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On the construction of Patchy Feedbacks for stabilization and optimization problems

Fabio ANCONA

University of Padova

ITN SADCO - Kick off Meeting

Ensta Paris Tech, Paris

March 3 - 4, 2011

Outline

- 1 Introduction
 - General Setting
 - Main Difficulties
- 2 Patchy Vector Fields
 - Definition and Basic Properties
 - Robustness of Patchy Vector Fields
- 3 Patchy Feedbacks
 - Definition
 - Stabilizing Patchy Feedback
 - Nearly Optimal Patchy Feedback
 - ISS Patchy Feedback

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Consider a control system

$$\dot{x} = f(x, u), \quad x \in \mathbb{R}^n, \quad u \in \mathbb{R}^m \quad (1)$$

- f smooth with sublinear growth

$$|f(x, u)| \leq c(1 + |x|) \quad \forall x, u$$

- (I) **Asymptotic Feedback Stabilization:** Seek feedback control $u = U(x)$ s.t. all trajectories of

$$\dot{x} = g(x) \doteq f(x, U(x)) \quad (2)$$

approach the origin as $t \rightarrow \infty$ (and the origin is Lyapunov stable).

- (II) **Optimal Feedback Control:** Given compact set $K \subset \mathbb{R}^n$, seek feedback control $u = U(x)$ s.t. all sol'ns of (1) reach given target set S in minimum time.

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- Smooth feedback controls that solve (I)-(II) in general may not exist

(I) Topological obstructions may prevent the existence of smooth (or even continuous) **stabilizing feedback**

(SUSSMANN '79; SONTAG & SUSSMANN '80; BROCKETT '83; CORON '90)

Ex: Brockett's nonholonomic integrator

$$\left. \begin{aligned} \dot{x}_1 &= u_1 \\ \dot{x}_2 &= u_2 \\ \dot{x}_3 &= x_1 u_2 - x_2 u_1 \end{aligned} \right\} \doteq f(x, u) \quad \begin{aligned} &(x_1, x_2, u_1, u_2) \rightarrow f(x, u) \\ &\text{not open at zero :} \\ &(0, 0, x_3) \notin \text{Im}(f) \quad \text{when } x_3 \neq 0 \end{aligned}$$

(II) **Optimal feedback** can be discontinuous with quite complicated structure, while optimal (open-loop) controls may have infinitely many switchings

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- Discontinuous stabilizing (or optimal) feedback in general are not robust w.r.t. (inner and outer) perturbations

$$\dot{x} = f(x, U(x + e_1(t))) + e_2(t) \quad (3)$$

(e_1 : measurement error, e_2 : external disturbance)

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Two possible approaches

in dealing with stabilization and optimization problems for

$$\dot{x} = f(x, U(x)).$$

1. Allow **arbitrary discontinuous feedback** controls $u = U(x)$ and work with weak or generalized solutions of discontinuous ODEs.
2. Use a particular class of feedback controls $U(x)$ whose **discontinuities** are **sufficiently tame** so to guarantee the existence of **Carathéodory solutions**

$$x(t) = \bar{x} + \int_0^t f(x(s), U(x(s))) ds.$$

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How to interpret solutions to discontinuous ODEs ?

- Define weaker concept of solution

For example, one can consider Krasovskii sol'ns, i.e. trajectories of the differential inclusion

$$\dot{x} \in G(x) \doteq \bigcap_{\varepsilon > 0} \overline{\text{co}} \{ g(y); |y - x| < \varepsilon \}, \quad g(y) \doteq f(x, U(x)). \quad (4)$$

Drawback: too many sol'ns are obtained. Not all enjoy desired properties.

- Introduce suitable generalized solutions:

"Sample-and-hold-solutions" & "Euler solutions": successfully implemented for problems (I)-(II)

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S-a-h solutions & Euler solutions of $\dot{x} = f(x, U(x))$

S-a-h solution $x(t)$ recursively defined as follows.

