



HAL
open science

Fixed-Time Output Stabilization and Fixed-Time Estimation of a Chain of Integrators

Francisco Lopez-Ramirez, Denis Efimov, Andrey Polyakov, Wilfrid Perruquetti

► **To cite this version:**

Francisco Lopez-Ramirez, Denis Efimov, Andrey Polyakov, Wilfrid Perruquetti. Fixed-Time Output Stabilization and Fixed-Time Estimation of a Chain of Integrators. *International Journal of Robust and Nonlinear Control*, 2018, 28 (16), pp.4647-4665. 10.1002/rnc.4275 . hal-01817585

HAL Id: hal-01817585

<https://inria.hal.science/hal-01817585>

Submitted on 18 Jun 2018

HAL is a multi-disciplinary open access archive for the deposit and dissemination of scientific research documents, whether they are published or not. The documents may come from teaching and research institutions in France or abroad, or from public or private research centers.

L'archive ouverte pluridisciplinaire **HAL**, est destinée au dépôt et à la diffusion de documents scientifiques de niveau recherche, publiés ou non, émanant des établissements d'enseignement et de recherche français ou étrangers, des laboratoires publics ou privés.

Fixed-Time Output Stabilization and Fixed-Time Estimation of a Chain of Integrators

Francisco Lopez-Ramirez^{a,b}, Denis Efimov^a, Andrey Polyakov^a and Wilfrid Perruquetti^{a,b}

^a*Inria, Non-A POST team, Parc Scientifique de la Haute Borne, 40 avenue Halley, 59650 Villeneuve d'Ascq, France.*

^b*CRISTAL (UMR-CNRS 9189), École Centrale de Lille, Cité Scientifique, 59651 Villeneuve-d'Ascq, France.*

Abstract

A solution to the problem of global fixed-time output stabilization and estimation of a chain of integrators is proposed. A nonlinear scheme comprising a state feedback controller and a dynamic observer are designed in order to guarantee both fixed-time estimation and fixed-time control. Robustness with respect to exogenous disturbances and measurement noises is established and a parameter optimization algorithm is provided. The performance of the obtained control and estimation algorithms are illustrated by numeric experiments.

1. Introduction

Feedback stabilization of linear and nonlinear systems is one of the central problems in control systems theory. There are many methods to design a control [11, 25, 3], which differ in the requirements imposed on the plant model and on the guaranteed performance of the closed-loop system. Among performance criteria the robustness with respect to external disturbances or measurement noises and the rate of convergence are the most popular. To assess robustness of nonlinear systems the input-to-state stability theory is frequently used [24, 10]. The rate of convergence to the goal state or set can be asymptotic (e.g. exponential) or non-asymptotic, i.e. finite-time or fixed-time [17, 23, 19]. In the latter case the system converges from any initial conditions of the state space in a uniform finite time (see more rigorous definitions below).

The present work studies the problem of output feedback design providing a fixed-time rate of convergence for a chain of integrators [20]. The chain of integrators is a very versatile and well studied system since all linear controllable systems and many nonlinear ones can be transformed, through a linear coordinate transformation in the first case and through feedback linearization in the second, into this particular form [15, 8]. Fixed-time stability, i.e. globally bounded convergence rate, is a relatively recent topic [9, 2, 21] and in [4] a fixed-time feedback regulator for a chain of integrators is presented based on Lyapunov analysis. Here we present a full control scheme, endowed with a state and output feedback control as well as with a state observer, all of whom exhibit the fixed-time stability property. Instead of using a Lyapunov approach, the proposed solution is based on homogeneity theory [3, 5]; and contrarily to [20], the presented control has an explicit form. Fixed-Time stability of the chain of integrators has also been achieved in [14, 22]. In both works, a switching in the homogeneous degree is applied to obtain fixed-time stability, and while [14] uses a recursive controller to complete a homogeneous system, [22] uses the hybrid formulation. Nonetheless, to the best of our knowledge, there is not any work that fully discloses the parameter tuning and its relationship with the settling-time estimates. In contrast, in this article we provide a homogeneous non-recursive fixed-time output feedback controller and we provide a tuning algorithm, based on Linear Matrix Inequalities (LMI) and on the Implicit Lyapunov Function approach, that allows to assert fixed-time stability and to adjust the settling time. In addition, the obtained control and estimation algorithms do not have a complex computational structure usually inherited by the solutions based on the Implicit Lyapunov Function method.

A robustness analysis with respect to bounded external disturbances and measurement noises, based on previous results on homogeneous systems [6], is also carried out.

The outline of this paper is as follows: Notation and preliminary results are introduced in Sections 2 and 3. The precise problem statement is given in Section 4. The proposed algorithms are presented in Section 5 and the parameter optimization is treated in Section 6. Concluding remarks and the discussion appear in Section 7.

2. Notation

Throughout the paper the following notation is used:

- $\mathbb{R}_+ = \{x \in \mathbb{R} : x \geq 0\}$, where \mathbb{R} is the set of real numbers.
- $|\cdot|$ denotes the absolute value in \mathbb{R} , $\|\cdot\|$ denotes the Euclidean norm on \mathbb{R}^n , $\|x\|_{\mathcal{A}} = \inf_{\xi \in \mathcal{A}} \|x - \xi\|$ is the distance from a point $x \in \mathbb{R}^n$ to a set $\mathcal{A} \subset \mathbb{R}^n$; $\|A\|_2$ is the induced matrix norm for $A \in \mathbb{R}^{n \times n}$.
- For a (Lebesgue) measurable function $d : \mathbb{R}_+ \rightarrow \mathbb{R}^m$, we use $\|d\|_{[t_0, t_1]} = \text{ess sup}_{t \in [t_0, t_1]} \|d(t)\|$ to define the norm of $d(t)$ in the interval $[t_0, t_1]$, then $\|d\|_{\infty} = \|d\|_{[0, +\infty)}$ and the set of essentially bounded measurable functions $d(t)$ with the property $\|d\|_{\infty} < +\infty$ is further denoted as \mathcal{L}_{∞} ; $\mathcal{L}_D = \{d \in \mathcal{L}_{\infty} : \|d\|_{\infty} \leq D\}$ for any $D > 0$.
- A continuous function $\alpha : \mathbb{R}_+ \rightarrow \mathbb{R}_+$ belongs to the class \mathcal{K} if $\alpha(0) = 0$ and the function is strictly increasing. The function $\alpha : \mathbb{R}_+ \rightarrow \mathbb{R}_+$ belongs to the class \mathcal{K}_{∞} if $\alpha \in \mathcal{K}$ and it is increasing to infinity. A continuous function $\beta : \mathbb{R}_+ \times \mathbb{R}_+ \rightarrow \mathbb{R}_+$ belongs to the class \mathcal{KL} if $\beta(\cdot, t) \in \mathcal{K}_{\infty}$ for each fixed $t \in \mathbb{R}_+$ and $\lim_{t \rightarrow +\infty} \beta(s, t) = 0$ for each fixed $s \in \mathbb{R}_+$.
- The notation $DV(x)f(x)$ stands for the directional derivative of a continuously differentiable function V with respect to the vector field f evaluated at point x .
- A series of integers $1, 2, \dots, n$ is denoted by $\overline{1, n}$.

3. Preliminaries

Consider the following nonlinear system

$$\dot{x}(t) = f(x(t), d(t)), \quad t \geq 0, \quad (1)$$

where $x(t) \in \mathbb{R}^n$ is the state, $d(t) \in \mathbb{R}^m$ is the input, $d \in \mathcal{L}_{\infty}$; $f : \mathbb{R}^{n+m} \rightarrow \mathbb{R}^n$ ensures forward existence of the system solutions at least locally, $f(0, 0) = 0$. For an initial condition $x_0 \in \mathbb{R}^n$ and input $d \in \mathcal{L}_{\infty}$ define the corresponding solution by $X(t, x_0, d)$ for any $t \geq 0$ for which the solution exists.

Following [23, 15, 19], let Ω be an open neighborhood of the origin in \mathbb{R}^n and $D > 0$.

Definition 3.1. At the steady state $x = 0$ the system (1) for $d \in \mathcal{L}_D$ is said to be

- (a) *uniformly Lyapunov stable* if for any $x_0 \in \Omega$ and $d \in \mathcal{L}_D$ the solution $X(t, x_0, d)$ is defined for all $t \geq 0$, and for any $\epsilon > 0$ there is $\delta > 0$ such that for any $x_0 \in \Omega$, if $\|x_0\| \leq \delta$ then $\|X(t, x_0, d)\| \leq \epsilon$ for all $t \geq 0$;
- (b) *uniformly asymptotically stable* if it is uniformly Lyapunov stable and for any $\kappa > 0$ and $\epsilon > 0$ there exists $T(\kappa, \epsilon) \geq 0$ such that for any $x_0 \in \Omega$ and $d \in \mathcal{L}_D$, if $\|x_0\| \leq \kappa$ then $\|X(t, x_0, d)\| \leq \epsilon$ for all $t \geq T(\kappa, \epsilon)$;
- (c) *uniformly finite-time stable* if it is uniformly Lyapunov stable and *uniformly finite-time converging from Ω* , i.e. for any $x_0 \in \Omega$ and all $d \in \mathcal{L}_D$ there exists $0 \leq T < +\infty$ such that $X(t, x_0, d) = 0$ for all $t \geq T$. The function $T_0(x_0) = \inf\{T \geq 0 : X(t, x_0, d) = 0 \forall t \geq T, \forall d \in \mathcal{L}_D\}$ is called the *uniform settling time* of the system (1);
- (d) *uniformly fixed-time stable* if it is uniformly finite-time stable and $\sup_{x_0 \in \Omega} T_0(x_0) < +\infty$.

The set Ω is called the *domain of stability/attraction*.

If $\Omega = \mathbb{R}^n$, then the corresponding properties are called *global* uniform Lyapunov/asymptotic/finite-time/fixed-time stability of (1) for $d \in \mathcal{L}_D$ at $x = 0$.

Stability notions can be similarly defined with respect to a set, by replacing the distance to the origin in Definition 3.1 with the distance to an invariant set. For example, the global uniform finite-time stability with respect to a set $\mathcal{A} \subset \mathbb{R}^n$ is equivalent to the following two properties:

- (i) *uniform Lyapunov stability*: for any $x_0 \in \mathbb{R}^n$ and $d \in \mathcal{L}_D$ the solution $X(t, x_0, d)$ is defined for all $t \geq 0$, and for any $\epsilon > 0$ there is $\delta > 0$ such that if $\|x_0\|_{\mathcal{A}} \leq \delta$ then $\|X(t, x_0, d)\|_{\mathcal{A}} \leq \epsilon$ for all $t \geq 0$;
- (ii) *uniform finite-time convergence*: for any $x_0 \in \mathbb{R}^n$ and all $d \in \mathcal{L}_D$ there exists $0 \leq T < +\infty$ such that $\|X(t, x_0, d)\|_{\mathcal{A}} = 0$ for all $t \geq T$.

3.1. Input-to-state stability

More details about this theory can be found in [10].

Definition 3.2. The system (1) is called *input-to-state practically stable (ISpS)*, if for any input $d \in \mathcal{L}_\infty$ and any $x_0 \in \mathbb{R}^n$ there are some functions $\beta \in \mathcal{KL}$, $\gamma \in \mathcal{K}$ and $c \geq 0$ such that

$$\|X(t, x_0, d)\| \leq \beta(\|x_0\|, t) + \gamma(\|d\|_{[0,t]}) + c \quad \forall t \geq 0.$$

The function γ is called *nonlinear asymptotic gain*. The system is called *input-to-state stable (ISS)* if $c = 0$.

