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Title:
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Date:
2004-01-01

Citation:
Nešić, D. & Teel, A. R. (2004). A note on input-to-state stability of networked control systems. Proceedings of the IEEE Conference on Decision and Control, 5, pp.4613-4618. IEEE. https://doi.org/10.1109/cdc.2004.1429511.

Persistent Link:
https://hdl.handle.net/11343/299640

A Note on Input-to-State Stability of Networked Control Systems

D. Nešić and A. R. Teel

***Abstract*— A new class of uniformly globally asymptotically stable (UGAS) protocols in networked control systems (NCS) is considered. It shown that if the controller is designed without taking into account the network so that it yields input-to-state stability (ISS) with respect to external disturbances (not necessarily with respect to the error that will come from the network implementation), then the same controller will achieve semi-global practical ISS for the NCS when implemented via the network with a UGAS protocol. The adjustable parameter with respect to which semi-global practical ISS is achieved is the so-called maximal allowable transfer interval (MATI) between transmission times.**

I. INTRODUCTION

In networked control systems (NCS), one or more dynamical systems are controlled by feedback over a communication network. The transmission capacity of the communication network is limited. This limits the number of bits or packets per second which can be transported via the network and, consequently, restricts the achievable performance. This area has grown rapidly in the last few years with the emergence of applications ranging from micro-electromechanical chips and Internet congestion protocols to "drive-by-wire" systems.

NCS are currently receiving considerable attention in the literature as illustrated by recent articles [5], [8], [16], [23], [24], [25], [26], [28], [29] and references listed therein. The area of NCS is still in its infancy and existing results can be improved in at least two directions. First, most existing literature considers only stabilization of *linear* NCS whereas *nonlinear* NCS have received little attention (with few exceptions, such as [17], [23]). Second, most results treat NCS without disturbances and we are aware only of limited results on stability of NCS with disturbances, such as the $\mathcal{L}_\infty$ to root-mean-square stability of a class of NCS considered in [7]; $\mathcal{L}_p$ stability of NCS considered in [17]; results on input-output stability of linear jump parameter systems in [3] that can be exploited for certain NCS with static protocols. Also, in some cases it is possible to use tools for linear sampled-data systems [4] for analysis and design of certain classes of linear NCS. In this paper we consider input-to-state stability (ISS) of *nonlinear NCS with disturbances*.

This research was supported by the Australian Research Council under the discovery grants scheme, by the AFOSR under grant F49620-03-1-0203 and the NSF under grant ECS-0324679. Part of this research was carried out while the second author was visiting the Mittag-Leffler Institute, Sweden in March 2003, during its emphasis on Mathematical Control and Systems Theory.

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We follow the method proposed in [23], [24], in which one first designs the controller without taking into account the network and then in the second step one determines a design parameter called the maximum allowable transfer interval (MATI) so that the closed loop remains stable when some control and sensor signals are transmitted via the network. This approach was shown to produce stabilizing controllers for linear NCS in [23] and nonlinear NCS in [24]. Moreover, $\mathcal{L}_p$ stability of nonlinear systems with a large class of uniformly globally exponentially stable (UGES) protocols was investigated in [17]. It was shown in [17] that several common static and dynamic protocols investigated in [23], [24], [25] belong to the class of UGES protocols.

In this paper we relax the protocol requirement introduced in [17], namely uniformly globally exponentially stable (UGES) protocols, considering uniformly globally asymptotically stable (UGAS) protocols. We show that if the controller is designed without taking into account the network so that it yields ISS of the closed loop system, then the same controller will achieve semi-global practical ISS of NCS when implemented via the network with a UGAS protocol. The parameter that can be adjusted in the protocol and that is used to achieve semi-global practical ISS is MATI (see [23], [24], [25]).

The paper is organized as follows. We present some mathematical preliminaries in Section 2. Definition of NCS is given in Section 3. In Section 3 we define UGAS protocols and present main properties of these protocols. Section 4 contains the main result of the paper. All proofs are presented in the appendix.

II. PRELIMINARIES

$\mathbb{R}$ and $\mathbb{N}$ denote, respectively, the sets of real and natural numbers. $\mathbb{R}_{\geq 0}$ denotes the set of non-negative integers. Given $t \in \mathbb{R}$ and a piecewise continuous function $f : \mathbb{R} \to \mathbb{R}^n$, we use the notation $f(t^+) := \lim_{s\to t, s>t} f(s)$. All vector norms, denoted as $|\cdot|$, are Euclidean norms unless otherwise stated. Given a measurable, locally essentially bounded signal $\varphi : [t_\circ, \infty) \to \mathbb{R}^n$ we denote its $\mathcal{L}_\infty$ norm as follows:

