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The nonlinear dynamic equation for a  
pendulum is given by  $m\ddot{\theta} + k\dot{\theta} + mgl\sin\theta = \tau$

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



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vertical axis through the pivot point,  
see Figure 1.1. PSfrag replacements ?  
Figure 1.1 The pendulum in Exercise  
1.1

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of nonlinear control systems ::" 4  
Chapter 1 Exercise 1.2 The behavior  
of a dynamical system is described by  
the equation  $\ddot{x} + 1.5\dot{x} + 0.5x + f_2x^2$

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$+ [x(1)]^2 g_1 = 2 = 0$ : (1) Determine the region of  $\mathbb{R}^n$ , such that  $X = 0$  is an exponentially stable equilibrium point of the given system. Solution. Denote  $x_1 = x$ ;  $x_2 = x(1)$ , and  $X = [x_1; x_2]^T$ . Hence, we have

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