System and Control Theory
Test of February 5, 2015
Questions and Exercises

Name:	
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1. Write the closed form solution of the differential equation $\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}(t)$ starting from the initial condition $\mathbf{x}(t_0)$:

$$\mathbf{x}(t) = e^{\mathbf{A}(t-t_0)}\mathbf{x}(t_0) + \int_{t_0}^{t} e^{\mathbf{A}(t-\tau)}\mathbf{B}\mathbf{u}(\tau)d\tau$$

2. Write the discrete time behavior of the output function $\mathbf{y}(k)$, solution of the difference equation $\mathbf{x}(k+1) = \mathbf{A}\mathbf{x}(k) + \mathbf{B}\mathbf{u}(k)$ and the static equation $\mathbf{y}(k) = \mathbf{C}\mathbf{x}(k) + \mathbf{D}\mathbf{u}(k)$ starting from the initial condition $\mathbf{x}(0)$ at time $h = 0$:

$$\mathbf{y}(k) = \mathbf{C}\,\mathbf{A}^k\mathbf{x}(0) + \mathbf{C}\sum_{j=0}^{k-1}\mathbf{A}^{k-j-1}\mathbf{B}\mathbf{u}(j) + \mathbf{D}\mathbf{u}(k)$$

3. Describe what the symbol $\mathcal{X}^+(k)$ represents for discrete systems $\mathbf{x}(k+1) = \mathbf{A}\mathbf{x}(k) + \mathbf{B}\mathbf{u}(k)$:

   It is the set of the states reachable from the origin in k steps.

   Moreover, write the usual way of computing the set $\mathcal{X}^+(k)$:

$$\mathcal{X}^+(k) = \mathrm{Im}\mathcal{R}^+(k) = \mathrm{Im}\left[\begin{array}{ccccc} \mathbf{B} & \mathbf{A}\mathbf{B} & \mathbf{A}^2\mathbf{B} & \dots & \mathbf{A}^{k-1}\mathbf{B} \end{array}\right]$$

4. Give the meaning of the symbol $\mathcal{E}^+(t_0, t_1, \mathbf{u}(\cdot), \mathbf{y}(\cdot))$:

   It is the set of the final states $\mathbf{x}(t_1)$ compatible with the input and output functions $\mathbf{u}(\cdot)$ and $\mathbf{y}(\cdot)$ in the time interval $[t_0, t_1]$.

5. Compute the reachability matrix $\mathcal{R}^+$ and the observability matrix $\mathcal{O}^-$ of the following system:

$$\begin{cases} \dot{\mathbf{x}}(t) = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & -1 \\ -1 & 0 & 1 \end{bmatrix}\mathbf{x}(t) + \begin{bmatrix} 0 & 0 \\ 1 & 1 \\ 0 & 1 \end{bmatrix} u(t) \\ y(t) = \begin{bmatrix} 0 & 1 & 1 \end{bmatrix}\mathbf{x}(t) \end{cases} \qquad \mathcal{R}^+ = \begin{bmatrix} 0 & 0 & 0 & 0 & 0 & 0 \\ 1 & 1 & 1 & 0 & 1 & -1 \\ 0 & 1 & 0 & 1 & 0 & 1 \end{bmatrix}, \quad \mathcal{O}^- = \begin{bmatrix} 0 & 1 & 1 \\ -1 & 1 & 0 \\ -1 & 1 & -1 \end{bmatrix}$$

   The system is: ○ reachable? ⊗ not-reachable? ⊗ observable? ○ not-observable?

   Provide a base $\mathcal{B}_R$ of the reachable subspace $\mathcal{X}^+$ and a base $\mathcal{B}_O$ of the not-observable subspace $\mathcal{E}^-$:

$$\mathcal{X}^+ = \mathrm{Im}\,[\mathcal{B}_R] = \mathrm{Im}\begin{bmatrix} 0 & 0 \\ 1 & 1 \\ 0 & 1 \end{bmatrix}, \qquad \mathcal{E}^- = \mathrm{Im}\,[\mathcal{B}_O] = \mathrm{Im}\begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}.$$

