Elective in Robotics 2014/2015

Analysis and Control of Multi-Robot Systems

Formation Control of Multiple Robots

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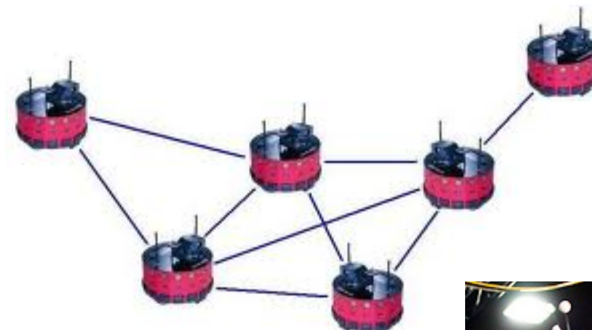
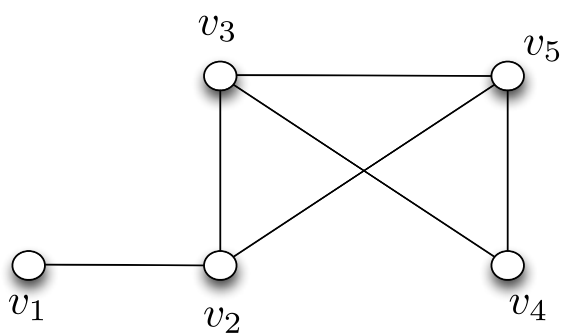
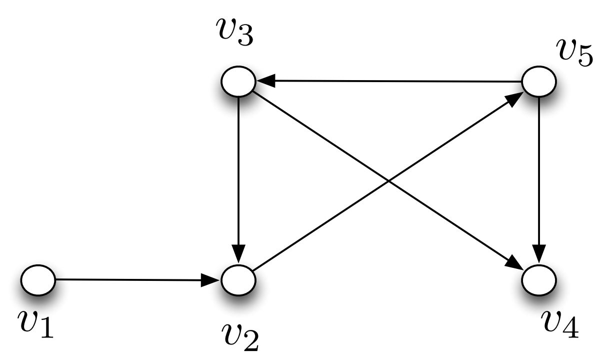
Formation Control of Multiple Robots



Summary of Previous Lectures

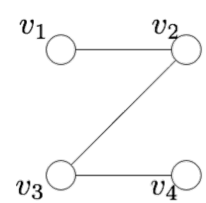
- What have we seen so far?
- **Graph Theory**
- Undirected graphs $\mathcal{G} = (\mathcal{V},\, \mathcal{E})$ and Directed graphs $\mathcal{D} = (\mathcal{V},\, \mathcal{E})$

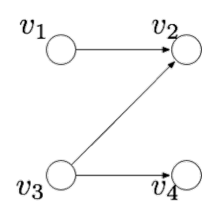




- Connected graphs/Disconnected graphs

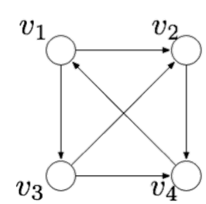
connected

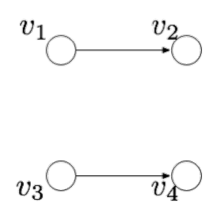




weakly connected

strongly connected

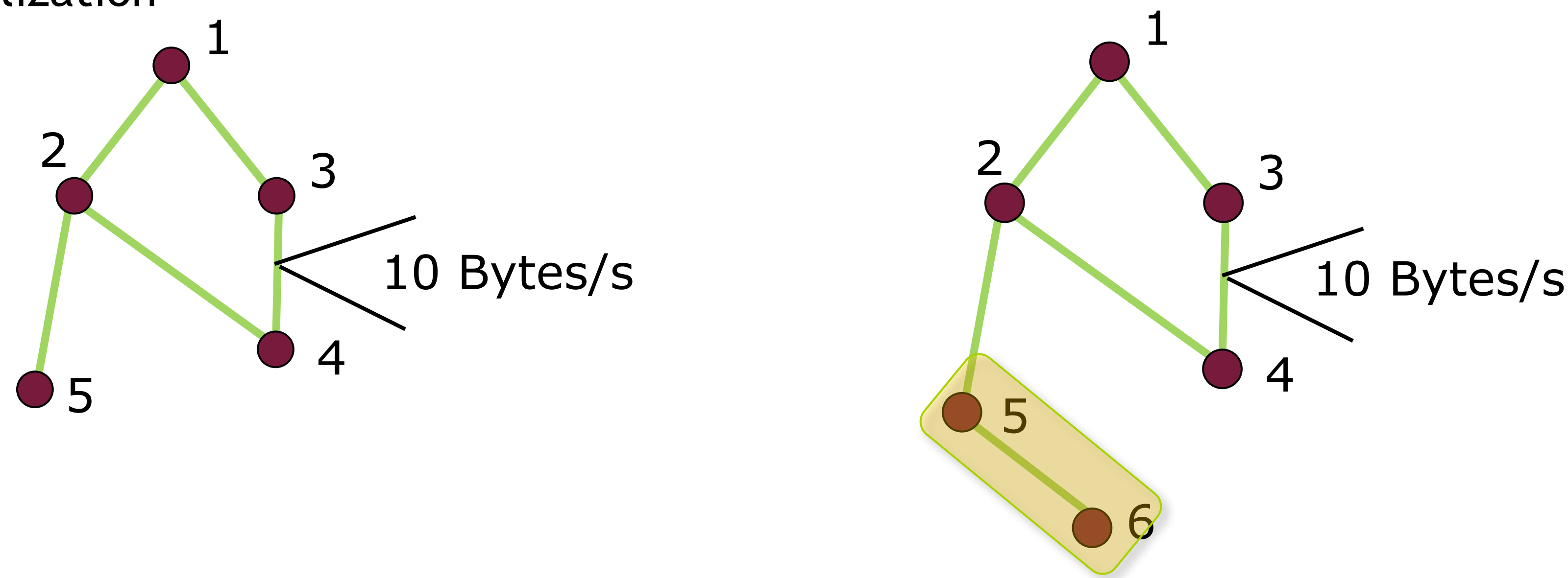




disconnected

Summary of Previous Lectures

- Decentralization



- Algebraic Graph Theory: Adjacency matrix $A \in \mathbb{R}^{N\times N}$, Degree matrix $\Delta \in \mathbb{R}^{N\times N}$
Incidence matrix $E \in \mathbb{R}^{N\times|\mathcal{E}|}$ and Laplacian matrix $L \in \mathbb{R}^{N\times N}$ with

$$L = \Delta - A = EE^T$$

- Properties of the Laplacian: $L\mathbf{1} = 0$ (and $\mathbf{1}^T L = 0$ for undirected graphs)

Summary of Previous Lectures

- Properties of the Laplacian: $0 = \lambda_1 \leq \lambda_2 \leq \ldots \leq \lambda_N$ (all eigenvalues real and non-negative for undirected graphs)

- Graph connected if and only if $\lambda_2 > 0 \;\Leftrightarrow\; \text{rank}(L) = N - 1$ and $\mathbf{1}$ is the eigenvector associated to $\lambda_1 = 0$

- Also, $E^T\mathbf{1} = 0$ and $\text{rank}(E) = N - 1$

- **Consensus protocol:**

- N agents with dynamics $\dot{x}_i = u_i$, find $u_i = u_i(x_i - x_j)$, $\forall j \in \mathcal{N}_i$, such that $\lim_{t\to\infty} x_i(t) = \bar{x}, \;\forall i$ for some common but unspecified $\bar{x}$

- Solution: $u_i = \sum_{j\in\mathcal{N}_i}(x_j - x_i)$ equivalent to $u = -Lx$, yielding $\dot{x} = -Lx$

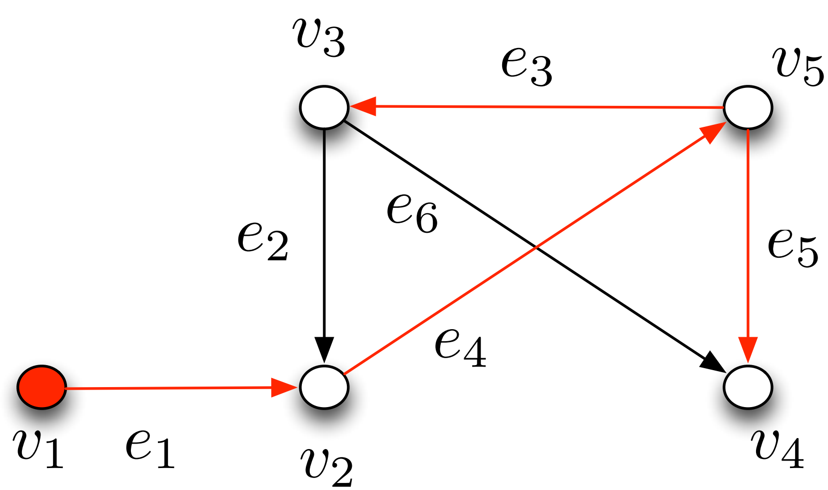
Summary of Previous Lectures

- Result: if the (undirected) graph is **connected** ($\lambda_2 > 0$ and/or $\text{rank}(L) = N - 1$ then the consensus converges to the average of the initial condition

$$\lim_{t \to \infty} x(t) = \frac{(\mathbf{1}^T x_0)\mathbf{1}}{N}$$

- The magnitude of λ_2 dictates the rate of convergence

- For directed graphs, the conditions for the consensus convergence, i.e., $\text{rank}(L) = N - 1,\ 0 < \Re(\lambda_2) \leq \ldots \leq \Re(\lambda_N)$, require presence of a rooted out-branching



Summary of Previous Lectures

- For directed graphs, in general no convergence to the average of the initial condition, but just

$$\lim_{t \to \infty} x(t) = (q_1^T x_0) p_1 = (q_1^T x_0) \mathbf{1}$$

for some $q_1 \neq 0$

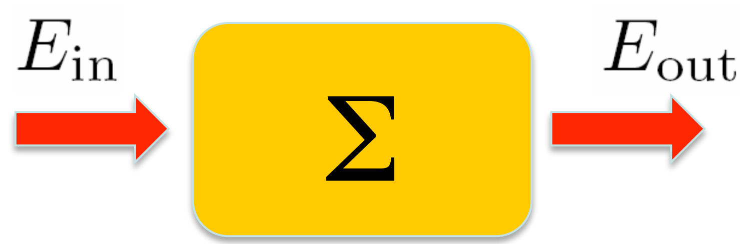
- If the graph is balanced, then we re-obtain $\lim_{t \to \infty} x(t) = \dfrac{(\mathbf{1}^T x_0)\mathbf{1}}{N}$

- Consensus protocol: paradigm of many decentralized algorithms based on relative information

- Can (and has been) extended to many variants (time-varying topologies, delays, more complex agent dynamics, etc.)

Summary of Previous Lectures

- **Passivity:**



$$E_{\text{out}} \leq E_{\text{in}}$$

- I/O characterization in "Energetic terms"
- No internal production of energy
- Passivity ingredients:
- a dynamical system $\begin{cases} \dot{x} &= f(x) + g(x)u \\ y &= h(x) \end{cases}$
- a lower-bounded Storage function $V(x) \in \mathcal{C}^1 : \mathbb{R}^n \to \mathbb{R}^+$
- a passivity condition $\begin{cases} V(x(t)) - V(x(t_0)) &\leq \int_{t_0}^{t} y^T(\tau)u(\tau)\mathrm{d}\tau \\ \dot{V}(x(t)) &\leq y^T(t)u(t) \end{cases}$

Summary of Previous Lectures

- Passivity is w.r.t. an input/output pair $(u,\ y)$ and w.r.t. a Storage function $V(x)$

Current energy is at most equal to the initial energy + exchanged energy with outside

$$V(x(t)) \leq V(x(t_0)) + \int_{t_0}^{t} y^T(s)u(s)\mathrm{d}s$$

- Passivity is strongly related to Lyapunov stability

- Stable free evolution ($u \equiv 0$) and stable zero-dynamics ($y \equiv 0$)

- "Easy" output feedback for (asympt.) stabilization $u = -\phi(y), \quad y^T\phi(y) > 0\, \forall y \neq 0$
e.g., $u = -ky, \quad k > 0$

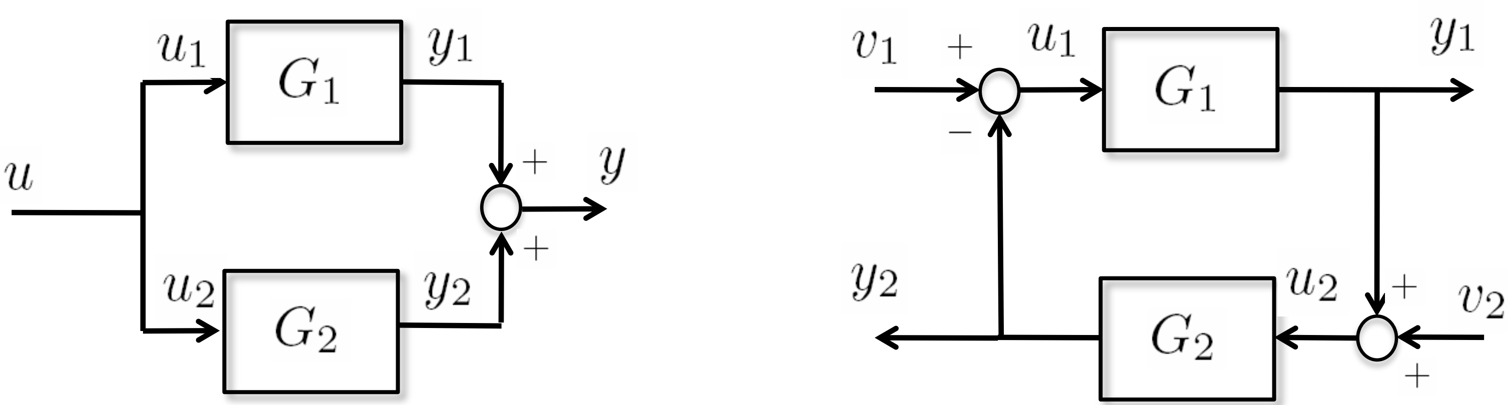
- When possible, one can choose the "right" output for enforcing passivity

- Many physical systems are passive, e.g., mechanical systems (robot manipulators) w.r.t. the pair force/velocity

Summary of Previous Lectures

- Proper compositions of passive systems are passive

- Example: parallel and feedback interconnection

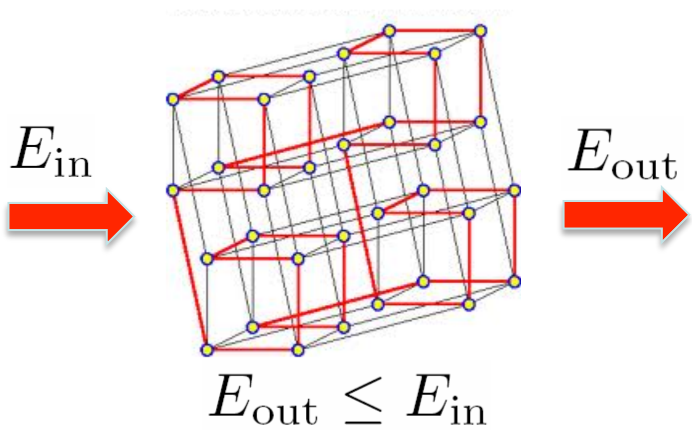


- In the feedback interconnection, the coupling is skew-symmetric (power-preserving interconnection)

$$\begin{bmatrix} u_1 \\ u_2 \end{bmatrix} = \begin{bmatrix} 0 & \pm 1 \\ \mp 1 & 0 \end{bmatrix} \begin{bmatrix} y_1 \\ y_2 \end{bmatrix} + \begin{bmatrix} v_1 \\ v_2 \end{bmatrix}$$

Summary of Previous Lectures

- Port-Hamiltonian Systems (PHS): look at the network structure behind passivity



- Passive systems are made of a "power-preserving interconnection" of:
  - Elements storing Energy
  - Elements dissipating Energy
  - Power ports with the external world

Summary of Previous Lectures

- In the general form, a PHS is

$$\begin{cases} \dot{x} &= [J(x) - R(x)]\dfrac{\partial H}{\partial x} + g(x)u, \quad J(x) = -J^T(x),\ R(x) \geq 0 \\ y &= g^T(x)\dfrac{\partial H}{\partial x} \end{cases}$$

with $H(x) \geq 0$ being the Hamiltonian (lower-bounded Storage function), and the passivity condition naturally embedded in the system structure

$$\dot{H} = -\frac{\partial H^T}{\partial x}R(x)\frac{\partial H}{\partial x} + \frac{\partial H^T}{\partial x}g(x)u \leq y^T u$$

- Among the many control techniques for PHS, we focused on the Energy Transfer control

$$\begin{cases} \dot{x}_1 &= J_1(x_1)\dfrac{\partial H_1}{\partial x_1} + g_1(x_1)u_1 \\ y_1 &= g_1^T(x_1)\dfrac{\partial H_1}{\partial x_1} \end{cases} \qquad \begin{cases} \dot{x}_2 &= J_2(x_2)\dfrac{\partial H_2}{\partial x_2} + g_2(x_2)u_2 \\ y_2 &= g_2^T(x_2)\dfrac{\partial H_2}{\partial x_2} \end{cases}$$

$$\begin{bmatrix} u_1 \\ u_2 \end{bmatrix} = \begin{bmatrix} 0 & -\alpha y_1(x_1)y_2^T(x_2) \\ \alpha y_2(x_2)y_1^T(x_1) & 0 \end{bmatrix} \begin{bmatrix} y_1 \\ y_2 \end{bmatrix}, \quad \alpha \in \mathbb{R}$$

Summary of Previous Lectures

- This allows to transfer energy from a PHS to another PHS in a lossless way

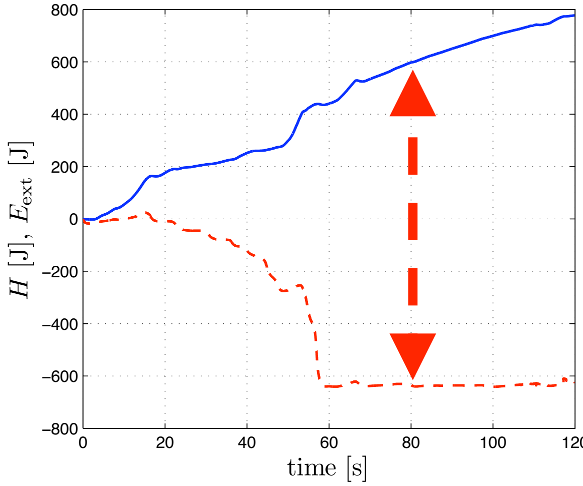
- The total does not change $\dot{H}(x_1, x_2) = 0$, but the individual energies may increase/decrease depending on the value of the parameter α

$$\dot{H}_1(x_1) = -\alpha \|y_1\|^2 \|y_2\|^2 \qquad \dot{H}_2(x_2) = \alpha \|y_1\|^2 \|y_2\|^2$$

- This technique can be used in conjunction with the so-called Energy Tanks

- In a PHS, there is an inherent passivity margin due to the internal dissipation

$$H(t) - H(t_0) = \int_{t_0}^{t} y^T u \, \mathrm{d}\tau \underbrace{- \int_{t_0}^{t} \frac{\partial H^T}{\partial x} R(x) \frac{\partial H}{\partial x} \mathrm{d}\tau}_{\leq 0}$$



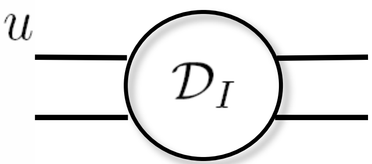
Summary of Previous Lectures

- Idea: store back the dissipated energy, and use it to passively implement whatever action w

- The PHS dissipated power is $D(x) = \dfrac{\partial H^T}{\partial x} R(x) \dfrac{\partial H}{\partial x}$

- Design a PHS Tank dynamics with energy function $T(x_t) = \dfrac{1}{2} x_t^2 \geq 0$ as

$$\begin{cases} \dot{x} &= [J(x) - R(x)] \dfrac{\partial H}{\partial x} + g(x) u \\ y &= g^T(x) \dfrac{\partial H}{\partial x} \end{cases}$$



$$\begin{cases} \dot{x}_t &= \dfrac{1}{x_t} D(x) + \tilde{u}_t \\ y_t &= x_t \end{cases}$$

and then interconnect Tank and PHS by means of the skew-symmetric coupling

$$\begin{bmatrix} u \\ \tilde{u}_t \end{bmatrix} = \begin{bmatrix} 0 & \dfrac{w}{x_t} \\ -\dfrac{w^T}{x_t} & 0 \end{bmatrix} \begin{bmatrix} y \\ y_t \end{bmatrix}$$

Summary of Previous Lectures

- The PHS becomes $\dot{x} = [J(x) - R(x)]\dfrac{\partial H}{\partial x} + g(x)w$ and the Tank dynamics is

$$\dot{x}_t = \frac{1}{x_t}D(x) - \frac{w^T}{x_t}g^T(x)\frac{\partial H}{\partial x}$$

- Singularity for $x_t = 0$: Tank empty, therefore the action w cannot be (passively) implemented

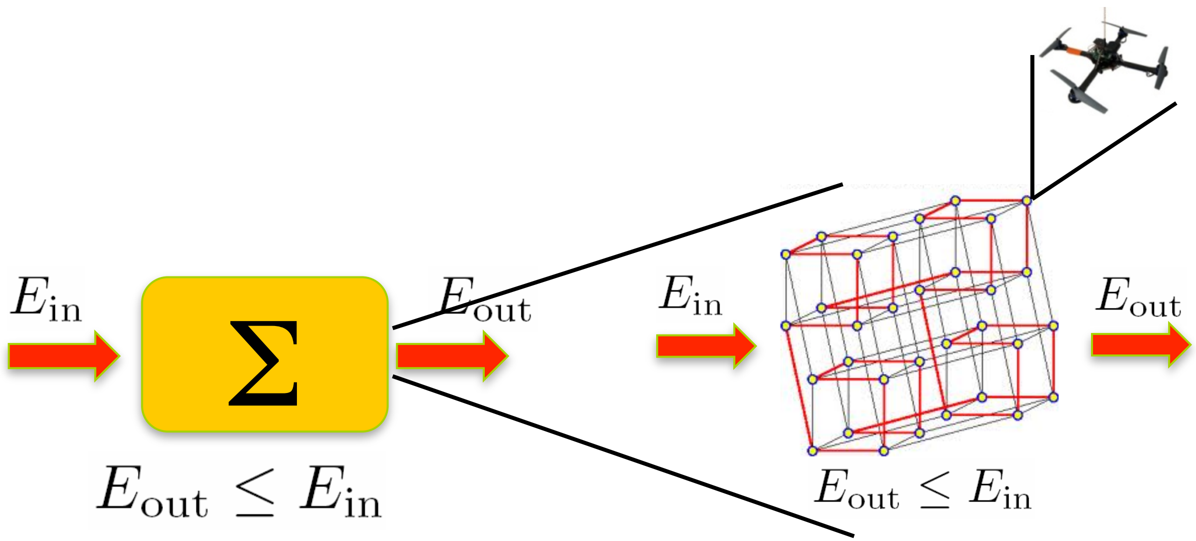
- Anyway: the Tank is
  - continuously refilled by the term $D(x)$
  - possibly refilled by the action w
  - and complete freedom in choosing the initial Tank energy level $T(x_t(t_0))$

Formation Control of Multiple UAVs

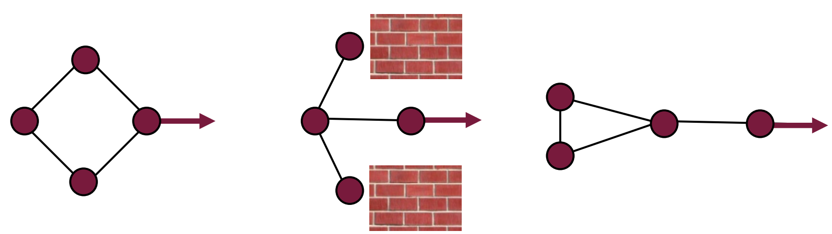
- We are finally ready for some action (Formation Control of UAVs)

Formation Control of Multiple UAVs

- Let us then focus on the Passivity-based Decentralized Control of Multiple UAVs



- We start with a basic problem: formation control under sensing/comm. constraints

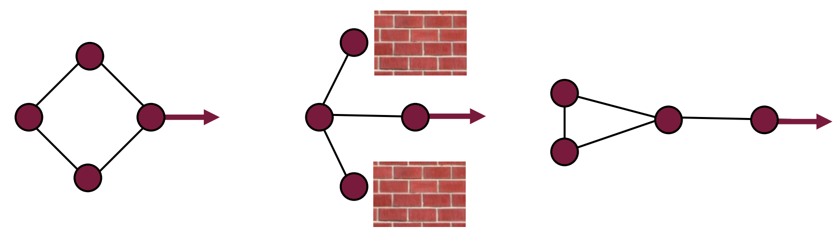


Formation Control of Multiple UAVs

- Formation Control with Time-varying graph topology

- Robots are loosely coupled together
  - can gain/lose neighbors, but must show some form of cohesive behavior

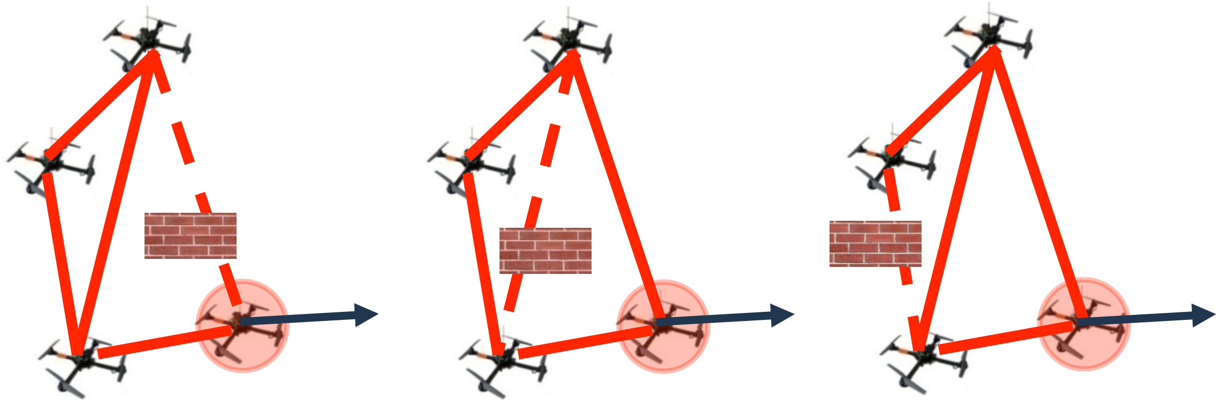
- Robots can decide to split or to join because of any constraint or task, e.g.
  - sensing and/or communication constraints
  - need to temporarily split for better maneuvering in cluttered environments



- Overall motion controlled by selected robots (leaders)

- Appropriate for “loose” tasks, e.g., coverage, persistent patrolling, exploration, etc.

