

# Model Documentation of the N Integrator Chain

## 1 Nomenclature

### 1.1 Nomenclature for Model Equations

$u_1$  input

## 2 Model Equations

State Vector and Input Vector:

$$\underline{x} = (x_1 \ x_2 \ \dots \ x_n)^T$$
$$\underline{u} = u_1$$

Model Equations:

$$\dot{x}_1 = x_2 \tag{1a}$$

$$\dot{x}_2 = x_3 \tag{1b}$$

$$\dots \tag{1c}$$

$$\dot{x}_{n-1} = x_n \tag{1d}$$

$$\dot{x}_n = u_1 \tag{1e}$$

Parameters: *⟨not defined⟩*

Outputs: *⟨not defined⟩*

## 3 Derivation and Explanation

*Not available*

## References

- [1] Wang, X.; Saberi1, A.; Stoorvogel, A. A.; Grip, H. F.: *Control of a chain of integrators subject to actuator saturation and disturbances*, international journal of robust and nonlinear control, 2011