$$\|\varphi\|_\infty := \text{ess} \sup_{s \geq t_\circ} |\varphi(s)| \ .$$

A function $\gamma : \mathbb{R}_{\geq 0} \to \mathbb{R}_{\geq 0}$ is said to be of class $\mathcal{G}$ if it is continuous, zero at zero and nondecreasing. It is of class $\mathcal{K}$ if it is of class $\mathcal{G}$ and strictly increasing. A function is $\mathcal{K}_\infty$ if it is of class $\mathcal{K}$ and unbounded. γ is of class $\mathcal{L}$ if it is continuous and decreasing to zero. A continuous function $\beta : \mathbb{R}_{\geq 0} \times \mathbb{R}_{\geq 0} \to \mathbb{R}_{\geq 0}$ is said to be of class $\mathcal{KL}$ if for each $s > 0$ the function $\beta(s, \cdot)$ is of class $\mathcal{L}$ and for each fixed $t \geq 0$ the function $\beta(\cdot, t)$ is of class $\mathcal{K}$. In a similar way we define functions of class $\mathcal{KK}$ and $\mathcal{KLL}$. To shorten notation we often use $(x, y) := (x^T \; y^T)^T$.

In our work we will use the following lemma, which is [1, Corollary IV.5].

Lemma 1: Given any function $\gamma : \mathbb{R}_{\geq 0} \times \mathbb{R}_{\geq 0} \to \mathbb{R}_{\geq 0}$ of class $\mathcal{KK}$, there exist functions γ_1 and γ_2 of class $\mathcal{K}_\infty$ such that

$$\gamma(s_1, s_2) \leq \gamma_1(s_1) \cdot \gamma_2(s_2) \qquad \forall s_1, s_2 \geq 0 \; .$$

■

III. Definition of Networked Control Systems

In this section we present a class of models with jumps that we use to describe NCS. In particular, we augment the model of NCS proposed in [24] with an equation that describes the operation of the scheduling protocol (see also [17]). Let the sequence $t_{s_i}, i \in \mathbb{N}$ of monotonically increasing transmission times satisfy $\epsilon \leq t_{s_{i+1}} - t_{s_i} \leq \tau$ for all $i \in \mathbb{N}$ and some fixed $\epsilon, \tau > 0$. We adopt terminology from [24] and refer to τ as the *maximum allowable transmission interval* (MATI). The number ϵ ensures that our model does not have any Zeno solutions where infinitely fast switching may occur. We consider general nonlinear NCS with disturbances of the following form

$$\begin{array}{rcll} \dot{x}_P &=& f_P(t, x_P, \hat{u}, w) & t \in [t_{s_{i-1}}, t_{s_i}] \\ y &=& g_P(t, x_P) & \\ \dot{x}_C &=& f_C(t, x_C, \hat{y}, w) & t \in [t_{s_{i-1}}, t_{s_i}] \\ u &=& g_C(t, x_C) & \\ \dot{\hat{y}} &=& \hat{f}_P(t, x_P, x_C, \hat{y}, \hat{u}, w) & t \in [t_{s_{i-1}}, t_{s_i}] \\ \dot{\hat{u}} &=& \hat{f}_C(t, x_P, x_C, \hat{y}, \hat{u}, w) & t \in [t_{s_{i-1}}, t_{s_i}] \\ \hat{y}(t_{s_i}^+) &=& \hat{y}(t_{s_i}) + h_u(i, e(t_{s_i})) & \\ \hat{u}(t_{s_i}^+) &=& \hat{u}(t_{s_i}) + h_y(i, e(t_{s_i})) & \end{array} \qquad (1)$$

where x_P and x_C are respectively states of the plant and the controller; y is the plant output and u is the controller output; w is an exogenous disturbance input; $\hat{y}$ and $\hat{u}$ are the vectors of most recently transmitted plant and controller output values via the network; e is the network induced error defined as

$$e(t) := \begin{pmatrix} \hat{y}(t) - y(t) \\ \hat{u}(t) - u(t) \end{pmatrix} = \begin{pmatrix} e_y \\ e_u \end{pmatrix} \; .$$

Note that if NCS has ℓ links, then the error vector can be partitioned as follows $e = [e_1^T \; e_2^T \; \ldots \; e_\ell^T]^T$. At each transmission time t_{s_j}, the protocol gives access to the network to one of the "nodes" e_i, $i \in \{1, 2, \ldots, \ell\}$ and this causes the vector $e_i(\cdot)$ to undergo a "jump" at t_{s_j} (see Remark 1 below).