Definition 3.3. A smooth function $V : \mathbb{R}^n \rightarrow \mathbb{R}_+$ is called *ISpS Lyapunov function* for the system (1) if for all $x \in \mathbb{R}^n$, $d \in \mathbb{R}^m$ and some $r \geq 0$, $\alpha_1, \alpha_2, \alpha_3 \in \mathcal{K}_\infty$ and $\theta \in \mathcal{K}$:

$$\begin{aligned} \alpha_1(\|x\|) &\leq V(x) \leq \alpha_2(\|x\|), \\ DV(x)f(x, d) &\leq r + \theta(\|d\|) - \alpha_3(\|x\|). \end{aligned}$$

Such a function V is called *ISS Lyapunov function* if $r = 0$.

Note that an ISS Lyapunov function can also satisfy the following equivalent condition for some $\chi \in \mathcal{K}_\infty$:

$$\|x\| > \chi(\|d\|) \Rightarrow DV(x)f(x, d) \leq -\alpha_3(\|x\|).$$

Theorem 3.1. *The system (1) is ISS (ISpS) if and only if it admits an ISS (ISpS) Lyapunov function.*

3.2. Weighted homogeneity

Following [3, 26], for strictly positive numbers r_i , $i = \overline{1, n}$ called weights and $\lambda > 0$, one can define:

- the *vector of weights* $r = (r_1, \dots, r_n)^T$, $r_{\max} = \max_{1 \leq j \leq n} r_j$ and $r_{\min} = \min_{1 \leq j \leq n} r_j$;
- the *dilation matrix* function $\Lambda_r(\lambda) = \text{diag}\{\lambda^{r_i}\}_{i=1}^n$; note that $\forall x \in \mathbb{R}^n$ and $\forall \lambda > 0$ we have $\Lambda_r(\lambda)x = (\lambda^{r_1}x_1, \dots, \lambda^{r_i}x_i, \dots, \lambda^{r_n}x_n)^T$;
- the r -homogeneous norm $\|x\|_r = (\sum_{i=1}^n |x_i|^{\frac{r}{r_i}})^{\frac{1}{r}}$ for any $x \in \mathbb{R}^n$ and $\rho \geq r_{\max}$, hence there exist some $\underline{\sigma}, \bar{\sigma} \in \mathcal{K}_\infty$ such that
$$\underline{\sigma}(\|x\|_r) \leq \|x\| \leq \bar{\sigma}(\|x\|_r) \quad \forall x \in \mathbb{R}^n.$$
- the *unit sphere* and a *ball in the homogeneous norm* $S_r = \{x \in \mathbb{R}^n : \|x\|_r = 1\}$ and $\mathcal{B}_r(\rho) = \{x \in \mathbb{R}^n : \|x\|_r \leq \rho\}$ for $\rho \geq 0$.

Definition 3.4. A function $g : \mathbb{R}^n \rightarrow \mathbb{R}$ is r -homogeneous with degree $\eta \in \mathbb{R}$ if $\forall x \in \mathbb{R}^n$ and $\forall \lambda > 0$ we have:

$$\lambda^{-\eta}g(\Lambda_r(\lambda)x) = g(x).$$

A vector field $\phi : \mathbb{R}^n \rightarrow \mathbb{R}^n$ is r -homogeneous with degree $\nu \in \mathbb{R}$, with $\nu \geq -r_{\min}$ if $\forall x \in \mathbb{R}^n$ and $\forall \lambda > 0$ we have:

$$\lambda^{-\nu}\Lambda_r^{-1}(\lambda)\phi(\Lambda_r(\lambda)x) = \phi(x),$$

which is equivalent to the i -th component of ϕ being a r -homogeneous function of degree $r_i + \nu$.

The system (1) for $d = 0$ is r -homogeneous of degree ν if the vector field f is r -homogeneous of degree ν for $d = 0$.

The property of r -homogeneity can also be defined not for all $x \in \mathbb{R}^n$ but for a subset of the state space (or it can be approximately satisfied [1, 12]).

An important advantage of r -homogeneous systems is that their rate of convergence can be evaluated qualitatively based on their degree of homogeneity.

Lemma 3.1. [18] *If (1) for $d = 0$ is r -homogeneous of degree ν and asymptotically stable at the origin, then it is*

- (i) *globally finite-time stable at the origin if $\nu < 0$;*
- (ii) *globally exponentially stable at the origin if $\nu = 0$;*
- (iii) *globally fixed-time stable with respect to the unit ball $\mathcal{B}_r(1)$ if $\nu > 0$.*

Define $\tilde{f}(x, d) = [f(x, d)^T \ 0_m]^T \in \mathbb{R}^{n+m}$, it is an extended auxiliary vector field for the system (1), where 0_m is the zero vector of dimension m .

Theorem 3.2. [6] *Let the vector field \tilde{f} be homogeneous with the weights $r = [r_1, \dots, r_n]^T > 0$, $\tilde{r} = [\tilde{r}_1, \dots, \tilde{r}_m]^T > 0$ with a degree $\nu \geq -r_{\min}$, i.e. $f(\Lambda_r(\lambda)x, \Lambda_{\tilde{r}}(\lambda)d) = \lambda^\nu \Lambda_r(\lambda)f(x, d)$ for all $x \in \mathbb{R}^n$, $d \in \mathbb{R}^m$ and all $\lambda > 0$. Assume that the system (1) is globally asymptotically stable for $d = 0$, then the system (1) is ISS.*

Therefore, for the homogeneous system (1), its ISS property follows from its asymptotic stability for $d = 0$ (as for linear systems [10]).

3.3. Implicit Lyapunov Function Method

Theorem 3.3. [21] *If there exist two continuous functions $Q_i : \mathbb{R}_+ \times \mathbb{R}^n \rightarrow \mathbb{R}$, $i = \{1, 2\}$ such that:*

C1 $Q_i(V, x)$ are continuously differentiable on $\mathbb{R}_+ \times \mathbb{R}^n \setminus \{0\}$;

C2 for any $x \in \mathbb{R}^n \setminus \{0\}$ there exists $V > 0$ such that $Q_i(V, x) = 0$;

C3 for $\Omega = \{(V, x) \in \mathbb{R}^{n+1} : Q_i(V, x) = 0\}$ we have:

$$\lim_{\substack{x \rightarrow 0 \\ (V, x) \in \Omega}} V = 0, \quad \lim_{\substack{V \rightarrow 0^+ \\ (V, x) \in \Omega}} \|x\| = 0, \quad \lim_{\substack{\|x\| \rightarrow \infty \\ (V, x) \in \Omega}} V = +\infty;$$

C4 for all $V > 0$ and for all $x \in \mathbb{R}^n \setminus \{0\}$ the inequality $-\infty < \frac{\partial Q_i(V, x)}{\partial V} < 0$ holds;

C5 $Q_1(1, x) = Q_2(1, x)$, for all $x \in \mathbb{R}^n \setminus \{0\}$;

C6 $\frac{\partial Q_1(V, x)}{\partial x} f(t, x) \leq c_1 V^{1-\mu} \frac{\partial Q_1(V, x)}{\partial V}$, for all $t \in \mathbb{R}$, for all $V \in (0, 1]$, for all $x \in \{z \in \mathbb{R}^n \setminus \{0\} : Q_1(V, z) = 0\}$, where $c_1 > 0$ and $0 < \mu < 1$ are some constants;

C7 $\frac{\partial Q_2(V, x)}{\partial x} f(t, x) \leq c_2 V^{1+\nu} \frac{\partial Q_2(V, x)}{\partial V}$, for all $t \in \mathbb{R}$, for all $V \geq 1$ and for all $x \in \{z \in \mathbb{R}^n \setminus \{0\} : Q_2(V, z) = 0\}$, where $c_2 > 0$ and $\nu > 0$ are some constants.

Then the origin of (1) is fixed-time stable with the settling time estimate $T_0 \leq \frac{1}{c_1 \mu} + \frac{1}{c_2 \nu}$.

4. Problem statement

Consider a chain of integrators:

$$\begin{aligned} \dot{x}(t) &= A_0 x(t) + bu(t) + d(t), \quad t \geq 0, \\ y(t) &= Cx(t) + v(t), \end{aligned} \tag{2}$$

where $x(t) \in \mathbb{R}^n$ is the state vector, $u(t) \in \mathbb{R}$ is the control input, $y(t) \in \mathbb{R}$ is the measured output; $d(t) \in \mathbb{R}^n$ and $v(t) \in \mathbb{R}$ are the exogenous disturbance and the measurement noise, respectively, $(d, v) \in \mathcal{L}_\infty$ and the matrices

$$A_0 = \begin{bmatrix} 0 & 1 & 0 \dots 0 & 0 \\ 0 & 0 & 1 \dots 0 & 0 \\ \vdots & \vdots & \ddots & \vdots \\ 0 & 0 & 0 \dots 0 & 1 \\ 0 & 0 & 0 \dots 0 & 0 \end{bmatrix}, \quad b = \begin{bmatrix} 0 \\ \vdots \\ 0 \\ 1 \end{bmatrix}, \quad C = [1 \ 0 \dots 0],$$

are in the upper-diagonal canonical form.

It is required to design a stabilizing dynamic output control $u(t)$ that ensures the ISpS property of the system (1) for any $(d, v) \in \mathcal{L}_\infty$; and that for $d = v = 0$ provides global fixed-time stability of the closed-loop system at the origin.

5. Main result

The solution of the problem is divided in three steps. First, a state feedback is proposed ensuring the problem solution. Second, the equations of the observer are introduced. Third, a combined output feedback is presented and analyzed.

5.1. State feedback

For $i = \overline{1, n}$, $x_i \in \mathbb{R}$ and $\alpha > 0$ and denote $[x_i]^\alpha = |x_i|^\alpha \text{sign}(x_i)$, then the control proposed in this work has the form:

$$u(x) = \sum_{i=1}^n a_i [x_i]^{\alpha_i(\nu(\|x\|))}, \quad (3)$$

$$\alpha_i(\nu) = \frac{1 + n\nu}{1 + (i-1)\nu},$$

$$\nu(\omega) = \begin{cases} \nu_1 & \text{if } \omega \leq m, \\ \nu_2 & \text{if } \omega \geq M, \\ \frac{\nu_2 - \nu_1}{M - m} \omega + \frac{M\nu_1 - m\nu_2}{M - m} & \text{otherwise,} \end{cases} \quad (4)$$

where $a = [a_1, \dots, a_n] \in \mathbb{R}^{1 \times n}$ is the vector of control coefficients forming a Hurwitz polynomial, $-\infty < \nu_1 < 0 < \nu_2 < +\infty$ and $0 < m < M < +\infty$ are the tuning parameters to be defined later. Denote

$$r_i(\nu) = 1 + (i-1)\nu, \quad i = \overline{1, n}, \quad (5)$$

then it is straightforward to verify that for $d = 0$ the system (2), (3) is $r(\nu_1)$ -homogeneous of degree $\nu_1 < 0$ for $\|x\| \leq m$ and $r(\nu_2)$ -homogeneous of degree $\nu_2 > 0$ for $\|x\| \geq M$. Let us show that for properly selected control parameters, the system (2), (3) is globally fixed-time stable at the origin.

