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   Nota di contenuto   1 Geometry of nonholonomic systems -- 2 First-order theory --
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                       flows of vector fields -- 5 Appendix B: The different systems of
                       privileged coordinates.

   Sommario/riassunto Nonholonomic systems are control systems which depend linearly on
                       the control. Their underlying geometry is the sub-Riemannian
                       geometry, which plays for these systems the same role as Euclidean
                       geometry does for linear systems. In particular the usual notions of
                       approximations at the first order, that are essential for control
                       purposes, have to be defined in terms of this geometry. The aim of
                       these notes is to present these notions of approximation and their
                       application to the motion planning problem for nonholonomic systems.