6. Given the following continuous-time linear system $\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}(t)$, $\mathbf{y}(t) = \mathbf{C}\mathbf{x}(t)$. Write the expression of the matrices $\mathbf{F}$, $\mathbf{G}$ and $\mathbf{H}$ that characterize the corresponding sampled system $\mathbf{x}(k+1) = \mathbf{F}\mathbf{x}(k) + \mathbf{G}\mathbf{u}(k)$, $\mathbf{y}(k) = \mathbf{H}\mathbf{x}(k)$:

$$\mathbf{F} = e^{\mathbf{A}T}, \qquad \mathbf{G} = \int_0^T e^{\mathbf{A}\sigma}\mathbf{B}\,d\sigma, \qquad \mathbf{H} = \mathbf{C}$$

7. Given a continuous-time linear system: $\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}(t)$ and $\mathbf{y}(t) = \mathbf{C}\mathbf{x}(t) + \mathbf{D}\mathbf{u}(t)$. Apply the Laplace transform to the system and provide the expression of the transform $\mathbf{y}(s)$ of the output vector $\mathbf{y}(t)$ corresponding to the *forced evolution* of the system:

$$\mathbf{y}(s) = [\mathbf{C}(s\mathbf{I} - \mathbf{A})^{-1}\mathbf{B} + \mathbf{D}]\mathbf{u}(s)$$

8. Applying to the dynamic system $\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}(t)$, $\mathbf{y}(t) = \mathbf{C}\mathbf{x}(t)$ the state space transformation $\mathbf{x} = \mathbf{T}\tilde{\mathbf{x}}$ one obtains a transformed system $\dot{\tilde{\mathbf{x}}}(t) = \tilde{\mathbf{A}}\tilde{\mathbf{x}}(t) + \tilde{\mathbf{B}}\mathbf{u}(t)$, $\mathbf{y}(t) = \tilde{\mathbf{C}}\,\tilde{\mathbf{x}}(t)$ characterized by the following matrices $\tilde{\mathbf{A}}$, $\tilde{\mathbf{B}}$ and $\tilde{\mathbf{C}}$:

$$\tilde{\mathbf{A}} = \mathbf{T}^{-1}\mathbf{A}\mathbf{T}, \qquad \tilde{\mathbf{B}} = \mathbf{T}^{-1}\mathbf{B}, \qquad \tilde{\mathbf{C}} = \mathbf{C}\mathbf{T}$$

9. Consider the following linear dynamic system:

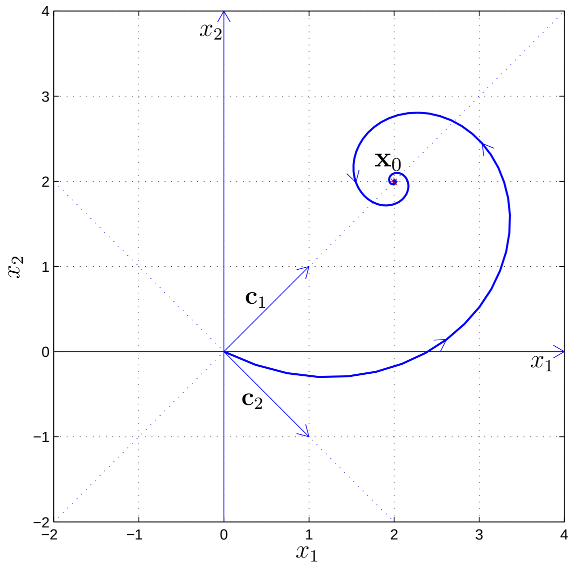
$$\dot{\mathbf{x}} = \begin{bmatrix} -1 & -3 \\ 3 & -1 \end{bmatrix}\mathbf{x} + \begin{bmatrix} 2 \\ -1 \end{bmatrix}\mathbf{u} = \mathbf{A}\,\mathbf{x} + \mathbf{B}\,\mathbf{u}, \qquad \mathbf{y} = \begin{bmatrix} y_1 \\ y_2 \end{bmatrix} = \begin{bmatrix} 1 & 1 \\ 1 & -1 \end{bmatrix}\mathbf{x} = \begin{bmatrix} \mathbf{c}_1 \\ \mathbf{c}_2 \end{bmatrix}\mathbf{x} = \mathbf{C}\,\mathbf{x}.$$

a) Write the formula used for computing the equilibrium point $\mathbf{x}_0$ corresponding to the constant input $\mathbf{u} = \mathbf{u}_0$:

$$\mathbf{x}_0 = -\mathbf{A}^{-1}\,\mathbf{B}\,\mathbf{u}_0.$$

It is easy to verify that for constant input $\mathbf{u}_0 = 4$ the equilibrium point of the given system is $\mathbf{x}_0 = [2,\, 2]^{\mathrm{T}}$.