Lemma 5.1. *Let $a \in \mathbb{R}^n$ form a Hurwitz polynomial, then for any $0 < m < M < +\infty$ there exists $\tau \in (0, n^{-1})$ such that if $\nu_1 \in (-\tau, 0)$ and $\nu_2 \in (0, \tau)$ then the system (2), (3) for $d = 0$ is globally fixed-time stable at the origin.*

Proof. Denote

$$A = A_0 + ba = \begin{bmatrix} 0 & 1 & 0 & \dots & 0 & 0 \\ 0 & 0 & 1 & \dots & 0 & 0 \\ \vdots & \vdots & \vdots & \ddots & \vdots & \vdots \\ 0 & 0 & 0 & \dots & 0 & 1 \\ a_1 & a_3 & a_3 & \dots & a_{n-1} & a_n \end{bmatrix},$$

then by the lemma conditions there are matrices $P \in \mathbb{R}^{n \times n}$ and $Q \in \mathbb{R}^{n \times n}$ such that

$$P = P^T > 0, \quad Q = Q^T > 0, \quad A^T P + PA = -Q.$$

Following [7] consider for (2), (3) a Lyapunov function

$$V(x) = x^T P x,$$

whose derivative admits a differential equation:

$$\dot{V}(x) = DV(x)[A_0 x + bu(x)] = -x^T Q x + 2x^T P b \delta(x),$$

where $\delta(x) = \sum_{i=1}^n a_i ([x_i]^{\alpha_i(\nu(\|x\|))} - x_i)$. By construction, $\nu(\|x\|) = 0$ for $\|x\| = \mu = \frac{m\nu_2 - M\nu_1}{\nu_2 - \nu_1}$. Since $\delta : \mathbb{R}^n \rightarrow \mathbb{R}$ is a continuous function and $\nu : \mathbb{R}_+ \rightarrow [\nu_1, \nu_2]$, it is possible to select the values of ν_1 and ν_2 sufficiently close to zero such that $|\delta(x)|$ stays small enough, and therefore $\dot{V}(x) < 0$, on any compact containing the level $\|x\| = \mu$. Thus, there exists $\tau \in (0, n^{-1})$ (if $\tau \geq n^{-1}$ then $\alpha_i(\nu(\|x\|))$ may become non-positive) such that with $\nu_1 \in (-\tau, 0)$ and $\nu_2 \in (0, \tau)$ for all $x \in \{x \in \mathbb{R}^n : \underline{m} \leq \|x\| \leq \overline{M}\}$ we have $\dot{V}(x) < 0$ for any selection of $0 < \underline{m} < m < M < \overline{M} < +\infty$. Using the arguments of [7] and Lemma 3.1, we can prove in this case that the system is $r(\nu_1)$ -homogeneous of degree $\nu_1 < 0$ and fixed-time stable at the origin from $\mathcal{B}_{r(\nu_1)}(\rho_1)$ for

$\mathcal{B}_{r(\nu_1)}(\rho_1) \subset \{x \in \mathbb{R}^n : \|x\| \leq m\}$, and it is $r(\nu_2)$ -homogeneous of degree $\nu_2 > 0$ and globally fixed-time stable with respect to any ball $\mathcal{B}_{r(\nu_2)}(\rho_2)$ such that $\{x \in \mathbb{R}^n : \|x\| = M\} \subset \mathcal{B}_{r(\nu_2)}(\rho_2)$. The constants $\tau, \underline{m}, \overline{M}$ can be selected in a way that $\mathcal{B}_{r(\nu_1)}(\rho_1) \subset \{x \in \mathbb{R}^n : \underline{m} \leq \|x\| \leq m\}$ and $\mathcal{B}_{r(\nu_2)}(\rho_2) \subset \{x \in \mathbb{R}^n : M \leq \|x\| \leq \overline{M}\}$, then (2), (3) is globally convergent and it is globally fixed-time stable at the origin (the time that the system spent in the set $\{x \in \mathbb{R}^n : \underline{m} \leq \|x\| \leq \overline{M}\}$ is finite). \square

In order to analyze robust stability properties of the closed loop dynamics (2), (3) let us introduce

$$f_\nu(x, \tilde{d}) = A_0 x + b \sum_{i=1}^n a_i \left[x_i + \tilde{d}_{1,i} \right]^{\alpha_i(\nu)} + \tilde{d}_2,$$

where $\tilde{d} = [\tilde{d}_1^T \ \tilde{d}_2^T]^T \in \mathbb{R}^{2n}$ is the new disturbance input, \tilde{d}_1 represents measurements noises and $\tilde{d}_2 = d$.

Corollary 5.1. *Let all conditions of Lemma 5.1 be satisfied, then the system (2), (3) is ISpS for any $\tilde{d} \in \mathcal{L}_\infty$.*

Proof. Consider the system (2), (3) for $\|x\| \geq M$, and $\dot{x} = f_{\nu_2}(x, \tilde{d})$ is the corresponding approximating system, which is $r(\nu_2)$ -homogeneous of degree $\nu_2 > 0$ and globally fixed-time stable with respect to any ball $\mathcal{B}_{r(\nu_2)}(\rho)$ with $\rho > 0$ for $\tilde{d} = 0$. Take $\tilde{r} = \begin{bmatrix} r(\nu_2) \\ r(\nu_2) + \nu_2 \end{bmatrix}$, then $f_{\nu_2}(\Lambda_r(\lambda)x, \Lambda_{\tilde{r}}(\lambda)\tilde{d}) = \lambda^\nu \Lambda_r(\lambda) f_{\nu_2}(x, \tilde{d})$ for all $x \in \mathbb{R}^n$, $\tilde{d} \in \mathbb{R}^{2n}$ and all $\lambda > 0$. Consequently, if all conditions of Lemma 5.1 are satisfied, then also all conditions of Theorem 3.2 are true and the system $\dot{x} = f_{\nu_2}(x, \tilde{d})$ is ISS with respect to $d \in \mathcal{L}_\infty$. Since $\dot{x} = f_{\nu_2}(x, \tilde{d})$ is the approximation of (2), (3) for $\|x\| \geq M$, then (2), (3) (the system $\dot{x} = f_{\nu(\|x\|)}(x, \tilde{d})$) is ISpS. \square

Thus, the presented state control (3) solves the posed problem of robust global fixed-time stabilization for the system (2). Obviously, for any $R \in \mathbb{R}^{n \times n}$, $R = R^T > 0$ the system (2), (3) with $\nu(\|x\|_R)$, where $\|x\|_R = \sqrt{x^T R x}$, possesses the same properties as (2), (3) with $\nu(\|x\|)$.

5.2. State observer

To explain the observer structure, let us first consider the case $d = v = 0$, then the proposed observer takes the form (see also [9, 2, 22]):

$$\begin{aligned} \dot{z}(t) &= A_0 z(t) + bu(t) + k(\nu(\zeta(t)), y(t) - Cz(t)), \\ k_i(\nu, e) &= L_i [e]^{\beta_i(\nu)}, \quad \beta_i(\nu) = 1 + i\nu \quad i = \overline{1, n}, \\ \dot{\zeta}(t) &= -0.5\zeta(t) + p(\nu(\zeta(t)), y(t) - Cz(t)), \\ p(\nu, e) &= 4\kappa^T(\nu, e)P\kappa(\nu, e), \quad \kappa(\nu, e) = Le - k(\nu, e), \end{aligned} \tag{6}$$

where $z(t) \in \mathbb{R}^n$ is the state estimate, $\zeta(t) \in \mathbb{R}_+$ is an auxiliary time function; the function ν is given in (4) with $-\infty < \nu_1 < 0 < \nu_2 < +\infty$ and $0 < m < M < +\infty$, are, as previously, the tuning parameters; $L = [L_1, \dots, L_n]^T$ is the vector of coefficients of the observer providing Hurwitz property of the matrix $A_0 - LC$; $P \in \mathbb{R}^{n \times n}$ is a matrix solution of the equations

$$P = P^T > 0, \quad (A_0 - LC)^T P + P(A_0 - LC) = -P.$$

In [2] instead of using an auxiliary ζ -filter to commute the right-hand sides of (6) with negative and positive homogeneity degree, a time switching between two systems with positive and negative homogeneity degree is proposed. In [22], in order to switch between observers with negative and positive homogeneity degrees, a comparison of output estimation errors for these observers is used.

Lemma 5.2. *Let $A_0 - LC$ be a Hurwitz matrix for a given $L \in \mathbb{R}^{n \times 1}$ and assume that the solutions of (2) are defined for all $t \geq 0$, then for any $0 < m < M < +\infty$ there exists $\tau \in (0, n^{-1})$ such that if $\nu_1 \in (-\tau, 0)$ and $\nu_2 \in (0, \tau)$ then the system (2), (6) for $d = v = 0$ is globally Lyapunov stable and fixed-time convergent with respect to the set $\mathcal{A} = \{(x, z, \zeta) \in \mathbb{R}^{2n+1} : x = z, \|\zeta\| \leq M\}$ for all $(x, z) \in \mathbb{R}^{2n}$, provided that $\zeta(0) > M$ is sufficiently big.*

A more precise restriction on the value of $\zeta(0)$ is given in the proof of this lemma, it is not related with the initial conditions $x(0), z(0)$, see (9).

Proof. Denote $e = x - z$ as the estimation error, then

$$\begin{aligned}\dot{e} &= A_0 e - k(\nu(\zeta), Ce + v) + d \\ &= (A_0 - LC)e - k(\nu(\zeta), Ce + v) + L(Ce + v) + d - Lv \\ &= (A_0 - LC)e + \kappa(\nu(\zeta), Ce + v) + d - Lv.\end{aligned}$$

Consider a Lyapunov function $V(e) = e^T P e$, then

$$\begin{aligned}\dot{V} &= -V + 2e^T P[\kappa(\nu(\zeta), Ce + v) + d - Lv] \\ &\leq -0.5V + p(\nu(\zeta), Ce + v) + 4(d - Lv)^T P(d - Lv).\end{aligned}$$

For an auxiliary error variable $\psi = V - \zeta$ we obtain:

$$\dot{\psi} \leq -0.5\psi + 4(d - Lv)^T P(d - Lv)$$

and ψ is exponentially converging to zero (ζ is converging to V) if $d = v = 0$. In addition, if there is an instant of time $t' \geq 0$ such that $\psi(t') \geq 0$, then $\psi(t) \geq 0$ for all $t \geq t'$.

Repeating the arguments of Lemma 5.1, for any $0 < m < M < +\infty$ there exists $\tau \in (0, n^{-1})$ such that if $\nu_1 \in (-\tau, 0)$ and $\nu_2 \in (0, \tau)$ then the system

$$\dot{e} = A_0 e - k(\nu, Ce) \tag{7}$$

is globally asymptotically stable for any fixed value of $\nu \in [\nu_1, \nu_2]$. Moreover, for $\nu = \nu_1$ it is $r(\nu_1)$ -homogeneous of degree $\nu_1 < 0$ and globally finite-time stable at the origin, and for $\nu = \nu_2$ the system (7) is $r(\nu_2)$ -homogeneous of degree $\nu_2 > 0$ and globally fixed-time stable with respect to any ball $\mathcal{B}_{r(\nu_2)}(\rho)$ with $\rho > 0$. In addition,

$$\dot{V}(e) < 0 \quad \forall e \in \{e \in \mathbb{R}^n : \underline{m} \leq V(e) \leq \overline{M}\} \tag{8}$$

for any selection of $0 < \underline{m} < m < M < \overline{M} < +\infty$ and any (possibly time-varying) value of $\nu(\zeta(t)) \in [\nu_1, \nu_2]$.

