# University of Waterloo Department of Electrical & Computer Engineering ECE 688: Nonlinear Systems

# Winter 2019

Lecture times, building and room number: Monday 11:30pm to 2:20pm; EIT 3141.

**Instructor**: Prof. Christopher Nielsen.

Office: CEIT 4106.

Office hours: By appointment.

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Website: http://learn.uwaterloo.ca/

**Course description**: Why should one study nonlinear systems? Virtually all physical systems are nonlinear in nature. Sometimes it is possible to describe the operation of a physical system by a linear model. This is the case, for example, if the mode of operation of the system does not deviate too much from the "nominal" set of operating conditions. But in analyzing the behaviour of any physical system, one often encounters situations where the linearized model is inadequate or inaccurate. That is the time that the material covered in this course may prove useful.

In this course we cover classical and modern approaches to the analysis of finite-dimensional, deterministic, nonlinear systems modeled by ordinary differential equations with an emphasis on stability, robustness and the effect of interconnecting dynamical systems. The material in this course may appeal to engineers interested in a rigorous treatment of nonlinear systems and finds applications in all branches of engineering.

Recommended background: ECE 380 (or equivalent) and familiarity with basic calculus.

#### **Textbook**

There is no required text for this course. Instructor will provide electronic course notes and write on the board. An excellent **optional** textbook is

Nonlinear Systems, 3rd edition, H.K. Khalil.

#### Additional references

- Nonlinear Systems Analysis, 2nd edition, M. Vidyasagar.
- Nonlinear Control Systems II, A. Isidori.
- $\mathcal{L}_2$ -Gain and Passivity Techniques in Nonlinear Control, A. van der Schaft.

#### **Evaluation**

- 50% Final exam: open book.
- 35% Assignments: Four (4) assignments spread over the term.
- 5% Tutorials: Schedule to be determined.
- 10% Course project.

# **Tentative Topics**

# 1. Introduction to nonlinear models and phenomena

Examples.

#### 2. Mathematical preliminaries

Functions, Norms, topology of  $\mathbb{R}^n$ , continuity on  $\mathbb{R}^n$ , differentiability on  $\mathbb{R}^n$ .

## 3. The vocabulary of dynamical systems

Phase and integral curves, phase portraits, state transition function, phase flows, vector fields, existence and uniqueness of solutions, equilibria, closed orbits, invariant sets and limit sets.

## 4. Lyapunov stability

Autonomous systems, invariance principle, sign definite functions, domain of attraction, linearization, converse theorems, stability and small perturbations.

# 5. Input-output models

" $\mathcal{L}$  spaces" and their extensions, input-output maps, small gain theorem, linear systems with nonlinear feedback.

#### 6. Input-to-state stability

Cascade connected systems, feedback connected systems, small gain theorem for ISS systems.

#### 7. Dissipative systems

Definitions, relationship with Lyapunov stability, classes of dissipative systems, control affine systems with quadratic supply rates, linear systems, absolute stability problem.

# 8. Introduction to output regulation

Centre-manifold theory, tracking for nonlinear control systems (local theory), single-input single-output control affine systems with relative degree.

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