b) In the box on the right draw the qualitative trajectory of the dynamic system $\dot{\mathbf{x}}(t) = \mathbf{A}\mathbf{x}(t) + \mathbf{B}\mathbf{u}$ obtained starting from the zero initial condition $\mathbf{x}(0) = 0$ when the input is constant: $\mathbf{u}_0 = 4$.



c) Compute the eigenvalues of the system:

$$\lambda_1 = -1 + 3j, \qquad \lambda_2 = -1 - 3j$$

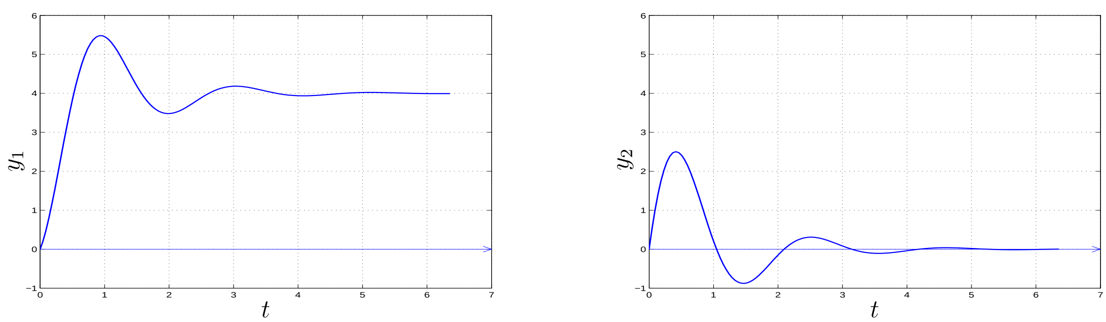
d) Which type of trajectory characterizes the time response of the system when $\mathbf{u}_0 = 4$:

○ Node? ○ Degen. Node? ⊗ Focus? ○ Saddle? ⊗ Stable? ○ Unstable?

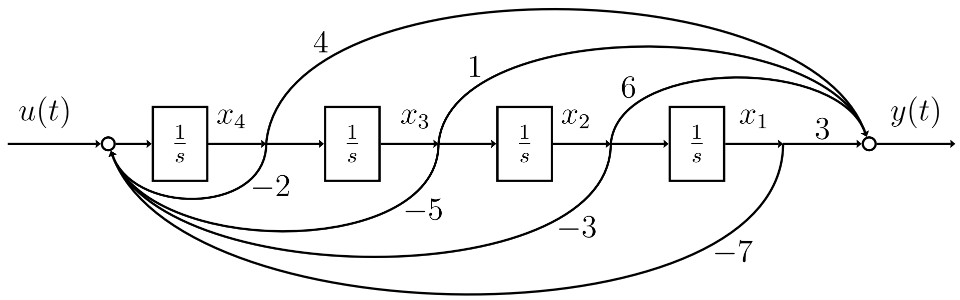
e) Compute the settling time T_a and the period T_ω of the oscillation of the time response $\mathbf{x}(t)$:

$$T_a = \frac{3}{\sigma} = \frac{3}{1} = 3 \text{ s}, \qquad T_\omega = \frac{2\pi}{\omega} = \frac{2\pi}{3} = 2.094 \text{ s}.$$

f) Draw the qualitative behavior of the time response of the two outputs $y_1(t)$ and $y_2(t)$:



10. Given following block scheme:



Compute the transfer function of the system:

$$G(s) = \frac{Y(s)}{U(s)} = \frac{4\,s^3 + s^2 + 6\,s + 3}{s^4 + 2\,s^3 + 5\,s^2 + 3\,s + 7}$$

Moreover, it is also possible to state that the system $G(s)$:

- ⊗ is completely reachable;
- ○ is completely observable;
- ○ is surely stable;
- ○ is in the reachability standard form;
- ○ is in the observability canonical form;
- ⊗ is stabilizable with the feedback $u = \mathbf{k}\,\mathbf{x}$;

11. Given a SISO linear system of the forth order ($n = 4$), completely observable, characterized by matrices $\mathbf{A}$, $\mathbf{b}$ and $\mathbf{c}$.
a) Write the structure of the matrices $\mathbf{A}_o$, $\mathbf{b}_o$ and $\mathbf{c}_o$ of the corresponding observability canonical form. Let $p(\lambda) = \lambda^4 + \alpha_3\lambda^3 + \alpha_2\lambda^2 + \alpha_1\lambda + \alpha_0$ be the characteristic polynomial of matrix $\mathbf{A}$.