We combine the controller and plant states into a vector $x := (x_P, x_C)$ and using the error vector defined earlier $e = (e_y, e_u)$ and the following definitions:

$$f(t, x, e, w) := \begin{pmatrix} f_P(t, x_P, g_C(t, x_C) + e_u, w) \\ f_C(t, x_C, g_P(t, x_P) + e_y, w) \end{pmatrix};$$

$$h(i, e) := \begin{pmatrix} h_y(i, e) \\ h_u(i, e) \end{pmatrix};$$

$$g(t, x, e, w) := \begin{pmatrix} g_1 \\ g_1 \end{pmatrix} \; ,$$

where

$$\begin{array}{l} g_1 := \hat{f}_P(t, x_P, x_C, g_P(t, x_P) + e_y, g_C(t, x_C) + e_u, w) \\ \quad - \frac{\partial g_P}{\partial t}(t, x_P) - \frac{\partial g_P}{\partial x_P}(t, x_P) f_P(t, x_P, g_C(t, x_C) + e_u, w) \\ g_2 := \hat{f}_C(t, x_P, x_C, g_P(t, x_P) + e_y, g_C(t, x_C) + e_u, w) \\ \quad - \frac{\partial g_C}{\partial t}(t, x_C) - \frac{\partial g_C}{\partial x_C}(t, x_C) f_C(t, x_C, g_P(t, x_P) + e_y, w) \; , \end{array}$$

we can rewrite (1) as a system with jumps that is more amenable for analysis:

$$\begin{array}{rcll} \dot{x} &=& f(t, x, e, w) & \forall t \in [t_{s_{i-1}}, t_{s_i}] \qquad (2) \\ \dot{e} &=& g(t, x, e, w) & \forall t \in [t_{s_{i-1}}, t_{s_i}] \qquad (3) \\ e(t_{s_i}^+) &=& h(i, e(t_{s_i})) \; , & \qquad (4) \end{array}$$

where $x \in \mathbb{R}^{n_x}$, $e \in \mathbb{R}^{n_e}$, $w \in \mathbb{R}^{n_w}$. In order to write (3), we assumed that functions g_P and g_C in (1) are continuously differentiable. The trajectories of the system (2), (3), (4) are generated as follows. Let the initial time $t_0 \geq 0$ be given and let $t_0 \in (t_{s_i}, t_{s_{i+1}})$. Then, from (t_0, x_0, e_0) and with a given $w(\cdot)$, let $x(\cdot)$ and $e(\cdot)$ be any absolutely continuous functions satisfying respectively $x(t_0) = x_0$, $\dot{x} = f(t, x, e, w)$ and $e(t_0) = e_0$, $\dot{e} = g(t, x, e, w)$ for almost all t in some maximal interval of definition $[t_0, t_0 + T_0)$. We assume enough regularity on f, g and $w(\cdot)$ to guarantee that such functions exist (see for instance [6]). If $t_0 + T_0 \leq t_{s_{i+1}}$, then $(x(\cdot), e(\cdot))$ is a solution of the system[1] and $[t_0, t_0 + T_0)$ is the maximal interval of definition of this solution. If, on the other hand, t_0 is such that $t_0 + T_0 > t_{s_{i+1}}$ then $(x(\cdot), e(\cdot))$ is the solution of (2), (3) on the interval $[t_0, t_{s_{i+1}}]$. Moreover, in this case we can extend the solution of (2), (3) beyond $t_{s_{i+1}}$ by using the new initial condition $(t_{s_{i+1}}, x(t_{s_{i+1}}), h(i+1, e(t_{s_{i+1}})))$ and repeating the above procedure. For initial times t_0 such that $t_0 = t_{s_i}$ for some $i \in \mathbb{N}$, we consider as solutions what results following the above procedure from both (t_0, x_0, e_0) and $(t_0, x_0, h(i, x_0))$. In this way, to each initial condition (t_0, x_0, e_0) and each disturbance $w(\cdot)$ we associate a solution maximally defined on an interval $[t_0, t_0 + T)$, where $T \in (0, \infty]$. We use $(x(\cdot, t_0, x_0, e_0, w), e(\cdot, t_0, x_0, e_0, w))$ to denote such a solution. When (t_0, x_0, e_0) and $w(\cdot)$ are clear from the context we use the shorthand notation $(x(\cdot), e(\cdot))$. We also assume that $x(\cdot)$ and $e(\cdot)$ are absolutely continuous except perhaps at transmission times t_{s_i} where they may be discontinuous. We use the following assumption that holds if f is locally Lipschitz in x, w and e, uniformly in t.

Assumption 1: There exist $L \in \mathcal{K}$ and $M \in \mathcal{KK}$ such that, for each $c > 0$,

$$\begin{array}{rcl} \max\{|x|, |\bar{x}|, |w|, |e|\} \leq c & \Longrightarrow & \qquad (5) \\ |f(t, x, w, e) - f(t, \bar{x}, w, 0)| & \leq & L(c+1)|x - \bar{x}| \\ & & + M(c+1, |e|) \; . \end{array}$$

[1] We note that in the absence of time dependence of f on time t all calculations would hold with f continuous, without requiring the uniqueness of solutions. However, these calculations are beyond the scope of this paper.