Formation Control of Multiple UAVs



- Features:
  - decentralized design (local and 1-hop communication/sensing)
  - flexible formation: splits/joins due to
    - **sensing/communication constraints**
    - execution of **extra tasks** in parallel to the collective motion
  - Autonomy in **avoiding obstacles** and **inter-agent collisions**

- Challenges:
  - Time-varying topology: ensure stability despite a switching dynamics
  - Guarantee passivity of the overall group behavior
  - Steady-state characteristics? (Velocity synchronization)
  - What if time delays are present in the communication links?
  - What about maintenance of group connectivity?

Agent Model

- Every agent is modeled as a free-floating mass in $\mathbb{R}^3$ with Energy $\mathcal{K}_i = \frac{1}{2} p_i^T M_i^{-1} p_i$

$$\begin{cases} \dot{p}_i = F_i^a + F_i^e - B_i M_i^{-1} p_i \\ v_i = \frac{\partial \mathcal{K}_i}{\partial p_i} = M_i^{-1} p_i \end{cases} \qquad i = 1, \ldots, N$$

- $p_i \in \mathbb{R}^3$ is the agent momentum and $v_i \in \mathbb{R}^3$ the agent velocity. Let also $x_i \in \mathbb{R}^3$, with $\dot{x}_i = v_i$, be the agent position

- $M_i \in \mathbb{R}^{3\times 3}$ is the agent Inertia matrix

- $B_i \geq 0 \in \mathbb{R}^{3\times 3}$ is a velocity damping term (either naturally present or artificially added)

- Force (input) $F_i^a \in \mathbb{R}^3$ represents the interaction (coupling) with the other agents

- Force (input) $F_i^e \in \mathbb{R}^3$ represents the interaction with the "external world" (e.g., obstacles)

Agent Model

- **Remarks:**

- In PHS terms, an agent represents an atomic element storing kinetic energy

$$\mathcal{K}_i = \frac{1}{2} p_i^T M_i^{-1} p_i$$

and endowed with two power ports $(F_i^a,\ v_i)$ and $(F_i^e,\ v_i)$

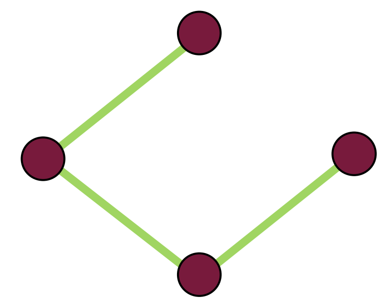
- We consider a simple "free-floating mass" mainly for easiness of exposition
  - Any other (more complex) mechanical (PHS) system would do the job, also constrained (e.g., ground robots)

- The Inertia matrix M_i can model different inertial properties in space
  - e.g., a quadrotor UAV with a faster vertical dynamics w.r.t. the horizontal one

- Heterogeneity in the group can be enforced by choosing different M_i and B_i

Neighboring Definition

- We want to allow for autonomous (and arbitrary) **split/join** decisions because of
  - Sensing/communication constraints
  - Any additional internal criterion (task)



- Let $d_{ij} = ||x_i - x_j||$ be the interdistance among two agents

- We assume (as usual) presence of a maximum sensing/communication range $D \in \mathbb{R}^+$

- Two agents cannot be neighbors if $d_{ij} > D$ (they cannot sense/communicate with each other)

- To also take into account more general requirements, we introduce a time-varying neighboring condition $\sigma_{ij} \in \{0,\ 1\}$ satisfying at least:

$$
\begin{aligned}
&1)\quad \sigma_{ij}(t) = 0,\ \text{if } d_{ij} > D \in \mathbb{R}^+; \\
&2)\quad \sigma_{ij}(t) = \sigma_{ji}(t).
\end{aligned}
$$

Neighboring Definition

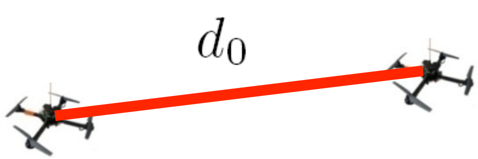
$$
\begin{aligned}
&1)\ \ \sigma_{ij}(t) = 0,\ \textit{if}\ d_{ij} > D \in \mathbb{R}^+; \\
&2)\ \ \sigma_{ij}(t) = \sigma_{ji}(t).
\end{aligned}
$$

- Interpretation:
  - Two agents cannot be neighbors if they are too far apart ($d_{ij} > D$)
  - The neighboring condition is symmetric $\sigma_{ij}(t) = \sigma_{ji}(t)$
  - Still, complete freedom in gaining/losing neighbors when $d_{ij} \leq D$
    - Additional sensing/comm. constraints
    - Additional parallel tasks
- This neighboring relationship induces a time-varying Undirected Graph $\mathcal{G} = (\mathcal{V}, \mathcal{E}(t))$ where

$$\mathcal{E}(t) = \{(i, j) \in \mathcal{V} \times \mathcal{V} \,|\, \sigma_{ij}(t) = 1 \Leftrightarrow j \in \mathcal{N}_i\}$$

Agent Interconnection

- When neighbors, the agents should keep a cohesive formation
- We consider the (simple) case of maintaining a desired interdistance $0 < d_0 < D$
  - Other more complex (e.g., relative position) cases are possible



$$\begin{cases} \dot{p}_i = F_i^a + F_i^e - B_i M_i^{-1} p_i \\ v_i = \dfrac{\partial \mathcal{H}_i}{\partial p_i} = M_i^{-1} p_i \end{cases}$$

- This cohesive motion must be achieved by means of local and 1-hop information (decentralization), and by exploiting the coupling force F_i^a in the agent dynamics

- When non-neighbors, no interaction among the agents

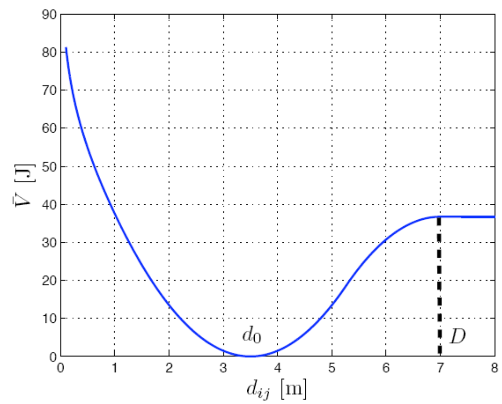
Agent Interconnection

- How to model this interagent coupling? Let us model it as a (nonlinear) elastic element

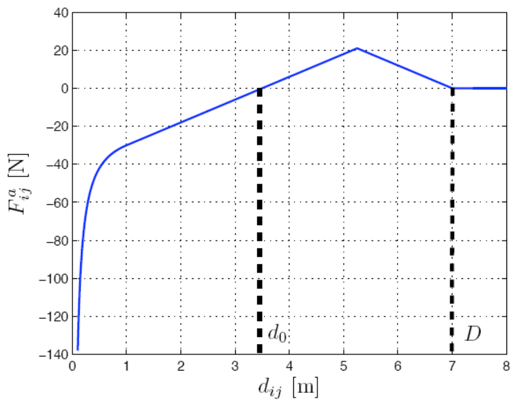
- Let $x_{ij} \in \mathbb{R}^3$ be the state of this element, and $V(x_{ij}) = \bar{V}(\|x_{ij}\|) \geq 0$ some (lower-bounded) Energy function (Hamiltonian)

- Take the usual PHS form for a storing element $\begin{cases} \dot{x}_{ij} = v_{ij} \\ F^a_{ij} = \dfrac{\partial V(x_{ij})}{\partial x_{ij}} \end{cases}$ where $v_{ij}, F^a_{ij} \in \mathbb{R}^3$ are the input/output vectors

- For $V(x_{ij})$, we take a function
  - lower-bounded
  - with a minimum at d_0
  - becoming flat for $d_{ij} > D$
  - growing unbounded for $d_{ij} \to 0$



$\bar{V}$



F^a_{ij}

Agent Interconnection

- Say i and j are neighbors, i.e., $\sigma_{ij}(t) = 1 \Leftrightarrow j \in \mathcal{N}_i$, how are they coupled with the elastic element?

$$\begin{cases} \dot{p}_i = F_i^a + F_i^e - B_i M_i^{-1} p_i \\ v_i = \frac{\partial \mathcal{K}_i}{\partial p_i} = M_i^{-1} p_i \end{cases} \qquad \begin{cases} \dot{x}_{ij} = v_{ij} \\ F_{ij}^a = \frac{\partial V(x_{ij})}{\partial x_{ij}} \end{cases} \qquad \begin{cases} \dot{p}_j = F_j^a + F_j^e - B_j M_j^{-1} p_j \\ v_j = \frac{\partial \mathcal{K}_j}{\partial p_j} = M_j^{-1} p_j \end{cases}$$

- Power preserving interconnection (assume for simplicity everything in $\mathbb{R}$)

$$\begin{bmatrix} F_i^a \\ F_j^a \\ v_{ij} \end{bmatrix} = \begin{bmatrix} 0 & 0 & -\sigma_{ij}(t) \\ 0 & 0 & \sigma_{ij}(t) \\ \sigma_{ij}(t) & -\sigma_{ij}(t) & 0 \end{bmatrix} \begin{bmatrix} v_i \\ v_j \\ F_{ij}^a \end{bmatrix}$$

- Motivation:

when neighbors $(\sigma_{ij} = 1)$

$$v_{ij} = \dot{x}_i - \dot{x}_j = v_i - v_j$$
$$F_i^a = -F_{ij}^a$$
$$F_j^a = F_{ij}^a = -F_{ji}^a$$

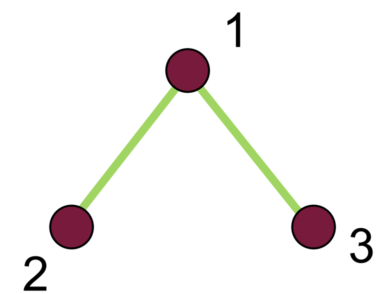
when non-neighbors $(\sigma_{ij} = 0)$

$$v_{ij} = 0$$
$$F_i^a = 0$$
$$F_j^a = 0$$

Agent Interconnection

- Note: for N agents, there exist $N(N-1)/2$ elastic elements (all the possible edges)

- Let us analyze the case of 3 agents with this interaction graph (3 agents and a total of 3 elastic elements)



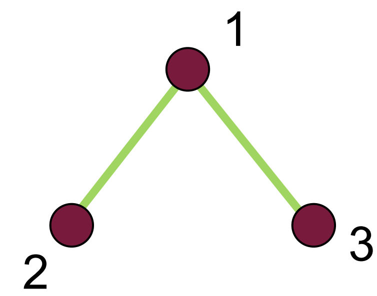
$$\begin{bmatrix} F_1^a \\ F_2^a \\ F_3^a \\ v_{12} \\ v_{13} \\ v_{23} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 0 & -1 & -1 & 0 \\ 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \\ 1 & -1 & 0 & 0 & 0 & 0 \\ 1 & 0 & -1 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \\ v_3 \\ F_{12}^a \\ F_{13}^a \\ F_{23}^a \end{bmatrix}$$

Missing edge “23”

Agent Interconnection

- What is the highlighted matrix?

$$\begin{bmatrix} F_1^a \\ F_2^a \\ F_3^a \\ v_{12} \\ v_{13} \\ v_{23} \end{bmatrix} = \begin{bmatrix} 0 & 0 & 0 & -1 & -1 & 0 \\ 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1 & 0 \\ 1 & -1 & 0 & 0 & 0 & 0 \\ 1 & 0 & -1 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \\ v_3 \\ F_{12}^a \\ F_{13}^a \\ F_{23}^a \end{bmatrix}$$



- Let us call it $E_{\mathcal{G}} \in \mathbb{R}^{N \times N(N-1)/2}$. This is (almost) the Incidence matrix of graph $\mathcal{G}$
  - labeling and orientation induced by the entries $(v_{12},\ v_{13},\ v_{23})$
  - however, also accounts (with zero columns) for all the missing edges

$$\begin{bmatrix} F_1^a \\ F_2^a \\ F_3^a \\ v_{12} \\ v_{13} \\ v_{23} \end{bmatrix} = \begin{bmatrix} 0 & E_{\mathcal{G}} \\ -E_{\mathcal{G}}^T & 0 \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \\ v_3 \\ F_{12}^a \\ F_{13}^a \\ F_{23}^a \end{bmatrix}$$

Agent Interconnection

- Note that $F_i^a = \sum_{j\in\mathcal{N}_i} e_{ij} F_{ij}^a := \sum_{j\in\mathcal{N}_i} e_{ij} \frac{\partial \bar{V}}{\partial d_{ij}} \frac{\partial d_{ij}}{\partial x_{ij}}$

- Therefore, the coupling Force F_i^a for agent i can be computed in a decentralized way
  - Need to know only x_i and $x_j,\ j \in \mathcal{N}_i$

- Let us now generalize for N agents

- Let $x = (x_{12}^T, \ldots, x_{1N}^T, x_{23}^T, \ldots, x_{2N}^T, \ldots, x_{N-1N}^T)^T \in \mathbb{R}^{\frac{3N(N-1)}{2}}$ collect all the elastic element states (edges), and implicitly defining an orientation for the graph $\mathcal{G}$ (labeling and orientation given by the entries in x)

- Let $p = (p_1^T, \ldots, p_N^T)^T \in \mathbb{R}^{3N}$ collect all the agent states (momenta)

- Let $B = diag(B_i) \in \mathbb{R}^{3N\times 3N}$ collect all the damping terms

- Let $H = \sum_{i=1}^{N} \mathcal{K}_i + \sum_{i=1}^{N-1} \sum_{j=i+1}^{N} V(x_{ij})$ be the Total Energy (Hamiltonian)

Agent Interconnection

- The overall group of interconnected agents becomes the PHS

$$\begin{cases} \begin{pmatrix} \dot{p} \\ \dot{x} \end{pmatrix} = \left[\begin{pmatrix} 0 & E(t) \\ -E^T(t) & 0 \end{pmatrix} - \begin{pmatrix} B & 0 \\ 0 & 0 \end{pmatrix} \right] \begin{pmatrix} \frac{\partial H}{\partial p} \\ \frac{\partial H}{\partial x} \end{pmatrix} + GF^e \\ v = G^T \begin{pmatrix} \frac{\partial H}{\partial p} \\ \frac{\partial H}{\partial x} \end{pmatrix} \end{cases}$$

- Here, $G = \left((I_N \otimes I_3)^T \quad 0^T \right)^T$ and $E(t) = E_{\mathcal{G}}(t) \otimes I_3$

- The symbol $\otimes$ denotes the Kronecker product among matrixes

$$A \otimes B = \begin{bmatrix} a_{11}B & \dots & a_{1N}B \\ \vdots & \ddots & \vdots \\ a_{N1}B & \dots & a_{NN}B \end{bmatrix}$$

- And with $F^e = (F_1^{eT} \dots F_N^{eT})^T \in \mathbb{R}^{3N}$ being the input and $v = (v_1^T \dots v_N^T) \in \mathbb{R}^{3N}$ the output vectors

Agent Interconnection

- The PHS group of agents

$$\begin{cases} \begin{pmatrix} \dot{p} \\ \dot{x} \end{pmatrix} = \left[\begin{pmatrix} 0 & E(t) \\ -E^T(t) & 0 \end{pmatrix} - \begin{pmatrix} B & 0 \\ 0 & 0 \end{pmatrix} \right] \begin{pmatrix} \frac{\partial H}{\partial p} \\ \frac{\partial H}{\partial x} \end{pmatrix} + GF^e \\ v = G^T \begin{pmatrix} \frac{\partial H}{\partial p} \\ \frac{\partial H}{\partial x} \end{pmatrix} \end{cases}$$

has then an external port $(v,\ F^e)$ where $F^e = (F_1^{eT} \dots F_N^{eT})^T \in \mathbb{R}^{3N}$ and

$$v = (v_1^T \dots v_N^T) \in \mathbb{R}^{3N}$$

$$\begin{cases} \dot{p}_i = F_i^a + F_i^e - B_i M_i^{-1} p_i \\ v_i = \frac{\partial K_i}{\partial p_i} = M_i^{-1} p_i \end{cases}$$

- The port $(v,\ F^e)$ is the one interacting with the external world (**obstacles, external commands**)

- Let us then study the passivity of the group w.r.t. the port $(v,\ F^e)$

Passivity of the Group

- Suppose for now a fixed topology for the graph, i.e., $E(t) = E = const$
- Since H is lower bounded, the group of agents is passive w.r.t. its external port

$$\dot{H} = -\frac{\partial^T H}{\partial p} B \frac{\partial H}{\partial p} + v^T F^e \leq v^T F^e$$

- Does this automatically extend to the general case $E(t)$?
- Consider first the case of a split $\sigma_{ij} = 1 \rightarrow \sigma_{ij} = 0$
- The edge $(i,\, j)$ is lost and the Incidence matrix is updated accordingly $E \rightarrow E'$
- The group dynamics becomes

$$\begin{cases} \begin{pmatrix} \dot{p} \\ \dot{x} \end{pmatrix} = \left[\begin{pmatrix} 0 & E' \\ -E'^T & 0 \end{pmatrix} - \begin{pmatrix} B & 0 \\ 0 & 0 \end{pmatrix} \right] \begin{pmatrix} \frac{\partial H}{\partial p} \\ \frac{\partial H}{\partial x} \end{pmatrix} + G F^e \\ v = G^T \begin{pmatrix} \frac{\partial H}{\partial p} \\ \frac{\partial H}{\partial x} \end{pmatrix} \end{cases}$$

Passivity of the Group

- Since E' appears in a skew-symmetric matrix, overall passivity is preserved

$$\dot{H} = -\frac{\partial^T H}{\partial p} B \frac{\partial H}{\partial p} + v^T F^e \leq v^T F^e$$

- Then, **exactly the same argument** holds for the join case $\sigma_{ij} = 0 \rightarrow \sigma_{ij} = 1$

- **<u>Unfortunately, it doesn't!!!</u>**

- During a join, the Incidence matrix is updated as before $E \rightarrow E'$

- BUT this is not the only action needed to join

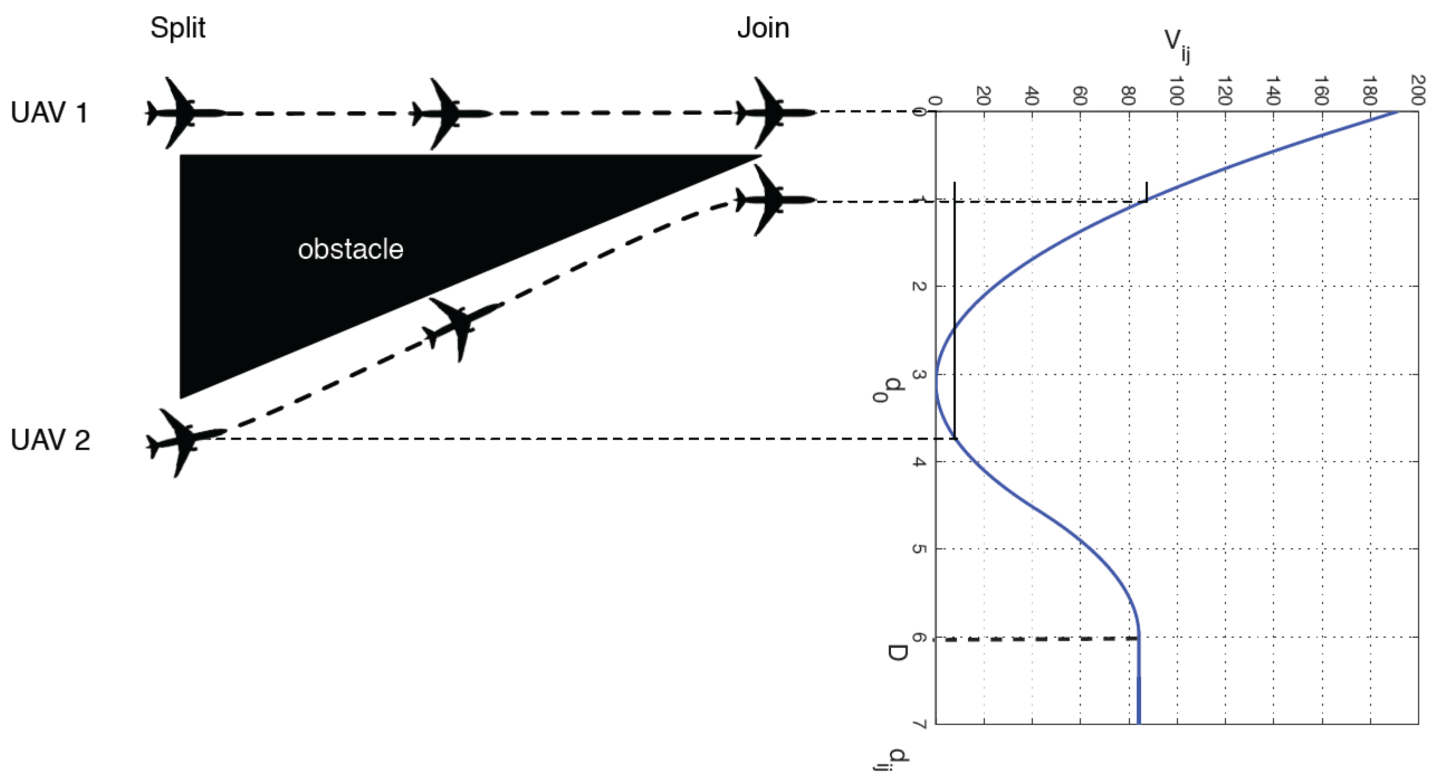
- At the join, the state of the elastic element must be reset to the actual relative position of agents i and j

$$x_{ij} \leftarrow x_i - x_j$$

- This action, in general, **<u>costs extra energy</u>**! (thus, can violate passivity)