$$\mathbf{A}_o = \begin{bmatrix} 0 & 0 & 0 & -\alpha_0 \\ 1 & 0 & 0 & -\alpha_1 \\ 0 & 1 & 0 & -\alpha_2 \\ 0 & 0 & 1 & -\alpha_3 \end{bmatrix}, \qquad \mathbf{b}_o = \begin{bmatrix} b_0 \\ b_1 \\ b_2 \\ b_3 \end{bmatrix}, \qquad \mathbf{c}_o = \begin{bmatrix} 0 & 0 & 0 & 1 \end{bmatrix}$$

b) Moreover, write the structure of matrix $\mathbf{P}$ which, together with the space transformation $\mathbf{x} = \mathbf{P}\mathbf{x}_o$, brings the system in the observability canonical form.

$$\mathbf{P} = [(\mathcal{O}_c^-)^{-1}\mathcal{O}^-]^{-1} = \left(\begin{bmatrix} \alpha_1 & \alpha_2 & \alpha_3 & 1 \\ \alpha_2 & \alpha_3 & 1 & 0 \\ \alpha_3 & 1 & 0 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} \mathbf{c} \\ \mathbf{cA} \\ \mathbf{cA}^2 \\ \mathbf{cA}^3 \end{bmatrix} \right)^{-1}$$

12. Compute, as function of the initial condition $\mathbf{x}(0) = [x_1(0),\ x_2(0),\ x_3(0),\ x_4(0)]^{\mathrm{T}}$, the free evolution of the following continuous-time autonomous system:

$$\dot{\mathbf{x}}(t) = \begin{bmatrix} 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & 0 & 0 & 0 \end{bmatrix} \mathbf{x}(t), \qquad \mathbf{x}(k) = \begin{bmatrix} 1 & t & \frac{t^2}{2} & \frac{t^3}{6} \\ 0 & 1 & t & \frac{t^2}{2} \\ 0 & 0 & 1 & t \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} x_1(0) \\ x_2(0) \\ x_3(0) \\ x_4(0) \end{bmatrix}$$

13. For the discret-time linear systems $\mathbf{x}(k+1) = \mathbf{A}\,\mathbf{x}(k) + \mathbf{B}\,\mathbf{u}(k)$, write the condition that must be satisfied such that it is possible to move the system from the initial state $\mathbf{x}(0)$ to the final state $\mathbf{x}(k)$ in the time interval $[0,\ k]$:

$$\mathbf{x}(k) - \mathbf{A}^k\mathbf{x}(0) \in \mathcal{X}^+(k)$$

14. Given the following continuous-time linear system:

$$\begin{cases} \dot{\mathbf{x}}(t) = \left[\begin{array}{cc|c} 0 & 1 & \mathbf{0} \\ -1 & 2 & \mathbf{0} \\ \hline \mathbf{0} & \mathbf{0} & -2 \end{array}\right] \mathbf{x}(t) + \left[\begin{array}{c} 0 \\ 1 \\ \hline \mathbf{0} \end{array}\right] u(t) \\ y(t) = \left[\begin{array}{cc|c} 1 & 2 & \mathbf{0} \end{array}\right] \mathbf{x}(t) \end{cases}$$

Thinking to the block structure of the systems in standard form it is possible to state that:

- ⊗ the system is in the standard observability form;
- ⊗ the system is in the reachability standard form;
- ⊗ for this system it is possibile to build an asymptotic state observer;
- ⊗ the system can be stabilized using a static state feedback;

Using the structural properties of the given system compute the transfer function $G(s) = \frac{Y(s)}{U(s)}$ which links the input $U(s) = \mathcal{L}[u(t)]$ to the output $Y(s) = \mathcal{L}[y(t)]$

$$G(s) = \mathbf{c}_1(s\,\mathbf{I} - \mathbf{A}_{11})^{-1}\mathbf{b}_1 = \frac{2s+1}{s^2 - 2s + 1} \qquad \text{where} \qquad \mathbf{c}_1 = [1\;\;2],\; \mathbf{A}_{11} = \begin{bmatrix} 0 & 1 \\ -1 & 2 \end{bmatrix},\; \mathbf{b}_1 = \begin{bmatrix} 0 \\ 1 \end{bmatrix}.$$