■

Remark 1: We refer to (4) as a protocol. The protocol determines the algorithm that assigns access to the network to different nodes in the system. It was shown in [17] that static protocols and the so called try-once-discard (TOD) dynamic protocol introduced in [23], [24] can be modelled in this manner. The functions h_u and h_y are typically such that, if the jth link gets access to the network at some transmission time t_{s_i} we have that the corresponding part of the error vector has a jump. For some protocols, such as the TOD protocol, we typically assume that e_j is reset to zero at time $t_{s_i}^+$, that is $e_j(t_{s_i}^+) = 0$. However, we emphasize that this assumption is not needed in general (see [17] for more details).

IV. Lyapunov UGAS protocols

In this section we introduce a class of Lyapunov UGAS protocols and show an important property that they possess under relatively weak conditions. In particular, we show for these protocols that for uniformly bounded plant state $x(\cdot)$ and the disturbance $w(\cdot)$, the state of the error dynamics $e(\cdot)$ satisfies a semi-global-practical stability bound in the MATI. This technical result is instrumental in establishing ISS properties of the NCS in the next section. Note that the equation (4) that describes the operation of the protocol is not a discrete-time system since this equation does not provide a relationship between error signals at consecutive transmission times t_{s_i} and $t_{s_{i+1}}$ for any $i \in \mathbb{N}$. However, we find it convenient to introduce an auxiliary discrete-time system induced by the protocol (4):

$$e(i+1) = h(i, e(i)) \ . \tag{6}$$

This idea was proposed for the first time in [17]. Moreover, in [17] we introduced the class of Lyapunov uniformly globally exponentially stable (UGES) protocols: the protocol (4) is Lyapunov UGES if there exists a Lyapunov function that verifies that the discrete-time system (6) induced by the protocol is UGES. In this paper we generalize this class of protocols and we consider uniformly globally asymptotically stable (UGAS) protocols defined as follows:

Definition 1: Let a function $W : \mathbb{R}_{\geq 0} \times \mathbb{R}^n \to \mathbb{R}_{\geq 0}$, $\alpha_1, \alpha_2 \in \mathcal{K}_\infty$ and a real number $\lambda \in [0, 1)$ be such that for all $e \in \mathbb{R}^n$ and all $i \in \mathbb{N}$ the following holds:

$$\alpha_1(|e|) \leq W(i, e) \leq \alpha_2(|e|) \tag{7}$$

$$W(i+1, h(i, e)) \leq \lambda W(i, e) \ . \tag{8}$$

Then, we say that the protocol (4) is Lyapunov uniformly globally asymptotically stable (UGAS) with (W, α_1, α_2, λ). ■

In the sequel we use the following:

Assumption 2: The protocol (4) is Lyapunov UGAS with (W, α_1, α_2, λ), where $W(i, e)$ is continuous in e, uniformly in i. ■

We note that results of [17] required that W is Lipschitz in e, uniformly in i. Hence, in this paper besides considering a more general class of Lyapunov UGAS protocols, we also relax the uniform Lipschitz property of W to uniform continuity. It is sometimes easier to prove (see Example 1) that instead of (8) we have that the following inequality holds:

$$W(i+1, h(i, e)) \leq W(i, e) - \alpha_3(W(i, e)) \ , \tag{9}$$

for some positive definite α_3. The following proposition shows that this is enough for our purposes.

Proposition 1: Suppose that (7) and (9) hold, where α_3 is a continuous, positive definite function and $W(i, e)$ is continuous in e, uniformly in i. Then, there exists a smooth function $\rho \in \mathcal{K}_\infty$ such that $U(i, e) := \rho(W(i, e))$ satisfies all conditions of Assumption 2. ■

Sketch of proof: Lyapunov UGAS with U can be shown to hold in a similar way as in the continuous-time literature (For example, see [21] and [13, Theorem 3.6.10] for the case when α_3 is a class $\mathcal{K}$ function. Also, the result that uses a similar transformation to go from a positive definite function α_3 to a class $\mathcal{K}$ function $\hat{\alpha}_3$ is given in [22, pp. 440]). Moreover, given any $\rho \in \mathcal{K}_\infty$ (which is by definition continuous) we have that $U(i, e)$ is continuous in e, uniformly in i, since W has the same property. ■

In some cases it is possible that (6) is Lyapunov UGAS in an appropriate sense but it may be hard to explicitly construct W satisfying Assumption 2 (see Example 2). The following propositions is useful in such situations and it makes use of converse Lyapunov theorems proved in [11] for difference inclusions with upper semi-continuous right hand sides (see also [2] for similar results for time-invariant systems with Lipschitz right hand sides).