1. fix a time mesh $t_0 = 0 < t_1 < \dots < t_i < \dots$, with size $\delta \doteq \sup |t_{i+1} - t_i|$;
2. sample $U(x(t_i)) \doteq u_i$ and compute $x(t) \doteq x_{i+1}(t)$, $t \in]t_i, t_{i+1}]$ solving

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Euler solution is a (uniform) limit of S-a-h solutions as size $\delta \rightarrow 0$.

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An alternative approach

1. Introduce a class of discontinuous, piecewise smooth vector fields **“Patchy Vector Fields” (PVF)** which admit (forward) Carathéodory solutions, and analyze their properties.
2. Construct piecewise smooth stabilizing or optimal feedback $U = U(x)$ so that corresponding vector field $g(x) \doteq f(x, U(x))$ belongs to such class of PVF.
3. Establish **robustness properties** of stabilizing or optimal feedback in this class, relative to **external disturbances** and **internal measurement errors**.

(A. & BRESSAN '99-2008; BRESSAN & PRIULI 2008; A. & PRIULI 2011)

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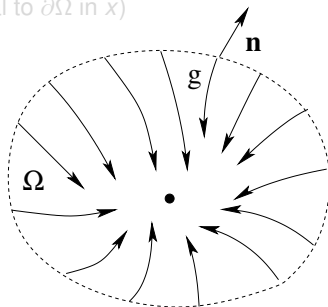
- **Patches**

(Ω, g) is said to be a **patch** if:

- $\Omega \subset \mathbb{R}^n$ is open domain with (piecewise) smooth boundary $\partial\Omega$
- g smooth vector field on a neighborhood of $\partial\Omega$, that points strictly inward at each point $x \in \partial\Omega$

$$\langle g(x), \mathbf{n}(x) \rangle < 0 \quad \forall x \in \partial\Omega$$

$\mathbf{n}(x)$ outer normal to $\partial\Omega$ in x



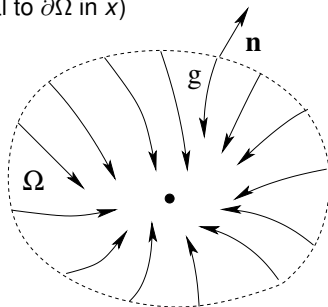
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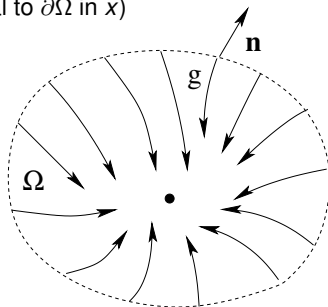
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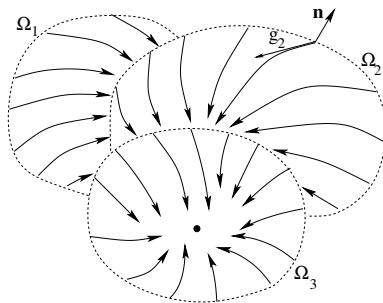
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• Patchy Vector Fields

locally finite covering in terms of patches (Ω_i, g_i) , $i \in \mathbb{Z}$.
 $g : \Omega \rightarrow \mathbb{R}^n$ is said to be a **patchy vector field** if:

$$g(x) = g_i(x) \iff x \in \Omega_i \setminus \bigcup_{j>i} \Omega_j$$

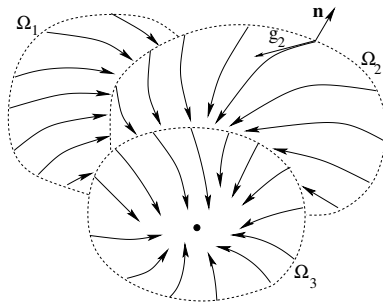


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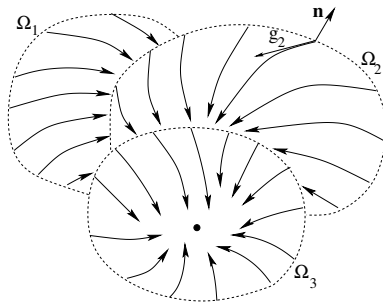