Passivity of the Group

- Consider this situation (visibility and interdistance determine neighboring)



- Because of different interdistances at the split and join decisions, it is $V_{\text{join}} > V_{\text{split}}$

- A naïve join would inject extra energy into the slave-side $\Delta V = V_{\text{join}} - V_{\text{split}} > 0$

Passivity of the Group

- How to still implement a join procedure? How to passify it?
- If some $\Delta V = V_{\text{join}} - V_{\text{split}} > 0$ is needed, this must be drawn from energy sources already present in the agent group
  - Passivity = no internal production of extra energy
- Can we find some internal energy storages from which to cover for ΔV ?
- Make use of Energy Tanks and Energy Transfer control
  - Store back the agent inherent dissipation $D_i = p_i^T M_i^{-T} B_i M_i^{-1} p_i$
  - Exploit Tank Energies for passively implement a (otherwise non-passive) join
  - Obviously, everything still to be done in a decentralized way…

Passivity of the Group

- Let us then apply the Tank machinery
- First, augment the agent state with the Tank dynamics, with $T(x_{t_i}) = \frac{1}{2}x_{t_i}^2 \geq 0$

$$\begin{cases} \dot{p}_i = F_i^a + F_i^e - B_i M_i^{-1} p_i \\ v_i = \frac{\partial \mathcal{K}_i}{\partial p_i} = M_i^{-1} p_i \end{cases} \Rightarrow \begin{cases} \dot{p}_i &= F_i^a + F_i^e - B_i M_i^{-1} p_i \\ \dot{x}_{t_i} &= \frac{1}{x_{t_i}} D_i + w_{ij}^t \\ y &= \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases}$$

- Second, endow the elastic elements with an additional input $w_{ij}^x \in \mathbb{R}^3$ for exchanging energy with the Tanks

$$\begin{cases} \dot{x}_{ij} &= v_{ij} \\ F_{ij}^a &= \frac{\partial V(x_{ij})}{x_{ij}} \end{cases} \Rightarrow \begin{cases} \dot{x}_{ij} &= v_{ij} + w_{ij}^x \\ F_{ij}^a &= \frac{\partial V(x_{ij})}{x_{ij}} \end{cases}$$

Passivity of the Group

$$\begin{cases} \dot{p}_i = F_i^a + F_i^e - B_i M_i^{-1} p_i \\ \dot{x}_{t_i} = \dfrac{1}{x_{t_i}} D_i + w_{ij}^t \\ y = \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases} \quad \Longleftrightarrow \quad \begin{cases} \dot{x}_{ij} = v_{ij} + w_{ij}^x \\ F_{ij}^a = \dfrac{\partial V(x_{ij})}{x_{ij}} \end{cases} \quad \Longleftrightarrow \quad \begin{cases} \dot{p}_j = F_j^a + F_j^e - B_j M_j^{-1} p_j \\ \dot{x}_{t_j} = \dfrac{1}{x_{t_j}} D_j + w_{ji}^t \\ y = \begin{bmatrix} v_j \\ x_{t_j} \end{bmatrix} \end{cases}$$

- Exploiting the Energy Transfer control:
  - inputs w_{ij}^x, w_{ij}^t and w_{ji}^t will allow for drawing ΔV from the Tanks of agents i and j
  - this allows implementing the join action (and resetting the spring state to the correct value $x_{ij} \leftarrow x_i - x_j$)

- Recall, the Energy Transfer control among two **PHS** was implemented by the coupling

$$\begin{bmatrix} u_1 \\ u_2 \end{bmatrix} = \begin{bmatrix} 0 & -\alpha y_1(x_1) y_2^T(x_2) \\ \alpha y_2(x_2) y_1^T(x_1) & 0 \end{bmatrix} \begin{bmatrix} y_1 \\ y_2 \end{bmatrix}, \quad \alpha \in \mathbb{R}$$

- Likewise, we choose $\begin{bmatrix} w_{ij}^x \\ w_{ij}^t \\ w_{ji}^t \end{bmatrix} = \begin{bmatrix} 0 & -\gamma_{ij} F_{ij}^a t_i & -\gamma_{ij} F_{ij}^a t_j \\ \gamma_{ij} {F_{ij}^a}^T t_i & 0 & 0 \\ \gamma_{ij} {F_{ij}^a}^T t_j & 0 & 0 \end{bmatrix} \begin{bmatrix} F_{ij}^a \\ t_i \\ t_j \end{bmatrix}, \; \gamma_{ij} \in \mathbb{R}$

Passivity of the Group

- The parameter γ_{ij} dictates the rate and direction of Energy transfer
- A value $\gamma_{ij} < 0$ refills the spring energy and draws from the two Tanks
- The machinery easily extends to multiple connections among agents and springs

$$\begin{cases} \dot{p}_i &= F_i^a + F_i^e - B_i M_i^{-1} p_i \\ \dot{x}_{t_i} &= \dfrac{1}{x_{t_i}} D_i + \sum_{j=1}^{N} w_{ij}^t \\ y &= \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases}$$

- Note that the previous interconnection can be implemented in a decentralized way
  - agent i needs to know F_{ij}^a and t_i (local and 1-hop information)
  - $\gamma_{ij} = 0$ by convention if $j \notin \mathcal{N}_i$

Passivity of the Group

- Strategy for implementing a join decision in a passive way among agents $(i,\ j)$:
  - 1. at the join moment, compute $\Delta V = V(x_i - x_j) - V(x_{ij})$
  - 2. if $\Delta V \leq 0$, implement the join (and store ΔV back into the tanks T_i and T_j)
  - 3. if $\Delta V > 0$, extract ΔV from T_i and T_j

- **What if $T_i + T_j < \Delta V$?**

- Must take a decision:
  - Do not join (and wait for better conditions)
  - Ask the rest of the group for "help"

- How to ask for "help" in a decentralized and passive way?
  - **<u>A possibility</u>**: run a **<u>consensus</u>** on all the Tank Energies
  - This redistributes the energies within the group
  - But it doesn't change the total amount of energy

Passivity of the Group

- Additional (and last) modification to the agent dynamics

$$\begin{cases} \dot{p}_i & = & F_i^a + F_i^e - B_i M_i^{-1} p_i \\ \dot{x}_{t_i} & = & (1-\beta_i)\left(\frac{1}{x_{t_i}} D_i + \sum_{j=1}^N w_{ij}^t\right) + \beta_i c_i \\ y & = & \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases}$$

- The parameter $\beta_i \in \{0,\ 1\}$ enables/disables the consensus mode

- During consensus ($\beta_i = 1$), we want $\dot{T}_i = -\sum_{j \in \mathcal{N}_i} (T_i - T_j)$

- This is achieved by setting $c_i = -\frac{1}{t_i} \sum_{j \in \mathcal{N}_i} (T_i(t_i) - T_j(t_j))$

Passivity of the Group

- Compact form of the Passive Join procedure (decentralized and passive)

Procedure PassiveJoin

Data: $x_i, x_j, x_{ij}^s, t_i, t_j$

1 *Compute* $\Delta E = V(x_i - x_j) - V(x_{ij}^s)$;
2 **if** $\Delta E \leq 0$ **then**
3   *Store* $(-\Delta E)/2$ in the tank through input w_{ij};
else
4   **if** $T_i(t_i) + T_j(t_j) < \Delta E + 2\varepsilon$ **then**
5   Run a *consensus* on the tank variables;
6   **if** $2T_i(t_i) < \Delta E + 2\varepsilon$ **then**
7   *Dampen* until $T(t_i) + T(t_j) \geq \Delta E + 2\varepsilon$;
8   *Extract* $\dfrac{T(t_i)}{T(t_i) + T(t_j)} \Delta E$ from the tank through input w_{ij};
9 *Join*;

- Note: if after the consensus still not enough energy (line 6)
  - The agents do not join
  - They can switch to a high damping mode for more quickly refilling the Tanks

Passivity of the Group

- By considering the Tank dynamics and the PassiveJoin Procedure, the group dynamics becomes

$$
\begin{cases}
\begin{bmatrix} \dot{p} \\ \dot{x} \\ \dot{x}_t \end{bmatrix} = \left(\begin{bmatrix} 0 & E(t) & 0 \\ -E^T(t) & 0 & \Gamma^T \\ 0 & -\Gamma & 0 \end{bmatrix} - \begin{bmatrix} B & 0 & 0 \\ 0 & 0 & 0 \\ -(I-\beta)PB & 0 & 0 \end{bmatrix} \right) \begin{bmatrix} \frac{\partial \mathcal{H}}{\partial p} \\ \frac{\partial \mathcal{H}}{\partial x} \\ \frac{\partial \mathcal{H}}{\partial x_t} \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ \beta c \end{bmatrix} + GF^e \\
v = G^T \begin{bmatrix} \frac{\partial \mathcal{H}}{\partial p} \\ \frac{\partial \mathcal{H}}{\partial x} \\ \frac{\partial \mathcal{H}}{\partial x_t} \end{bmatrix}
\end{cases}
$$

where the new Hamiltonian is $\mathcal{H} = \sum_{i=1}^{N} \mathcal{K}_i + \sum_{i=1}^{N-1} \sum_{j=i+1}^{N} V(x_{ij}) + \sum_{i=1}^{N} T_i$ and $\beta = diag(\beta_i)$, $P = diag(\frac{1}{t_i} p_i^T M_i^{-T})$, and matrix $\Gamma \in \mathbb{R}^{N \times \frac{3N(N-1)}{2}}$ representing the interconnection between Tanks and springs

Passivity of the Group

- Proposition: the group dynamics (with Tanks, Energy Transfer, Consensus, and PassiveJoin Procedure)

$$
\begin{cases}
\begin{bmatrix} \dot{p} \\ \dot{x} \\ \dot{x}_t \end{bmatrix} = \left(\begin{bmatrix} 0 & E(t) & 0 \\ -E^T(t) & 0 & \Gamma^T \\ 0 & -\Gamma & 0 \end{bmatrix} - \begin{bmatrix} B & 0 & 0 \\ 0 & 0 & 0 \\ -(I-\beta)PB & 0 & 0 \end{bmatrix} \right) \begin{bmatrix} \frac{\partial \mathcal{H}}{\partial p} \\ \frac{\partial \mathcal{H}}{\partial x} \\ \frac{\partial \mathcal{H}}{\partial x_t} \end{bmatrix} + \begin{bmatrix} 0 \\ 0 \\ \beta c \end{bmatrix} + GF^e \\
v = G^T \begin{bmatrix} \frac{\partial \mathcal{H}}{\partial p} \\ \frac{\partial \mathcal{H}}{\partial x} \\ \frac{\partial \mathcal{H}}{\partial x_t} \end{bmatrix}
\end{cases}
$$

is still passive $\dot{\mathcal{H}} \leq v^T F^e$

- **Proof: left as exercise**

Passivity of the Group

- Additional remarks:

- We can always enforce a limiting strategy for the Tank refilling action by means of a parameter $\alpha_i \in \{0,\ 1\}$

$$\begin{cases} \dot{p}_i & = & F_i^a + F_i^e - B_i M_i^{-1} p_i \\ \dot{x}_{t_i} & = & \alpha_i \dfrac{1}{x_{t_i}} D_i + \sum_{j=1}^{N} w_{ij}^t \\ y & = & \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases}$$

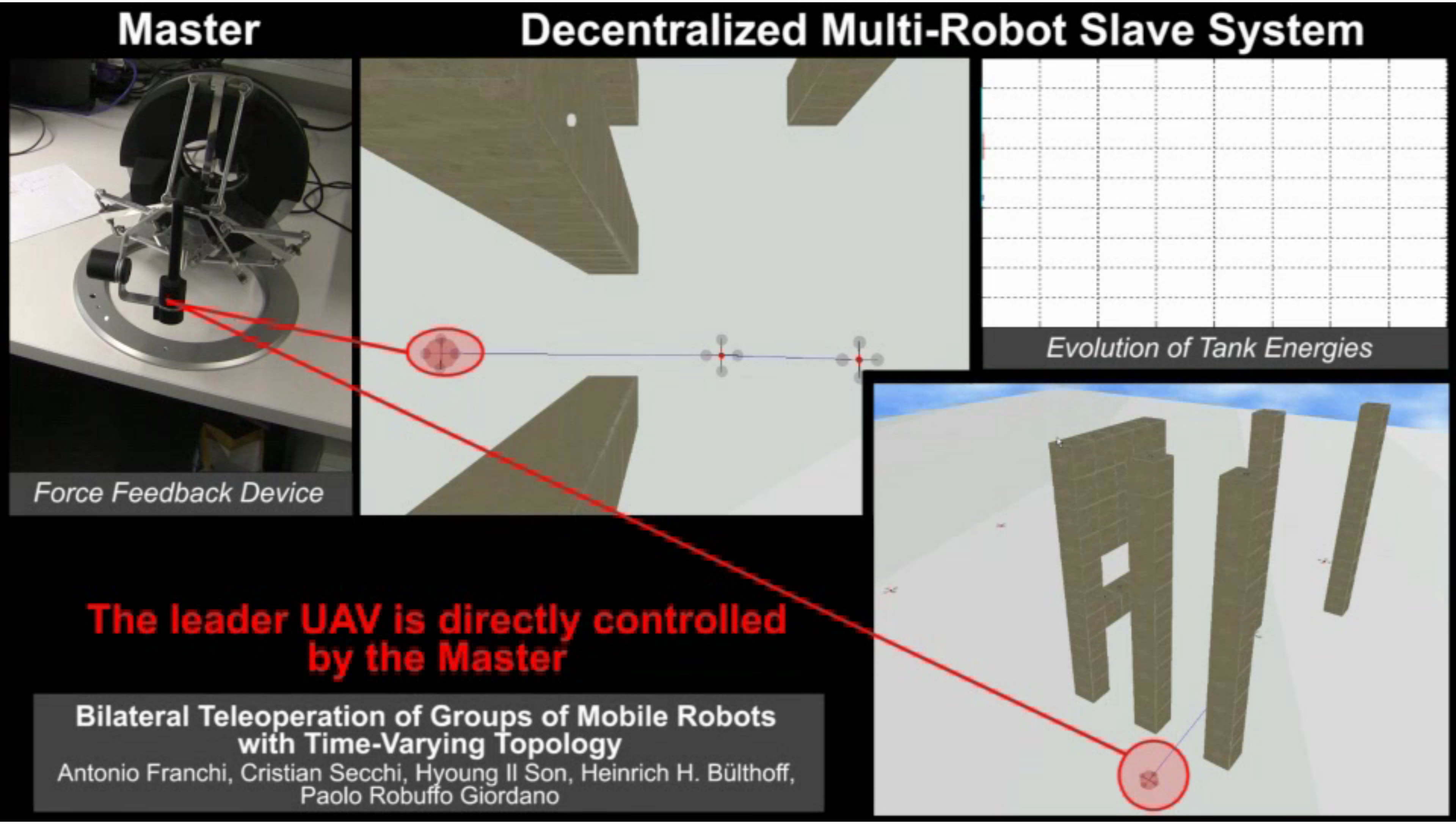
such that $\alpha_i = \begin{cases} 0, & \text{if} \quad T_i \geq \bar{T}_i \\ 1, & \text{if} \quad T_i < \bar{T}_i \end{cases}$ where $\bar{T}_i$ is a suitable upper bound for the Tank energy level

- This way, we can avoid a too large accumulation and prevent **practical** non-passive behaviors over short periods of time

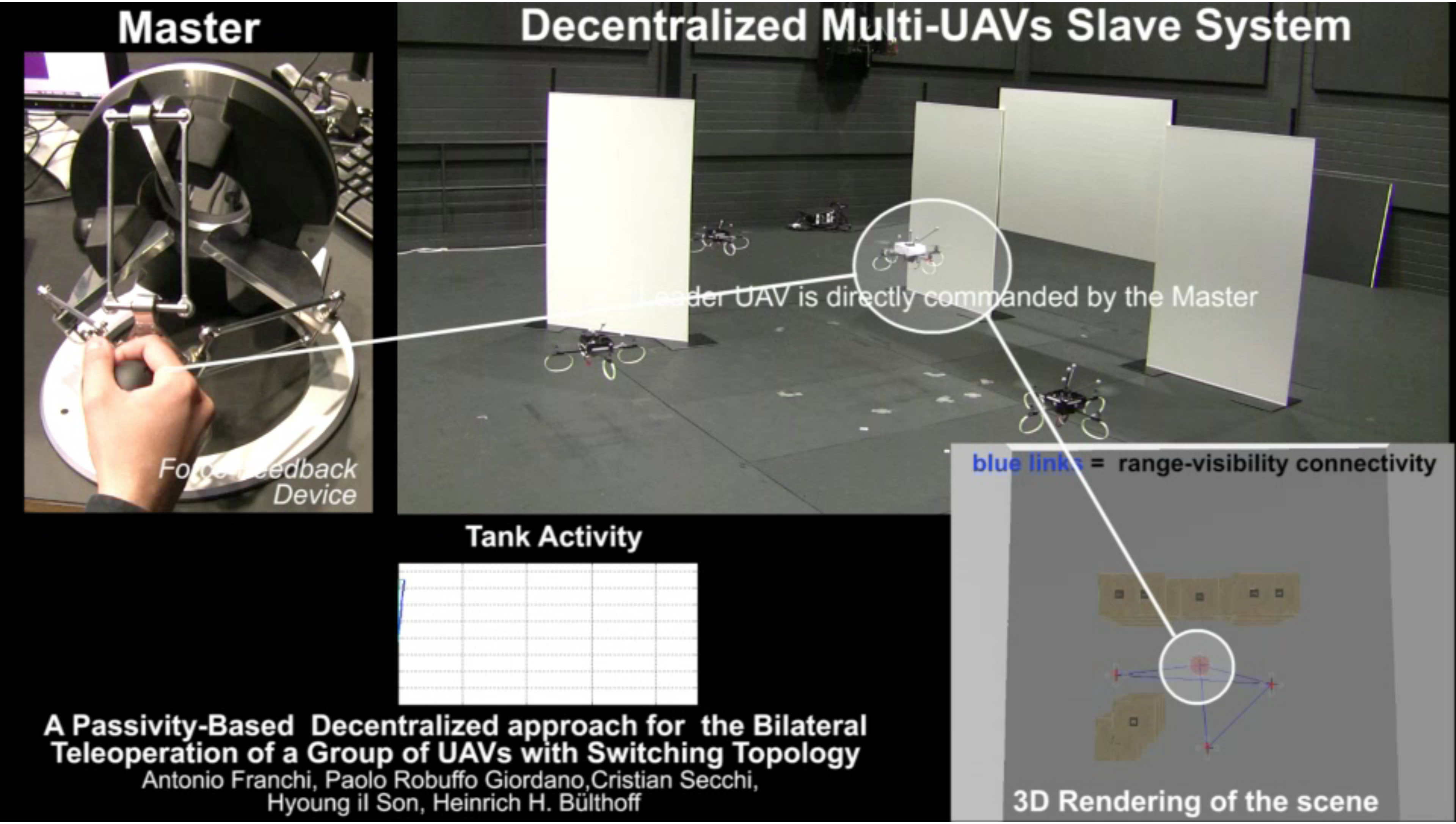
Steering the UAV formation

- Consider one leader, and split its external force as $F_l^e = F_s + F_l^{\text{env}}$
- Assume the leader must track a given velocity command $r_M \in \mathbb{R}^3$
- This can be achieved by adding this "force" to the leader $F_s = b_T(r_M - v_l)$ where v_l is the leader velocity
- Essentially: proportional controller on the velocity error $r_M - v_l$

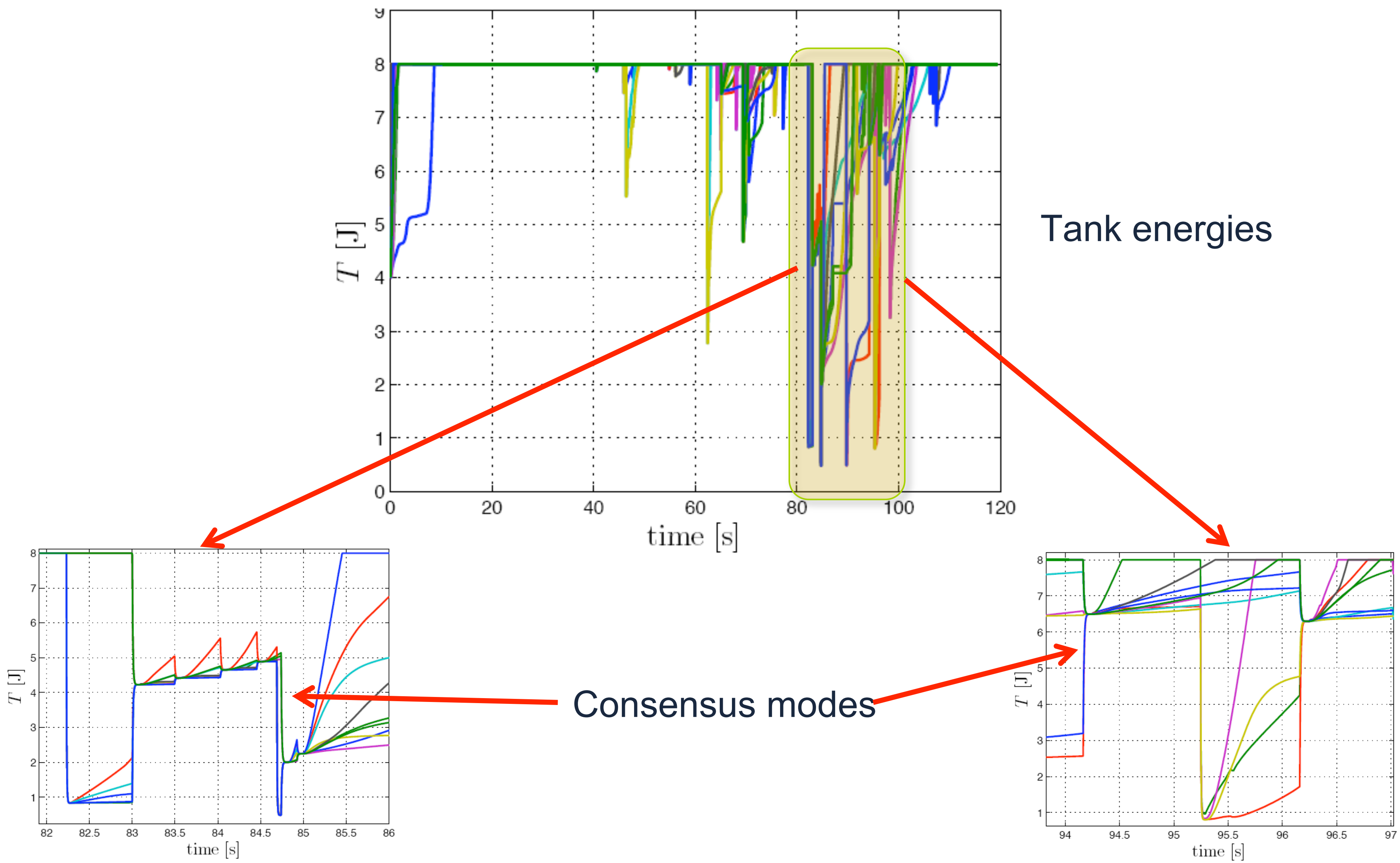
Steering the UAV formation



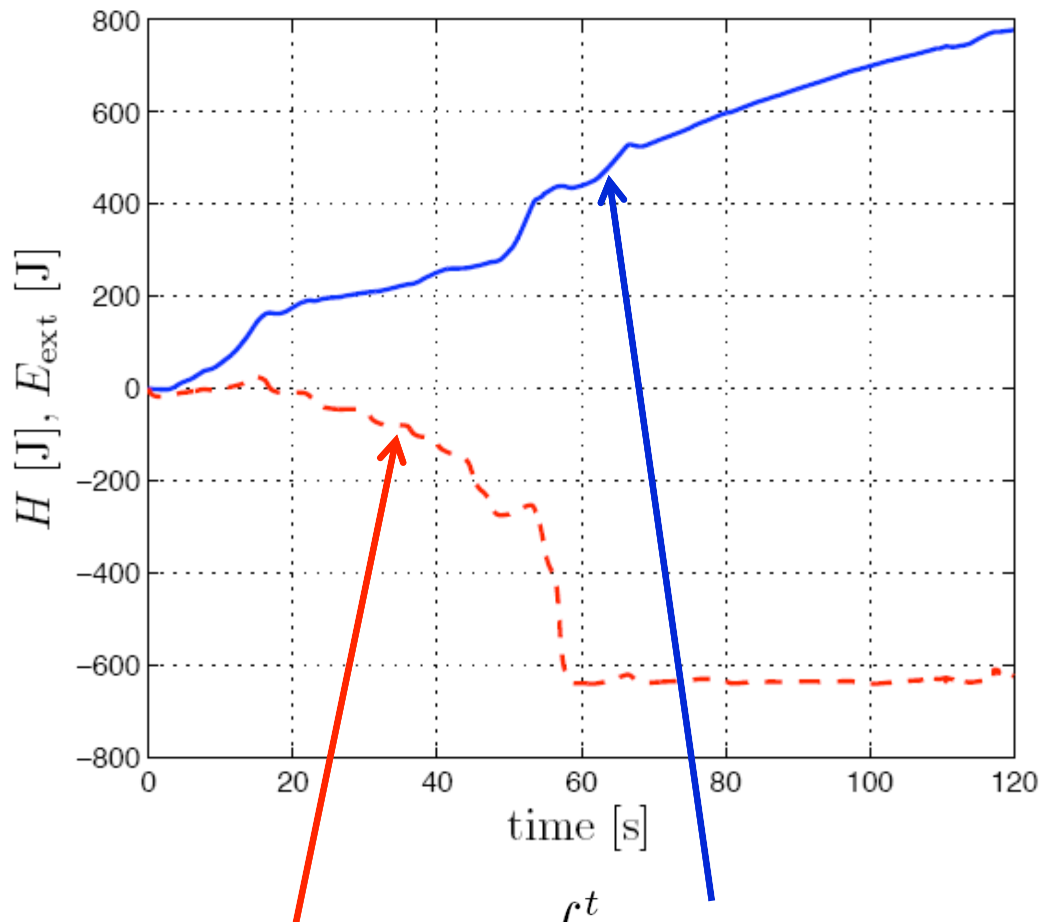
Steering the UAV formation



Steering the UAV formation



Steering the UAV formation



Slave-side Passivity condition

$$\mathcal{H}(t) - \mathcal{H}(t_0) \leq \int_{t_0}^{t} v^T(\tau) F^e(\tau) \mathrm{d}\tau$$

