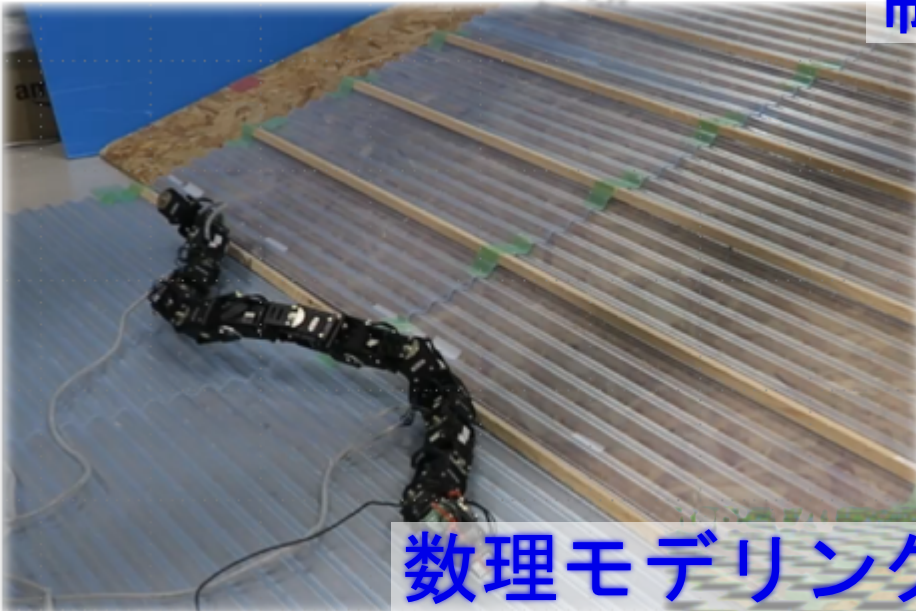
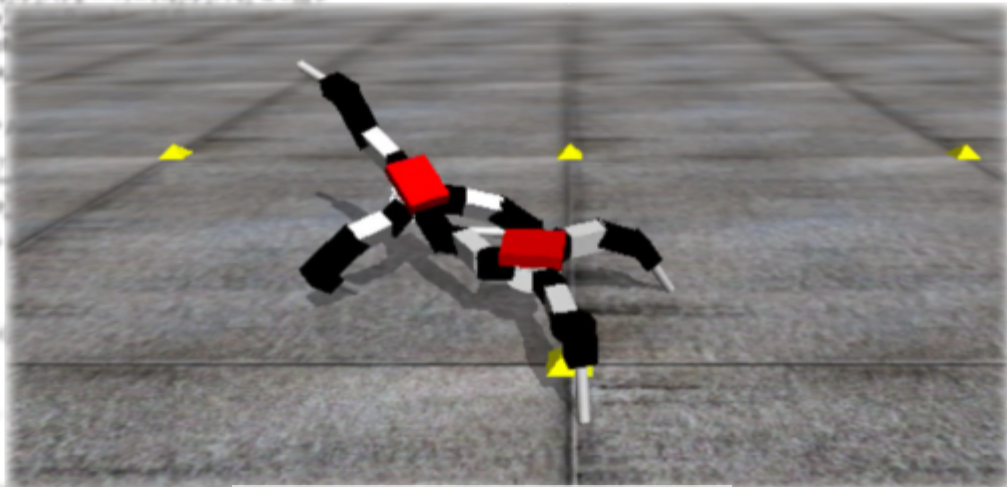


ロボットの「頭のいい」動きをデザインする 動きのデザインを科学する

制御工学



Therefore, if $\dot{x} = x_1 + x_2$, we have
 $\frac{dx_1}{dt} = x_2$
Let us choose p_1
and consider the be
 $\dot{x} = x_1 + x_2 + x_3 + \dots$
invariant
subset of
 $(\dot{x} = 0) =$
show that any
is invariant
 $\frac{d}{dt}(p_1^2 x_1) = \frac{dx_1}{dt} p_1^2 +$
 $= p_1^2 x_2 + p_1^2$
 $= (p_1^2 x_2 + p_1^2$
 $= p_1^2 (x_2 +$
and
(44) $p_1^2 x_1 = p_1^2 (x_1) +$
and
 $p_1^2 x_1 = -\frac{d}{dt} x_1$



数理モデリング

AI・機械学習

