

CSE 591: Theoretical Aspects of CPS

Multi-affine control systems:
Tabuada Ch 8.4

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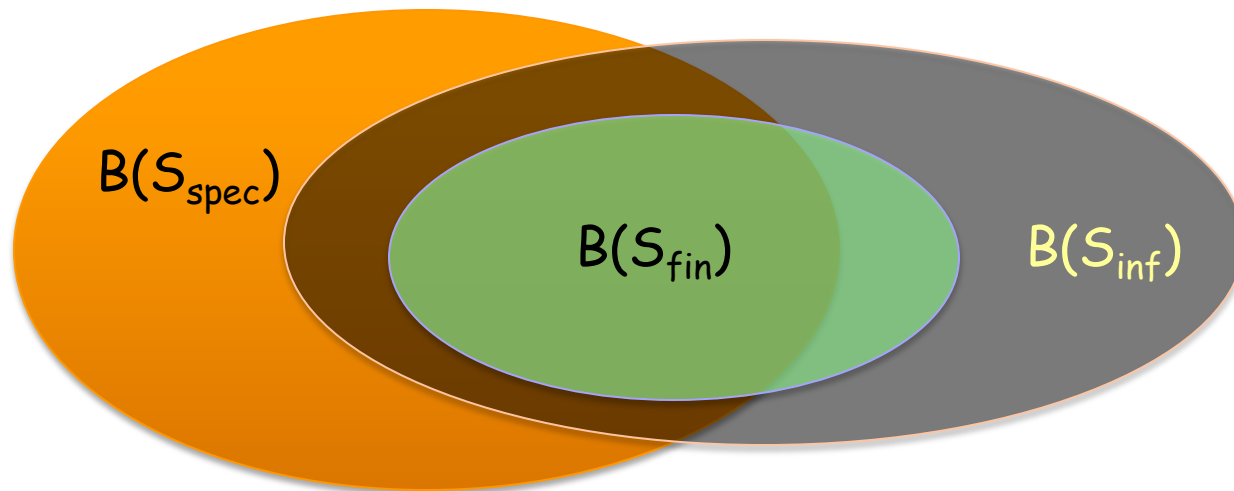
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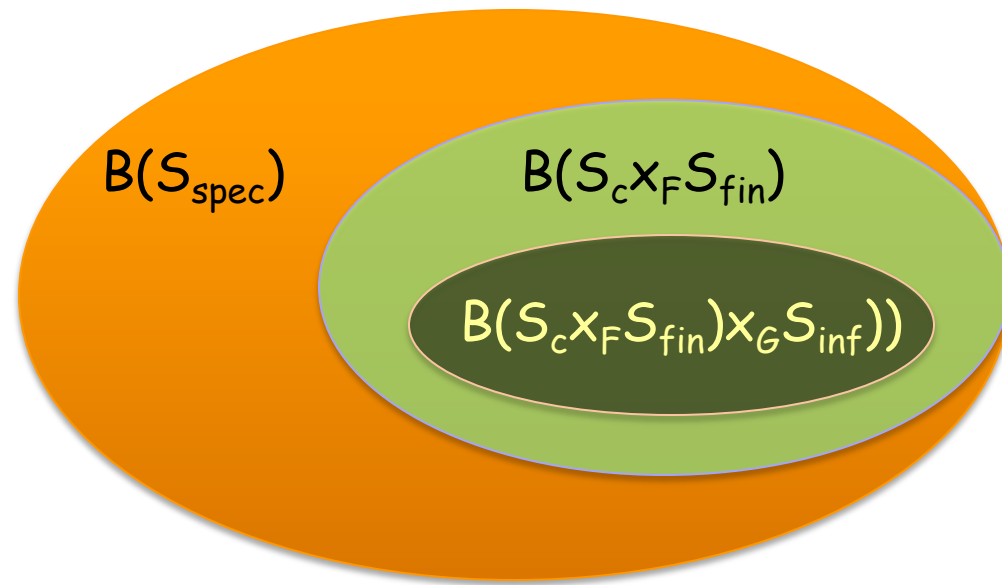
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Control through Refinement

- Given a infinite-state system S_{inf} , find a controller $S_{c'}$ such that $S_{c'} \times_F S_{inf}$ satisfies a specification S_{spec}
- In some cases, we can find a finite-state system S_{fin} such that $S_{fin} \preceq_{AS} S_{inf}$
- We know how to design a controller S_c for S_{fin} . How can we use S_c to control S_{inf} ?