Denote by $T_M > 0$ the uniform settling-time of convergence to the ball $\mathcal{B}_{r(\nu_2)}(\rho_M)$ of (7) for $\nu = \nu_2$, where $\rho_M > 0$ is such that $\{e \in \mathbb{R}^n : V(e) \leq M\} \subset \mathcal{B}_{r(\nu_2)}(\rho_M)$. Let

$$T_M < 2 \ln(\zeta(0) - M), \tag{9}$$

then $\zeta(t) \geq M$ for $t \in [0, t_M)$ with $t_M \geq T_M$ (t_M can also be infinite), therefore $\nu(\zeta(t)) = \nu_2$ for $t \in [0, t_M)$ from (4) and the estimation error dynamics is $r(\nu_2)$ -homogeneous and fixed-time stable with respect to the ball $\mathcal{B}_{r(\nu_2)}(\rho_M)$ on this interval of time. Since $t_M \geq T_M$, then the system (7) with $\nu = \nu(\zeta(t))$ enters in the ball $\mathcal{B}_{r(\nu_2)}(\rho_M)$ and there is an instant of time $t' \in [0, t_M)$ such that $\psi(t) \geq 0$ for all $t \geq t'$ (i.e. $\zeta(t) \geq V(e(t))$ for all $t \geq t'$). Next, due to (8), the system (7) with $\nu = \nu(\zeta(t))$ reaches the set $\{e \in \mathbb{R}^n : V(e) \leq \overline{m}\}$ in a finite time $T_m > T_M$, where it stays for all $t \geq T_m$. By the properties of dynamics of ψ and ζ , the instant $t_M < +\infty$ and there is another time instant $t_m \geq \max\{t', T_m\}$ such that $\zeta(t) \leq m$ for all $t \geq t_m$ ($\zeta(t)$ is exponentially approaching $V(e(t))$ from above, while $V(e(t)) \leq \overline{m} < m$ for $t \geq T_m$). Consequently, $\nu(\zeta(t)) = \nu_1$ for $t \geq t_m$ and it reaches for the origin in a uniform time. Summarizing the arguments we obtain that the system (7) with $\nu = \nu(\zeta(t))$ is globally fixed-time stable at the origin if $d = v = 0$. The variable ζ is also bounded and exponentially converging to zero. \square

Corollary 5.2. *Let all conditions of Lemma 5.2 be satisfied, then the system (2), (6) is ISpS with respect to the set \mathcal{A} for any $(d, v) \in \mathcal{L}_\infty$.*

Proof. From the equation for ψ we have that:

$$V(t) \leq \zeta(t) + (V(0) - \zeta(0))e^{-0.5t} + 8\chi(\|v\|_\infty, \|d\|_\infty),$$

where $\sup_{t \geq 0} (d(t) - Lv(t))^T P(d(t) - Lv(t)) \leq \chi(\|v\|_\infty, \|d\|_\infty) = \|P\|_2(\|d\|_\infty^2 + \|L\|_2^2 \|v\|_\infty^2)$ and $\|\cdot\|_2$ is the induced matrix norm. Consider the set $\Upsilon_0 = \{(e, \zeta) \in \mathbb{R}^{n+1} : V(e) \geq M + \max\{0, V(0) - \zeta(0)\} + 8\chi(\|v\|_\infty, \|d\|_\infty)\}$. From the inequality above $\zeta(t) \geq M$ for $e(t) \in \Upsilon_0$. Thus, $\nu(t) = \nu_2$ if $e(t) \in \Upsilon_0$ and the estimation error dynamics takes the form:

$$\dot{e} = f(e, \tilde{d}) = A_0 e - k(\nu_2, Ce + \tilde{d}_1) + \tilde{d}_2.$$

Denote $\tilde{r} = \begin{bmatrix} r_1(\nu_2) \\ r(\nu_2) + \nu_2 \end{bmatrix}$, then $f(\Lambda_r(\lambda)e, \Lambda_{\tilde{r}}(\lambda)\tilde{d}) = \lambda^\nu \Lambda_r(\lambda)f(x, \tilde{d})$ for all $x \in \mathbb{R}^n$, $\tilde{d} \in \mathbb{R}^{n+1}$ and all $\lambda > 0$. Consequently, if all conditions of Lemma 5.2 are satisfied (the system $\dot{e} = f(e, 0)$ corresponds to (7)), then also all conditions of Theorem 3.2 are true and the system $\dot{e} = f(e, \tilde{d})$ is ISS with respect to $\tilde{d} \in \mathcal{L}_\infty$. Therefore, there exists an ISS Lyapunov function $W : \mathbb{R}^n \rightarrow \mathbb{R}_+$ (an alternative choice of W can be found in [6]) and some function ϱ of class \mathcal{K}_∞ such that $W(e) \geq \varrho(M + \max\{0, V(0) - \zeta(0)\} + 8\chi(\|v\|_\infty, \|d\|_\infty))$ implies that $e \in \Upsilon_0$. Then either an ISS estimate holds for W or $W(e) \leq \varrho(M + \max\{0, V(0) - \zeta(0)\} + 8\chi(\|v\|_\infty, \|d\|_\infty))$, which implies boundedness of W , and the same property for ζ . Consequently, all solutions of (6) are defined for all $t \geq 0$ ($x(t)$ is also defined for all $t \geq 0$ by conditions of Lemma 5.2). Then the term $(V(0) - \zeta(0))e^{-0.5t}$ can be skipped and the above consideration can be repeated for the set $\Upsilon = \{(e, \zeta) \in \mathbb{R}^{n+1} : V(e) \geq M + 8\chi(\|v\|_\infty, \|d\|_\infty)\}$ in order to prove ISpS with respect to the set \mathcal{A} of the system (2), (6). Obviously, the variable $\zeta(t)$ is also asymptotically bounded by $M + 16\chi(\|v\|_\infty, \|d\|_\infty)$ in this case. \square

5.3. Output feedback

The proposed dynamic output feedback consists in the application of the state feedback (3) with the state estimates generated by the observer (6):

$$u(z) = \sum_{i=1}^n a_i [z_i]^{\alpha_i(\nu(\|z\|))}, \quad (10)$$

then the dynamics of the closed-loop system (2), (6), (10) can be written in the coordinates x , $e = x - z$ and ζ as follows:

$$\begin{aligned} \dot{x} &= A_0 x + b \sum_{i=1}^n a_i [x_i - e_i]^{\alpha_i(\nu(\|x-e\|))} + d, \\ \dot{e} &= A_0 e - k(\nu(\zeta), Ce + v) + d, \\ \dot{\zeta} &= -0.5\zeta + p(\nu(\zeta), Ce + v). \end{aligned} \quad (11)$$

The main result is a direct consequence of lemmas 5.1, 5.2 and corollaries 5.1, 5.2.

Theorem 5.1. *Let the following conditions be satisfied:*

- (i) $a \in \mathbb{R}^{1 \times n}$ forms a Hurwitz polynomial;
- (ii) $A_0 - LC$ is a Hurwitz matrix for given $L \in \mathbb{R}^n$;
- (iii) $\zeta(0) > M$ is sufficiently big,

then for any $0 < m < M < +\infty$ there exists $\tau \in (0, n^{-1})$ such that for $\nu_1 \in (-\tau, 0)$ and $\nu_2 \in (0, \tau)$ the system (2), (6), (10) is

- 1) fixed-time converging with respect to the set $\{(x, z, \zeta) \in \mathbb{R}^{2n+1} : x = z = 0\}$ for $d = v = 0$ and for any initial conditions $(x(0), z(0)) \in \mathbb{R}^{2n}$,
- 2) ISpS for any $(d, v) \in \mathcal{L}_\infty$.

Proof. The system (11) is a cascade of the (e, ζ) - and x -dynamics. If $d = v = 0$ then (e, ζ) -subsystem is autonomous and globally fixed-time converging with respect to the set $\{(e, \zeta) \in \mathbb{R}^{n+1} : e = 0\}$ (with the uniform settling-time $T_o > 0$) according to Lemma 5.2. During the interval $[0, T_o]$ the system (2) has bounded trajectories due to the ISpS property with respect to measurement noises (estimation errors e) established in Corollary 5.1, and for $t \geq T_o$ the x -subsystem is also autonomous and globally fixed-time converging at the origin by Lemma 5.1.

For $(d, v) \in \mathcal{L}_\infty$ the ISpS property follows the results of corollaries 5.1, 5.2 and the cascade structure of (11). \square

In Theorem 5.1, the same parameters m , M , ν_1 and ν_2 have been selected for the controller (10) and for the observer (6) in order to keep the notation compact, however, they can be chosen differently in applications and the result of Theorem 5.1 stays correct.

Example 5.1. Let $n = 3$, $L = [1.5 \quad 1.01 \quad 0.25]^T$, $a = -2.5[1 \ 1 \ 1]$, $m = 1$, $M = 5$, $\nu_2 = -\nu_1 = 0.1$, $\zeta(0) = 5M$ and

$$P = \begin{bmatrix} 0.121 & -0.13 & 0.047 \\ -0.13 & 0.261 & -0.308 \\ 0.047 & -0.308 & 0.617 \end{bmatrix},$$

then all conditions of Theorem 5.1 are satisfied. We test first the system without any perturbations; the results are depicted in the upper plot of Figure 1 where the initial conditions of the system are $x_0 = (5, 10, 0)$ and those of the observer are $z_0 = (0, 0, 0)$. The solid color lines represent the actual state x while the dotted color lines represent the estimated state z . It can be seen how the estimated states converge rapidly to the actual states before converging both to zero. In the lower part of Figure 1 we can appreciate the elements of the control scheme, the upper and lower limits of the homogeneity degree M and n are shown as straight lines. The norm of the observed states $\|z\|$ is depicted in purple, while this norm is between M and m the control's degree of homogeneity lies over the line $\frac{\nu_2 - \nu_1}{M - m} \|z\| + \frac{M\nu_1 - m\nu_2}{M - m}$. In the case of the observer, the filter $\zeta(t)$ acts as the modulator of the observer's homogeneity degree. The control signal is shown in light blue.

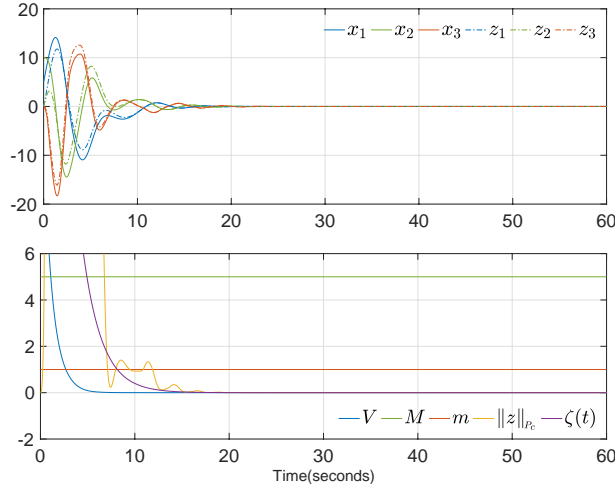


Figure 1: Results of simulation of (2), (6) and (10) for $n = 3$ without disturbances and with initial conditions $x_0 = (5, 10, 0)$.

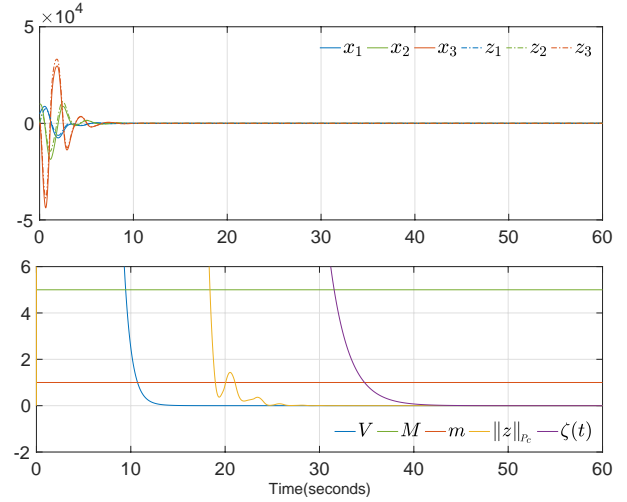


Figure 2: Results of simulation of (2), (6) and (10) for $n = 3$ with initial conditions $x_0 = 10^3(5, 10, 0)$.