15. Given a system $(\mathbf{A},\ \mathbf{c})$ completely observable. The corresponding sampled system (being T the sampling period) is completely observable if and only if for each couple λ_i, λ_j of eigenvalues of $\mathbf{A}$ having the same real part, it is:

$$\mathrm{Im}(\lambda_i - \lambda_j) \neq \frac{2k\pi}{T} \qquad\qquad k = \pm 1,\ \pm 2,\ \ldots$$

16. Given the discrete-time linear system $\mathbf{x}(k+1) = \mathbf{A}\mathbf{x}(k) + \mathbf{B}\mathbf{u}(k)$, write the structure of:

a) an *open loop* state estimator:

$$\hat{\mathbf{x}}(k+1) = \mathbf{A}\hat{\mathbf{x}}(k) + \mathbf{B}\mathbf{u}(k)$$

b) a *full order closed loop* state estimator:

$$\hat{\mathbf{x}}(k+1) = (\mathbf{A} + \mathbf{L}\mathbf{C})\hat{\mathbf{x}}(k) + \mathbf{B}\mathbf{u}(k) - \mathbf{L}\mathbf{y}(k)$$

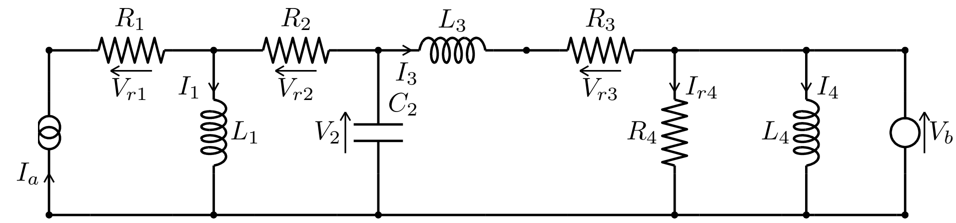
c) the time evolution of the estimation errors $\mathbf{e}(k) = \mathbf{x}(k) - \hat{\mathbf{x}}(k)$ in the two previous cases a) and b) starting from the initial condition $\mathbf{e}(0)$:

$$\mathbf{e}(k) = \mathbf{A}^k\mathbf{e}(0), \qquad\qquad \mathbf{e}(k) = (\mathbf{A} + \mathbf{L}\mathbf{C})^k\mathbf{e}(0)$$

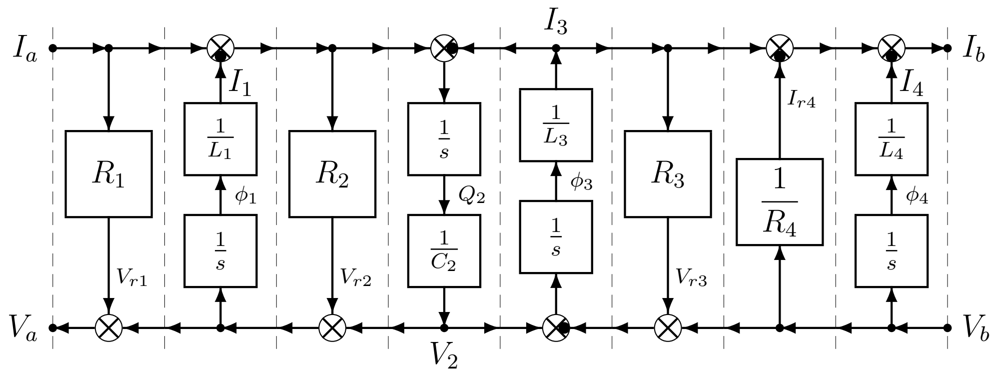
17. Write, within the following table, the symbols and the names of the energy variables and the power variables that characterize the Energetic Domain: **Electromagnetic**. Moreover, write the constitutive relation (both linear and nonlinear) and the differential equation which characterize the physical elements:

	Symbols	Constitutive Rel.	Linear Case	Differential Eq.
$\mathcal{D}_1$	C Capacity			
q_1	Q Charge	$Q = \Phi_C(V)$	$Q = C\,V$	$\frac{dQ}{dt} = I$
v_1	V Voltage			
$\mathcal{D}_2$	L Inductance			
q_2	ϕ Flux	$\phi = \Phi_L(I)$	$\phi = L\,I$	$\frac{d\phi}{dt} = V$
v_2	I Current			
$\mathcal{R}$	R Resistance	$V = \Phi_R(I)$	$V = R\,I$	

18. Consider the following electric circuit composed by the inductances L_1, L_3, L_4, the capacity C_2 and the resistances R_1, R_2, R_3 and R_4. Two inputs act on the system: the current I_a and the voltage V_b. The outputs of the system are: the voltage V_a and the current I_b.



