J. E. (Jean-Jacques E.) Applied nonlinear control / Jean-Jacques E. Slotine, Weiping Li p. cm. Includes bibliographical references. ISBN 0-13-040890-5 1, Nonlinear control theory. I. Li, Weiping. II. Title. QA402.35.S56 1991 90-33365 ...

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Student Solutions Manual for \Design of nonlinear control systems :::" 4 Chapter 1 Exercise 1.2 The behavior of a dynamical system is described by the equation  $\ddot{x} + 1.5\dot{x} + 0.5x + f(x) = 0$ : (1) Determine the region of  $x$ , such that  $X = 0$  is an exponentially stable equilibrium point of the given system. Solution. Denote  $x_1 = x$ ;  $x_2 = \dot{x}$ , and  $X = [x_1; x_2]^T$ . Hence, we have

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