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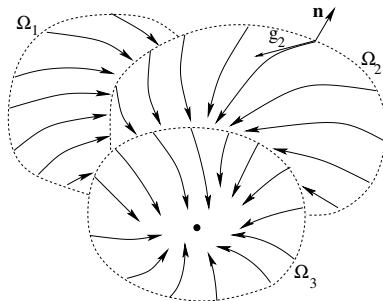


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Properties of Patchy Vector Fields

$$\dot{x} = g(x) = g_{j^*(x)}(x)$$

ODEs with patchy right hand side (A. & BRESSAN '99)

Let g be a patchy vector field on $\Omega \subset \mathbb{R}^n$. Then the following holds.

i) For every $\bar{x} \in \Omega$

$$\begin{cases} \dot{x} = g(x) \\ x(0) = \bar{x} \end{cases}$$

has

at least 1 (local) forward at most 1 backward
--

Carathéodory soln

- ii) sol'ns $x(t)$ are piecewise smooth, with derivatives having finite set of jumps on any compact time interval. The map $t \mapsto j_*(x(t))$ is **piecewise constant, non-decreasing**.
- iii) Set of Carathéodory sol'ns is closed in the topology of uniform convergence.

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Let g be a patchy vector field on $\Omega \subset \mathbb{R}^n$. Then the following holds.

i) For every $\bar{x} \in \Omega$

$$\begin{cases} \dot{x} = g(x) \\ x(0) = \bar{x} \end{cases} \text{ has } \begin{array}{l} \text{at least 1 (local) forward} \\ \text{at most 1 backward} \end{array} \text{ Carathéodory soln}$$

- ii) sol'ns $x(t)$ are piecewise smooth, with derivatives having finite set of jumps on any compact time interval. The map $t \mapsto i_*(x(t))$ is piecewise constant, non-decreasing.
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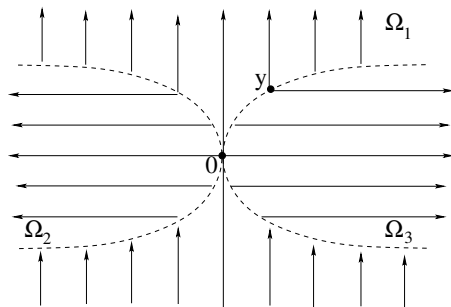
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Properties of Patchy Vector Fields ... continued

Note: in general, the **set of Carathéodory solutions** to a Cauchy problem is **not connected**, not acyclic.

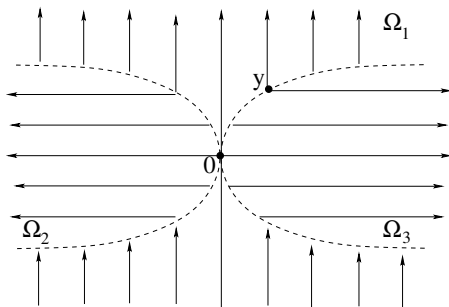
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Robustness w.r.t. (small) inner and outer perturbations

$$\dot{y} = g(y + e_1(t)) + e_2(t) \quad (5)$$

Flow stability of a Patchy Vector Field (A. & BRESSAN 2003, 2004)

Let g be a patchy vector field on $\Omega \subset \mathbb{R}^n$. Given any compact subset $C_0 \subset \Omega$, and any $T, \varepsilon > 0$, there exists $\delta > 0$ such that the following holds.

If $y : [0, T] \mapsto \Omega$ is a solution of the perturbed system (5), with $y(0) \in C_0$, and

$$\|e_1\|_{BV} \leq \delta, \quad \|e_2\|_{L^1} \leq \delta,$$

then there exists a solution $x : [0, T] \mapsto \Omega$ of the unperturbed equation

$$\dot{x} = g(x),$$

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$$|x(t) - y(t)| < \varepsilon \quad \forall t \in [0, T].$$

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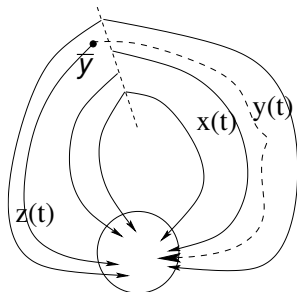
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Note: Since Cauchy problem for PVF lacks of forward uniqueness & continuous dependence, one cannot expect to have single sol'n's of PVF be stable w.r.t. perturbations.