The POG model of the given electric circuit has the following structure:



Let $\mathbf{x} = \begin{bmatrix} I_1 & V_2 & I_3 & I_4 \end{bmatrix}^{\mathrm{T}}$ be the state vector, $\mathbf{u} = \begin{bmatrix} I_a & V_b \end{bmatrix}^{\mathrm{T}}$ the input vector and $\mathbf{y} = \begin{bmatrix} V_a & I_b \end{bmatrix}^{\mathrm{T}}$ the output vector. Write the corresponding dynamic system $\overline{\mathbf{L}}\dot{\mathbf{x}} = \overline{\mathbf{A}}\mathbf{x} + \overline{\mathbf{B}}\mathbf{u}$ and $\mathbf{y} = \overline{\mathbf{C}}\mathbf{x} + \overline{\mathbf{D}}\mathbf{u}$ in the state space:

$$\underbrace{\begin{bmatrix} L_1 & 0 & 0 & 0 \\ 0 & C_2 & 0 & 0 \\ 0 & 0 & L_3 & 0 \\ 0 & 0 & 0 & L_4 \end{bmatrix}}_{\overline{\mathbf{L}}} \underbrace{\begin{bmatrix} \dot{I}_1 \\ \dot{V}_2 \\ \dot{I}_3 \\ \dot{I}_4 \end{bmatrix}}_{\dot{\mathbf{x}}} = \underbrace{\begin{bmatrix} -R_2 & 1 & 0 & 0 \\ -1 & 0 & -1 & 0 \\ 0 & 1 & -R_3 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix}}_{\overline{\mathbf{A}}} \underbrace{\begin{bmatrix} I_1 \\ V_2 \\ I_3 \\ I_4 \end{bmatrix}}_{\mathbf{x}} + \underbrace{\begin{bmatrix} R_2 & 0 \\ 1 & 0 \\ 0 & -1 \\ 0 & 1 \end{bmatrix}}_{\overline{\mathbf{B}}} \underbrace{\begin{bmatrix} I_a \\ V_b \end{bmatrix}}_{\mathbf{u}}$$

$$\underbrace{\begin{bmatrix} V_a \\ I_b \end{bmatrix}}_{\mathbf{y}} = \underbrace{\begin{bmatrix} -R_2 & 1 & 0 & 0 \\ 0 & 0 & 1 & -1 \end{bmatrix}}_{\overline{\mathbf{C}}} \mathbf{x} + \underbrace{\begin{bmatrix} R_1 + R_2 & 0 \\ 0 & -\frac{1}{R_4} \end{bmatrix}}_{\overline{\mathbf{D}}} \underbrace{\begin{bmatrix} I_a \\ V_b \end{bmatrix}}_{\mathbf{u}}$$

19. Write the direct Lyapunov stability criterion for discrete-time nonlinear systems.

Consider the nonlinear system $\mathbf{x}(k+1) = \mathbf{f}(\mathbf{x}(k), \mathbf{u}_0)$ *and let* $\mathbf{x}_0$ *an equilibrium point corresponding to the constant input* $\mathbf{u}_0$.

1) If in a neighborhood W *of point* $\mathbf{x}_0$ *it exists a continuous function* $V(\mathbf{x}) : W \to \mathcal{R}$ positive definite *and if the function* $\Delta V(\mathbf{x})$ *is* negative semidefinite, *then the point* $\mathbf{x}_0$ *is* stable. *If the function* $\Delta V(\mathbf{x})$ *is* negative definite, *then the point* $\mathbf{x}_0$ *is* asymptotically stable.