Proposition 2: Suppose that[2] for each $e \in \mathbb{R}^{n_e}$ the function $h(\cdot, e)$ is periodic in i. Then, there exists W satisfying Assumption 2 if and only if the origin of the difference inclusion $e^+ \in H(i, e)$, where $H(i, e) := cl \bigcap_{|v| \leq \delta, \delta > 0} \{z : z \in h(i, e + v)\}$, is stable and globally attractive.

It was shown in [17] that token ring and try once discard (TOD) protocols are Lyapunov UGES (see [17], [24]). We present next two examples of Lyapunov UGAS protocols that are not Lyapunov UGES. The first example behaves for large e in the same way as TOD protocol but for small e the error jumps are smaller because we transmit less information. The second example is a modified token ring protocol that for large error e behaves exactly in the same way as token ring but for small e it transmits less frequently.

Example 1 (Modified TOD Protocol): Consider the protocol (6), where $h(e) = (I - \Psi(e))e$ and $\Psi(e) := diag\{\psi_1(e)I_{n_1}, \ldots, \psi_\ell(e)I_{n_\ell}\}$, where $\psi_j(e) = \text{sat}(|e_j|)$ if $j = \min(\arg\max_j |e_j|)$ and $\psi_j(e) = 0$ otherwise. This protocol behaves like TOD for large $|e|$ and for small $|e|$ it makes the error jumps smaller (e.g. because it is transmitting less information). Using $W(e) = |e|$, which is continuous, we can show that the inequality (9) holds and

[2] In this proposition we use the usual definitions of stability and global attractivity for the origin of a time varying system.

via Proposition 1 we conclude that there exists $U(e) := \rho(W)$ for some $\rho \in \mathcal{K}_\infty$ such that the protocol satisfies Assumption 2 with U and some $\alpha_1, \alpha_2, \lambda$. The protocol is not UGES since convergence is slower for smaller e.

Example 2 (Modified Token Ring Protocol): Define for $x \in \mathbb{R}_{\geq 0}$ the following function $\lfloor x \rfloor = \min\{z : x \leq z, z \in \mathbb{N}\}$. Also, let $sat(s) := \min\{s, 1\}$ for all $s \geq 0$. Consider the protocol (6) where $h(i,e) = (I - \Delta(i,e))e$ and $\Delta(i,e) = diag\{\delta_1(i,e)I_{n_1}, \ldots, \delta_\ell(i,e)I_{n_\ell}\}$, $\sum_{i=1}^{\ell} n_i = n_e$ and

$$\delta_k(i,e) = \begin{cases} 1 & \text{if } |e| > 0, i = \left\lfloor \frac{1}{sat(|e|)} \right\rfloor (k + j\ell), j \in \mathbb{N} \\ 0 & \text{otherwise} \end{cases}$$

This protocol behaves exactly like the token ring for $|e| > \frac{1}{2}$ and for small $|e|$ it transmits less frequently (e.g. for $|e| \in \left(\frac{1}{11}, \frac{1}{10}\right]$ the protocol transmits at a frequency that is 10 times smaller than that of the token ring protocol). $\Delta(\cdot,\cdot)$ is positive semi-definite, it has a norm less than 1 and for every $\delta > 0$ there exist $L := \left\lfloor \frac{1}{sat(\delta)} \right\rfloor \cdot \ell$ such that for all $k_0 \in \mathbb{N}$ we have

$$|e| \geq \delta \implies \sum_{i=k_0}^{k_0+L} \Delta(i,e) \geq I \ . \tag{10}$$

Stability of the corresponding difference inclusion [3] follows immediately using the Lyapunov function $|e|$. Global attractivity can be established using the uniform δ-PE concept in [14] and [15] (see [18] for related tools in discrete-time).

Note that we often abuse the terminology and refer either to (4) or (6) as the protocol. For instance, in the above definition we say that (4) is Lyapunov UGAS with $(W, \alpha_1, \alpha_2, \lambda)$ when this data can be used to show UGAS properties of the system (6).

Our results are stated for arbitrary UGAS protocol in the sense of Definition 1. Hence, they are applicable to a large class of protocols that were considered in the literature. For instance, the token ring protocols and try-once-discard (TOD) protocol were shown to be Lyapunov UGES protocols in [17] and, hence, they are also Lyapunov UGAS protocols. The proof of the following proposition is omitted due to space reasons (see the journal version of this paper [19] for complete proofs).

Proposition 3: Suppose that the following conditions hold:

1) $W(i,e)$ is continuous in e, uniformly in i;
2) $g(t,x,e,w)$ is bounded on compact sets, uniformly in t.