Control through Refinement



Control problem

Initial
conditions

Goal Set

Control problem

	Initial conditions		
			Goal Set

Affine maps

- A function $f : \mathbb{R} \rightarrow \mathbb{R}$ is **affine** if $\forall x, y \in \mathbb{R}$ and $\forall \alpha, \beta \in \mathbb{R}$ s.t. $\alpha + \beta = 1$, we have $f(\alpha x + \beta y) = \alpha f(x) + \beta f(y)$
- Alternative def.: $f((1-\lambda)x + \lambda y) = (1-\lambda)f(x) + \lambda f(y)$ with $\lambda \in \mathbb{R}$
- Let $f : A_1 \times \dots \times A_n \rightarrow \mathbb{R}$ then $f_{\hat{a}_i} : A_i \rightarrow \mathbb{R}$ is a map obtained from f by fixing all the other coordinates
- A function $f : \mathbb{R}^n \rightarrow \mathbb{R}$ is multi-affine if $\forall i$ $f_{\hat{a}_i} : \mathbb{R} \rightarrow \mathbb{R}$ is affine
- A function $f : \mathbb{R}^n \rightarrow \mathbb{R}^m$ is multi-affine if $\forall i$ $f_{\hat{a}_i} : \mathbb{R}^n \rightarrow \mathbb{R}$ is multi-affine

Some results

- Proposition 8.17

Let E be an n -rectangle in \mathbb{R}^n and $f : \mathbb{R}^n \rightarrow \mathbb{R}^m$ be a multi-affine function, then:

$$x \in E \implies f(x) = \sum_{v \in V(E)} \lambda_v f(v) \text{ with } \sum_{v \in V(E)} \lambda_v = 1$$

- Proposition 8.18

Let E be an n -rectangle in \mathbb{R}^n and $g : V(E) \rightarrow \mathbb{R}^m$.

There exists a unique multi-affine function $f|_{V(E)} = g$

Multi-affine control system

- A system $\Sigma=(\mathbb{R}^n,U,f)$ is multi-affine control system if

$$f(x,u) = g(x)+B(u)$$

with $B \in \mathbb{R}^{n \times m}$ and $g : \mathbb{R}^n \rightarrow \mathbb{R}^m$ is a multi-affine function

- We write $\Sigma=(\mathbb{R}^n,U,g,B)$

Problem: Rectangular invariant

- Consider $\Sigma=(\mathbb{R}^n,U,g,B)$ and E an n -rectangle
- Does there exist a multi-affine feedback control law $k : \mathbb{R}^n \rightarrow \mathbb{R}^m$ s.t. any solution ξ of $(\mathbb{R}^n,U,g+Bk)$ satisfies $\xi(0) \in E \implies \xi(t) \in E$ for all t ?

Problem: Control to facet

- Let $\Sigma=(\mathbb{R}^n,U,g,B)$, E an n -rectangle and a facet F of E
- Does there exist a multi-affine feedback control law $k : \mathbb{R}^n \rightarrow \mathbb{R}^m$ s.t. any solution ξ of $(\mathbb{R}^n,U,g+Bk)$ satisfies
 - $\xi(0) \in E \implies \exists \tau > 0$ s.t.
 - $\xi(t) \in E$ for all $t \in [0, \tau)$
 - $\xi(\tau) \in F$
 - $\xi(t) \notin E \cup F$ for $t \in (\tau, \tau + \varepsilon]$

Theorem 8.22

- Consider $\Sigma=(\mathbb{R}^n,U,g,B)$ and E an n -rectangle
- The controller invariance problem is solvable if
- $\forall v \in V(E) . U_E(v) = \bigcap_{F \in F(v)} \{u \in \mathbb{R}^m \mid n_F^T (g(v)+Bu) < 0\} \neq \emptyset$

