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(e) The right-hand-side function is continuously differentiable; hence it is locally = u . Since $0 < u < 1$, the partial $\partial u / \partial x_i = u$ for $i = 1, \dots, n$. Thus, the Jacobian matrix is $J = [u \quad u \quad \dots \quad u]$.

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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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presence of unknown external disturbances and varying parameters of the plant. The solutions manual is accompanied by Matlab-Simulink files for calculations and simulations related with Exercises.

Student Solutions Manual for Design of Nonlinear Control

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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 "arkningsatsen) is fulfilled the Nyquist criterion is also fulfilled. 1.2 Consider a static nonlinear system described by an ideal relay given by the function $y(t) = f(u(t)) = 1, u > 0$ $0, u = 0$ $-1 \dots$

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