Then, there exists $\tau_1^* \in \mathcal{KL}$ such that for each pair of strictly positive real numbers (ε, c) the following holds:

$$\underbrace{\begin{array}{c} [t_a, t_b] \subseteq [t_{s_k}, t_{s_{k+1}}] \subseteq [t_{s_k}, t_{s_k} + \tau_1^*(\varepsilon, c)] \\ \max\{||x||_\infty, ||w||_\infty, W(k, e(t_a))\} \leq c \end{array}}_{\Downarrow} \tag{11}$$
$$W(k, e(t_b)) \leq W(k, e(t_a)) + \varepsilon \ .$$

[3]Note that in this example $H(i,e)$ defined in Proposition 2 is set valued at points where $1/|e|$ is an integer.

■

The main result of this section is presented next and its proof can be found in the Appendix. It states that any UGAS protocol yields semi-global practical uniform asymptotic stability (in the MATI) of the error dynamics (3). Note that this stability property is uniform with respect to initial times $t_\circ$, as well as disturbances w.

Theorem 1: Let $W : \mathbb{R}_{\geq 0} \times \mathbb{R}^n \to \mathbb{R}_{\geq 0}$, $\alpha_1, \alpha_2 \in \mathcal{K}_\infty$ and $\lambda \in [0,1)$ be given. Suppose that the following holds for system (2)-(4):

1) Assumption 2 holds;
2) $g(t,x,e,w)$ is bounded on compact sets, uniformly in t.

Then, there exist $\beta_e \in \mathcal{KL}$, $\gamma_e \in \mathcal{K}_\infty$ and $\tau^* \in \mathcal{KL}$ such that, for each pair of strictly positive real numbers (ε, c) the following holds

$$\underbrace{\begin{array}{c} \tau \leq \tau^*(\varepsilon, c) \\ \max\{||x||_\infty, ||w||_\infty, |e(t_\circ)|\} \leq c \end{array}}_{\Downarrow} \tag{12}$$
$$|e(t)| \leq \max\left\{\beta_e\left(|e(t_\circ)|, \tfrac{t-t_\circ}{\tau}\right), \gamma_e(\varepsilon)\right\} \ ,$$

for all $t \geq t_\circ \geq 0$. ■

V. MAIN RESULT

Our main result (Theorem 2) is stated in this section. The result states that under appropriate conditions any controller that achieves ISS of the closed loop system in the absence of network will also achieve semi-global-practical ISS of NCS in the MATI. The results is true for any UGAS protocol in the sense of Definition 1. In particular, we use the properties of the following auxiliary system:

$$\dot{\bar{x}} = f(t, \bar{x}, w, 0) \ , \tag{13}$$

which is the model of the closed loop system when there is no network (i.e. $e(\cdot) \equiv 0$). Then, we can state:

Theorem 2: Suppose that the following conditions hold:

1) Assumption 1 holds.
2) All conditions of Theorem 1 hold.
3) There exist $\beta \in \mathcal{KL}$ (continuous) and $\gamma \in \mathcal{G}$ such that, for each $t_\circ \geq 0$, the solutions of (13) satisfy
$$|\bar{x}(t)| \leq \max\{\beta(|\bar{x}(t_\circ)|, t - t_\circ), \gamma(||w||_\infty)\} \tag{14}$$
for all $t \geq t_\circ \geq 0$.

Then, there exist $\beta_e, \tau^* \in \mathcal{KL}$ such that, for each pair of strictly positive numbers (ε, c) and each $t_\circ \geq 0$, the following holds:

$$\underbrace{\begin{array}{c} \tau \leq \tau^*(\varepsilon, c) \\ \max\{|x(t_\circ)|, ||w||_\infty, |e(t_\circ)|\} \leq c \end{array}}_{\Downarrow}$$
$$\begin{array}{rcl} |x(t)| & \leq & \max\{\beta(|x(t_\circ)|, t - t_\circ), \gamma(||w||_\infty)\} + \varepsilon \\ |e(t)| & \leq & \max\left\{\beta_e\left(|e(t_\circ)|, \dfrac{t - t_\circ}{\tau}\right), \varepsilon\right\} \\ & \forall & t \geq t_\circ \geq 0 \end{array}$$

■

Remark 2: Theorem 2 suggests that the ISS controller design can be carried in two steps. In the first step the control designer ignores the network and designs the controller to achieve ISS of the closed loop system. In the second step the control designer needs to choose sufficiently small MATI that will achieve appropriate ISS stability bounds on an appropriate bounded set of initial states and disturbances. ■

The proof technique that we use to prove Theorem 2 is similar to the one exploited in [20]. The proof makes use of ISS of the auxiliary system (13) to show that we can achieve semi-global practical ISS in MATI of the NCS (2)-(4). The main technical step in establishing this result is presented below and its proof is omitted due to space limitations. This result states that the solutions of the auxiliary system (13) and the actual NCS (2)-(4) can be made arbitrarily close on arbitrarily long time intervals if the MATI is chosen sufficiently small.

