

Nonlinear Control Systems

A continuous-time nonlinear time-invariant state space model takes the form

$$\begin{aligned}\dot{x}(t) &= f(x(t), u(t)) & x(t_0) &= x_0 \\ y(t) &= g(x(t), u(t))\end{aligned}$$

where $x \in \mathbb{R}^n$ is the state vector, $u \in \mathbb{R}^m$ is the control signal, $y \in \mathbb{R}^p$ is the output, $x_0 \in \mathbb{R}^n$ is the state vector at time $t = t_0$ and $f(x,u)$ and $g(x,u)$ are nonlinear functions of appropriate dimensions.

Nonlinear control systems -- nonlinear functions $f(x,u)$ and $g(x,u)$

Nonlinear Systems And Control Lecture 1 Introduction

N Colangelo



Nonlinear Systems And Control Lecture 1 Introduction:

The Enigmatic Realm of **Nonlinear Systems And Control Lecture 1 Introduction**: Unleashing the Language is Inner Magic

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