(Integral version of $\dot{\mathcal{H}} \leq v^T F^e$)

Velocity Synchronization

- Assume a constant velocity command for the leader $r_M = const$
- Do the agents, at steady-state, synchronize with this velocity command?

$$v_i \to r_M, \quad \forall i \ ?$$

- We must characterize the steady-state of the system (**<u>if it exists</u>**)

- Assumptions for the steady-state:
  - 1) $F_i^{\text{env}} = 0, \quad \forall i = 1, \ldots, N$ (no environmental forces – no close obstacles)
  - 2) Tanks are full to $\bar{T}_i$ and $\Gamma = 0$ (no joins, no energy exchanges with elastic elements)
  - 3) $\mathcal{G}$ is **connected** (can always reduce to the connected component of the leader)

- Also assume (w.l.o.g.) that the leader is agent 1
  - For the leader, $F_1^e = F_s = b_T(r_M - v_1)$
  - For all the others, $F_i^e = F_i^{\text{env}} = 0$ (because of Assumption 1)

Velocity Synchronization

- Step 1: with $r_M = const$ and Assumptions 1), 2), 3), prove existence of a steady-state

- It can be proven that a steady-state exists such that $(\dot{p},\, \dot{x},\, \dot{t}) = (0,\, 0,\, 0)$
  - follows from "exosystem"-like arguments + output strictly passivity of the slave-side (see, e.g., Isidori's book Nonlinear Control Systems)

- At steady-state:
  - Velocities stay constant $(\dot{p} = \dot{v} = 0)$ (assuming constant mass for the agents)
  - Spring lengths (relative positions) stay constant $(\dot{x} = 0)$
  - Tank energies stay constant $(\dot{t} = 0)$. This follows from Assumption 2)

- To which steady-state velocity do the agents converge? Is it $v_i = r_M = const$ for all of them?

Velocity Synchronization

- Under these assumptions, and splitting F_s into the two contributions $b_T r_M$ and $-b_T v_1$, one can rewrite the agent group dynamics as

$$\begin{pmatrix} \dot{p} \\ \dot{x} \\ \dot{t} \end{pmatrix} = \begin{pmatrix} -B' & E & 0 \\ -E^T & 0 & 0 \\ 0 & 0 & 0 \end{pmatrix} \begin{pmatrix} \frac{\partial \mathcal{H}}{\partial p} \\ \frac{\partial \mathcal{H}}{\partial x} \\ \frac{\partial \mathcal{H}}{\partial t} \end{pmatrix} + u$$

where $B' = \mathrm{diag}(B_i')$, $B_1' = B_1 + b_T I_3$, $B_i' = B_i$ and $u = \left(b_T r_M^T\, 0 \ldots 0\right)^T \in \mathbb{R}^{3N}$

- And then impose the steady-state condition $(\dot{p},\ \dot{x},\ \dot{t}) = (0,\ 0,\ 0)$

- The first "row" becomes $B' \frac{\partial \mathcal{H}}{\partial p} - E \frac{\partial \mathcal{H}}{\partial x} = u$

- The second "row" becomes $E^T \frac{\partial \mathcal{H}}{\partial p} = 0$

Velocity Synchronization

- Two conditions: $B' \frac{\partial \mathcal{H}}{\partial p} - E \frac{\partial \mathcal{H}}{\partial x} = u$ and $E^T \frac{\partial \mathcal{H}}{\partial p} = 0$
- We know that, for connected graphs, $\ker E^T = \mathbf{1}_{N_3}$ where $\mathbf{1}_{N_3} = \mathbf{1}_N \otimes I_3$
- Therefore, $\frac{\partial \mathcal{H}}{\partial p} = \mathbf{1}_{N_3} v_{ss}$ for some $v_{ss} \in \mathbb{R}^3$. All the agents have the same velocity
- By plugging this result into the first condition, we get $B' \mathbf{1}_{N_3} v_{ss} - E \frac{\partial \mathcal{H}}{\partial x} = u$
- Pre-multiply both sides by $\mathbf{1}_{N_3}^T$ to get $\mathbf{1}_{N_3}^T B' \mathbf{1}_{N_3} v_{ss} = \mathbf{1}_{N_3}^T u = b_T r_M$
- This finally results into the sought value $v_{ss} = (\mathbf{1}_{N_3}^T B' \mathbf{1}_{N_3})^{-1} b_T r_M$

Velocity Synchronization

- Conclusions: at steady-state (Assumptions 1), 2), 3) and $r_M = const$), all the agent velocities reach

$$v_i \to v_{ss} = (\mathbf{1}_{N_3}^T B' \mathbf{1}_{N_3})^{-1} b_T r_M$$

- One can check that $\|v_{ss}\| < \|r_M\|$

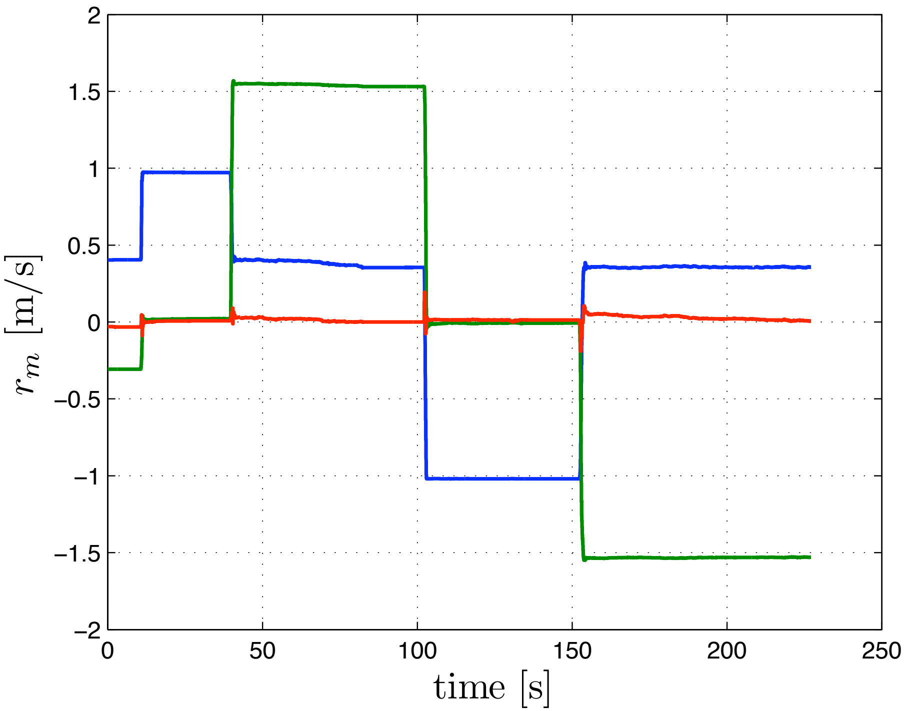
- For instance, for "scalar" damping terms $B_i = b_i I_3$ this reduces to

$$v_{ss} = \frac{b_T r_M}{b_T + \sum b_i}$$

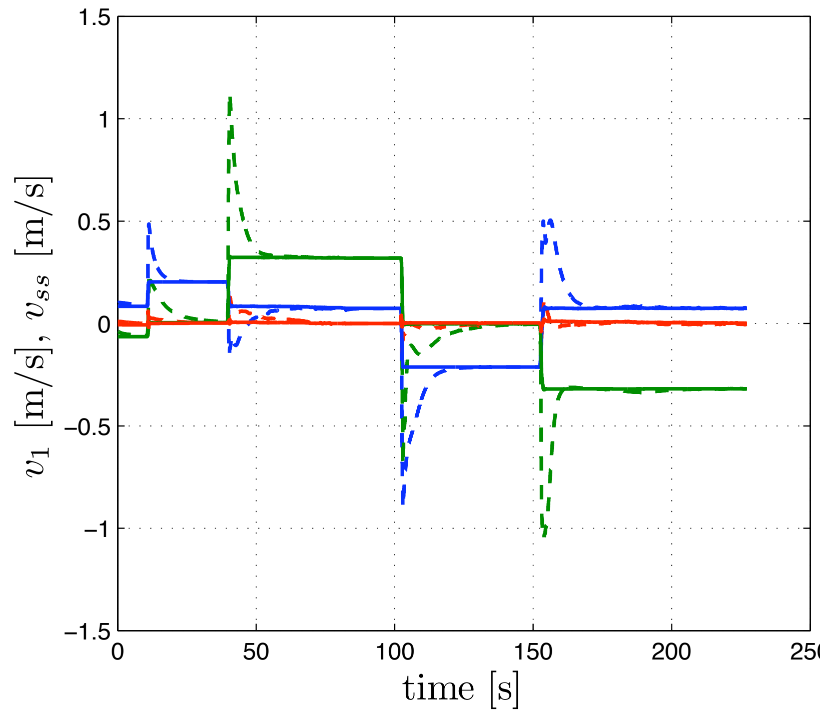
- The agents always travel "slower" than the commanded r_M

- Perfect synchronization only if $b_i = 0$ (no damping on any agent!)

Velocity Synchronization

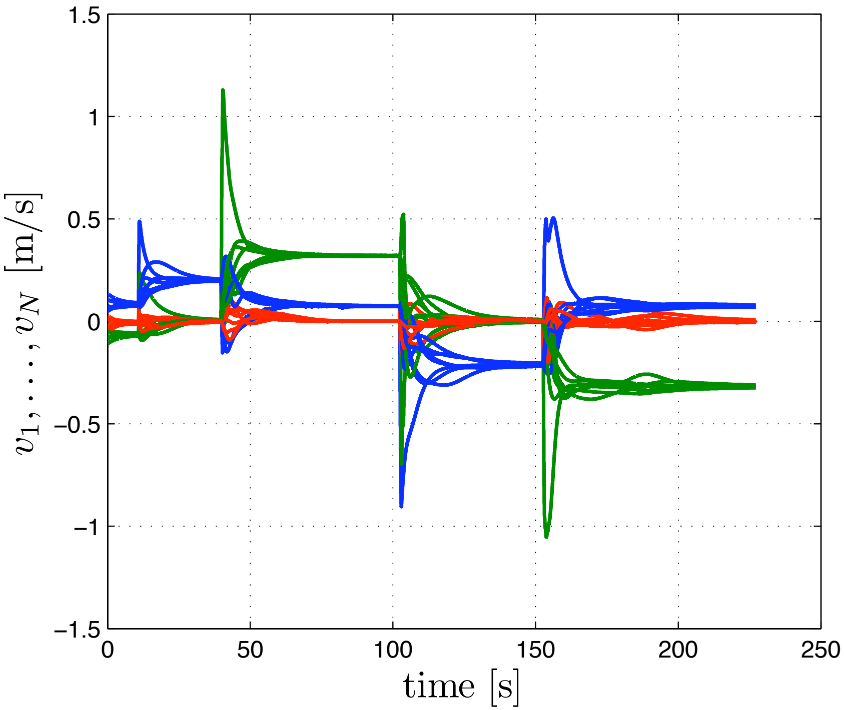


Leader velocity command r_M

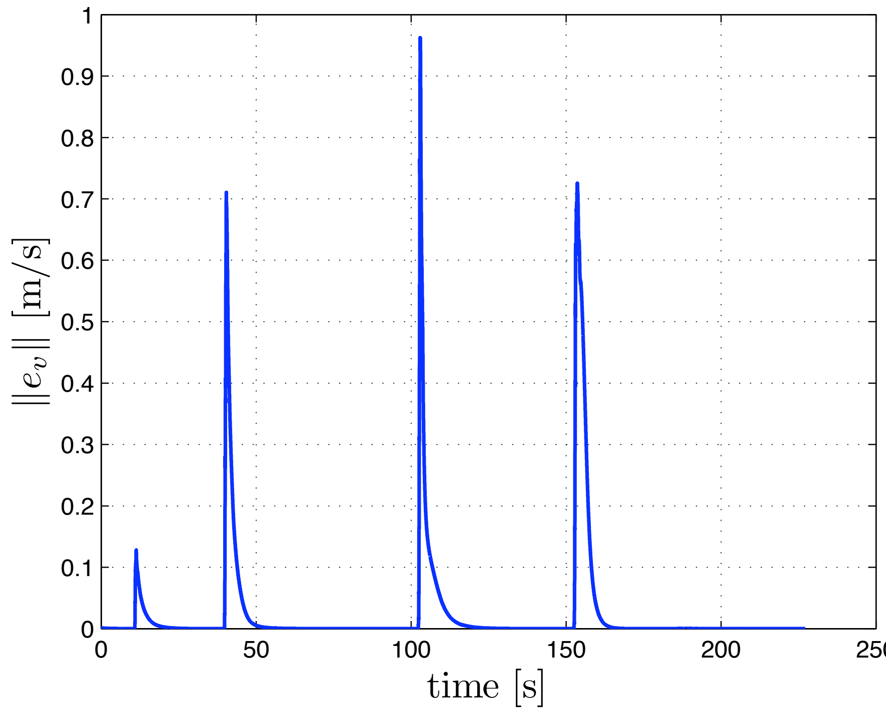


Leader vel. v_1 vs. predicted v_{ss}

Velocity Synchronization



All agent velocities



Norm of velocity synchronization error

$$\|e_v\| = \|v - \mathbf{1}_{N_3} v_{ss}\|$$

Velocity Synchronization

- How to synchronize velocities with r_M (at steady-state)?

- The damping terms B_i are
  - good for stabilization and Tank refill
  - bad for vel. synchronization, as they "slow down" the agents....
  - ....it seems they should be "switched off"

- Must modify the agent dynamics: consider

$$\begin{cases} \dot{p}_i &= F_i^a + F_i^e - B_i M_i^{-1} p_i \\ \dot{x}_{t_i} &= \dfrac{1}{x_{t_i}} D_i + \sum_{j=1}^{N} w_{ij}^t \\ y &= \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases} \quad \Rightarrow \quad \begin{cases} \dot{p}_i &= F_i^a + F_i^e + F_i^s + F_i^d \\ \dot{x}_{t_i} &= \dfrac{1}{x_{t_i}} D_i + \sum_{j=1}^{N} w_{ij}^t \\ y &= \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases}$$

where $F_i^d = -B_i(t_i) M_i^{-1} p_i$ is the "damping" force, but with a **variable damping term**

$$B_i(t_i) = \begin{cases} 0 & \text{if} \quad T(t_i) = \bar{T}_i \\ \bar{B}_i & \text{if} \quad T(t_i) < \bar{T}_i \end{cases}$$

Velocity Synchronization

- The damping B_i is now active only when needed to refill the Tank T_i

$$\begin{cases} \dot{p}_i = F_i^a + F_i^e + F_i^s + F_i^d \\ \dot{x}_{t_i} = \dfrac{1}{x_{t_i}} D_i + \sum_{j=1}^{N} w_{ij}^t \\ y = \begin{bmatrix} v_i \\ x_{t_i} \end{bmatrix} \end{cases}$$

- The additional (synchronization) force F_i^s is designed as $F_i^s = -b \sum_{j \in \mathcal{N}_i} (v_i - v_j)$ (<u>**consensus among velocities**</u>)

- The group dynamics takes the form

$$\begin{cases} \begin{pmatrix} \dot{p} \\ \dot{x} \\ \dot{t} \end{pmatrix} = \left[\begin{pmatrix} 0 & E & 0 \\ -E^T & 0 & \Gamma^T \\ 0 & -\Gamma & 0 \end{pmatrix} - \begin{pmatrix} \mathcal{L} + B & 0 & 0 \\ 0 & 0 & 0 \\ -PB & 0 & 0 \end{pmatrix} \right] \nabla \mathcal{H} + G F^e \\ v = G^T \nabla \mathcal{H} \end{cases}$$

Velocity Synchronization

- Matrix $\mathcal{L} = bL \otimes I_3$ where L is the Laplacian of the Graph $\mathcal{G}$

$$\begin{cases} \begin{pmatrix} \dot{p} \\ \dot{x} \\ \dot{t} \end{pmatrix} = \left[\begin{pmatrix} 0 & E & 0 \\ -E^T & 0 & \Gamma^T \\ 0 & -\Gamma & 0 \end{pmatrix} - \begin{pmatrix} \mathcal{L} + B & 0 & 0 \\ 0 & 0 & 0 \\ -PB & 0 & 0 \end{pmatrix} \right] \nabla \mathcal{H} + G F^e \\ v = G^T \nabla \mathcal{H} \end{cases}$$

- Exercise: prove that the system is passive

$$\dot{\mathcal{H}} = -\frac{\partial^T \mathcal{H}}{\partial p} \mathcal{L} \frac{\partial \mathcal{H}}{\partial p} + v^T F^e \leq v^T F^e$$

- What can be said about the steady-state regime?

Velocity Synchronization

- Assumptions (analogously to before):
  - 1) $F_i^{\text{env}} = 0, \quad \forall i = 1, \ldots, N$ (no external forces – no close obstacles)
  - 2) $B_i(t_i) = 0$ and $\Gamma = 0$ (tanks full and no energy exchange with elastic elements)
  - 3) $\mathcal{G}$ is **connected**

- Then, at steady-state:
  - 1) $v_i \to r_M = const$ (all agents synchronize with the commanded velocity)
  - 2) $\dot{x} = 0$ (all spring lengths/relative positions stay constant)

- Proof: apply the change of coordinates $(p,\, x,\, t) \to (\tilde{p},\, x,\, t)$ where $\tilde{p}_i = p_i - M_i r_M$
- The quantity $\tilde{p}_i$ is the "**momentum (velocity) synchronization error**"

- New "energy" $\tilde{\mathcal{K}}_i = \frac{1}{2}\tilde{p}_i^T M_i^{-1} \tilde{p}_i,$

$$\tilde{H} = \sum_{i=1}^{N} \tilde{\mathcal{K}}_i + \sum_{i=1}^{N-1} \sum_{j=i+1}^{N} V(x_{ij}) + \sum_{i=1}^{N} T_i$$

Velocity Synchronization

- What is the dynamics of $\tilde{p}$? $\dot{\tilde{p}} = \dot{p} = E\dfrac{\partial \mathcal{H}}{\partial x} - (\mathcal{L} + B)\dfrac{\partial \mathcal{H}}{\partial p} + GF^e$

- **Facts:**
  - 1) $\dfrac{\partial \mathcal{H}}{\partial x} = \dfrac{\partial \tilde{\mathcal{H}}}{\partial x}$ and $\dfrac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} = v - \mathbf{1}_{N_3} r_M = \dfrac{\partial \mathcal{H}}{\partial p} - \mathbf{1}_{N_3} r_M$
  - 2) $\mathcal{L}\dfrac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} = \mathcal{L}\dfrac{\partial \mathcal{H}}{\partial p}$ and $E^T\dfrac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} = E^T\dfrac{\partial \mathcal{H}}{\partial p}$
  - 3) $B = 0$ and $\Gamma = 0$ (assumption 2))

- Then, the group dynamics can be rewritten in terms of new coordinates and new energy function

$$\dot{\tilde{p}} = E\frac{\partial \tilde{\mathcal{H}}}{\partial x} - \mathcal{L}\frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} + GF^e$$

$$\dot{x} = -E^T\frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}}$$

Velocity Synchronization

- New dynamics

$$\begin{cases} \begin{pmatrix} \dot{\tilde{p}} \\ \dot{x} \\ \dot{t} \end{pmatrix} = \left[\begin{pmatrix} 0 & E & 0 \\ -E^T & 0 & 0 \\ 0 & 0 & 0 \end{pmatrix} - \begin{pmatrix} \mathcal{L} & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \end{pmatrix} \right] \nabla \tilde{H} + G F^e \\ v = G^T \nabla \tilde{H} \end{cases}$$

- Let us study the asymptotic stability: $\dot{\tilde{H}} = -\frac{\partial^T \tilde{\mathcal{H}}}{\partial \tilde{p}} \mathcal{L} \frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} + \frac{\partial^T \tilde{\mathcal{H}}}{\partial \tilde{p}} F^e$

- By using Assumption 1) and the expression of $F_s = b_T (r_M - v_1) = -b_T \frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}_1}$

we obtain $\dot{\tilde{\mathcal{H}}} = -\frac{\partial^T \tilde{\mathcal{H}}}{\partial \tilde{p}} \mathcal{L} \frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} - \frac{\partial^T \tilde{\mathcal{H}}}{\partial \tilde{p}_1} b_T \frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}_1} \leq 0$