Figure 2 shows the same setup with initial conditions $x_0 = 10^3(5, 10, 0)$, it can be seen that although the initial state is significantly larger, the settling time remains within the same interval, showing the expected uniformity w.r.t the initial state. In the lower part of the figure it can be seen that the control signal u grows considerably to cope with the conditions imposed. We next go back to the previous initial settings and introduce in the control scheme the disturbance

$$d(t) = \sin(2t) + \begin{cases} 10 & \text{if } t \in [30, 31] \\ 0 & \text{otherwise} \end{cases}. \quad (12)$$

The results are shown in Figure 3. We can notice that the system is robust against this disturbance and its effect in the control scheme elements are depicted in the lower plot of this figure. In particular we can see that the disturbance modifies both $\|z\|$ and $\zeta(t)$ therefore changing the homogeneity degree of both the controller and the observer.

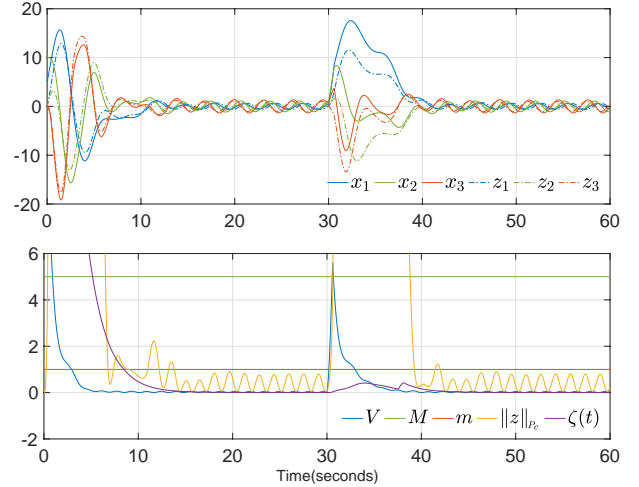


Figure 3: Simulation plots of (2), (6) and (10) for $n = 3$ with initial conditions $x_0 = (5, 10, 0)$ and the disturbance term (12).

Remark 5.1. Since in Theorem 5.1, the ISpS property with respect to d is proven, then considering d as a function of x and assuming that the norm of such a function is less than the asymptotic gain function of the system for x sufficiently large, it is possible to prove fixed-time convergence to a zone and global boundedness of the system solutions for a nonlinear system also in the closed-loop with the proposed control (10) and the observer (6).

6. Parameter Tuning

In this section we provide effective algorithms to tune the parameters involved in the feedback controller. Based on the concept of Implicit Lyapunov Functions [21], these algorithms transform the design procedure to an LMI feasibility problem, which simplifies significantly the practical applicability of the proposed method. In addition, they will provide an upper bound, even if conservative, of the settling time.

Consider the following implicit Lyapunov function candidate

$$Q(V, x) = x^T \Lambda_{r(\nu)}(V^{-1}) P \Lambda_{r(\nu)}(V^{-1}) x - 1, \quad (13)$$

where $V \in \mathbb{R}_+$, $x \in \mathbb{R}^n$, $P \in \mathbb{R}^{n \times n}$ and $P = P^T > 0$. Although this particular function possesses many properties¹, for the parametrization of the feedback controller and the state observer it will be sufficient to remark that $Q(1, x) = 0$ implies $x^T P x = 1$ and that the implicitly defined function $V(x)$ is r -homogeneous of degree 1.

6.1. Controller Parametrization

For brevity in the notation, the following representation of system (2), (3) will be used:

$$\dot{x} = A_0 x + b a [x]^{\alpha(\nu(\|x\|_P))}, \quad (14)$$

where $[x]^{\alpha(\nu)} = (|x_1|^{\alpha_1(\nu)} \text{sign}(x_1), \dots, |x_n|^{\alpha_n(\nu)} \text{sign}(x_n))^T$. Remark that without loss of generality, the usual norm of the argument of ν in control (3) has been replaced with a weighted one. Let us introduce the matrix $H_{r(\nu)} = -\text{diag}(r_1(\nu), r_2(\nu), \dots, r_n(\nu))$. When ν takes a fixed value ν_j denote, for brevity, the homogeneous weights $r_j = r(\nu_j)$, $H_{r_j} = -\text{diag}(r_{j,1}, r_{j,2}, \dots, r_{j,n})$, $\Lambda_{r_j}(\lambda) = \text{diag}(\lambda^{r_{j,1}}, \lambda^{r_{j,2}}, \dots, \lambda^{r_{j,n}})$ and $\alpha_j = \alpha(\nu_j)$. Accordingly,

$$Q_j(V, z) = z^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) z - 1. \quad (15)$$

Theorem 6.1. *Let for some $\nu_1 \in (-\frac{1}{n}, 0)$, $\nu_2 = -\nu_1$, $\phi, \beta, \kappa, \gamma_j > 0$, $\beta < \phi$ and $\epsilon \in (0, 1)$ the system of matrix inequalities*

$$A_0 X + X A_0^T + b Y + Y^T b^T + \phi X + \beta b b^T \leq 0 \quad (16a)$$

$$-\gamma_j X \leq H_{r_j} X + X H_{r_j} < 0, \quad (16b)$$

$$\xi I_n \leq X \leq \frac{1}{\kappa} I_n, \quad \begin{pmatrix} \frac{\beta^2 \xi}{\|\bar{z}_j\|^2} & Y \\ Y^T & X \end{pmatrix} \geq 0, \quad (16c)$$

$$\bar{z}_{j,i} = \begin{cases} g_{j,i}(\kappa^{-1/2}) + \kappa^{-1/2} \bar{p}_i \epsilon & \text{if } \kappa^{-1/2} \leq \alpha_{j,i}^{1/(1-\alpha_{j,i})} \\ \max\{g_{j,i}(\alpha_{j,i}^{1/(1-\alpha_{j,i})}), g_{j,i}(\kappa^{-1/2})\} + \kappa^{-1/2} \bar{p}_i \epsilon, & \text{if } \kappa^{-1/2} > \alpha_{j,i}^{1/(1-\alpha_{j,i})}, \end{cases} \quad (17)$$

where $g_{j,i} : \mathbb{R} \rightarrow \mathbb{R}$, $g_{j,i}(z) = |[z]^{\alpha_{j,i}} - z|$, $\bar{p}_i = (n - i + 1)\nu_2$ and $\alpha_{j,i} = (\frac{1+\nu_j}{r_{j,1}}, \dots, \frac{1+\nu_j}{r_{j,n}})$, be feasible for some $\xi > 0$, $X \in \mathbb{R}^{n \times n}$, $X = X^T > 0$, $Y \in \mathbb{R}^{1 \times n}$, with $j = 1, 2$, $i = \overline{1, n}$.

Then the system (2), (3) for $d = 0$, $a = Y P$ and $P = X^{-1}$ is globally fixed-time stable at the origin with

$$m = \sqrt{\lambda_{\max}(P^{-\frac{1}{2}} \Lambda_{r_1}(1-\epsilon) P \Lambda_{r_1}(1-\epsilon) P^{-\frac{1}{2}})} < 1 < M = \sqrt{\lambda_{\min}(P^{-\frac{1}{2}} \Lambda_{r_2}(1+\epsilon) P \Lambda_{r_2}(1+\epsilon) P^{-\frac{1}{2}})}$$

and the settling time estimate $T_{\max} \leq \frac{\gamma_1}{(\phi-\beta)|\nu_1|} + \frac{\gamma_2}{(\phi-\beta)\nu_2}$.

Before presenting the proof of this theorem, let us introduce a constructive procedure to calculate the controller's parameters. To this end, the system of LMI (16) can be solved using standard optimization tools such as MATLAB.

Constructive procedure to obtain the controller's parameters P , a , m and M .

¹For a detailed explanation of the function (13) and its properties, the reader is referred to [21].

1. Set the size of the chain of integrators n .
2. Fix a negative value for ν_1 . Start with values close to zero *e.g.* -0.001 .
3. Fix positive values for ϵ and κ (a possible initial value is 0.5 for both).
4. Calculate the vectors $\bar{z}_{i,j}$ using (17).
5. Fix positive values for $\phi, \beta, \gamma_1, \gamma_2, \beta < \phi$ (possible starting values are given in the examples).
6. Verify the feasibility of the system of inequalities (16).
7. If unfeasible, reduce the value of ϵ or modify the value of κ and repeat from step 3. If feasible, the value of $|\nu_1|$ might be increased in step 2 until a desired value of T_{\max} is obtained without losing feasibility (recall that in practice, this value might be conservative).
8. From the obtained matrices X and Y , calculate P, a, m and M as described in Theorem 6.1.

Note that the parameters that influence directly the settling-time are $\nu_1, \nu_2, \gamma_1, \gamma_2, \phi$ and β . The parameters ϵ and κ modify the bounds of the inequality (16c), so that its manipulation may relax the feasibility conditions of (16).

Proof of Theorem 6.1. I The functions $Q_j(V, x)$, $j = 1, 2$ defined in (15) satisfy the conditions **C1-C3** of Theorem 3.3. Indeed, they are continuously differentiable for all $V \in \mathbb{R}_+$ and for all $x \in \mathbb{R}^n$. Since $P > 0$ then the inequalities

$$\frac{\lambda_{\min}(P)\|x\|^2}{\max\{V^{2\min r_i}, V^{2\max r_i}\}} \leq Q_j(V, x) + 1 \leq \frac{\lambda_{\max}(P)\|x\|^2}{\min\{V^{2\min r_i}, V^{2\max r_i}\}},$$

imply that for any $x \in \mathbb{R}^n \setminus \{0\}$ there exist $V^- \in \mathbb{R}_+$ and $V^+ \in \mathbb{R}_+$: $Q_j(V^-, x) < 0 < Q_j(V^+, x)$. Moreover, if $Q_j(V, x) = 0$ then, obviously, the condition **C3** of Theorem 3.3 holds and there exists a Lyapunov function candidate $V : \mathbb{R}^n \rightarrow \mathbb{R}_+$ implicitly defined by the identity $x^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) x = 1$.

II Since

$$\frac{\partial Q_j}{\partial V} = V^{-1} x^T \Lambda_{r_j}(V^{-1}) (P H_{r_j} + H_{r_j} P) \Lambda_{r_j}(V^{-1}) x,$$

taking into account (16b), we have that $\frac{\partial Q_j}{\partial V} < 0 \forall V \in \mathbb{R}_+$ and $x \in \mathbb{R}^n \setminus \{0\}$. So the condition **C4** of Theorem (3.3) also holds and therefore $Q_j(V, z) = 0$ implicitly defines a proper positive definite Lyapunov function candidate $V : \mathbb{R}^n \rightarrow \mathbb{R}$.