Lemma 2: Consider system (2)-(4) and suppose that all conditions of Theorem 2 hold. Then, there exists $\tau^* \in \mathcal{KLL}$ such that, for each strictly positive triple (ρ, T, c), each $t_\circ \geq 0$ and each $|x(t_\circ)| \leq c$, there exists $\bar{x}(t_\circ) \in \mathbb{R}^n$ such that

$$\underbrace{\begin{array}{c}\tau \leq \tau^*(\rho, T, c) \\ \max\{||x||_\infty, ||w||_\infty, ||e||_\infty\} \leq c\end{array}}_{\Downarrow} \qquad (15)$$
$$|x(t) - \bar{x}(t)| \leq \rho \quad \forall t \in [t_\circ, t_\circ + T] \ .$$

■

Remark 3: The conclusion of Lemma 2 may hold when Assumption 1 is weakened. For example, in the time invariant case, continuity of f is sufficient. ■

The next proposition follows directly using the proof of [20, Theorem 1] and its proof is omitted. This proposition establishes under conditions of Lemma 2 that an ISS stability bound holds for (2).

Proposition 4: Under the conclusion of Lemma 2 there exists $\tau^* \in \mathcal{KL}$ such that, for each pair of strictly positive numbers (ε, c) and each $t_\circ \geq 0$,

$$\underbrace{\begin{array}{c}\tau \leq \tau^*(\varepsilon, c) \\ \max\{|x(t_\circ)|, ||w||_\infty, ||e||_\infty\} \leq c\end{array}}_{\Downarrow}$$
$$|x(t)| \leq \max\{\beta(|x(t_\circ)|, t - t_\circ), \gamma(||w||_\infty)\} + \varepsilon,$$

for all $t \geq t_\circ \geq 0$. ■

Sketch of proof of Theorem 2: The proof of the main result follows by combining Lemma 2, Theorem 1 and Proposition 4 and using causality to remove the assumptions on $||x||_\infty$ and $||e||_\infty$. This proof technique very similar to the proof of the ISS small gain theorem in [10] and for space reasons it is omitted. ■

VI. CONCLUSIONS

We considered input to state stability of networked control systems with a large class of (UGAS) protocols. We showed that if a controller that is designed with the assumption that there is no network achieves ISS of the closed loop system, then the same controller when implemented via the network achieves semi-global-practical ISS (in the MATI) of NCS.

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VII. Appendix

A. Proof of Theorem 1

Let all conditions of Theorem 1 be satisfied. Let τ_1^* come from Proposition 3. We will, henceforth, use the notation $W_+(k) := W(k, e(t_{s_k}^+))$ and $W_-(k) := W(k, e(t_{s_k}^-))$. We prove Proposition for (ε, c) such that:

$$\begin{aligned} \varepsilon &\le \min\left\{1, \widetilde{c}(c)\left(\frac{1}{\lambda} - 1\right)\right\} , & (16)\\ \widetilde{c}(s) &:= \max\{s, \alpha_2(s) + 1\} . & (17) \end{aligned}$$

Once this is proved, then the result follows directly for arbitrary $\varepsilon > 0$ and $c > 0$.

Note first that since (16) implies $\varepsilon \le 1$, we can write using (7):

$$\underbrace{\begin{array}{c} \tau \le \tau^*(\varepsilon, c) \\ \max\{||x||_\infty, ||w||_\infty, |e(t_\circ)|\} \le c \end{array}}_{\Downarrow} \quad (18)$$
$$\begin{array}{c} \tau \le \tau_1^*(\varepsilon, \widetilde{c}(c)) \\ \max\{||x||_\infty, ||w||_\infty, \alpha_2(|e(t_\circ)|) + \varepsilon\} \le \widetilde{c}(c) \ . \end{array}$$

To shorten notation, we use $\widetilde{c} := \widetilde{c}(c) = \max\{c, \alpha_2(c)+1\}$. From item 2 with $(\varepsilon, \widetilde{c})$ we may write (11) with $t_a = t_{s_k}^+$ and $t_b = t_{s_{k+1}}^-$ as

$$\underbrace{\begin{array}{c} \tau \le \tau_1^*(\varepsilon, \widetilde{c}) \\ \max\{||x||_\infty, ||w||_\infty, W_+(k)\} \le \widetilde{c} \end{array}}_{\Downarrow} \quad (19)$$
$$W_-(k+1) \le W_+(k) + \varepsilon \ .$$

and write (8) as

$$W_+(k+1) \le \lambda W_-(k+1) \ . \quad (20)$$

The relations (19) and (20) can be combined to write

$$\underbrace{\begin{array}{c} \tau \le \tau_1^*(\varepsilon, \widetilde{c}) \\ \max\{||x||_\infty, ||w||_\infty, W_+(k)\} \le \widetilde{c} \end{array}}_{\Downarrow} \quad (21)$$
$$W_+(k+1) \le \lambda(W_+(k) + \varepsilon) \ .$$