- Energy function non-increasing -> system trajectories are bounded

Velocity Synchronization

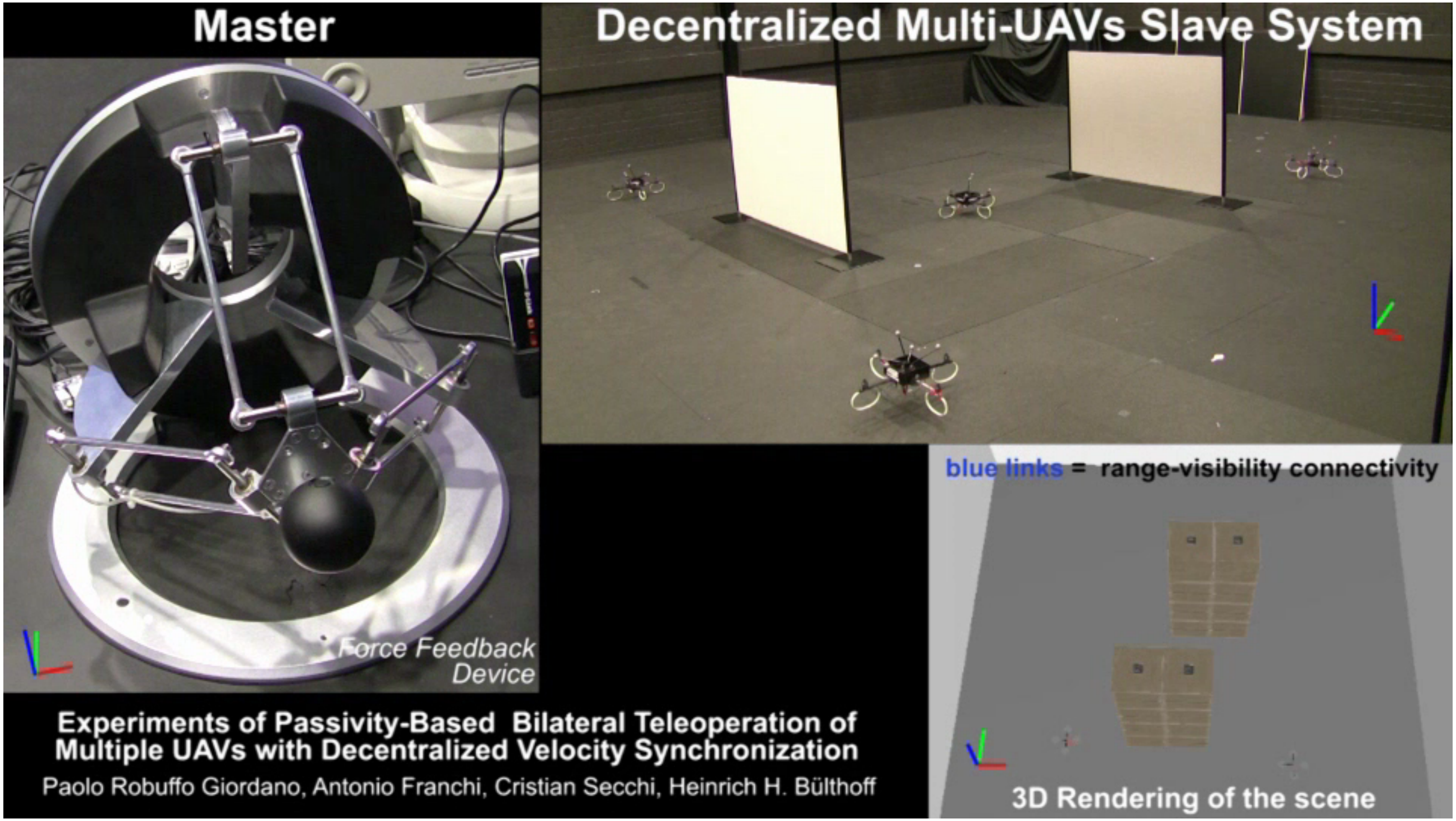
$$\dot{\tilde{\mathcal{H}}} = -\frac{\partial^T \tilde{\mathcal{H}}}{\partial \tilde{p}} \mathcal{L} \frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} - \frac{\partial^T \tilde{\mathcal{H}}}{\partial \tilde{p}_1} b_T \frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}_1} \leq 0$$

- Must study the properties of the set $S = \{(\tilde{p}, x, t) \mid \dot{\tilde{H}} = 0\}$ (~ LaSalle)
- In this set, it is $\frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} \in \ker \mathcal{L}$ and $\frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}_1} = 0$
- Since $\ker \mathcal{L} = \mathbf{1}_{N_3}$, the set S is characterized by $\frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} = 0$
- From the dynamics -> $\dot{x} = -E^T \frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} = 0$ (proof of Item 2)
- The condition $\frac{\partial \tilde{\mathcal{H}}}{\partial \tilde{p}} = 0$ implies $v - \mathbf{1}_{N_3} r_M = M(v - \mathbf{1}_{N_3} r_M) = \tilde{p} = 0$

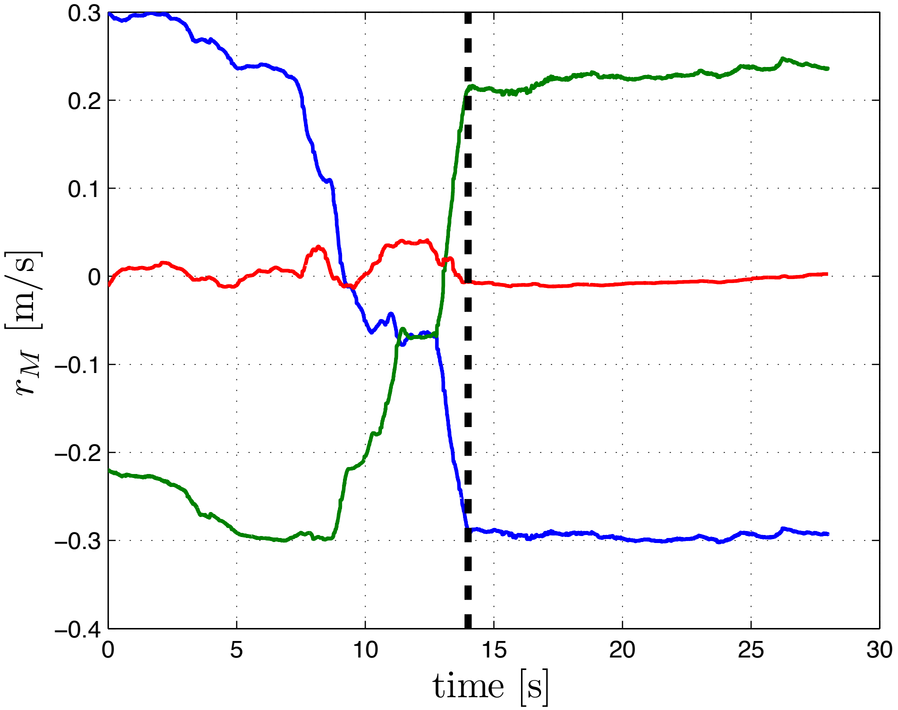
and $\dot{\tilde{p}} = 0$ (proof of Item 1)

Velocity Synchronization

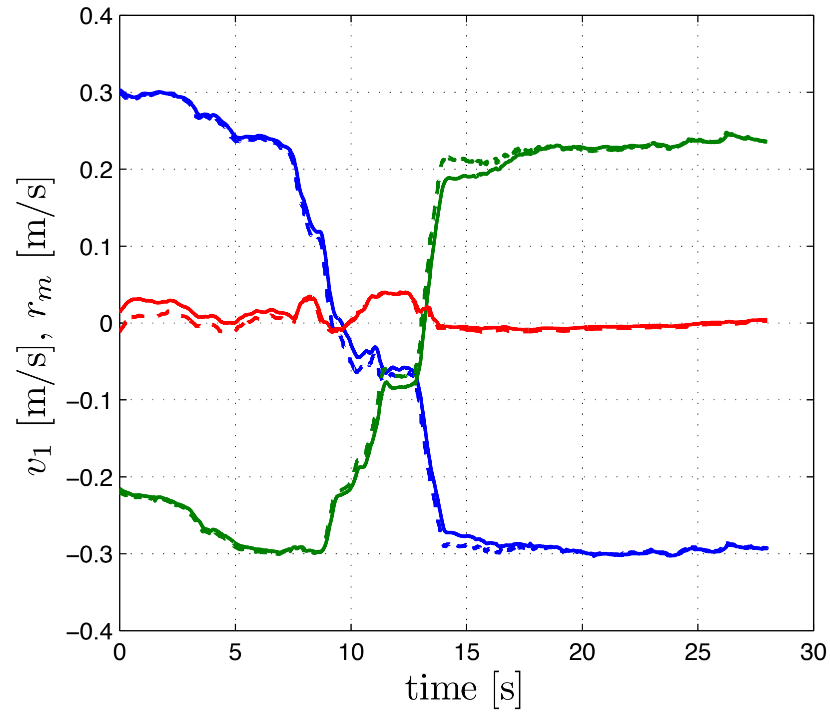
- Therefore, the system converges towards a steady-state condition $(\dot{\tilde{p}},\, \dot{x},\, \dot{t}) = (0,\, 0,\, 0)$ and $v = \mathbf{1}_{N_3} r_M$ (perfect synchronization with leader velocity commands)



Velocity Synchronization

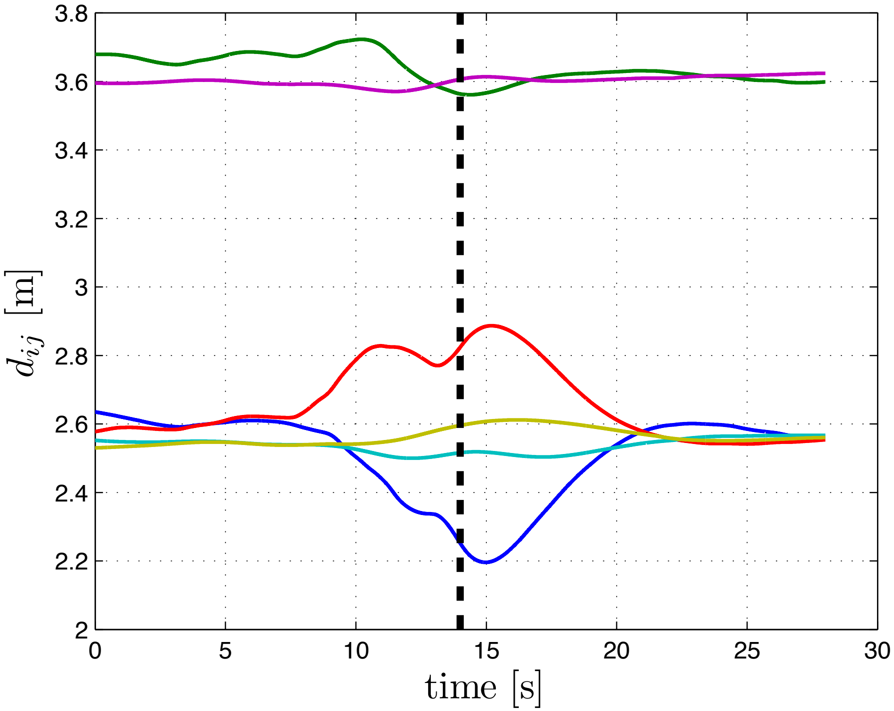


Master velocity commands r_M

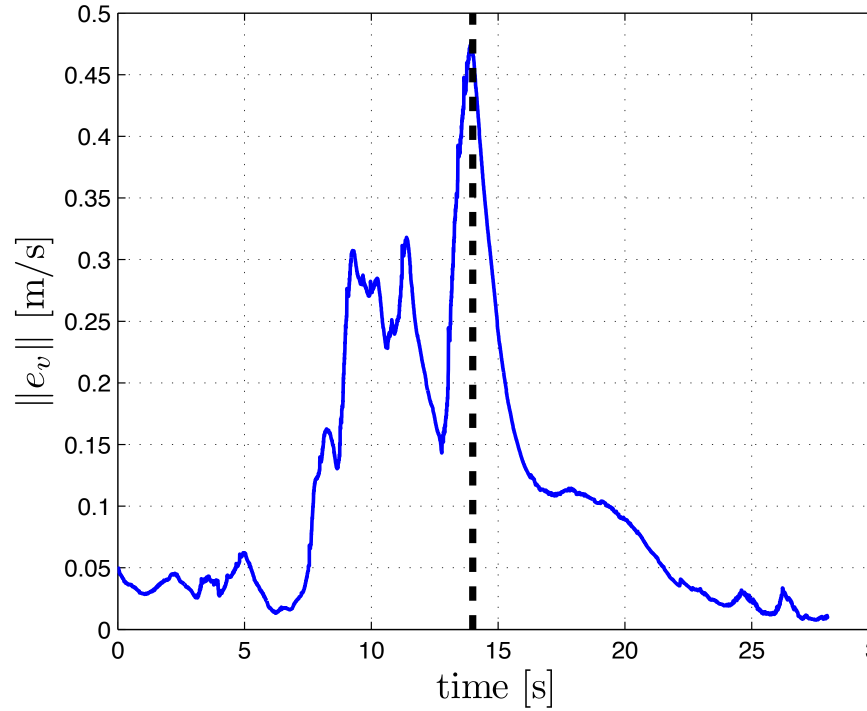


Leader vel. v_1 vs. r_M

Velocity Synchronization



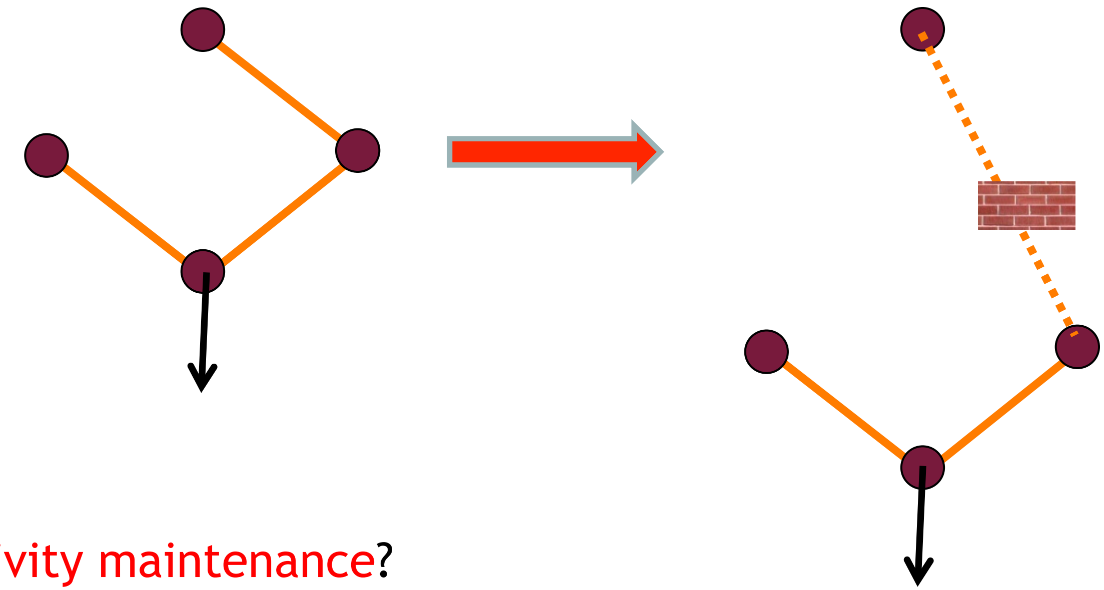
Interdistances



Norm of velocity synchronization error

$$\|e_v\| = \|v - \mathbf{1}_{N_3} r_M\|$$

Connectivity Maintenance



- What about connectivity maintenance?

- Can the graph $\mathcal{G}$ stay connected while still allowing **arbitrary split** and **join** as before?

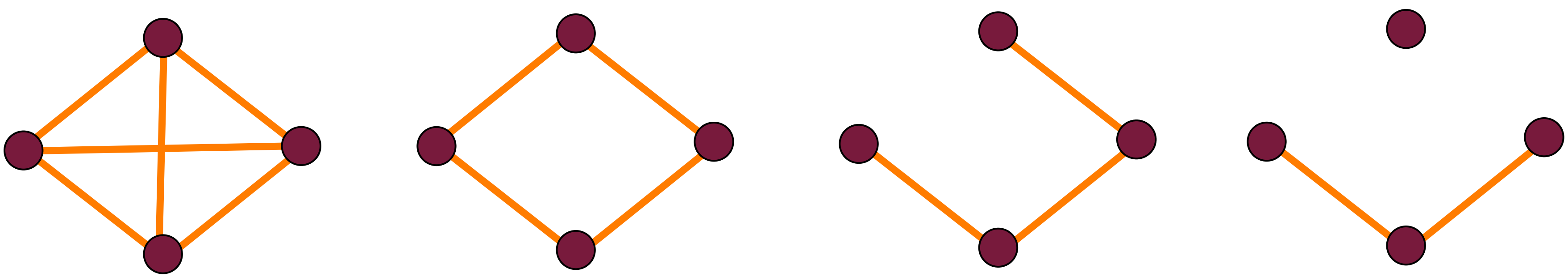
- And...

- How to do it in a decentralized and stable/passive way?

Connectivity Maintenance

- Connected graph -> $\lambda_2 > 0$ (second smallest eigenvalue of the graph Laplacian L)

- λ_2 is a measure of the degree of connectivity in a graph
  - The larger its value, the "more connected" the graph



$\lambda_2 = 4$ $\lambda_2 = 2$ $\lambda_2 = 0.58$ $\lambda_2 = 0$

- However:
  - λ_2 is a global quantity ⟶ against decentralization?
  - λ_2 does not vary smoothly over time ⟶ cannot take "derivatives"

Connectivity Maintenance

- **As illustration**, it would be nice if one could have $\lambda_2 = \lambda_2(x)$ and then just implement some gradient-like controller $u = \dfrac{\partial \lambda_2}{\partial x}$

- This situation is actually possible: assume the weights of the Adjacency matrix are smooth functions of the state $A_{ij} = A_{ij}(x) \geq 0$ rather than $A_{ij} = \{0,\ 1\}$

- Then, the Laplacian itself becomes a smooth function of the state

$$L = \Delta(x) - A(x) = L(x)$$

- Let v_2 be the normalized eigenvector associated to λ_2

- By definition, it is $\lambda_2 = v_2^T L v_2$

- Then, $\mathrm{d}\lambda_2 = \mathrm{d}v_2^T L v_2 + v_2^T \mathrm{d}L v_2 + v_2^T L \mathrm{d}v_2$

Connectivity Maintenance

- How can we simplify $\mathrm{d}\lambda_2 = \mathrm{d}v_2^T L v_2 + v_2^T \mathrm{d}L v_2 + v_2^T L \mathrm{d}v_2$?

- Fact 1: since L is symmetric, it is $\mathrm{d}v_2^T L v_2 = v_2^T L \mathrm{d}v_2$

- Fact 2: $\mathrm{d}v_2^T L v_2 = \lambda_2 \mathrm{d}v_2^T v_2 = 0$ since v_2 is a normalized vector ($\|v_2\| = 1$)

- Then, $\mathrm{d}\lambda_2 = v_2^T \mathrm{d}L v_2$

- This implies that $\dfrac{\partial \lambda_2}{\partial x_i} = \displaystyle\sum_{(i,j)\in\mathcal{E}} \frac{\partial A_{ij}}{\partial x_i}(v_{2_i} - v_{2_j})^2$ (follows from the definition of L)

- Note the nice "decentralized structure": <u>sum over the neighbors</u>

Connectivity Maintenance

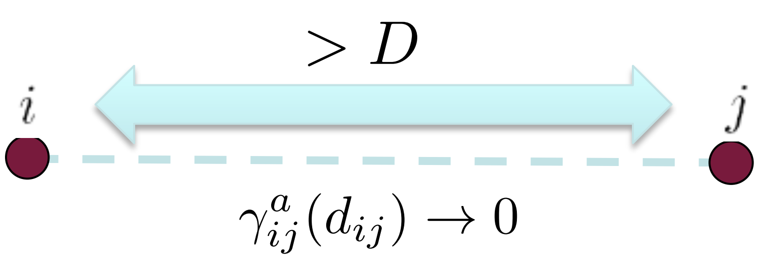
- Now, we are just left with a proper design of the weights $A_{ij}(x)$
- The weights $A_{ij}(x)$ should possess the following features:
  - 1) they should be function of relative quantities, e.g., $A_{ij}(x_i - x_j)$
  - 2) they should smoothly vanish as a disconnection is approaching
    - for example, $A_{ij}(x_i - x_j) \to 0$ as $d_{ij} \to D$ for the max. range constraint
- One can exploit and extend this idea in order to embed in the weights A_{ij}
  - presence of physical limitations for interacting (e.g., occlusions, maximum range)
  - additional agent requirements which should be preferably met (e.g., keeping a desired interdistance)
  - additional agent requirements which must be necessarily met (avoiding collisions with obstacles and other agents)
- Everything achieved by the sole "maximization" of the unique scalar quantity $\lambda_2(x)$
  - **"physical" connectivity** + any **additional group requirement**

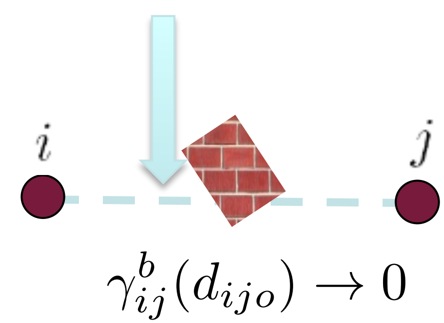
Connectivity Maintenance

- A possibility: define the weights A_{ij} as the product of three terms

$$A_{ij} = \alpha_{ij}\beta_{ij}\gamma_{ij}$$

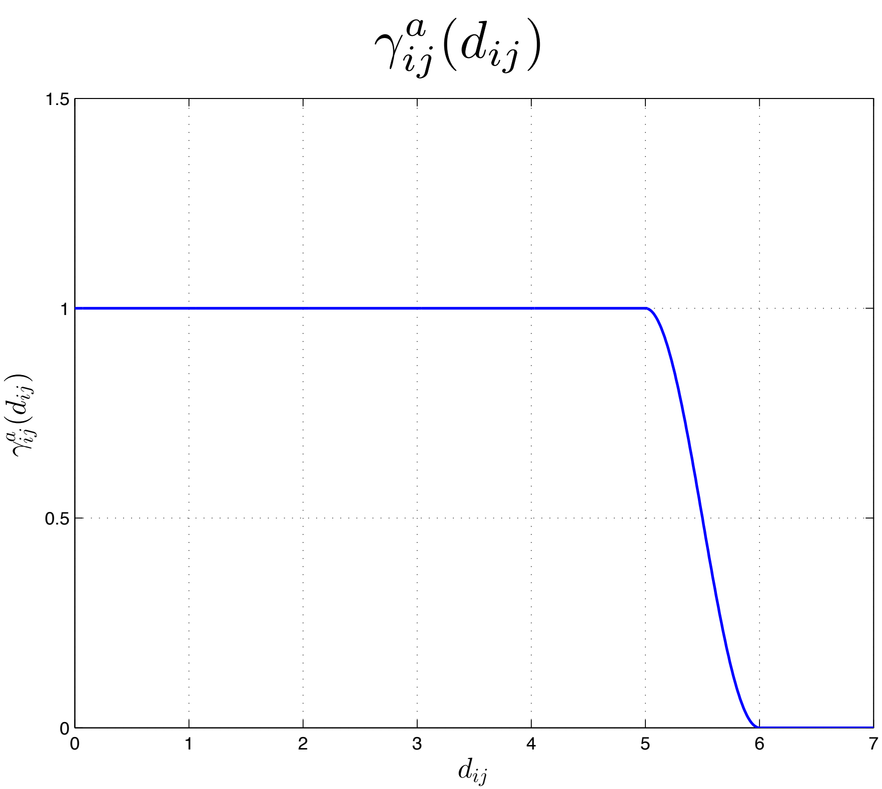
- The term $\gamma_{ij} \geq 0$ accounts for "physical" limitations in the relative sensing/communication, it represents the **sensing/communication model**
  - For instance, take $\gamma_{ij} = \gamma_{ij}^a(d_{ij})\gamma_{ij}^b(d_{ijo})$ where d_{ijo} is the distance from the segment joining agents i and j and the closest obstacle point o_{ij} and design
  - $\gamma_{ij}^a(d_{ij}) \to 0$ when exceeding the maximum range ($d_{ij} \to D$)
  - $\gamma_{ij}^b(d_{ijo}) \to 0$ when being occluded by an obstacle ($d_{ijo} \to 0$)

