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(e) The right-hand-side function f is continuously differentiable; hence it is locally C^1 . Since $0 < u < 1$, the partial $\frac{\partial f}{\partial u} = u + 1$.

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CONTROL SYSTEMS, ROBOTICS AND AUTOMATION - Vol. XII - Control of Nonlinear Systems - Hassan K. Khalil ©Encyclopedia of Life Support Systems (EOLSS) which is strictly increasing and vanishes at zero, and β is a nonnegative bias constant.

Control Of Nonlinear Systems

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In Nonlinear Control, author Hassan K. Khalil employs a writing style that is intended to make the book accessible to a wider audience without compromising the rigor of the presentation. Teaching and Learning Experience

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Many people have contributed to this material in nonlinear control. Originally, it was developed by Bo Bernhardsson. Originally, it was developed by Bo Bernhardsson, Karl Henrik Johansson, and Mikael Johansson.

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