From (16) we have that $\varepsilon \le \widetilde{c}\left(\frac{1}{\lambda} - 1\right)$ and this implies using (21) and induction that if for some ℓ we have $W_+(\ell) \le \widetilde{c}$, then for all $k \ge \ell$ we have $W_+(k) \le \lambda(\widetilde{c}+\varepsilon) \le \widetilde{c}$. Using this we can write for each $k \ge \ell$ that

$$\underbrace{\begin{array}{c} \tau \le \tau_1^*(\varepsilon, \widetilde{c}) \\ \max\{||x||_\infty, ||w||_\infty, W_+(\ell)\} \le \widetilde{c} \end{array}}_{\Downarrow} \quad (22)$$
$$W_+(k) \le \lambda^{k-\ell} W_+(\ell) + \varepsilon \tfrac{\lambda}{1-\lambda} \ .$$

Next, taking into account the inter-sample behavior from (11) we can write

$$\underbrace{\begin{array}{c} t \in [t_{s_k}, t_{s_{k+1}}) \ , \ t_\circ \in [t_{s_\ell}, t_{s_{\ell+1}}) \ , \ t \ge t_\circ \\ \tau \le \tau_1^*(\varepsilon, \widetilde{c}) \\ \max\{||x||_\infty, ||w||_\infty, W(\ell, e(t_\circ)) + \varepsilon\} \le \widetilde{c} \end{array}}_{\Downarrow}$$
$$\begin{aligned} W(k, e(t)) &\le \lambda^{k-\ell}\left(W(\ell, e(t_\circ)) + \varepsilon\right) + \varepsilon \frac{1}{1-\lambda} \\ &\le \lambda^{k-\ell} W(\ell, e(t_\circ)) + \varepsilon \frac{2-\lambda}{1-\lambda} \ . \end{aligned}$$

Next we observe that $t - t_\circ \le (k - \ell + 2)\tau$, i.e., $k - \ell \ge -2 + \frac{t - t_\circ}{\tau}$. Then, defining $\eta := -\ln(\lambda) > 0$, we get

$$\underbrace{\begin{array}{c} t \in [t_{s_k}, t_{s_{k+1}}) \ , \ t_\circ \in [t_{s_\ell}, t_{s_{\ell+1}}) \ , \ t \ge t_\circ \\ \tau \le \tau_1^*(\varepsilon, \widetilde{c}) \\ \max\{||x||_\infty, ||w||_\infty, W(\ell, e(t_\circ)) + \varepsilon\} \le \widetilde{c} \end{array}}_{\Downarrow}$$
$$\begin{aligned} &W(k, e(t)) \le \exp(2\eta) \exp\left(-\frac{\eta}{\tau}(t - t_\circ)\right) W(\ell, e(t_\circ)) \\ &\quad + \varepsilon \tfrac{2-\lambda}{1-\lambda} \\ &\le \max\left\{2\exp(2\eta)\exp\left(-\frac{\eta}{\tau}(t - t_\circ)\right) W(\ell, e(t_\circ)) \ , \right. \\ &\quad \left. \varepsilon \tfrac{2(2-\lambda)}{1-\lambda})\right\} \ . \end{aligned}$$

Then we use (7) to write

$$\underbrace{\begin{array}{c} \tau \le \tau_1^*(\varepsilon, \widetilde{c}) \\ \max\{||x||_\infty, ||w||_\infty, \alpha_2(|e(t_\circ)|) + \varepsilon\} \le \widetilde{c} \end{array}}_{\Downarrow}$$
$$\begin{aligned} |e(t)| &\le \max\left\{\alpha_1^{-1}\left(2\exp(2\eta)\exp\left(-\frac{\eta}{\tau}(t - t_\circ)\right)\alpha_2(|e(t_\circ)|)\right) \ , \right. \\ &\quad \left. \alpha_1^{-1}\left(\varepsilon \tfrac{2(2-\lambda)}{1-\lambda}\right)\right\} \\ &= \max\left\{\beta_e\left(|e(t_\circ)|, \frac{t - t_\circ}{\tau}\right), \gamma_e(\varepsilon)\right\} \ , \end{aligned}$$

for all $t \ge t_\circ \ge 0$. The last inequality, together with (18), concludes the proof. ■