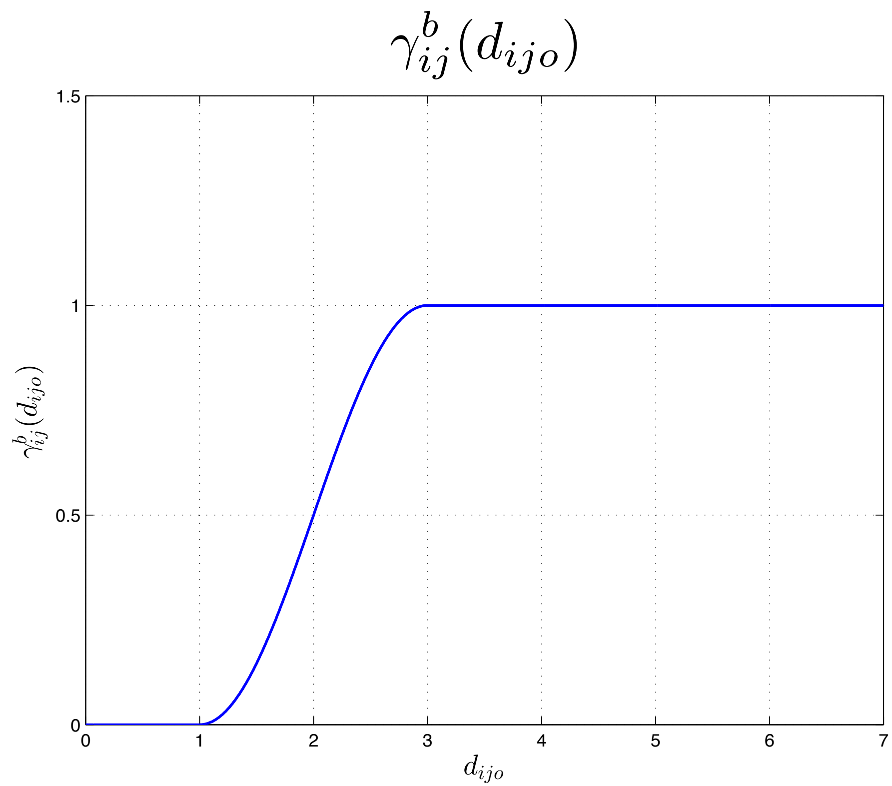




Connectivity Maintenance

- The weight $\gamma_{ij} = \gamma_{ij}^a(d_{ij})\gamma_{ij}^b(d_{ijo})$ is made of two terms
- $\gamma_{ij}^a(d_{ij}) \geq 0$ accounts for the maximum range constraint
- $\gamma_{ij}^b(d_{ijo}) \geq 0$ accounts for the minimum distance between line-of-sight and obstacles

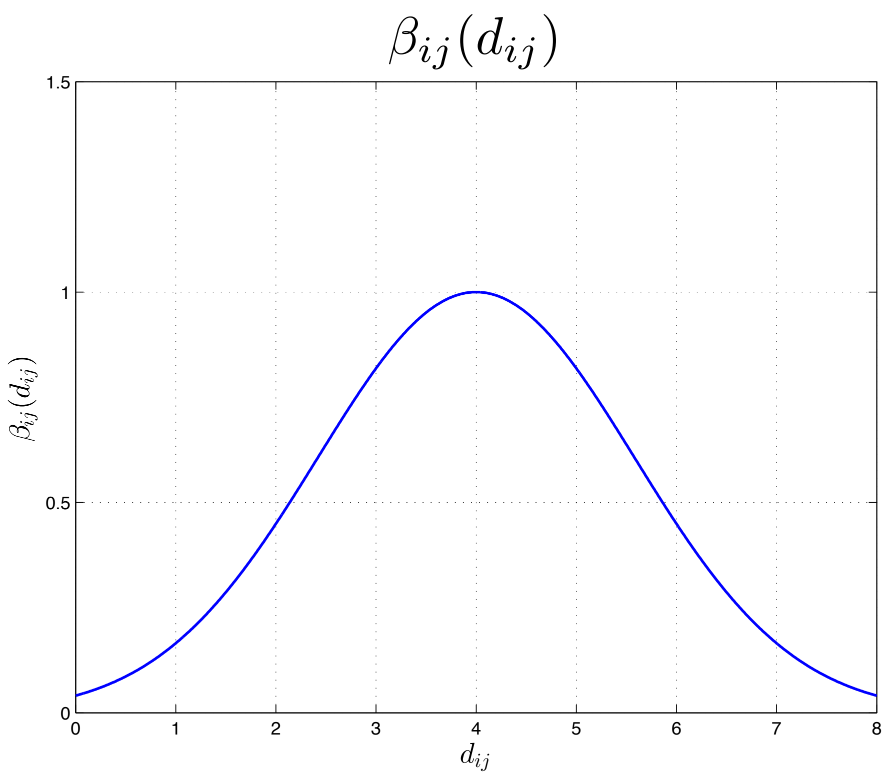




Connectivity Maintenance

- The term $\beta_{ij} \geq 0$ accounts for "**soft requirements**" that should be "preferably" realized by the agents (e.g., keep a desired distance)
  - For instance, $\beta_{ij}(d_{ij}) \to 0$ as $\|d_{ij} - d_0\| \to \infty$, and $\beta_{ij}(d_{ij})$ has a unique maximum at $d_{ij} = d_0$

$$A_{ij} = \alpha_{ij}\beta_{ij}\gamma_{ij}$$



Connectivity Maintenance

- The last term $\alpha_{ij} \geq 0$ accounts for "hard/mandatory" requirements that must be necessarily realized by the agents (e.g., avoid collisions)
  - As before, $\alpha_{ij}(d_{ij}) \to 0$ as $d_{ij} \to 0$ (i and j disconnect if they get too close)
  - **But also:** $\alpha_{ik} \to 0, \ \forall k \in \mathcal{N}_i$ (all the neighbors of i will disconnect!)
  - Approaching another agent will necessarily lead to a disconnected graph ($\lambda_2 \to 0$)

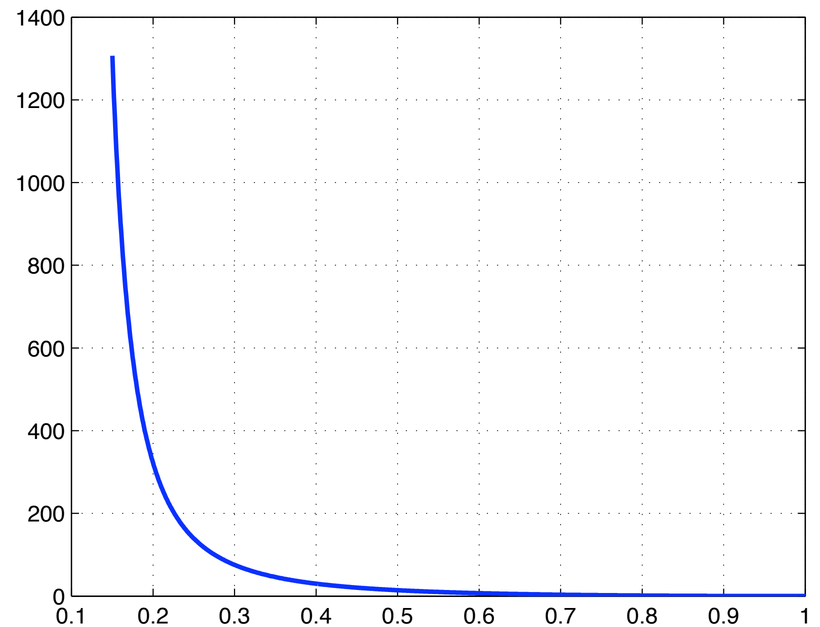
$$A_{ij} = \alpha_{ij}\beta_{ij}\gamma_{ij}$$

Connectivity Maintenance

- We have almost all the ingredients

- In view of the PHS form of the group dynamics, we still lack an Energy (Hamiltonian) function

- Let us then define a Connectivity Potential function $V^{\lambda}(\lambda_2) \geq 0$ which
  - vanishes for $\lambda_2 \to \lambda_2^{\max}$
  - grows unbounded for $\lambda_2 \to \lambda_2^{\min} < \lambda_2^{\max}$



- This will be the Storage function for our passivity arguments

- Its gradient (connectivity force) is

$$F_i^{\lambda}(x) = -\frac{\partial V^{\lambda}(\lambda_2(x))}{\partial x_i}$$

Connectivity Maintenance

- Thanks to the structure $\frac{\partial \lambda_2}{\partial x_i} = \sum_{(i,j)\in\mathcal{E}} \frac{\partial A_{ij}}{\partial x_i}(v_{2_i} - v_{2_j})^2$ the resulting connectivity force $F_i^\lambda = -\frac{\partial V^\lambda(\lambda_2(x))}{\partial x_i} = -\frac{\partial V^\lambda(\lambda_2)}{\partial \lambda_2}\frac{\partial \lambda_2(x)}{\partial x_i}$ can be shown to possess the following features:

  - function of only relative quantities (relative positions among robots and between robots/obstacle)

  - almost decentralized evaluation (local and 1-hop information plus current value of λ_2, and of the relative entries of v_2)

  - one can resort to a **decentralized estimation** to obtain $\hat{\lambda}_2,\ \hat{v}_{2_i},\ \hat{v}_{2_j},\ j \in \mathcal{N}_i$ and then $\hat{F}_i^\lambda$

- Stability of the closed-loop dynamics can by resorting to passivity theory (energetic considerations)

- In particular, tank machinery exploited to cope with estimation errors

Connectivity Maintenance

- Let $\hat{v}_2$ be the current estimate of the eigenvector v_2

- The estimation algorithm is a continuous-time version of the Power Iteration Procedure for computing eigenvectors and eigenvalues of a matrix

- It consists of **three steps**:

- 1) Deflation $\dot{\hat{v}}_2 = -\frac{k_1}{N}\mathbf{1}\mathbf{1}^T\hat{v}_2$ for removing the components spanned by $v_1 = \mathbf{1}$

- 2) Direction update $\dot{\hat{v}}_2 = -k_2 L\hat{v}_2$ for moving towards v_2

- 3) Renormalization $\dot{\hat{v}}_2 = -k_3\left(\frac{\hat{v}_2^T\hat{v}_2}{N} - 1\right)\hat{v}_2$ from staying away from the null-vector

- Altogether: $\dot{\hat{v}}_2 = -\frac{k_1}{N}\mathbf{1}\mathbf{1}^T\hat{v}_2 - k_2 L\hat{v}_2 - k_3\left(\frac{\hat{v}_2^T\hat{v}_2}{N} - 1\right)\hat{v}_2$

- And it can be shown that $\hat{\lambda}_2 = \frac{k_3}{k_2}\left(1 - \|\hat{v}_2\|^2\right)$

Connectivity Maintenance

- Is $\dot{\hat{v}}_2 = -\frac{k_1}{N}\mathbf{1}\mathbf{1}^T\hat{v}_2 - k_2 L\hat{v}_2 - k_3\left(\frac{\hat{v}_2^T\hat{v}_2}{N} - 1\right)\hat{v}_2$ decentralized?

- **<u>Almost:</u> everything is decentralized** apart from
  - the average $\frac{\mathbf{1}^T\hat{v}_2}{N}$
  - the average norm $\frac{\hat{v}_2^T\hat{v}_2}{N}$

- These last two quantities can be (themselves) estimated in a decentralized way by making use of the PI-ACE estimator (**<u>proportional/integral-Average Consensus Estimator</u>**)

$$\begin{cases} \dot{z}^i &= \gamma(\alpha^i - z^i) - K_P\sum_{j\in\mathcal{N}_i}(z^i - z^j) + K_I\sum_{j\in\mathcal{N}_i}(w^i - w^j) \\ \dot{w}^i &= -K_I\sum_{j\in\mathcal{N}_i}(z^i - z^j) \end{cases}$$

- The quantities $(z^i,\ w^i)$ are the PI-ACE states, and $\alpha_i = \{\hat{v}_{2_i},\ \hat{v}_{2_i}^2\}$ are the external signals of which a moving average is taken (in a decentralized way)

Connectivity Maintenance

- Let us then see some results of this Connectivity Maintenance algorithm

- **Summarizing:** the single scalar quantity λ_2 encodes
  - physical connectivity (max. range, line-of-sight occlusion)
  - extra "soft-requirements" (keep a desired interdistance)
  - extra "hard-requirements" (avoid collisions with obstacles and agents)
  - still, possibility to split/join at anytime as long as the graph $\mathcal{G}$ stays connected
  - everything decentralized
  - everything passive (in **PHS** form, by making use of the Tank machinery)

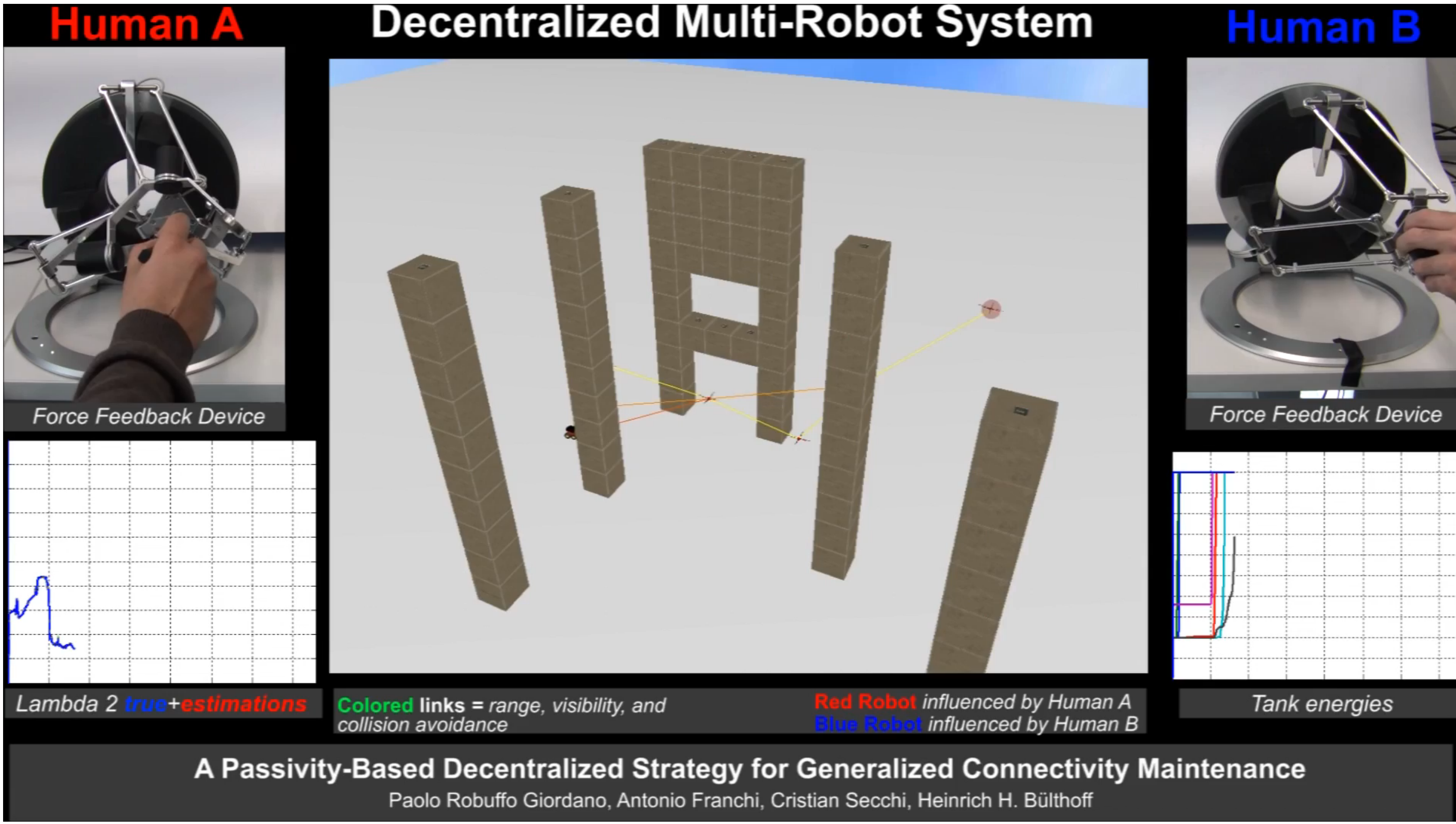
- In the next simulations/videos, the usual group of N quadrotor UAVs

- **Two of them** are also commanded by two human operators

- The whole group must keep connectivity (as defined before)

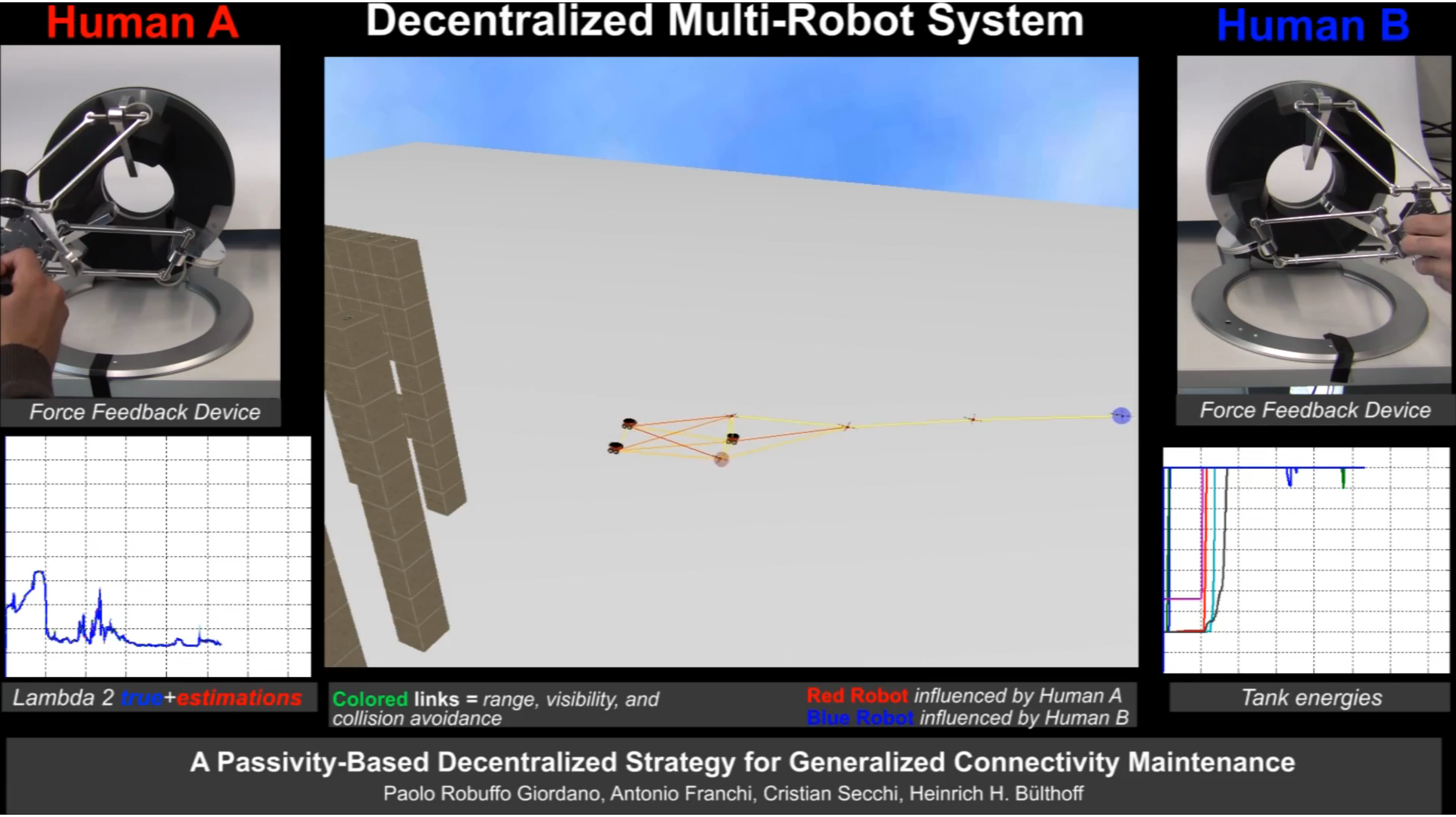
Connectivity Maintenance

- Simulations with $N = 8$ robots (quadrotor UAVs and ground robots)

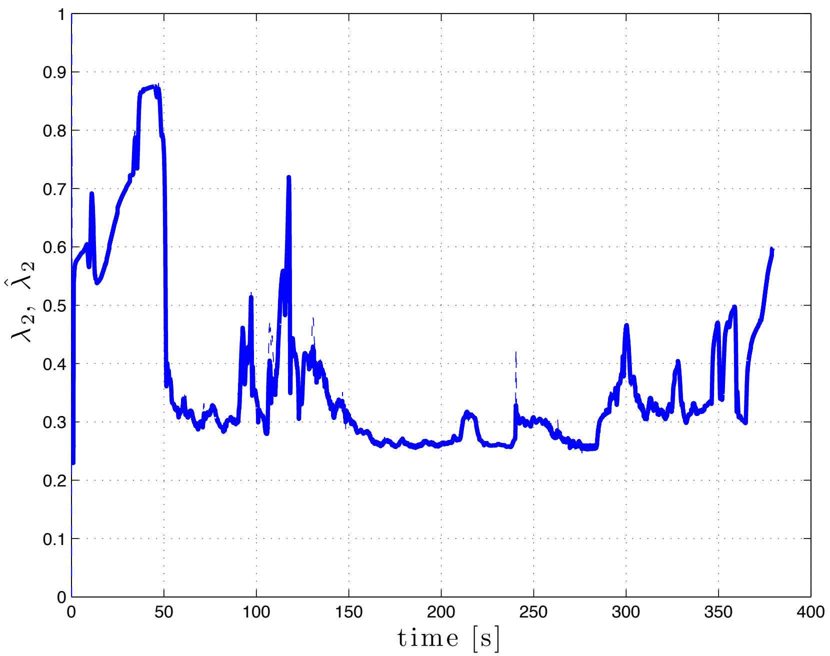


Connectivity Maintenance

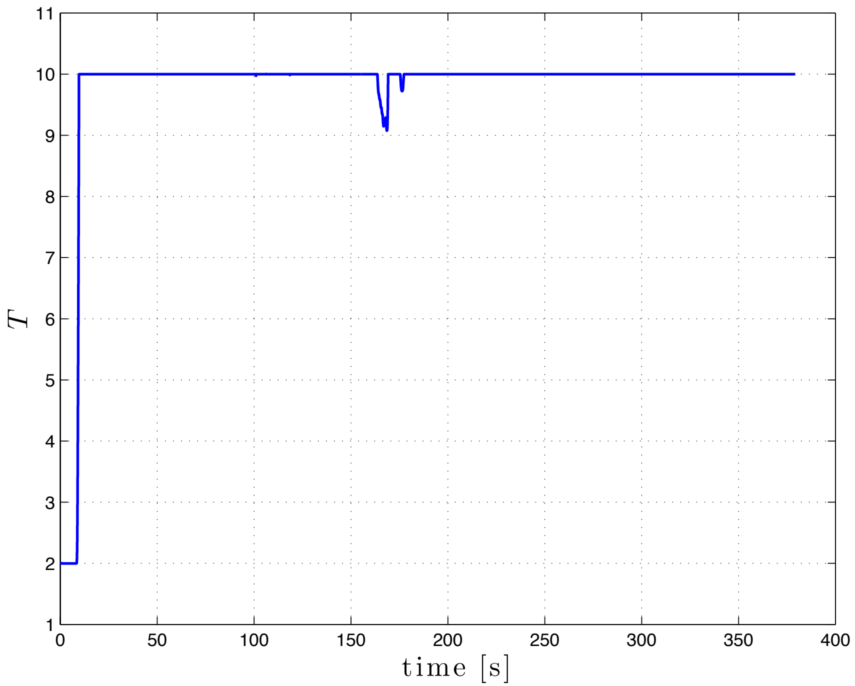
- Simulations with $N = 8$ robots (quadrotor UAVs and ground robots)