III By denoting $\frac{\partial Q_j(V, x)}{\partial x}$ as the partial derivative of Q_j along the trajectories of (14) we obtain

$$\frac{\partial Q_j(V, x)}{\partial x} = 2x^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) [A_0 x + b a [x]^{\alpha(\nu)}].$$

By adding and subtracting inside the brackets the auxiliary term $V^{1+n\nu_j} b a \Lambda_{r_j}(V^{-1}) x$ and taking into account that $\Lambda_{r_j}(V^{-1}) A_0 \Lambda_{r_j}^{-1}(V^{-1}) = V^{-\nu_j} A_0$ and that $\Lambda_{r_j}(V^{-1}) b = V^{-1-(n-1)\nu_j} b$, we simplify the derivative as

$$\frac{\partial Q_j(V, x)}{\partial x} = \begin{pmatrix} \Lambda_{r_j}(V^{-1}) x \\ d(V, x) \end{pmatrix}^T \begin{pmatrix} V^{-\nu_j} (P A_0 + A_0^T P + P b a + a^T b^T P) & P b \\ b^T P & 0 \end{pmatrix} \begin{pmatrix} \Lambda_{r_j}(V^{-1}) x \\ d(V, x) \end{pmatrix},$$

where $d(V, x) = V^{-\nu_j} (a(V^{-1-n\nu_j} [x]^{\alpha(\nu)} - \Lambda_{r_j}(V^{-1}) x))$. By adding and subtracting the terms $\phi V^{-\nu_j} x^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) x$ and $\frac{1}{\beta} V^{\nu_j} d^T(V, x) d(V, x)$ we obtain

$$\frac{\partial Q_j(V, x)}{\partial x} = \begin{pmatrix} \Lambda_{r_j}(V^{-1}) x \\ d(V, x) \end{pmatrix}^T \Theta \begin{pmatrix} \Lambda_{r_j}(V^{-1}) x \\ d(V, x) \end{pmatrix} - \phi V^{-\nu_j} x^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) x + \frac{V^{\nu_j}}{\beta} d^T(V, x) d(V, x),$$

where

$$\Theta = \begin{pmatrix} V^{-\nu_j} (P A_0 + A_0^T P + P b a + a^T b^T P + \phi P) & P b \\ b^T P & \frac{V^{\nu_j}}{\beta} \end{pmatrix}.$$

Using the Schur complement, $\begin{pmatrix} P^{-1} & 0 \\ 0 & \eta \end{pmatrix}^T \Theta \begin{pmatrix} P^{-1} & 0 \\ 0 & \eta \end{pmatrix}$, for any $\eta \in \mathbb{R}$, it is equivalent to the left-hand side of (16a) and we arrive to

$$\frac{\partial Q_j(V, x)}{\partial x} \leq -V^{-\nu_j} \phi x^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) x + V^{\nu_j} \beta^{-1} d^T(V, x) d(V, x).$$

The term $d(V, x)$ can be rewritten as $d(V, x) = V^{-\nu_j} d_0(V, x)$ where $d_0(V, x) = a(V^{-1-n\nu_j} [x]^{\alpha(\nu)} - \Lambda_{r_j}(V^{-1})x)$, and we have that

$$\frac{\partial Q_j(V, x)}{\partial x} \leq -V^{-\nu_j} \phi x^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) x + V^{-\nu_j} \beta^{-1} d_0^T(V, x) d_0(V, x).$$

If the latter term is bounded as follows $d_0^T(V(x), x) d_0(V(x), x) < \beta^2$ then we derive

$$\frac{\partial Q_j(V, x)}{\partial x} \leq -\phi V^{-\nu_j} + \beta V^{-\nu_j},$$

and using inequality (16b) we arrive to

$$\frac{\partial Q_j(V, x)}{\partial x} \leq \frac{\phi - \beta}{\gamma_j} V^{1+\nu_j} \frac{\partial Q_j}{\partial V}.$$

for $(V, x) : x^T \Lambda_{r_j}(V^{-1}) P \Lambda_{r_j}(V^{-1}) x = 1$. Then, by defining $c_j = \frac{\phi - \beta}{\gamma_j}$, the conditions of Theorem 3.3 are satisfied.

IV Proof of the estimate $d_0^T(V, x) d_0(V, x) \leq \beta^2$.

IV.a Let us introduce the sets $\Omega_1 = \{x : m^2 \leq x^T P x \leq 1\}$ and $\Omega_2 = \{x : 1 \leq x^T P x \leq M^2\}$. Considering first the set Ω_2 and using the change of variables $y = \Lambda_{r_2}(V^{-1})x$ we obtain

$$\max_{\substack{(V, x) : x^T \Lambda_{r_2}(V^{-1}) P \Lambda_{r_2}(V^{-1}) x = 1 \\ \text{and } x^T P x \in [1, M^2]}} V = \max_{\substack{(V, y) : y^T P y = 1 \\ \text{and } y^T \Lambda_{r_2}(V) P \Lambda_{r_2}(V) y \in [1, M^2]}} V = 1 + \epsilon.$$

Indeed, from inequality (16b) we know that $\frac{\partial}{\partial V} y^T \Lambda_{r_2}(V) P \Lambda_{r_2}(V) y > 0$ and therefore $\min_{y : y^T P y = 1} y^T \Lambda_{r_2}(V) P \Lambda_{r_2}(V) y > \min_{y : y^T P y = 1} y^T \Lambda_{r_2}(1 + \epsilon) P \Lambda_{r_2}(1 + \epsilon) y = M^2$ if $V > 1 + \epsilon$ and $1 < \|x\|_P \leq M$ implies $1 \leq V(x) \leq 1 + \epsilon$. Similarly, we show

$$\min_{\substack{(V, x) : x^T \Lambda_{r_1}(V^{-1}) P \Lambda_{r_1}(V^{-1}) x = 1 \\ \text{and } x^T P x \in [m^2, 1]}} V = 1 - \epsilon.$$

Hence, we immediately conclude that $m \leq \|x\|_P^2 \leq M \Rightarrow 1 - \epsilon \leq V(x) \leq 1 + \epsilon$.

IV.b Recall the function ν is defined as follows

$$\nu(\|x\|_P) = \begin{cases} \nu_1, & \text{if } \|x\|_P \leq m, \\ \nu_2, & \text{if } \|x\|_P \geq M. \\ \frac{\nu_2 - \nu_1}{M - m} \|x\|_P + \frac{M\nu_1 - m\nu_2}{M - m}, & \text{otherwise} \end{cases}.$$

Then we have that

$$\max_{x \in \Omega_2} d_0^T(V(x), x) d_0(V(x), x) = \max_{x \in \Omega_2} \delta_\epsilon(V(x), x)^T a^T a \delta_\epsilon(V(x), x) \leq a a^T \max_{x \in \Omega_2} \delta_\epsilon(V(x), x)^T \delta_\epsilon(V(x), x),$$

where

$$\delta_\epsilon(V, x) = V^{-1-n\nu_2} ([x]^{\alpha(\nu(\|x\|_P))} - \Lambda_{r_2}(V^{-1})x).$$

Using again the change of variables $y = \Lambda_{r_2}(V^{-1})x$ and considering that $x \in \Omega_2 \implies V \in [1, 1 + \epsilon]$ we have that

$$a a^T \max_{x \in \Omega_2} \delta_\epsilon(V(x), x)^T \delta_\epsilon(V(x), x) \leq a a^T \max_{\substack{V \in [1, 1 + \epsilon] \\ \|y\|_P = 1}} \psi(V, y)^T \psi(V, y),$$

where $\psi(V, y) = |V^{-1-n\nu_2} [\Lambda_{r_2}(V)y]^{\alpha(\nu)} - y|$, and in a component-wise expression we have

$$\psi_i(V, y) = |V^{-1-n\nu_2+r_{2,i}\alpha_i(\nu)} [y_i]^{\alpha_i(\nu)} - y_i| = V^{-p_i(\nu)} |[y_i]^{\alpha_i(\nu)} - V^{p_i(\nu)} y_i|,$$

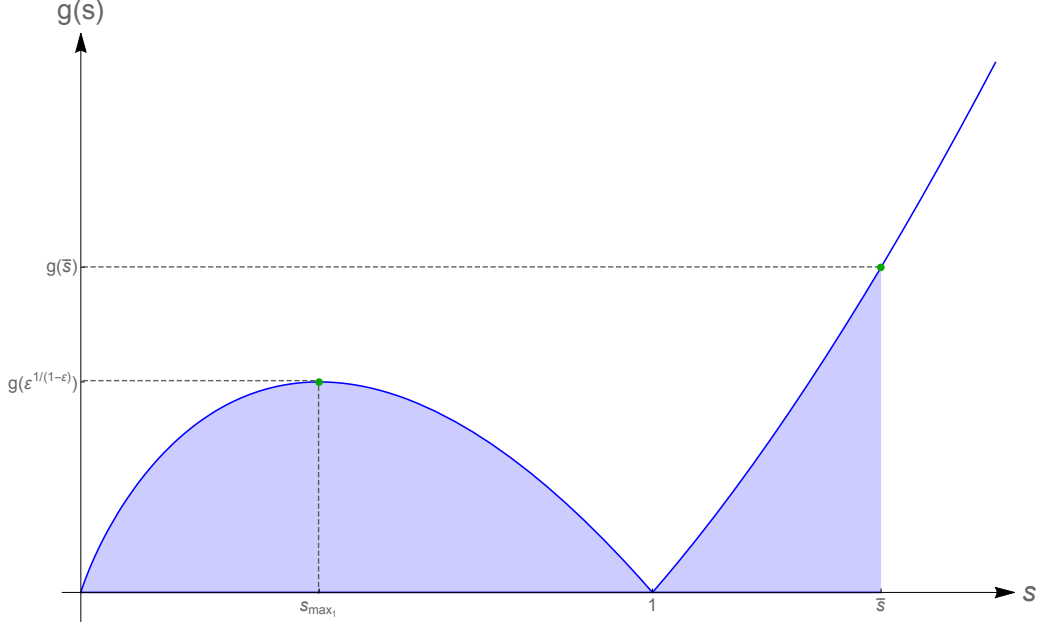


Figure 4: Plot of function $g(s, \varepsilon) = |\lceil s \rceil^\varepsilon - s|$, with fixed $\varepsilon \in \mathbb{R}_+$. Remark that if $\bar{s} > 1$, the maximum value of $g(s)$ in the interval $s \leq \bar{s}$ is the maximum between $g(\varepsilon^{1/(1-\varepsilon)}, \varepsilon)$ and $g(\bar{s}, \varepsilon)$.

where $p_i(\nu) = 1 + n\nu_2 - r_{2,i}\alpha_i(\nu) \geq 0$. Hence,

$$\begin{aligned}
\psi_i(V, y) &\leq \max_{\substack{V \in [1, 1+\varepsilon] \\ \|y\|_p = 1}} \left| \lceil y_i \rceil^{\alpha_i(\nu)} - V^{p_i(\nu)} y_i \right| \\
&= \max_{y: y^T P x = 1} \left\{ \left| |y_i|^{\alpha_i(\nu)} - |y_i| \right|, \left| |y_i|^{\alpha_i(\nu)} - (1+\varepsilon)^{p_i(\nu)} |y_i| \right| \right\} \\
&= \max_{y: y^T P x = 1} \left\{ \left| \lceil y_i \rceil^{\alpha_i(\nu)} - y_i \right|, \left| |y_i|^{\alpha_i(\nu)} - y_i + y_i - (1+\varepsilon)^{p_i(\nu)} y_i \right| \right\} \\
&\leq \max_{y: y^T P x = 1} \left(\left| |y_i|^{\alpha_i(\nu)} - |y_i| \right| + |y_i| \left| 1 - (1+\varepsilon)^{p_i(\nu)} \right| \right).
\end{aligned}$$

Lemma 6.1. *The function $g : \mathbb{R}_+^2 \rightarrow \mathbb{R}_+$ defined as $g(s, \varepsilon) = |s^\varepsilon - s|$, $s, \varepsilon \in \mathbb{R}_+$ admits the following estimate*

$$\max_{s \in [0, \bar{s}], \varepsilon \in [0, \bar{\varepsilon}]} g(s, \varepsilon) = \begin{cases} g(\bar{s}, \bar{\varepsilon}), & \text{for } \bar{s} \leq \bar{\varepsilon}^{1/(1-\bar{\varepsilon})} \\ \max\{g(\bar{\varepsilon}^{1/(1-\bar{\varepsilon})}, \bar{\varepsilon}), g(\bar{s}, \bar{\varepsilon})\}, & \text{for } \bar{s} > \bar{\varepsilon}^{1/(1-\bar{\varepsilon})}. \end{cases} \quad (18)$$

