**Contents**

Chapter 1. Introduction

1.1. Nonlinear systems and robots

1.2. Some basic results

Chapter 2. Nonlinear Modeling

2.1. Rigid body motion

2.2. Manipulator kinematics

2.3. Manipulator dynamics

Chapter 3. Nonlinear Analysis

3.1. Periodic solutions

3.2. Second order systems

3.3. Lyapunov stability theory

3.4. Lyapunov’s direct method

3.5. Stability of invariant set

3.6. Nonsmooth and switching systems

Chapter 4. Nonlinear Control

4.1. Motion and force control

4.2. Nonholonomic robots and controllability

4.3. Perception and observability

4.4. Kalman filter and extended Kalman filter

4.5. Steady state response and center manifold

4.6. Center manifold theory

4.7. Zero dynamics and its applications

4.8. Disturbance decoupling problem (DDP)

4.9. Exact linearization via feedback

Chapter 5. PMP: A Special Case

5.1. Linear Quadratic Control

5.2. Derivation Using Dynamic Programming (Optional)

Chapter 6. PMP: General Results

6.1. Autonomous Systems: Fixed Initial and Final States

6.2. Optimal Control to a Manifold

6.3. Some Generalizations

6.4. How to Use PMP

**Schedule**

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| **2014.7.14 (Monday) Room N420** | |
| Lecture 1 (9:00~11:00)  Introduction and modeling | Lecture 2 (15:00-17:00)  Modeling and analysis |
| **2014.7.16 (Wednesday) Room N208** | |
| Lecture 3 (9:00~11:00)  Nonlinear analysis | Lecture 4 (15:00-17:00)  Nonlinear analysis and control |
| **2014.7.18 (Friday) Room N208** | |
| Lecture 5 (9:00~11:00)  Nonlinear controllability | Lecture 6 (15:00-17:00)  Zero dynamics and applications |
| **2014.7.21(Monday) Room N420** | |
| Lecture 7 (9:00~11:00)  Kalman filter and EKF |  |
| **2014.7.22 (Tuesday) Room N420** | |
| Lecture 8 (9:00~11:00)  Optimal control |  |
| **2014.7.23 (Wednesday ) Room N420** | |
| Lecture 9 (9:00~11:00)  Optimal control to a manifold |  |

Hu Xiaoming received the B.S. degree from the University of Science and Technology of China in 1983, and the M.S. and Ph.D. degrees from the Arizona State University in 1986 and 1989 respectively. He served as a research assistant at the Institute of Automation, the Chinese Academy of Sciences, from 1983 to 1984. From 1989 to 1990 he was a Gustafsson Postdoctoral Fellow at the Royal Institute of Technology, Stockholm, where he is currently a professor of Optimization and Systems Theory. His main research interests are in nonlinear control systems, nonlinear observer design, sensing and active perception, motion planning, control of multi-agent systems, and mobile manipulation.

注：参加此课程的博士生在课程结束后完成相关试卷，可作为博士生课程。