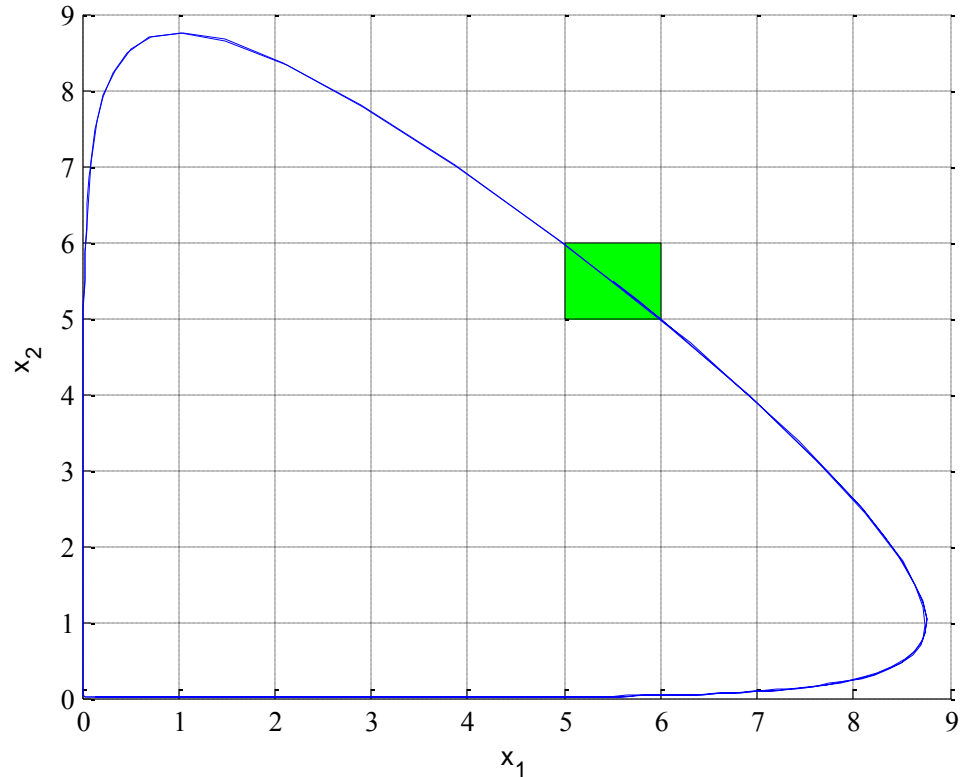
Theorem 8.23

- Consider $\Sigma=(\mathbb{R}^n,U,g,B)$, E an n -rectangle and F be a facet
- The control to facet problem is solvable if
- $\forall v \in V(E) . U_E(v) = \bigcap_{G \in F(v)} \{u \in \mathbb{R}^m \mid \eta_G^T (g(v)+Bu) < 0\} \neq \emptyset$
with $F \notin F(v)$
- $\forall v \in V(E) . U_E(v) = \bigcap_{G \in F(v), G \neq F} \{u \in \mathbb{R}^m \mid \eta_G^T (g(v)+Bu) < 0 \text{ and } \eta_F^T (g(v)+Bu) > 0\} \neq \emptyset$