Here we have **stability property** involving whole Carathéodory **solution set**: upper semicontinuity property of the solution set.



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$$\dot{x} = f(x, u), \quad x \in \mathbb{R}^n, \quad u \in K \subset \mathbb{R}^m$$

A piecewise smooth map $U : \Omega \rightarrow \mathbb{R}^m$ is a **patchy feedback** control on open domain $\Omega \subset \mathbb{R}^n$ if:

- there exist $U_i : \Omega_i \rightarrow \mathbb{R}^m$, $i \in \mathbb{Z}$, smooth maps, with $\{\Omega_i\}_{i \in \mathbb{Z}}$ locally finite covering of Ω ;
- (Ω_i, g_i) , with

$$g_i(x) \doteq f(x, U_i(x)), \quad x \in \Omega_i,$$

is a **patch** for every $i \in \mathbb{Z}$;

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$$U(x) = U_i(x) \quad \forall x \in \Omega_i \setminus \bigcup_{j>i} \Omega_j.$$

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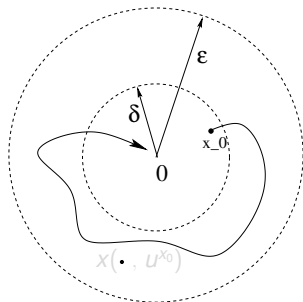
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$$\dot{x} = f(x, u), \quad x \in \mathbb{R}^n, \quad u \in K \subset \mathbb{R}^m \quad (6)$$

Stabilization by Patchy Feedback (A. & BRESSAN 1999)

Assume: (6) is globally asymptotically controllable to the origin:

1. **Attractiveness:** $\forall x_0 \in \mathbb{R}^n \exists$ admissible open-loop control $u^{x_0}(t)$ s.t. the trajectory $x(\cdot, u^{x_0})$ starting at x_0 is defined $\forall t \geq 0$ and satisfies $x(t, u^{x_0}) \rightarrow 0$ as $t \rightarrow \infty$.
2. **Lyapunov stability:** $\forall \varepsilon > 0 \exists \delta > 0$ s.t. $\forall x_0 \in \mathbb{R}^n, |x_0| \leq \delta$, \exists admissible control $u^{x_0}(t)$ as in 1., with $|x(t, u^{x_0})| \leq \varepsilon, \forall t \geq 0$.

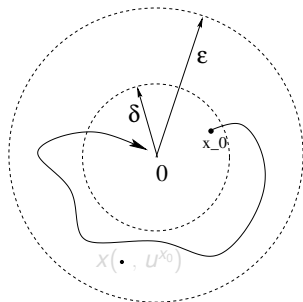


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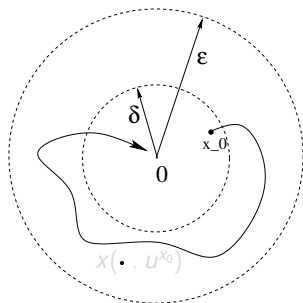


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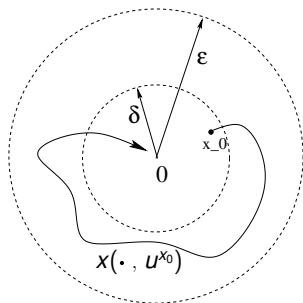


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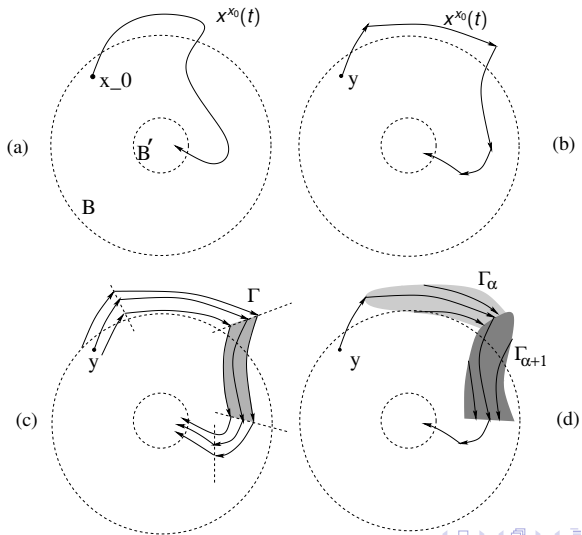
Stabilization by Patchy Feedback ... continued