20. Which of the following functions $V(x_1, x_2)$ are positive definite in the vicinity of the origin?

- ⊗ $V(x_1, x_2) = x_1^2(1 - x_1^2) + x_2^2(1 - x_2^2)$;
- ○ $V(x_1, x_2) = x_1^2 + x_2^2 + x_1 + x_2$;
- ○ $V(x_1, x_2) = x_1^2 \sin(x_2) + x_2^2 \sin(x_1)$;
- ⊗ $V(x_1, x_2) = x_1^2 \cos(x_2) + x_2^2 \cos(x_1)$;

21. Given the following nonlinear system $\dot{\mathbf{x}}(t) = \mathbf{f}(\mathbf{x})$, continuous-time and autonomous:

$$\begin{cases} \dot{x}_1 &= \alpha\, x_1 - x_1^3 \\ \dot{x}_2 &= x_1^4 - x_2^3 + \beta\, x_3 \\ \dot{x}_3 &= -\beta\, x_2 - \, x_3^3 \end{cases}$$

It is easy to verify that the origin $\mathbf{x}_0 = (0,\,0,\,0) = 0$ is an equilibrium point for the system.

a) Compute, as a function of parameters α and β, the Jacobian $\mathbf{A}(\mathbf{x})$ of the nonlinear system:

The Jacobian $\mathbf{A}(\mathbf{x})$ has the following structure:

$$\mathbf{A}(\mathbf{x}) = \frac{\partial \mathbf{f}(\mathbf{x})}{\partial \mathbf{x}} = \begin{bmatrix} \alpha - 3x_1^2 & 0 & 0 \\ 4x_1^3 & -3x_2^2 & \beta \\ 0 & -\beta & -3x_3^2 \end{bmatrix}$$

b) Compute, as a function of α and β, the matrix $\mathbf{A}_0$ of the linearized system at point $\mathbf{x}_0 = 0$:

The matrix $\mathbf{A}_0$ of the linearized system has the following structure:

$$\mathbf{A}_0 = \begin{bmatrix} \alpha & 0 & 0 \\ 0 & 0 & \beta \\ 0 & -\beta & 0 \end{bmatrix}$$

c) Study, for varying α and β, the stability of the nonlinear system in the neighborhood of point $\mathbf{x}_0 = 0$ using the reduced Lyapunov criterion:

The eigenvalues of matrix $\mathbf{A}_0$ are:

$$\lambda_1 = \alpha, \qquad \lambda_{2,3} = \pm j\beta.$$

Using the reduced Lyapunov criterion it can be stated that: 1) for $\alpha > 0$ and $\forall\beta$ the equilibrium point $\mathbf{x}_0 = 0$ of the nonlinear system is unstable; 2) for $\alpha \leq 0$ and $\forall\beta$ the criterion cannot be used.

d) For $\alpha = 0$, study for varying parameter β the stability of the nonlinear system in the neighborhood of point $\mathbf{x}_0 = 0$ using the "direct" Lyapunov criterion and the function: $V(\mathbf{x}) = x_1^2 + x_2^2 + x_3^2$. Eventually, use the La Salle - Krasowskii criterion.

In the neighborhood of point $\mathbf{x}_0 = 0$ the function $V(\mathbf{x}) = x_1^2 + x_2^2 + x_3^2$ is positive definite. For $\alpha = 0$, the function $\dot{V}(\mathbf{x})$ computed along the system's trajectories is:

$$\begin{aligned} \dot{V}(\mathbf{x}) &= 2x_1(-x_1^3) + 2x_2(x_1^4 - x_2^3 + \beta\, x_3) + 2x_3(-\beta\, x_2 - \, x_3^3) \\ &= -2x_1^4(1 - x_2) - 2x_2^4 - 2\, x_3^4 < 0 \end{aligned}$$

In point $\mathbf{x}_0 = 0$ the function $\dot{V}(\mathbf{x})$ is negative definite and therefore, using the "direct" Lyapunov criterion, it can be stated that in the neighborhood of point $\mathbf{x}_0 = 0$ the nonlinear system is asymptotically stable for all the values of β.

22. Compute the 2 equilibrium points $\tilde{\mathbf{x}}_1$ and $\tilde{\mathbf{x}}_2$ of the following *discrete-time* nonlinear system:

$$\begin{cases} x_1(k+1) &= x_2(k) \\ x_2(k+1) &= x_1(k) + x_2(k)(x_1(k) + 3) \end{cases} \quad \underset{\mathbf{x}(k+1)=\mathbf{x}(k)}{\Rightarrow} \quad \begin{cases} \tilde{\mathbf{x}}_1 &= (\;0,\;\;0\;) \\ \tilde{\mathbf{x}}_2 &= (-3, -3\;) \end{cases}$$