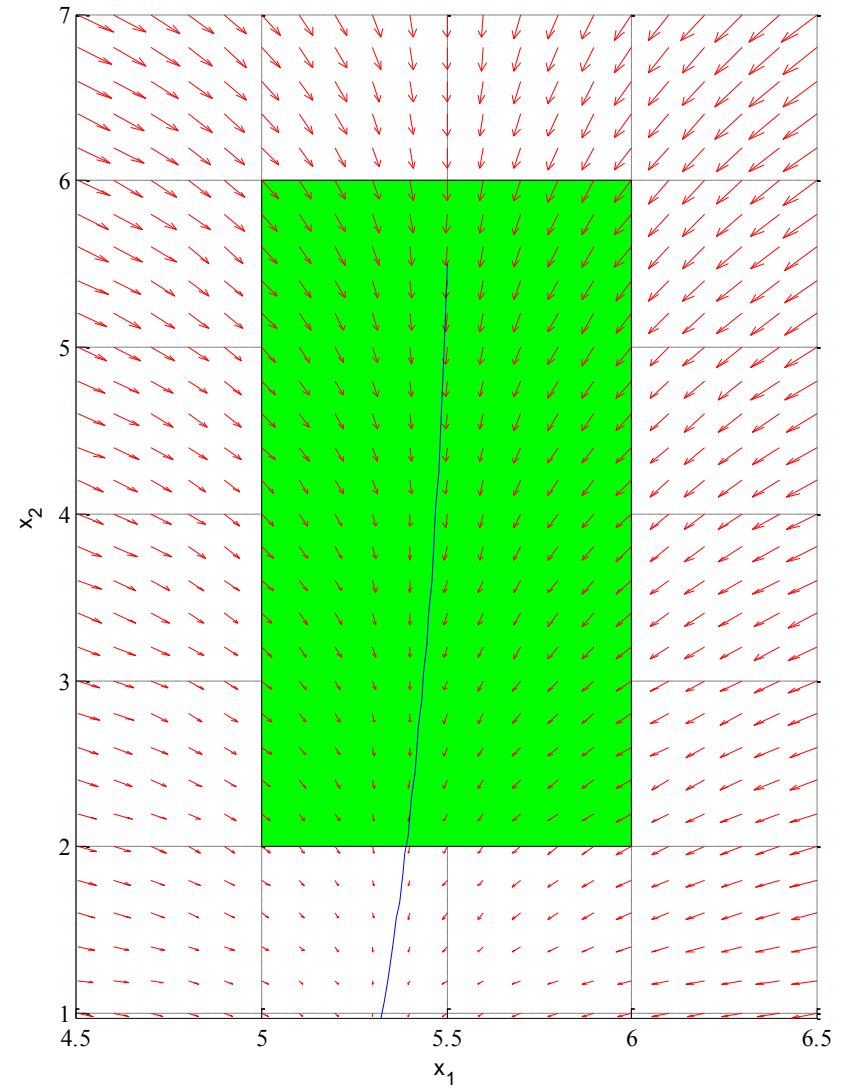
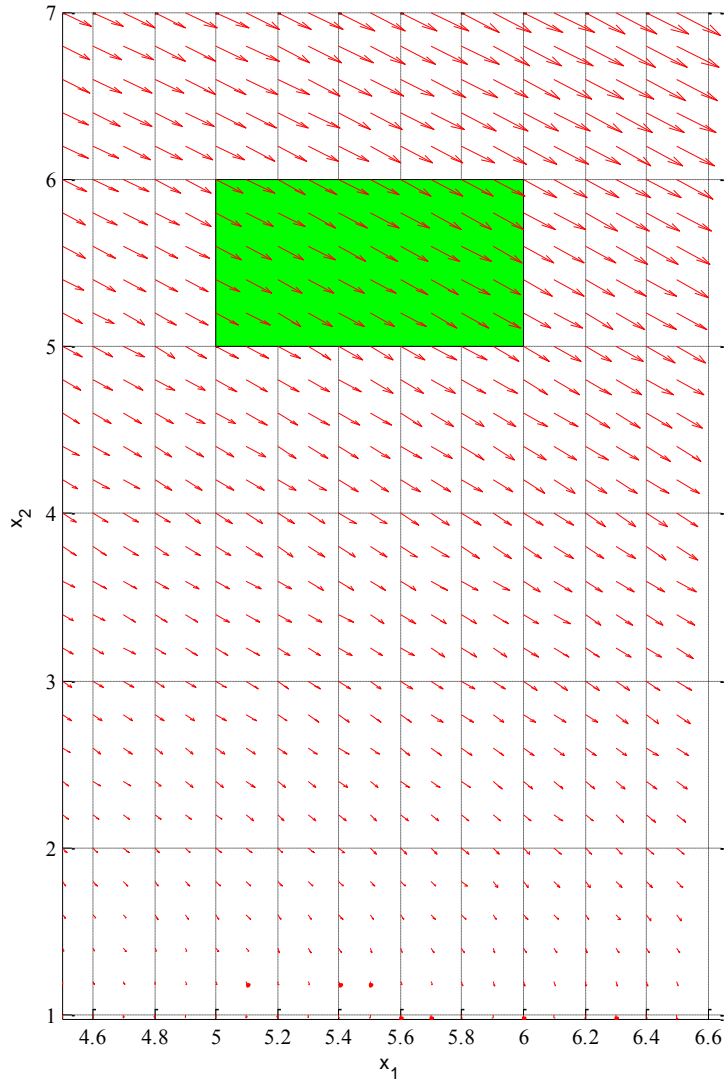
Example 8.24

$$\begin{aligned}\dot{\xi}_1 &= -\xi_1 + \xi_1\xi_2 - v \\ \dot{\xi}_2 &= \xi_2 + \xi_1\xi_2\end{aligned}$$

ξ_1 predators
 ξ_2 prays



Example 8.24



Finite state system

- $\Sigma = (\mathbb{R}^n, U, g, B)$ and let P be a partition that completes \mathcal{E}
- The system $S_\varepsilon = \{X_\varepsilon, U_\varepsilon, \rightarrow_\varepsilon, Y_\varepsilon, H_\varepsilon\}$, where
 1. $X_\varepsilon = \mathcal{E}$
 2. $U_\varepsilon = \mathcal{E}$
 3. $(x, x', x') \in \rightarrow_\varepsilon$ if
 1. $x = x'$ and the control invariance problem can be solved
 2. x, x' share a facet F and the control to facet problem is solvable
 4. $Y_\varepsilon = \mathbb{R}^n / Q$
 5. $H_\varepsilon(E) = P(E)$