Connectivity Maintenance



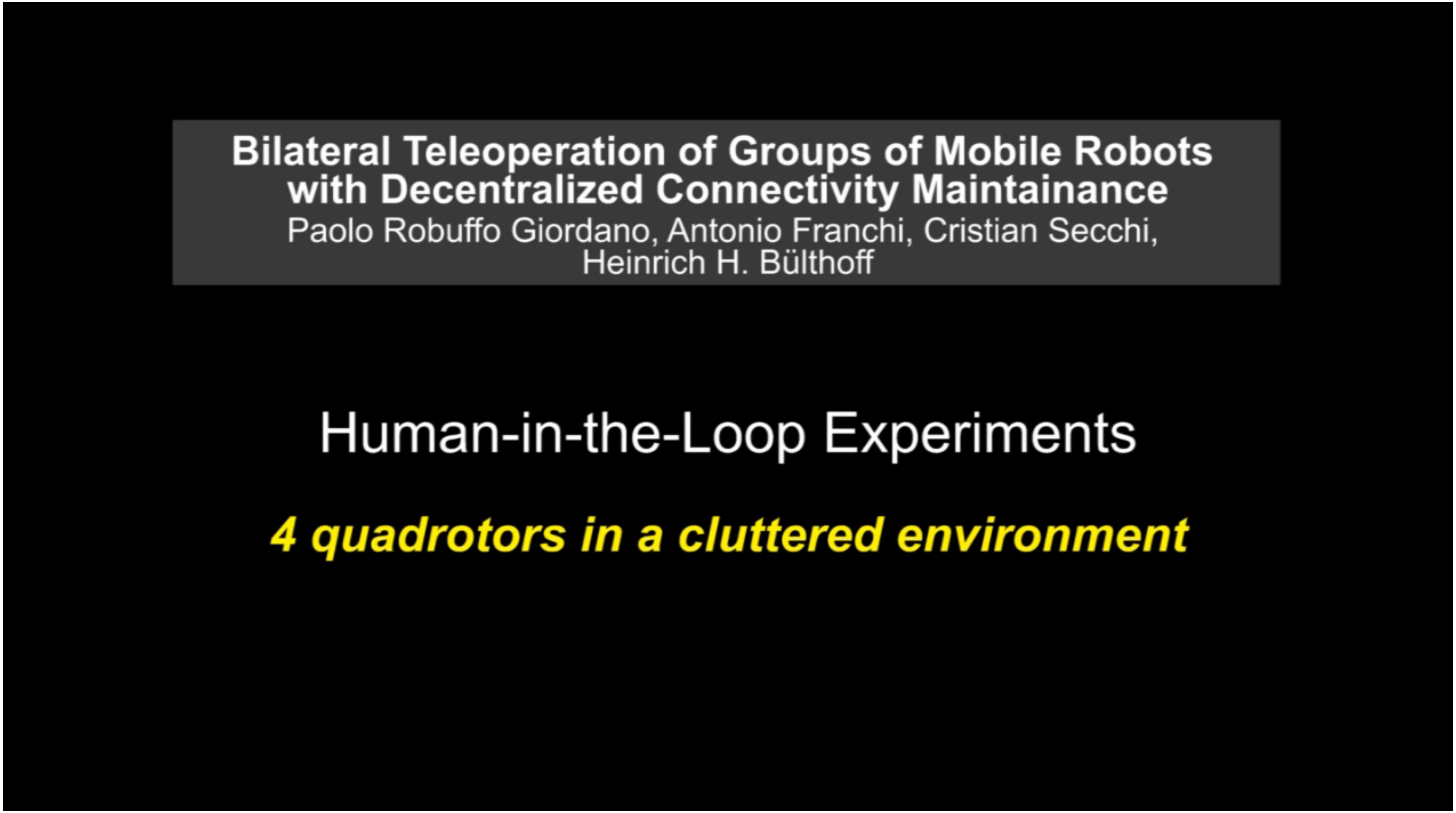
Real λ_2 (solid) vs. estimated $\hat{\lambda}_2^i$ (dashed)



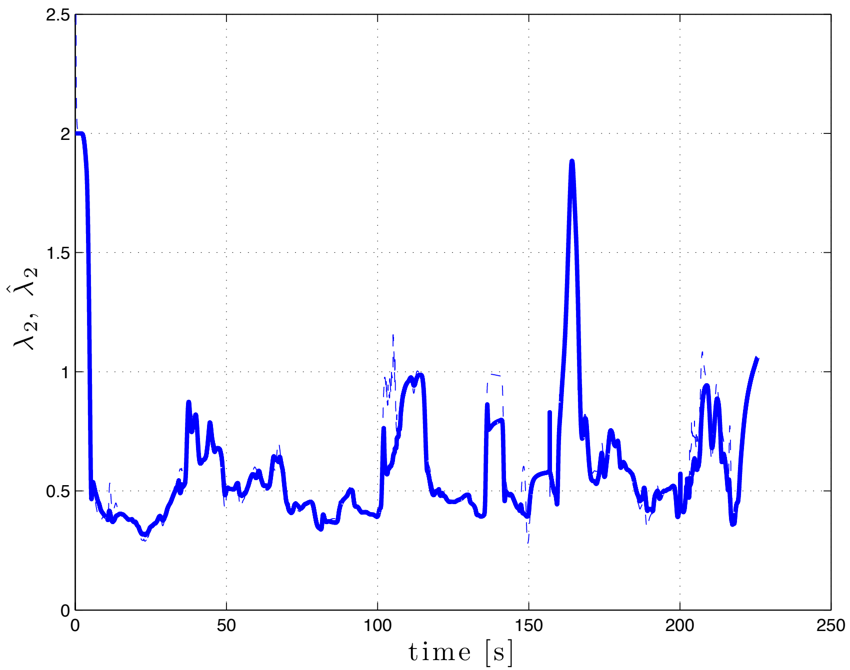
Tank energies $T(x_t)$

Connectivity Maintenance

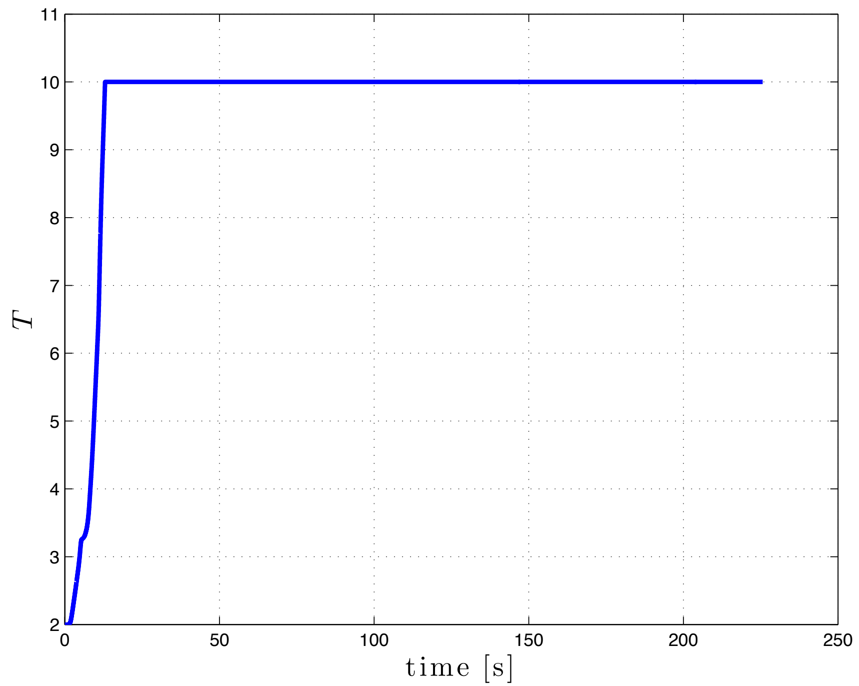
- Experiments with $N = 4$ quadrotor UAVs



Connectivity Maintenance



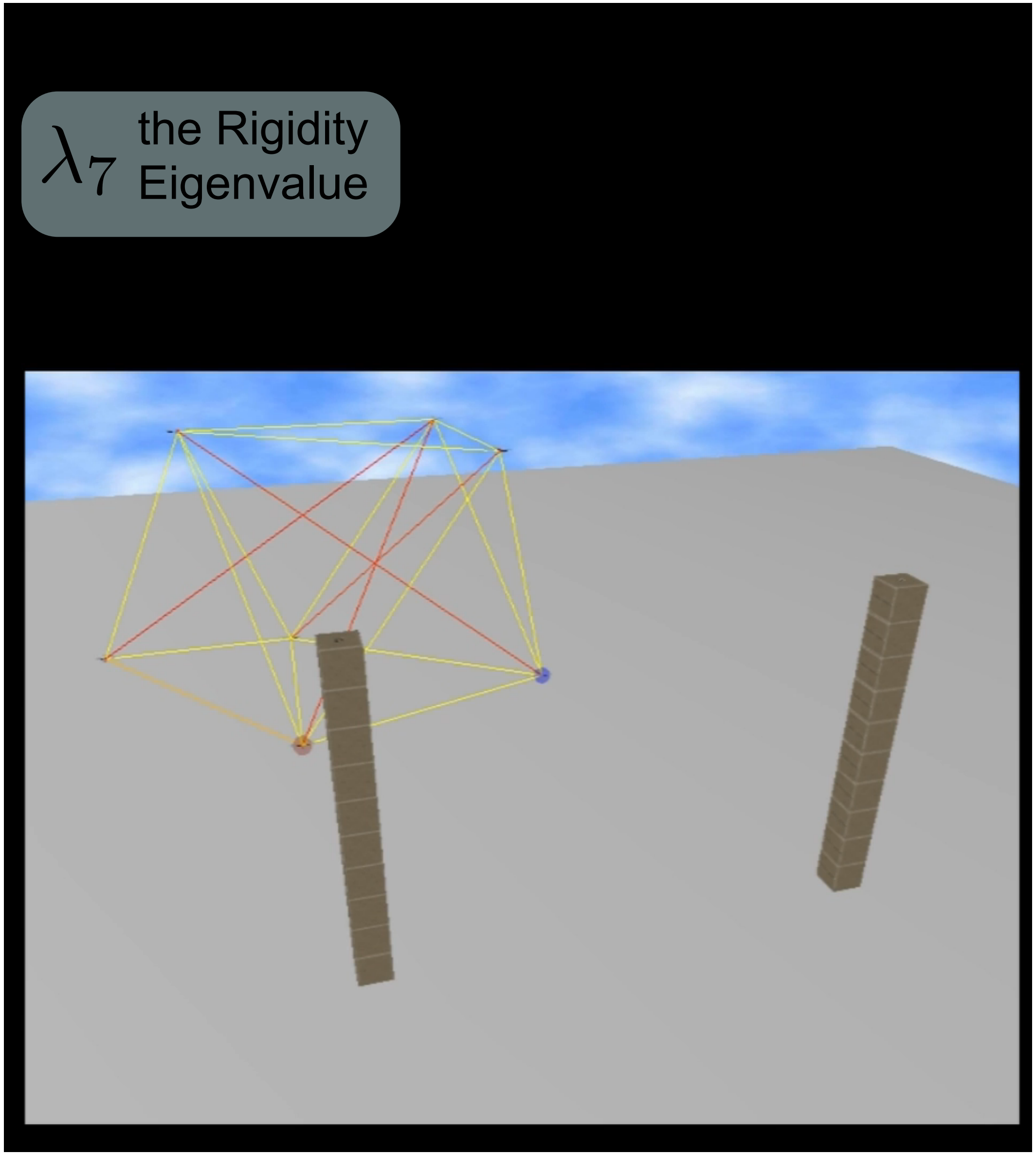
Real λ_2 (solid) vs. estimated $\hat{\lambda}_2^i$ (dashed)



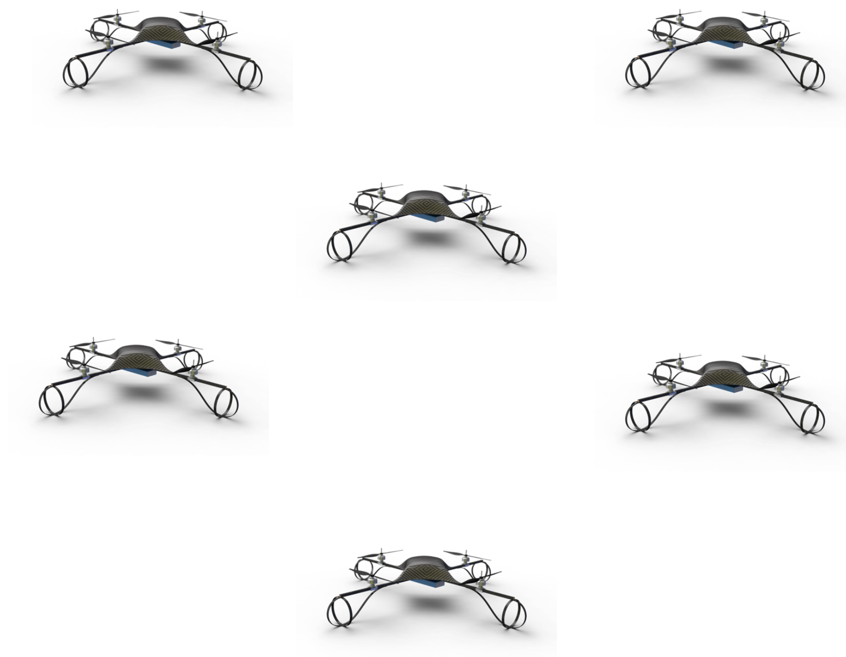
Tank energies $T(x_t)$

Rigidity Maintenance

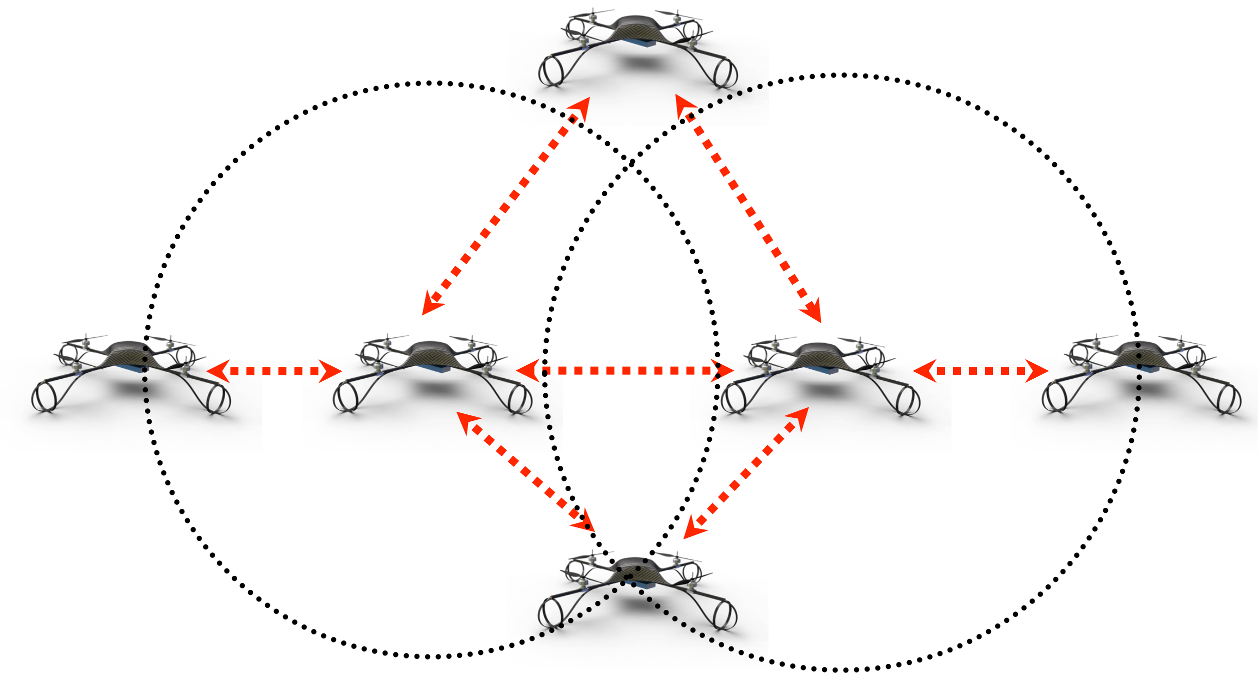
- An extension (RSS 2012, IJRR (in preparation))
- one can also define a "Rigidity Eigenvalue" λ_7 and apply the same machinery
- rigidity maintenance with the same constraints and requirements as before
- Still flexibility in the graph topology $\lambda_7 > 0$



What is rigidity?



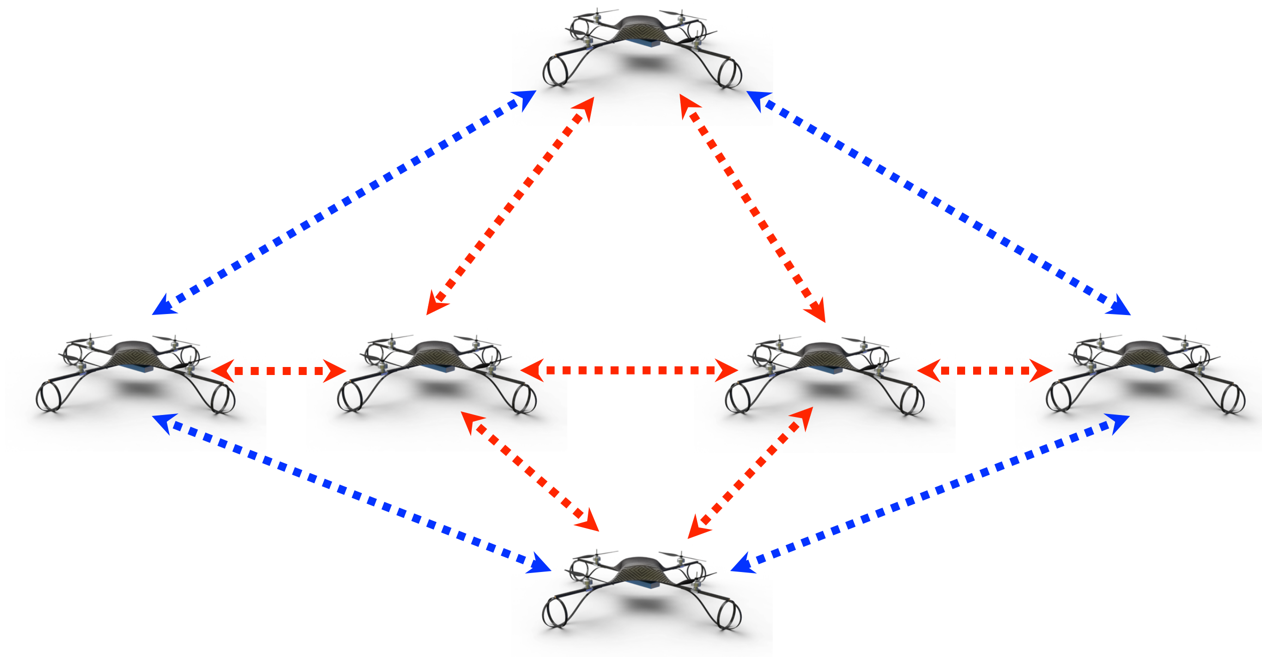
What is rigidity?



Can the desired formation be maintained using only the available distance measurements?

No!

What is rigidity?



A minimum number of distance measurements are required to uniquely determine the desired formation!

Graph Rigidity

Rigidity Maintenance

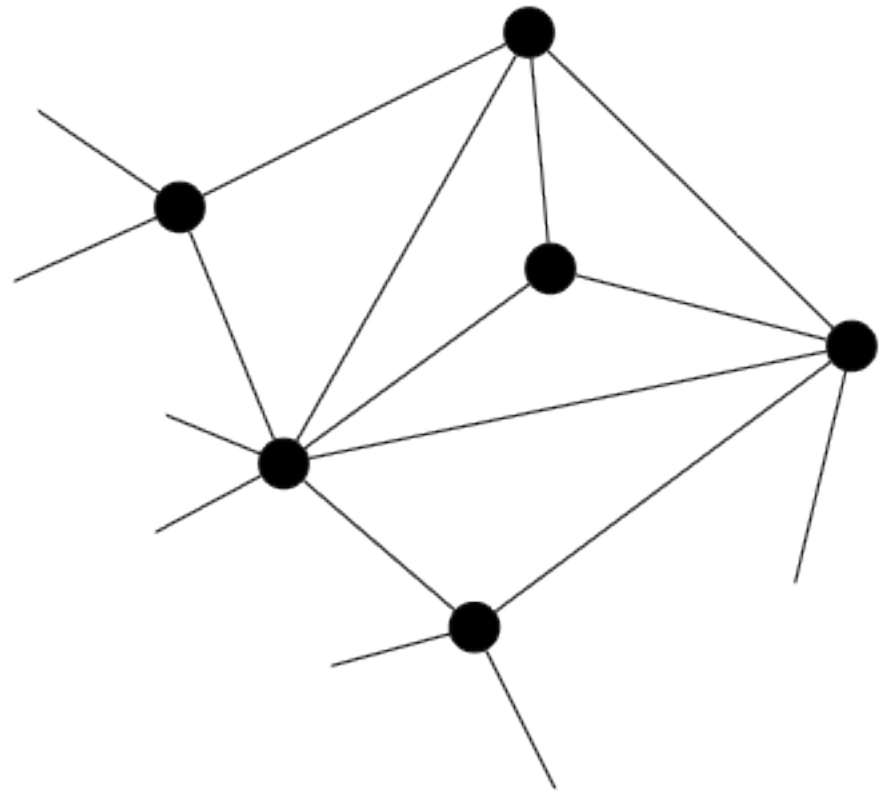
The Symmetric Rigidity Matrix

$$\mathcal{R} = R(p)^T R(p)$$

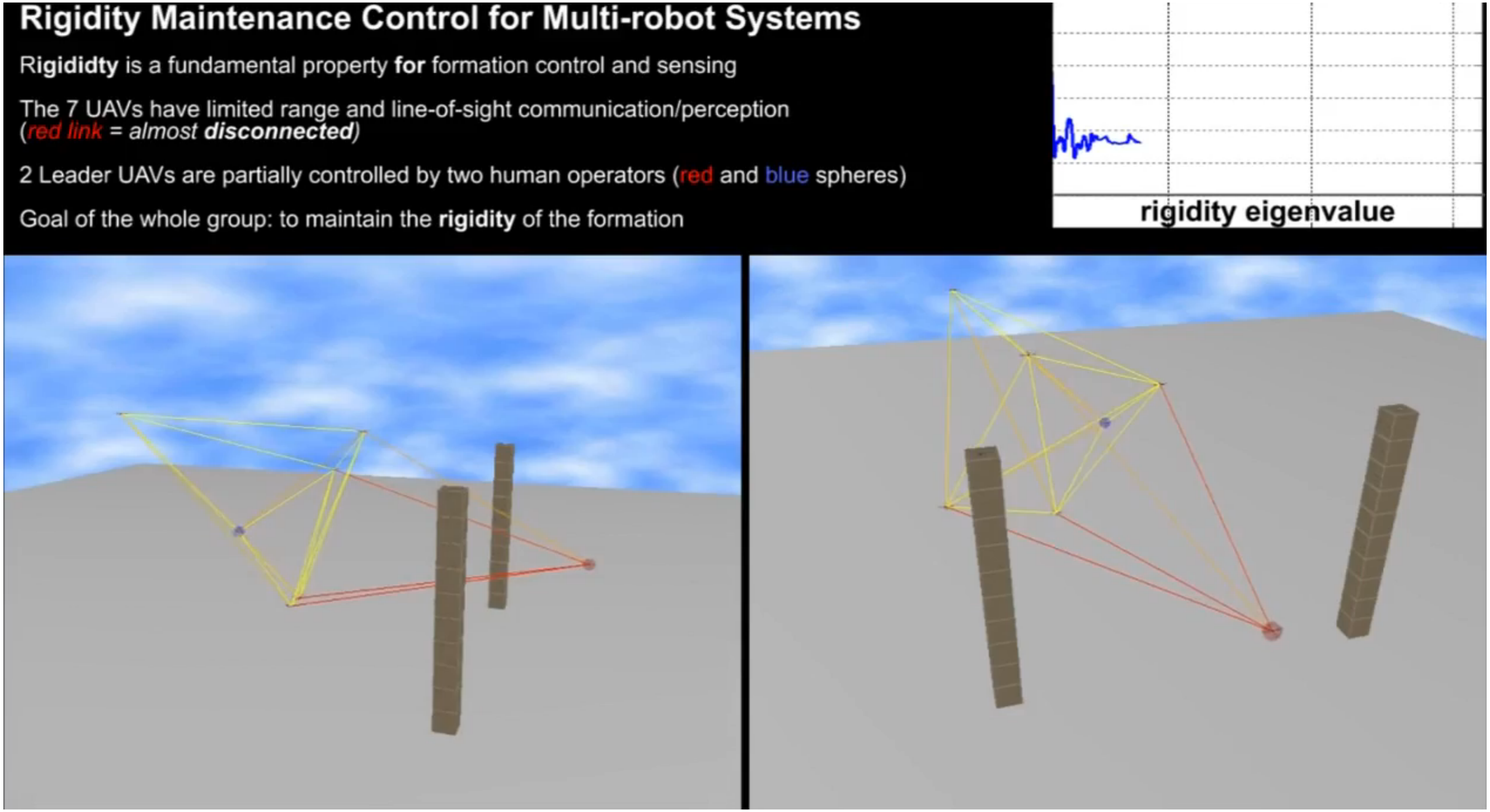
λ_7 the Rigidity Eigenvalue

velocity command

$$u_i = -\frac{\partial V^\lambda}{\partial \lambda_7} \frac{\partial \lambda_7}{\partial p_i}$$