Proof. The function g is depicted in Figure 4. It is easy to show that function g_ε attains a local maximum at $s_{\max_1} = \varepsilon^{1/(1-\varepsilon)}$ within the interval $s \in [0, 1]$, therefore, if $\bar{s} \leq s_{\max_1}$ then $\max_{s \in [0, \bar{s}]} g(s, \varepsilon) = g(\bar{s}, \varepsilon)$ and if $\bar{s} > s_{\max_1}$ then $\max_{s \in [0, \bar{s}]} g(s, \varepsilon) = \max\{g(\varepsilon^{1/(1-\varepsilon)}, \varepsilon), g(\bar{s}, \varepsilon)\}$. Taking into account that $\frac{\partial(s^\varepsilon - s)}{\partial \varepsilon} = s^\varepsilon \ln s$, we complete the proof. \square

Since $y^T P y \implies |y_i| \leq \lambda_{\min}^{-1/2}(P) = \kappa^{-1/2}$ then using Lemma 6.1 the term $\left| |y_i|^{\alpha_i(\nu)} - |y_i| \right|$ can be bounded as follows:

$$\left| \lceil y_i \rceil^{\alpha_i(\nu)} - y_i \right| \leq \tilde{z}_{2,i} = \begin{cases} g_{\alpha_{2,i}}(\kappa^{-1/2}), & \text{for } \kappa^{-1/2} \leq \alpha_{2,i}^{1/(1-\alpha_{2,i})} \\ \max\{g_{2,i}(\alpha_{2,i}^{1/(1-\alpha_{2,i})}), g_{2,i}(\kappa^{-1/2})\}, & \text{for } \kappa^{-1/2} > \alpha_{2,i}^{1/(1-\alpha_{2,i})}. \end{cases}$$

Then for $V \in [1, 1+\varepsilon]$ and $y^T P y = 1$ one has

$$\psi_i(V, y) \leq \tilde{z}_{2,i} + \kappa^{-1/2} \left((1+\varepsilon)^{p_i(\nu)} - 1 \right) \leq \bar{z}_{2,i} + \kappa^{-1/2} \left((1+\varepsilon)^{\bar{p}_i} - 1 \right),$$

where $\nu = \nu(\|x\|_P) \in [0, \nu_2]$, $p_i(\nu) = 1 + n\nu_2 - (1 + (i-1)\nu_2)\frac{1+n\nu}{1+(i-1)\nu}$ and $\bar{p}_i = p_i(0) = (n-i+1)\nu_2$. Here, the fact that, for any x in the interval $1 \leq \|x\|_P \leq M$, $p_i(\nu(\|x\|_P)) \leq \bar{p}_i$ has been used.

By applying the mean value theorem with $h: \mathbb{R} \rightarrow \mathbb{R}$, $h(\theta) = \theta^{\bar{p}_i}$, we obtain that $h(1+\epsilon) - h(1) = h'(\theta^*)\epsilon$, where $\theta^* \in [1, 1+\epsilon]$. Noting that $0 < \bar{p}_i < 1$, we have that $(1+\epsilon)^{\bar{p}_i} - 1 \leq \bar{p}_i\epsilon$ and we arrive to the following estimate

$$\psi_i(V, y) \leq \tilde{z}_{2,i} + \kappa^{-1/2}\bar{p}_i\epsilon,$$

for $V \in [1, 1+\epsilon]$ and $\|y\|_P = 1$. Therefore, it has been proven that

$$\max_{x \in \Omega_2} d_0^T(V(x), x)d_0(V(x), x) \leq a^T a \|\bar{z}_2\|^2.$$

where $\bar{z}_2 = (\bar{z}_{2,1}, \dots, \bar{z}_{2,n})^T \in \mathbb{R}_+^n$ and $\bar{z}_{2,i} = \tilde{z}_{2,i} + \kappa^{-1/2}\bar{p}_i\epsilon$.

Accordingly, proceeding in the same fashion for the set Ω_1 , we obtain

$$\max_{x \in \Omega_1 \cup \Omega_2} d_0^T(V(x), x)d_0(V(x), x) \leq a^T a \|\bar{z}_2\|^2.$$

Using the Schur complement, inequality (16c) becomes $aP^{-1}a^T \leq \frac{\xi\beta^2}{\|\bar{z}_j\|^2}$ and since $aa^T\xi \leq aP^{-1}a^T$, we have that $aa^T \leq \frac{\beta^2}{\|\bar{z}_j\|^2}$ and we conclude that

$$d_0(V(x), x)^T d_0(V(x), x) \leq \beta^2$$

if $x \in \Omega_1 \cup \Omega_2$.

IV.c Boundedness of $d_0^T(V(x), x)d_0(V(x), x)$ in $\mathbb{R}^n \setminus (\Omega_1 \cup \Omega_2)$

If $x \in \mathbb{R}^n \setminus \{x: \|x\|_P \leq M\}$ then $\nu(\|x\|_P) = \nu_2$ and

$$d_0(V(x), x) = aV^{-1-n\nu_2}(\lceil x \rceil^{\alpha(\nu_2)} - \Lambda_{r_2}(V^{-1})x) = a(\lceil y \rceil^{\alpha(\nu_2)} - y)$$

where $y = \Lambda_{r_2}(V^{-1}(x))x$ and $y^T P y = 1$ (since $Q(V(x), x) = 0$). Hence, $\psi_i(V, y) \leq \tilde{z}_{2,i}$ and the required estimate $d_0(V, x)^T d_0(V, x) \leq \beta^2$ is straightforward. Similar considerations can be provided for $x: \|x\|_P \leq m$. \square

Finally let us remark that following a similar procedure, along with the ideas presented in [16], analogous algorithms can be developed for the observer.

Example 6.1 (Controller Parametrization). We start by choosing $n = 3$, $\nu_1 = -0.02$, $\nu_2 = -\nu_1$, $\epsilon = \kappa = 0.5$ and calculating \bar{z}_j ; following Theorem 6.1 we obtain $\bar{z}_1 = (0.0715, 0.0662, 0.0605)$, $\bar{z}_2 = (0.0721, 0.0689, 0.0661)$. We now choose the parameters $\phi = 0.5$, $\beta = 0.3$, $\gamma_1 = \gamma_2 = 3$ and solve the set of LMIs (16a-16c) to obtain

$$P_c = \begin{pmatrix} 2.3367 & 1.8430 & 1.7795 \\ 1.8430 & 4.8778 & 2.1295 \\ 1.7795 & 2.1295 & 4.2590 \end{pmatrix}, \quad a = (-0.5952, -1.7576, -1.3889).$$

With this parameter choice, the maximum settling time of the controller is $T_{\max} = 1500s$.

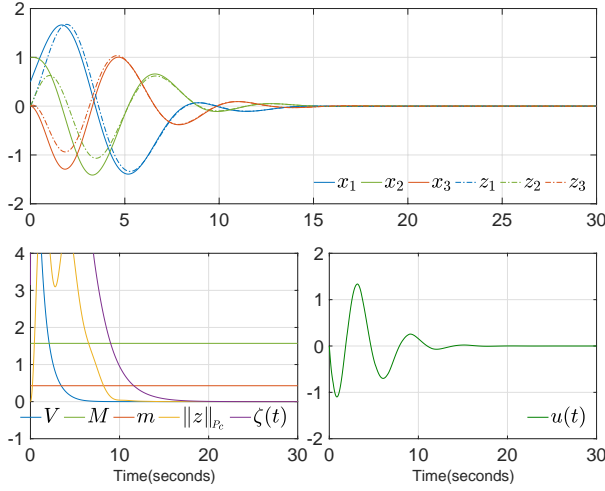


Figure 5: Results of simulation of (2), (6) and (10) for $n = 3$ without disturbances and with initial conditions $x_0 = (0.5, 1, 0)$.

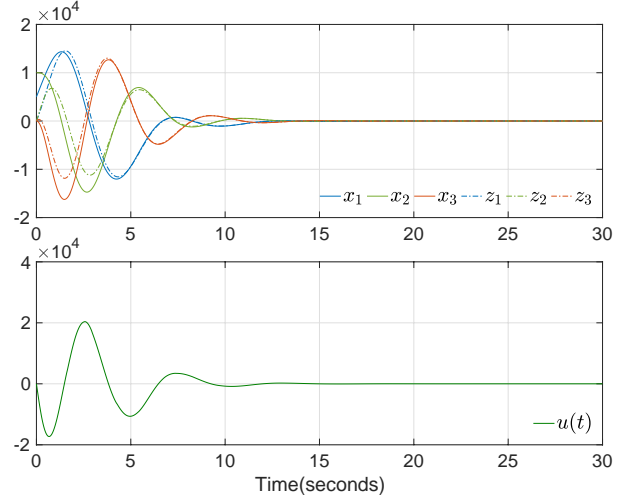


Figure 6: Results of simulation of (2), (6) and (10) for $n = 3$ with initial conditions $x_0 = 10^3(0.5, 1, 0)$.

Figure 5 depicts the substitution of these values in the system (2), (6) with initial conditions $x(0) = (5, 10, 0)$. It is possible to see a fast convergence to the real states before converging also rapidly to the origin. In Figure 6 the initial conditions have been changed to $x(0) = 10^3(5, 10, 0)$, it is possible to see that the settling time is not significantly modified and that in both cases the systems reach the equilibrium long before the settling time estimates. Finally, in Figure 7 the initial conditions were reset to $x(0) = (5, 10, 0)$ and the disturbance term

$$d(t) = \sin(2t) + \begin{cases} 10 & \text{if } t \in [30, 31] \\ 0 & \text{otherwise} \end{cases} \quad (19)$$

was added. We can see that the convergence to zero is preserved and with a much better performance than in the Example 1.

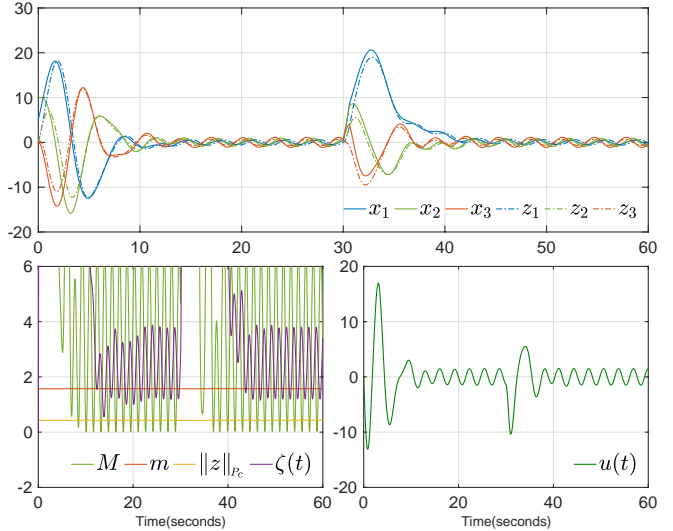


Figure 7: Results of simulation of (2), (6) and (10) for $n = 3$ with initial conditions $x_0 = (5, 10, 0)$ and the disturbance (19).

