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from Nonlinear Systems While Nonlinear Systems was intended as a reference and a text on nonlinear system analysis and its application to control, this book is intended as a text for a first course on nonlinear control that can be taught in one semester (forty lectures) The writing style is intended to make it accessible

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NonlinearControl Lecture#1 Introduction

with $x(t_0)=x_0$, has a unique solution over $[t_0,t_1]$ The global Lipschitz condition is satisfied for linear systems of the form $x' = A(t)x+g(t)$ but it is a restrictive condition for general nonlinear systems NonlinearControlLecture#1Introduction

Nonlinear Systems and Control Lecture # 1 Introduction

Nonlinear Systems and Control Lecture # 1 has a unique solution over $[t_0,t_0 +\delta]$ Without the local Lipschitz condition, we cannot ensure uniqueness of the solution For example, $x' = x^{1/3}$ has $x(t) = (2t/3)^{3/2}$ and $x(t) \equiv 0$ as two different solutions when the initial state is $x(0) = 0$

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2 Two-Dimensional Systems 9 3 Stability of Equilibrium Points 51 4 Time-Varying and Perturbed Systems 81 5 Passivity 99 6 Input-Output Stability 107 7 Stability of Feedback Systems 123 8 Special Nonlinear Forms 137 9 State Feedback Stabilization 155 10 Robust State feedback Stabilization 181 11 Nonlinear Observers 223 12 Output Feedback

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