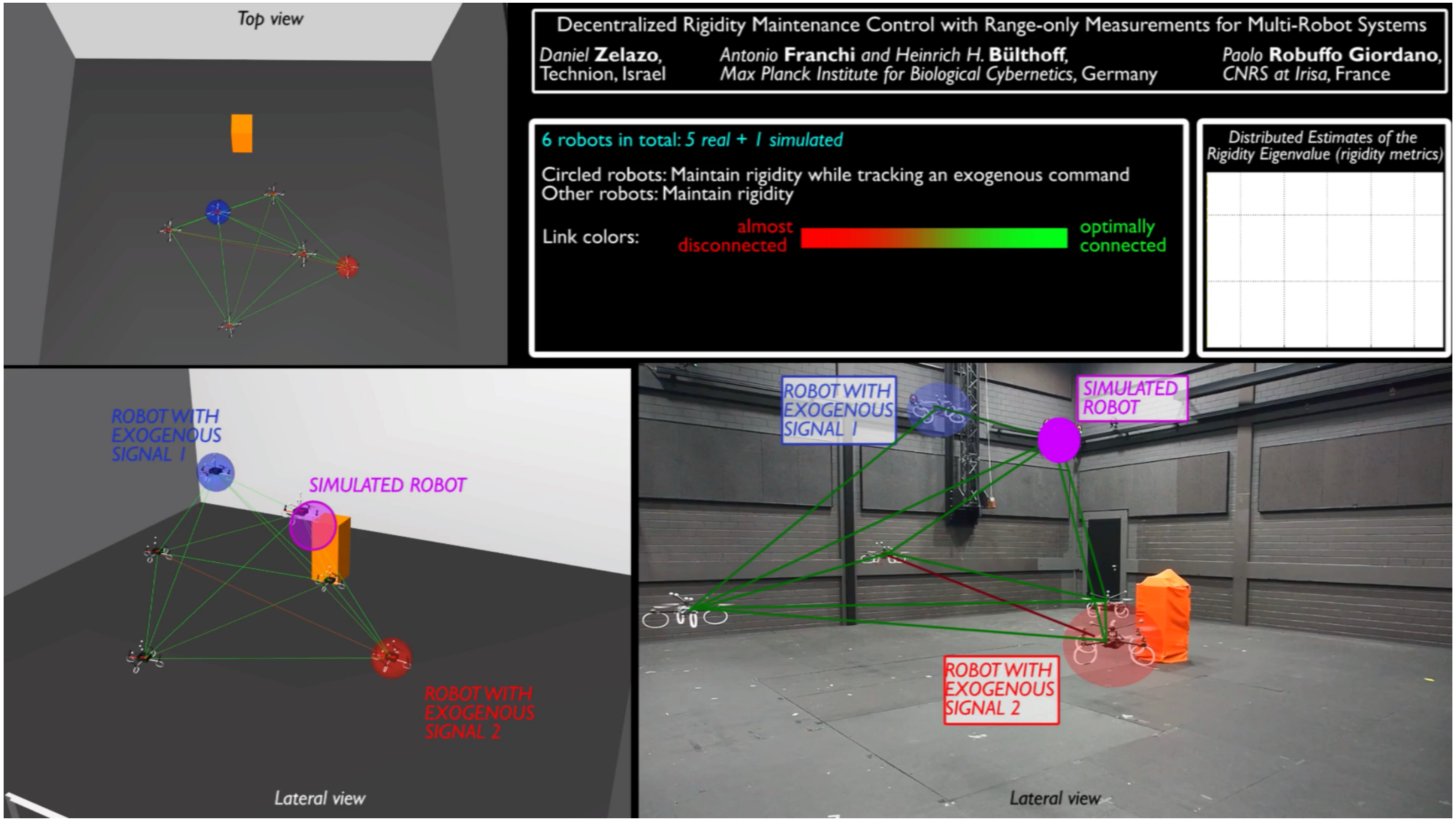
Rigidity Maintenance



RSS 2012

In collaboration with  D. Zelazo Technion, Isreal

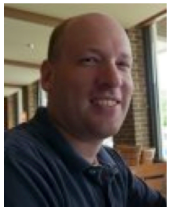
Rigidity Maintenance



IJRR 2014

- The quadrotors are maintaining formation rigidity
- This allows them to run a decentralized estimator able to obtain relative positions out of measured relative distances
- Relative positions are then needed by the rigidity controller

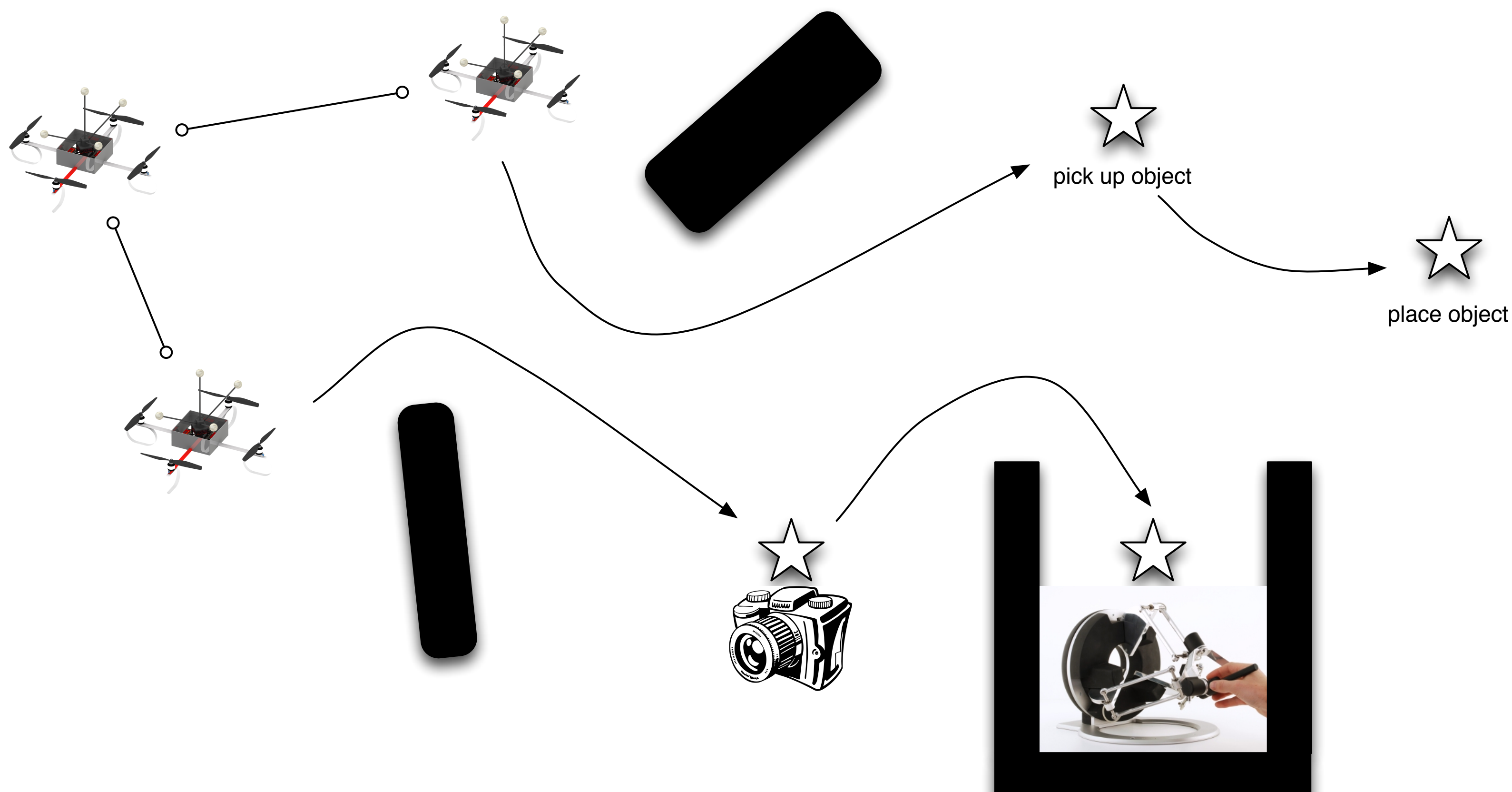
In collaboration with



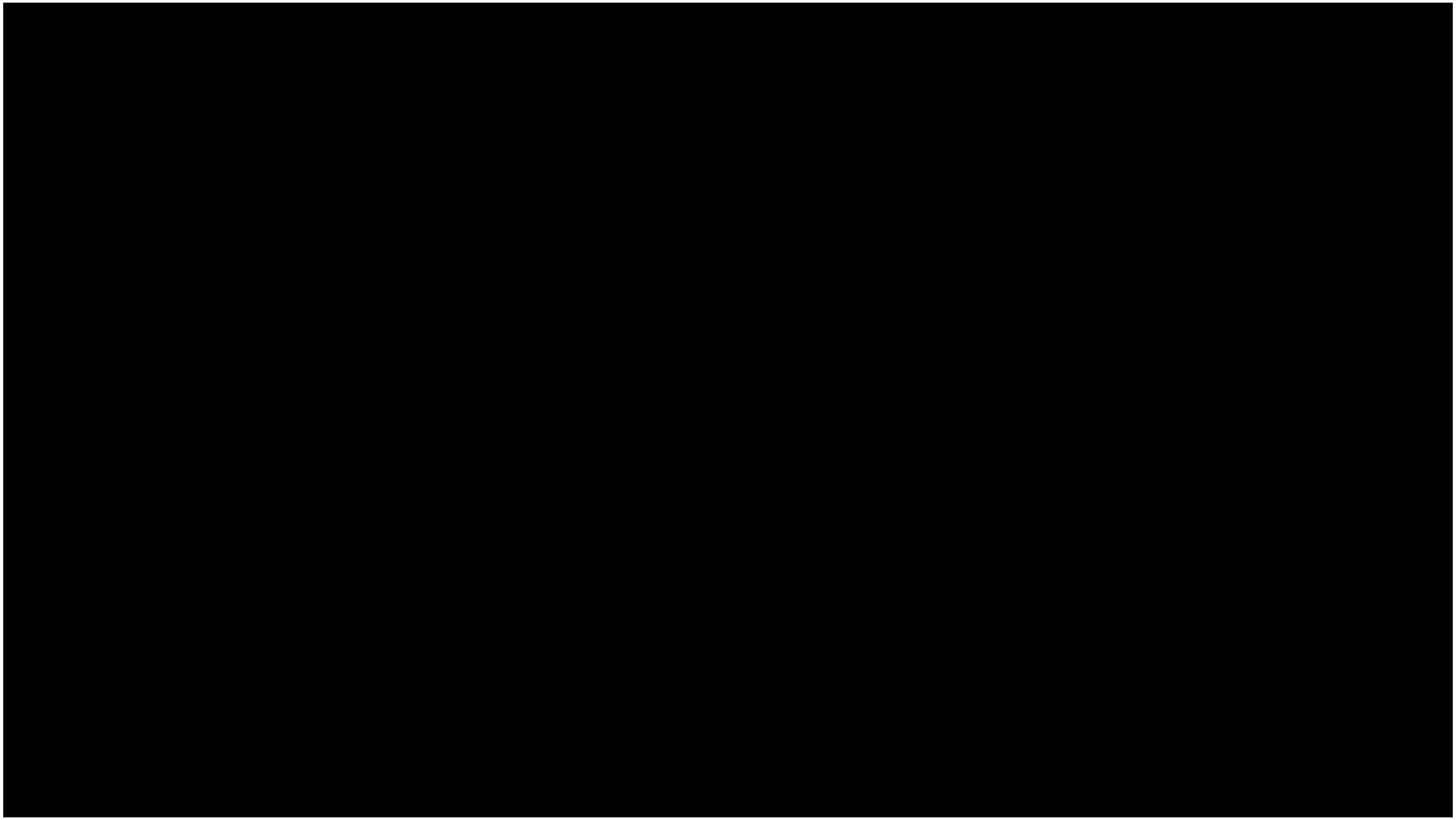
D. Zelazo
Technion,
Isreal

Simultaneous Multi-target Exploration with Connectivity Maintenance

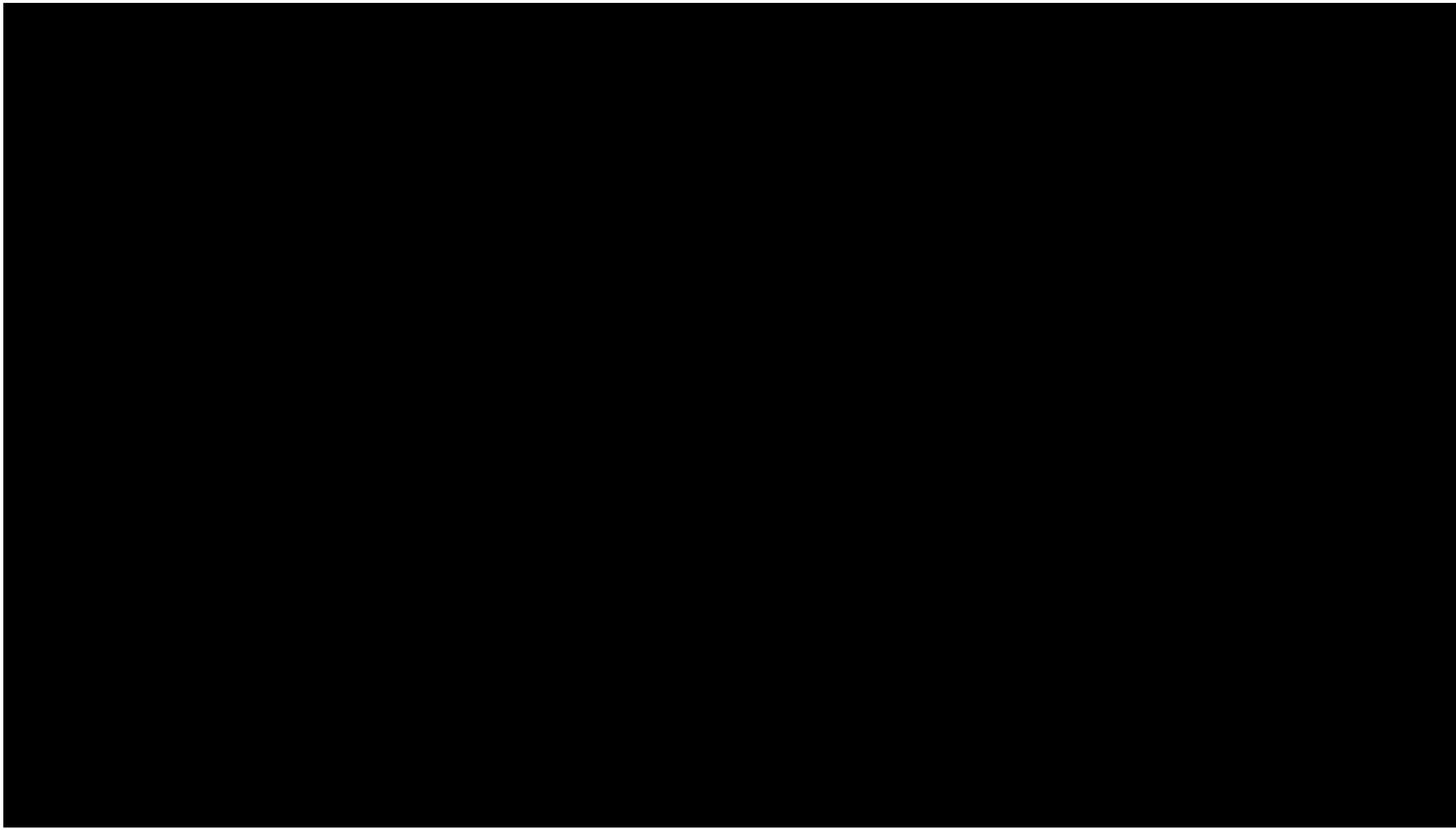
- Decentralized Multi-target Exploration and Connectivity Maintenance with a Multi-robot System



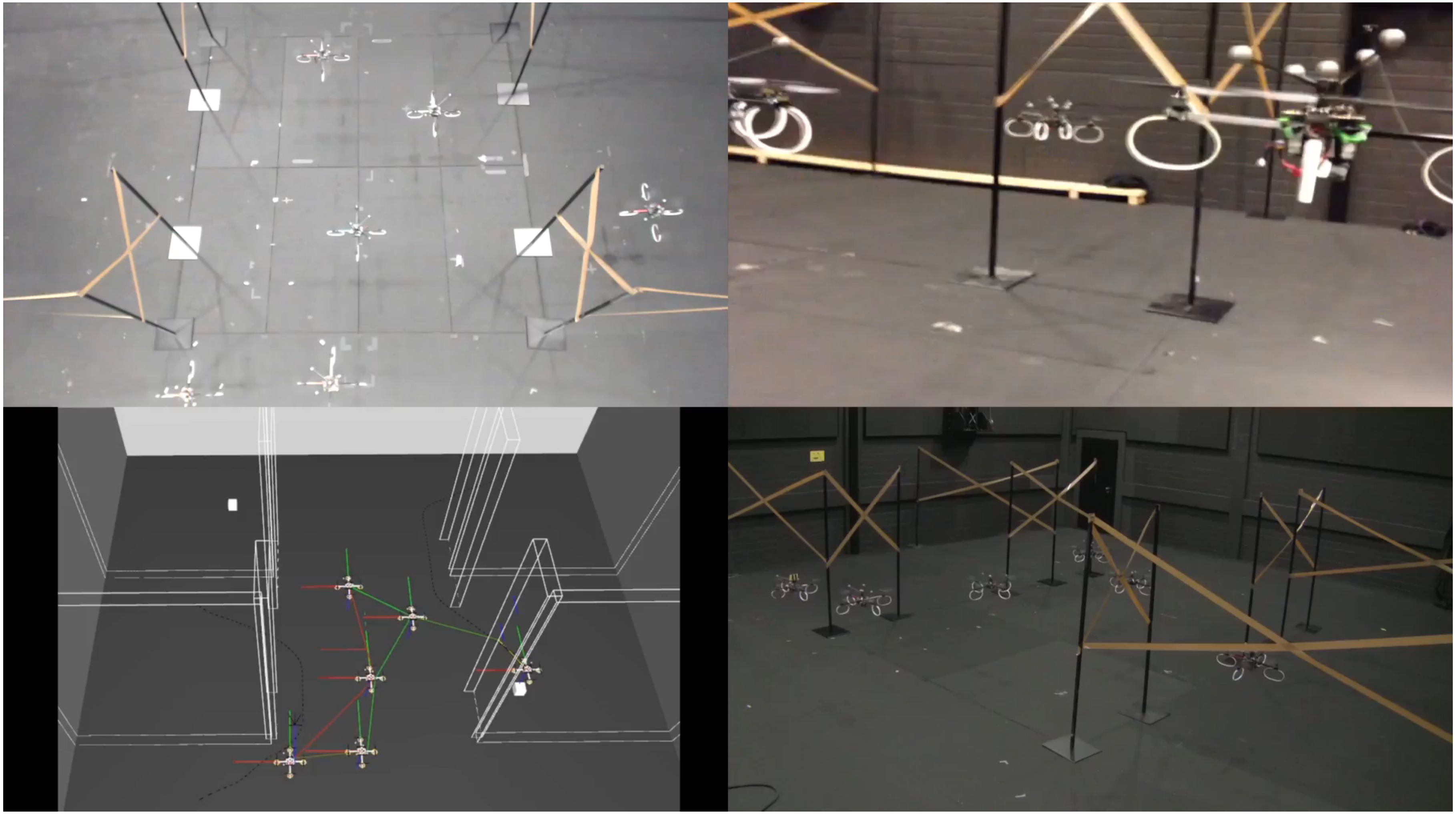
Simultaneous Multi-target Exploration with Connectivity Maintenance



Simultaneous Multi-target Exploration with Connectivity Maintenance



Simultaneous Multi-target Exploration with Connectivity Maintenance



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MPI for Biological Cybernetics

Dr. C. Secchi
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Dr. H. Il Son
MPI for Biological Cybernetics

Dr. D.Zelazo
University of Stuttgart

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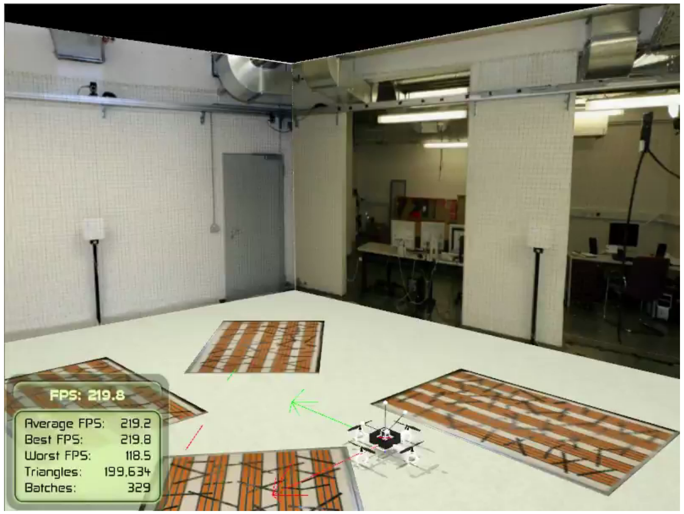
- The simulation environment and middleware software for running simulations and experiments was co-designed with



Johannes Lächele

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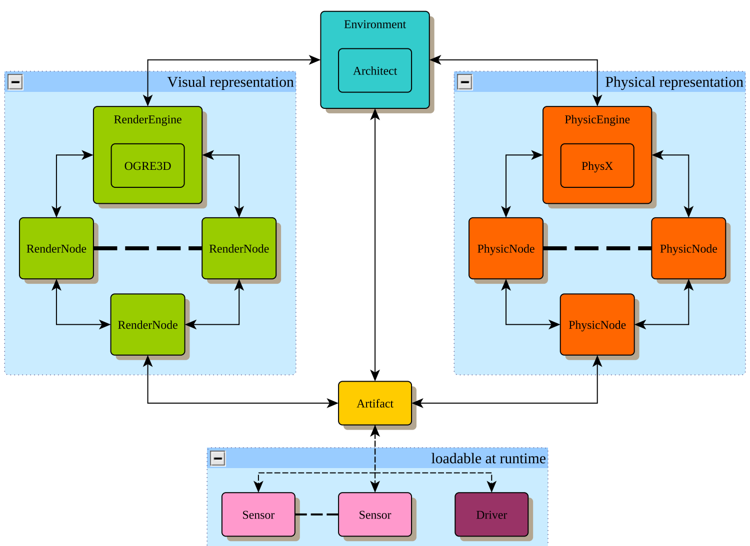
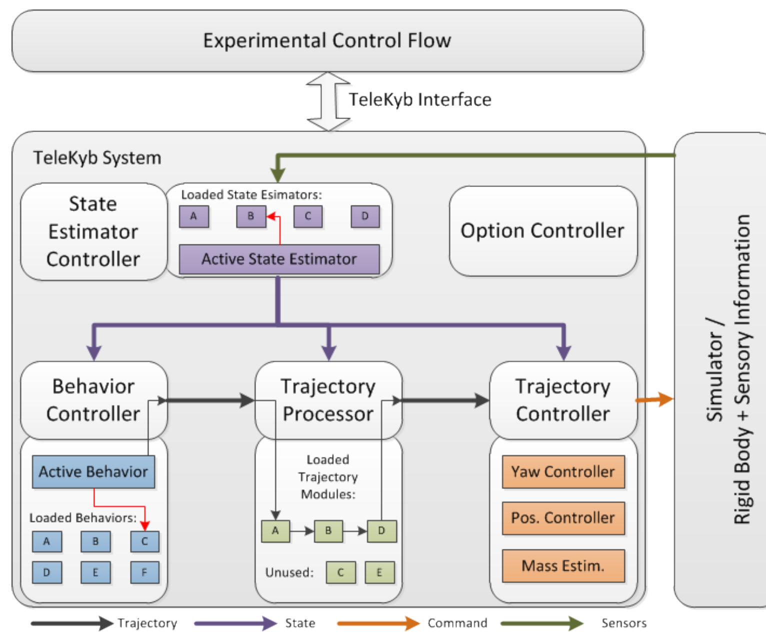
Martin Riedel

MPI for Biological Cybernetics





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