Then: there exists a **patchy feedback** control $U(x)$ that makes **asymptotically stable** the closed-loop system

$$\dot{x} = f(x, U(x)) \quad (7)$$

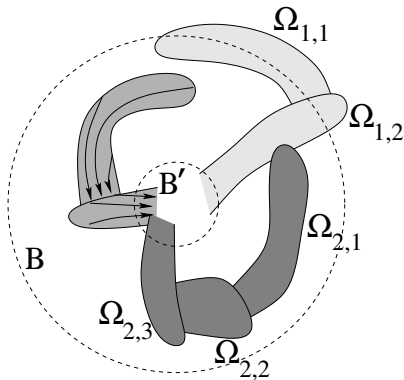
every Carathéodory solution of (7) either tends asymptotically to the origin, or reaches the origin in finite time. System enjoys (7) Lyapunov stability.

Construction of a stabilizing patchy feedback by patching together open-loop controls



Semi-global practical stabilization by a patchy feedback

Construct a patchy feedback that steers every point of a ball B inside a smaller ball $B' \subsetneq B$, within finite time.



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Nearly Time Optimal Patchy Feedback

(A. & BRESSAN 2007; BRESSAN & PRIULI 2008)

Given $\varepsilon > 0$, $\tau > 0$, there exists a sub-optimal patchy feedback $u = U(x)$ defined on sub-level set

$$R_\tau = \{y : T(y) \leq \tau\},$$

such that $\forall y \in R_\tau$, $|y| > \varepsilon$, any (Carathéodory) solution of

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reaches the ε -ball $B_\varepsilon = \{|x| \leq \varepsilon\}$ within time $T(y) + \varepsilon$.

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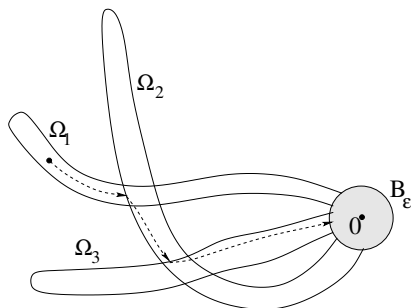
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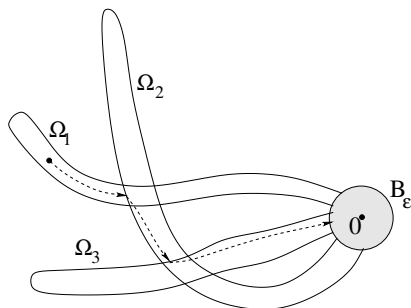
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Alternative construction: work with the value function

Construction of Nearly Time Optimal Patchy Feedback

- Approximate the minimum time function $T(\cdot)$ with a semi-concave, piecewise quadratic function:

$$\tilde{T}(x) = \min_{j=1,\dots,N} \left\{ a_j + \mathbf{b}_j \cdot x \right\} + M \cdot |x|^2.$$

- Set of points where \tilde{T} not differentiable is contained in finite union of hyperplanes

$$\Gamma_{i,j} \doteq \left\{ a_i + \mathbf{b}_i \cdot x = a_j + \mathbf{b}_j \cdot x \right\}.$$

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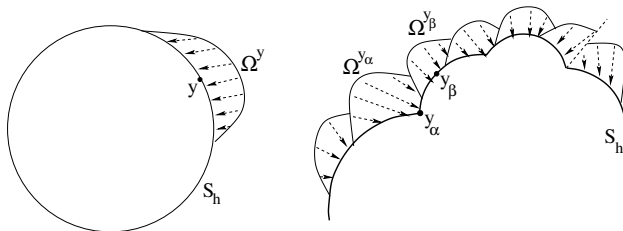
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Construction of Nearly Time Optimal Patchy Feedback ... continued

- Construct the patchy feedback by induction, progressively working on larger sub-level sets of \tilde{T}