Example 6.2 (Comparative Example). This last example is meant to compare the fixed-time controller (2), (3), referred here as the *non-recursive* controller, with the finite-time and fixed-time ones described in [14], referred accordingly as the *recursive* ones. The parameter choice for the tuning algorithm 6.1 is as follows: $\nu_1 = -1/400, \nu_2 = -\nu_1, \epsilon = 0.1, \phi = 8, \beta = 7, \kappa = 0.5, \gamma_1 = \gamma_2 = 3$. And the obtained parameter values are $a = -(384, 136.08, 16.94)$ and $P_c = 10^3 \begin{pmatrix} 2.3195 & 0.5083 & 0.0359 \\ 0.5083 & 0.1455 & 0.0113 \\ 0.0359 & 0.0113 & 0.0014 \end{pmatrix}$, $\bar{z}_1 = (0.0047, 0.0056, 0.0064)$ and $\bar{z}_2 = (0.0047, 0.0056, 0.0065)$. The corresponding parameters for both the finite-time and the fixed-time controllers in [14] are the same as the ones used in the example section of the cited article. Figure 8 shows the unperturbed states of the chain of integrators with initial conditions $x_0 = (1, 1, 1)$. Clearly, the fixed-time controller outperforms the finite-time one. In Figure 9 it is possible to see how in the finite-time case, the variation of initial conditions affects the settling-time while the fixed-one remains within two seconds. Finally, Figure 10 shows an improvement of over two seconds in the settling time with respect to the recursive fixed-time controller, illustrating that with the tuning algorithm, the settling time can be adjusted. As shown in the interior plots, fixed-time stability is assumed whenever all the states enter a strip of magnitude 10^{-4} (depicted between black

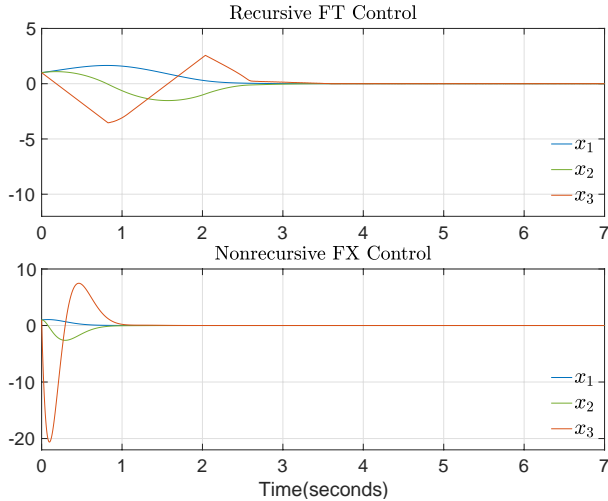


Figure 8: Comparison results between the recursive finite-time observer and the nonrecursive fixed-time one for $n = 3$, without disturbances and with initial conditions $x_0 = (1, 1, 1)$.

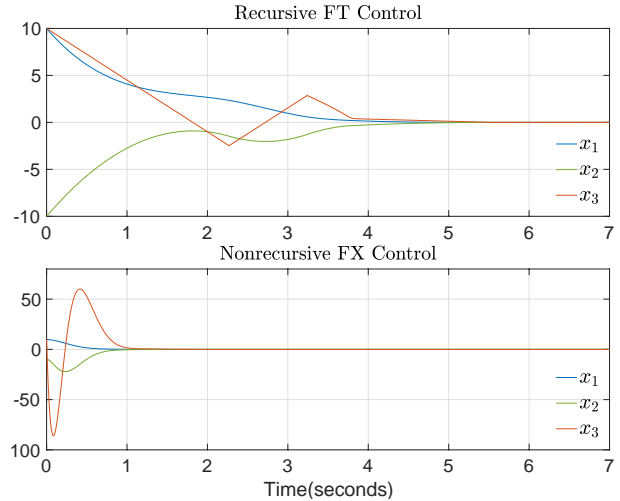


Figure 9: Comparison results between the recursive finite-time observer and the nonrecursive fixed-time one for $n = 3$, without disturbances and with initial conditions $x_0 = (10, 10, 10)$.

lines in Fig. 10) and remain there for the rest of the simulation.

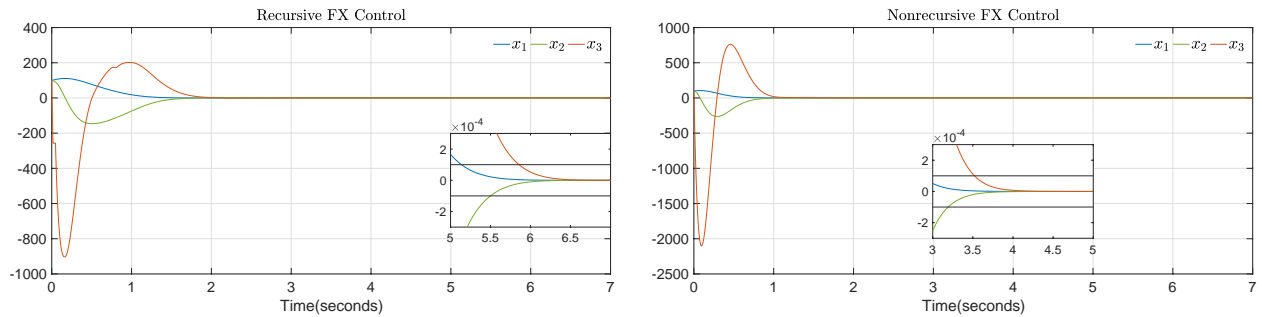


Figure 10: Comparison results between the recursive finite-time observer and the nonrecursive fixed-time one for $n = 3$, without disturbances and with initial conditions $x_0 = (10, 10, 10)$.

7. Conclusion

A state feedback control has been constructed for a chain of integrators, which ensures global convergence of all trajectories to the origin with an upper bound of the settling-time that is independent of the initial conditions (fixed-time stability). An observer has been proposed, which provides a global estimation of the plant state (global differentiation) with a fixed-time convergence rate. Both control and estimation algorithms are robust with respect to disturbances and noises. It has been shown that the combination of these algorithms results in a global fixed-time output stabilization control law. Effective tools to optimize the scheme's parameters, allowing the maximum settling time to be estimated have been presented and the efficacy of this scheme has been demonstrated in simulations. In the perturbed case, practical fixed-time stabilization is obtained, this is fixed-time stabilization to a ball containing the origin whose radius depends on the size of the perturbation.

As with many control algorithms that focus on *fast* convergence rates, the control signal magnitude might grow significantly to cope with the time constraints imposed. In practice, these constraints can only be granted locally due to boundedness of the admissible control magnitude. However, in contrast to other control algorithms, the fixed-time controllers do not need to be retuned if the admissible control magnitude (and, consequently, the domain of fixed-time convergence) is increased. A related issue deals with the methods used for simulation, which have to be adapted to treat highly nonlinear systems [13].

REFERENCES

- [1] Vincent Andrieu, Laurent Praly, and Alessandro Astolfi. Homogeneous Approximation, Recursive Observer Design, and Output Feedback. *SIAM J. Control Optimization*, 47(4):1814–1850, 2008.
- [2] M. T. Angulo, J. A. Moreno, and L. Fridman. Robust exact uniformly convergent arbitrary order differentiator. *Automatica*, 49(8):2489–2495, 2013.
- [3] A. Bacciotti and L. Rosier. *Lyapunov Functions and Stability in Control Theory*. Springer, 2nd edition, 2005.
- [4] M. Basin, Y. Shtessel, and F. Aldukali. Continuous finite- and fixed-time regulators. In *2016 14th International Workshop on Variable Structure Systems (VSS)*, pages 120–125, June 2016.
- [5] E. Bernuau, D. Efimov, W. Perruquetti, and A. Polyakov. On homogeneity and its application in sliding mode. *International Journal of Franklin Institute*, 351(4):1866–1901, 2014.
- [6] E. Bernuau, A. Polyakov, D. Efimov, and W. Perruquetti. Verification of ISS, iISS and IOSS properties applying weighted homogeneity. *Systems & Control Letters*, 62(12):1159–1167, 2013.
- [7] S. P. Bhat and D. S. Bernstein. Geometric homogeneity with applications to finite-time stability. *Mathematics of Control, Signals and Systems*, 17:101–127, 2005.
- [8] Ben M Chen, Zongli Lin, and Yacov Shamash. *Linear systems theory: a structural decomposition approach*. Springer Science & Business Media, 2004.
- [9] E. Cruz-Zavala, J.A. Moreno, and L.M. Fridman. Uniform robust exact differentiator. *IEEE Transactions on Automatic Control*, 56(11):2727–2733, 2011.
- [10] S.N. Dashkovskiy, D.V. Efimov, and E.D. Sontag. Input to state stability and allied system properties. *Automation and Remote Control*, 72(8):1579–1614, 2011.
- [11] J. Doyle, B. Francis, and A. Tannenbaum. *Feedback Control Systems*. Mac Millan Publishing Co, 1992.
- [12] D. Efimov and W. Perruquetti. Conditions of oscillations and multi-homogeneity. *Mathematics of Control, Signals, and Systems*, 28(3):1–37, 2016.
- [13] Denis Efimov, Andrey Polyakov, Arie Levant, and Wilfrid Perruquetti. Realization and discretization of asymptotically stable homogeneous systems. *IEEE Transactions on Automatic Control*, 2017.
- [14] Mohamed Harmouche, Salah Laghrouche, Yacine Chitour, and Mustapha Hamerlain. Stabilisation of perturbed chains of integrators using Lyapunov-based homogeneous controllers. *International Journal of Control*, 90(12):2631–2640, 2017.
- [15] H. K. Khalil. *Nonlinear Systems*. NJ 07458. Prentice-Hall, Upper Saddle River, 1996.
- [16] Francisco Lopez-Ramirez, Andrey Polyakov, Denis Efimov, and Wilfrid Perruquetti. Finite-time and fixed-time observers design via implicit Lyapunov function. In *Control Conference (ECC), 2016 European*, pages 289–294. IEEE, 2016.
- [17] E. Moulay and W. Perruquetti. Finite time stability of non linear systems. In *IEEE Conference on Decision and Control*, pages 3641–3646, Hawaii, USA, 2003.
- [18] Hisakazu Nakamura, Yuh Yamashita, and Hirokazu Nishitani. Smooth Lyapunov functions for homogeneous differential inclusions. In *SICE 2002. Proceedings of the 41st SICE Annual Conference*, volume 3, pages 1974–1979. IEEE, 2002.
- [19] A. Polyakov. Nonlinear feedback design for fixed-time stabilization of linear control systems. *IEEE Transactions on Automatic Control*, 57(8):2106–2110, 2012.
- [20] A. Polyakov, D. Efimov, and W. Perruquetti. Robust stabilization of MIMO systems in finite/fixed time. *International Journal of Robust and Nonlinear Control*, 26(1):69–90, 2016.

- [21] Andrey Polyakov, Denis Efimov, and Wilfrid Perruquetti. Finite-time and fixed-time stabilization: Implicit Lyapunov function approach. *Automatica*, 51:332–340, 2015.
- [22] Héctor Ríos and Andrew R Teel. A hybrid observer for fixed-time state estimation of linear systems. In *Decision and Control (CDC), 2016 IEEE 55th Conference on*, pages 5408–5413. IEEE, 2016.
- [23] E. Roxin. On finite stability in control systems. *Rendiconti del Circolo Matematico di Palermo*, 15:273–283, 1966.
- [24] Eduardo D. Sontag. The ISS philosophy as a unifying framework for stability-like behavior. In *Nonlinear control in the year 2000, Vol. 2 (Paris)*, volume 259 of *Lecture Notes in Control and Inform. Sci.*, pages 443–467. Springer, London, 2001.
- [25] Arjan van der Schaft. *L₂-gain and passivity techniques in nonlinear control*, volume 218 of *Lecture Notes in Control and Information Sciences*. Springer-Verlag London Ltd., London, 1996.
- [26] V.I. Zubov. On systems of ordinary differential equations with generalized homogenous right-hand sides. *Izvestia vuzov. Mathematica.(in Russian)*, 1:80–88, 1958.