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great advances in the theory and applications of nonlinear control. In terms of theory, major strides have been made in the areas of feedback linearization, sliding control, and nonlinear adaptation techniques. In terms of applications, many practical nonlinear control systems have been developed, ranging from digital "fly-by-wire"

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Many people have contributed to this material in nonlinear control. Originally, it was developed by Bo Bernhardsson, Karl Henrik Johansson, and Mikael Johansson.

### EL2620 Nonlinear Control Exercises and Homework

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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  $\dot{x}(2) + 1.5x(1) + 0.5x + f_2x^2 + [x(1)]^2g_1 = 2 = 0$ : (1) Determine the region of  $\mu$ , such that  $X = 0$  is an exponentially stable equilibrium point of the given system. Solution. Denote  $x_1 = x$ ;  $x_2 = x(1)$ , and  $X = [x_1; x_2]^T$ . Hence, we have

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Consider the linear feedback control system given by the figure below.  $\Sigma G(s) - F(s)$  Show that if the small gain theorem (Swe: l° agf" orst " arkningsssatsen) is fulfilled the Nyquist criterion is also fulfilled. 1.2 Consider a static nonlinear system described by an ideal relay given by the function  $y(t) = f(u(t)) = 1, u > 0, u = 0 -1 \dots$

### CONTROL THEORY, TSRT09, TSRT06 Exercises & solutions

"On Contraction Analysis for Nonlinear Systems," Automatica, 34(6), 1998 R2 Slotine, J.J.E., "Modular Stability Tools for Distributed Computation and Control," Int. J. Adaptive Control and Signal Processing, 17(6), 2003

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(e) The right-hand-side function  $f$  is continuously differentiable; hence it is locally  $\frac{df}{du} = u$ . Since  $0 < u < 1$ , the partial  $\frac{\partial}{\partial u} (u + u^2) = 1 + 2u > 1$

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