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Second Method | Nonlinear  
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Systems Problem 1 on Block  
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Controller Intro to Control - 6.4

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Stability using Describing

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Stability Analysis, State Space -  
3D visualization What is a PID  
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What is LQR control? Intro to  
Control - 5.2 System Linearization  
~~06 Feedback Linearization I by~~  
~~Prof Ravi N Banavar, IIT Bombay~~  
~~Trimming and Linearization, Part~~



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~~Exercise~~ 1: What is Linearization? Stability  
of Systems | Nonlinear Control  
Systems Iteration Method | Fixed  
Point Iteration Method | Numerical  
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Density Practice Problems

Nonlinear Systems and Control

Lecture 3 – Phase Plane Analysis

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### Exercise

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The nonlinear dynamic equation for a pendulum is given by  $ml \ddot{\theta} = -m \hat{\sin} \theta - kl \dot{\theta}$ , where  $l > 0$  is the length of the pendulum,  $m > 0$  is the mass,  $k > 0$  is a friction

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parameter and  $\theta$  is the angle subtended by the rod and the vertical axis through the pivot point, see Figure 1.1. PSfrag replacements Figure 1.1 The pendulum in Exercise 1.1

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(and automotive areas). figure 1.1  
figure 1.2 figure 1.3 figure 1.4  
figure 1.5 figure 1.6 figure 2.1  
figure 2.10 ...

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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  $\dot{x}(2) + 1.5x(1)$   
 $+ 0.5x + \dots f(2x^2 + [x(1)]^2)g_1 = 2 =$   
0: (1) Determine the region of  $\dots$

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Exercise 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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