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Textbook reference for lectures 1-13 is . Applied Nonlinear Control, Slotine and Li, Prentice-Hall 1991. Main references for lectures 14-20 are . R1 Lohmiller, W., and Slotine, J.J.E., "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 ...

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1. Nonlinear Models and Simulation Exercise 1.1[Khalil, 1996] The nonlinear dynamic equation for a pendulum is given by  $m l \ddot{\theta} = -m g \sin \theta - k l \dot{\theta}$ , 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.

### Exercises in Nonlinear Control Systems

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