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The nonlinear dynamic equation for a pendulum is given by  $m\ddot{\theta} + mgl\sin\theta = 0$  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. PSfrag replacements ? Figure 1.1 The pendulum in Exercise 1.1

Exercises in Nonlinear Control Systems

Acces PDF Slotine Nonlinear Control Solution Exercise Slotine Nonlinear Control Solution Exercise Slotine, 1.-J. E. (Jean-Jacques E.) Applied nonlinear control / Jean-Jacques E. Slotine, Weiping Li p. cm. Includes bibliographical references. ISBN 0-13-040890-5 1, Nonlinear control theory. I. Li, Weiping. II. Title. QA402.35.S56 1991 90-33365 ...

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