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ISS Stability: robustness of stabilization in presence of **large external perturbations** (SONTAG 1989)

- In presence of large external disturbances, solutions remain in a ball around the origin of the same size of the L^∞ -strength of the perturbation
- If there exists a continuous stabilizing feedback control $U(x)$, then one can easily modify U so that the resulting system becomes ISS
- systems with a quadratic scalar control may not admit (even discontinuous) ISS stabilizing feedback

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- In presence of large external disturbances, solutions remain in a ball around the origin of the same size of the L^∞ -strength of the perturbation
- If there exists a continuous stabilizing feedback control $U(x)$, then one can easily modify U so that the resulting system becomes ISS
- systems with a quadratic scalar control may not admit (even discontinuous) ISS stabilizing feedback

Consider affine system

$$f_0(x) + \sum_{i=1}^m u_i f_i(x) \quad x \in \mathbb{R}^n$$

ISS Stability S-a-h solns (MALISOFF, RIFFORD & SONTAG 2004)

$$\dot{x} = f_0(x) + \sum_{i=1}^m \left(U_i(x + \zeta(t)) + d_i(t) \right) f_i(x)$$

ISS Stabilizing Patchy Feedback for Carathéodory solns
(A. & PRIULI 2011)

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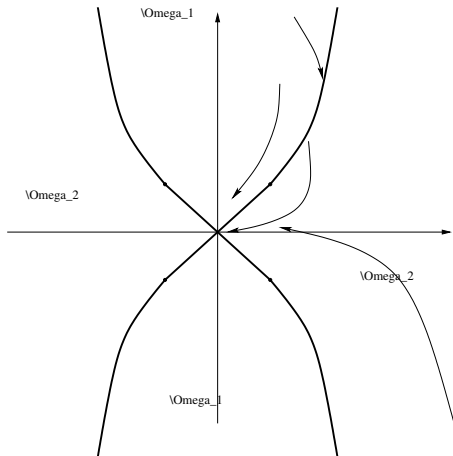
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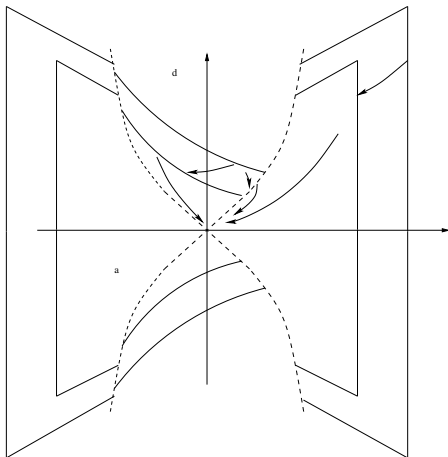
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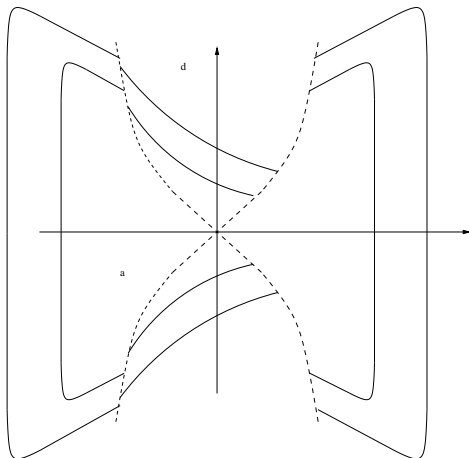
Stabilizing Patchy Feedback for Nonholonomic Integrator



ISS Stabilizing Patchy Feedback for Nonholonomic Integrator



ISS Stabilizing Patchy Feedback for Nonholonomic Integrator



Future directions

- Construction of stabilizing or sub-optimal patchy feedback for control **problems with constraints**.
- Construction of stabilizing or sub-optimal **hybrid** patchy feedback.
(GOEBEL, PRIEUR, TEEL)
- Introduction of **numeric schemes** to solve HJ or HJB equations, based on patchy decomposition technique.
(NEVASCA & KRENER 2007-2008; FALCONE & PICARELLI 2011)

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et finalement....

Merci de votre attention!