

Lecture 2

Textbooks

Main textbook:

The Art of Hybrid Systems

robotics.eecs.berkeley.edu/~sastry/ee291e/book.pdf

Good complementary lecture notes (chp. 1 - 4)

robotics.eecs.berkeley.edu/~sastry/ee291e/lygeros.pdf

Other textbooks:

A. van der Schaft and H. Schumacher. An Introduction to Hybrid Dynamical Systems. Lecture Notes in Control and Information Sciences 251, Springer-Verlag, 2000.

D. Liberzon. Switching in Systems and Control. Systems & Control: Foundations and Applications series. Birkhauser, Boston, 2003.

Evaluate the following advice...



Stefan Sagmeister

Be careful whose advice you take.

Be passionate about your education. Work on finding your passions.

View work as a hobby. Enjoy it (it's your hobby after all).

Don't strive for success. Avoid mediocracy.

Worrying solves nothing[†]. Act or forget.

Don't waste time on jealousy. Everybody who is honest is interesting[†]

Money does not make me happy. Neither does makeup.

Trying to look good limits my life[†]. Appreciate and enjoy your body.

Everybody thinks they are right[†].

Traveling opens new perspectives. Travel alone (once in a while).

Learn a foreign language. Learn think mathematically.

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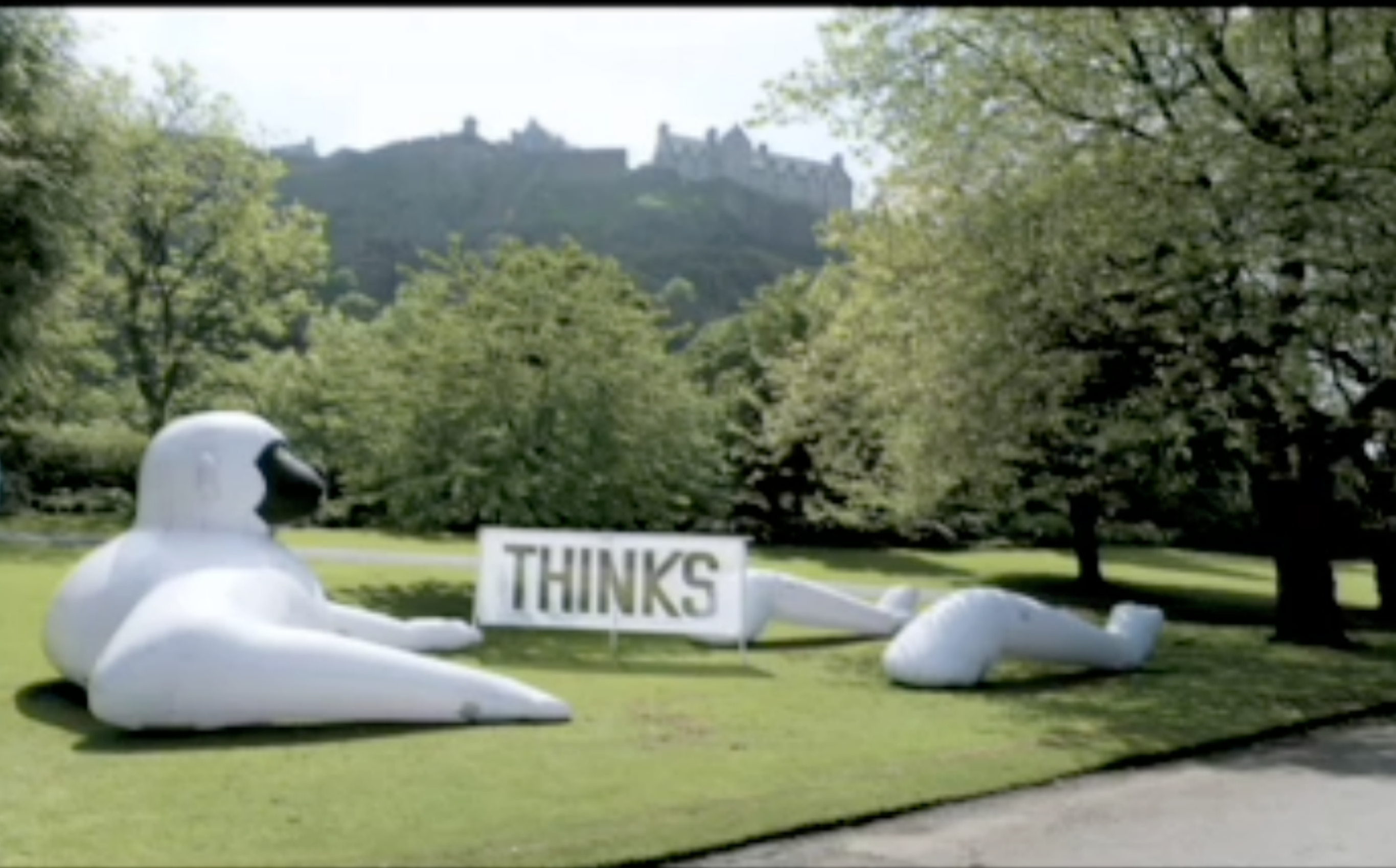
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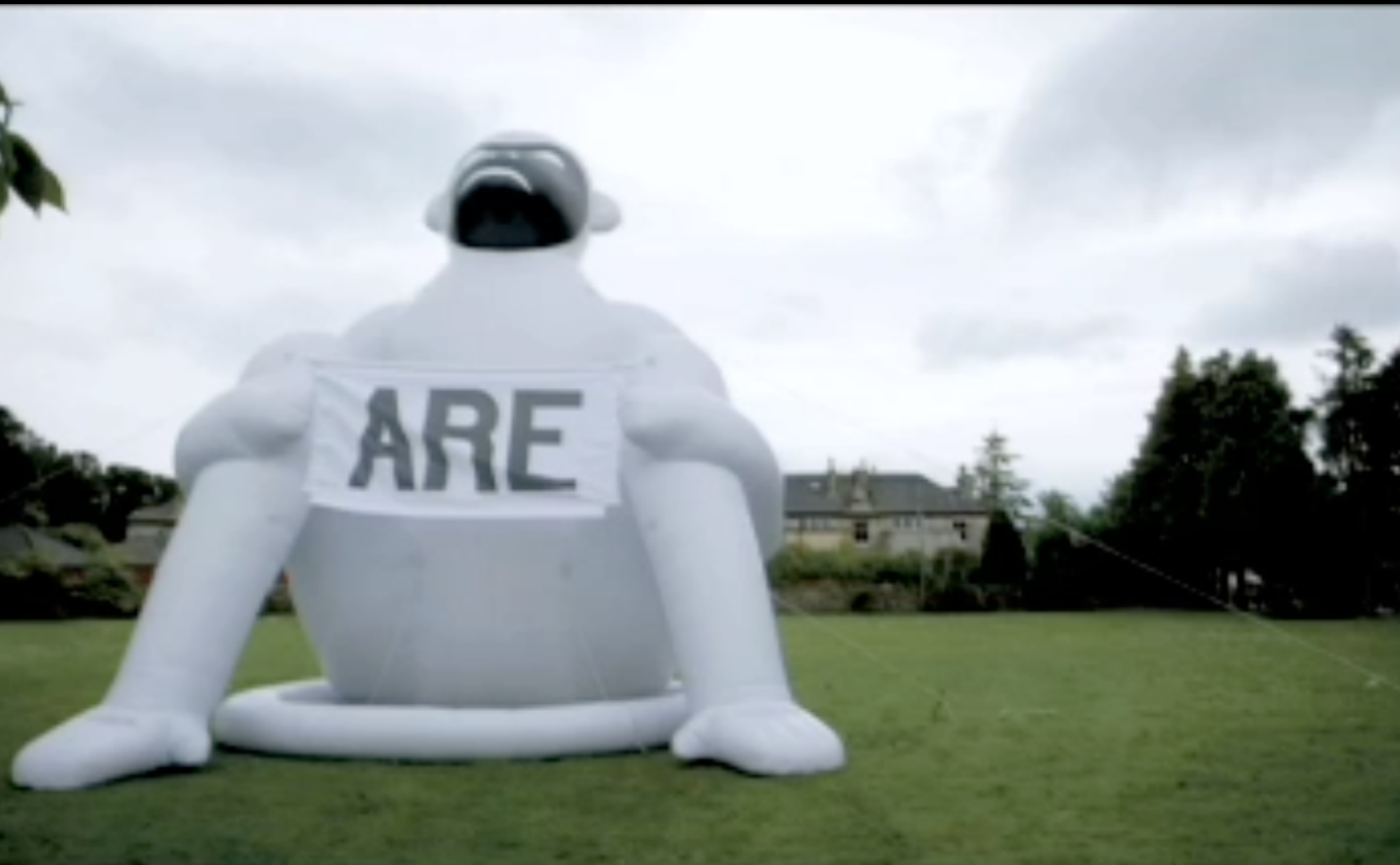
Inflatable monkey in Scotland (Stefan Sagmeister)





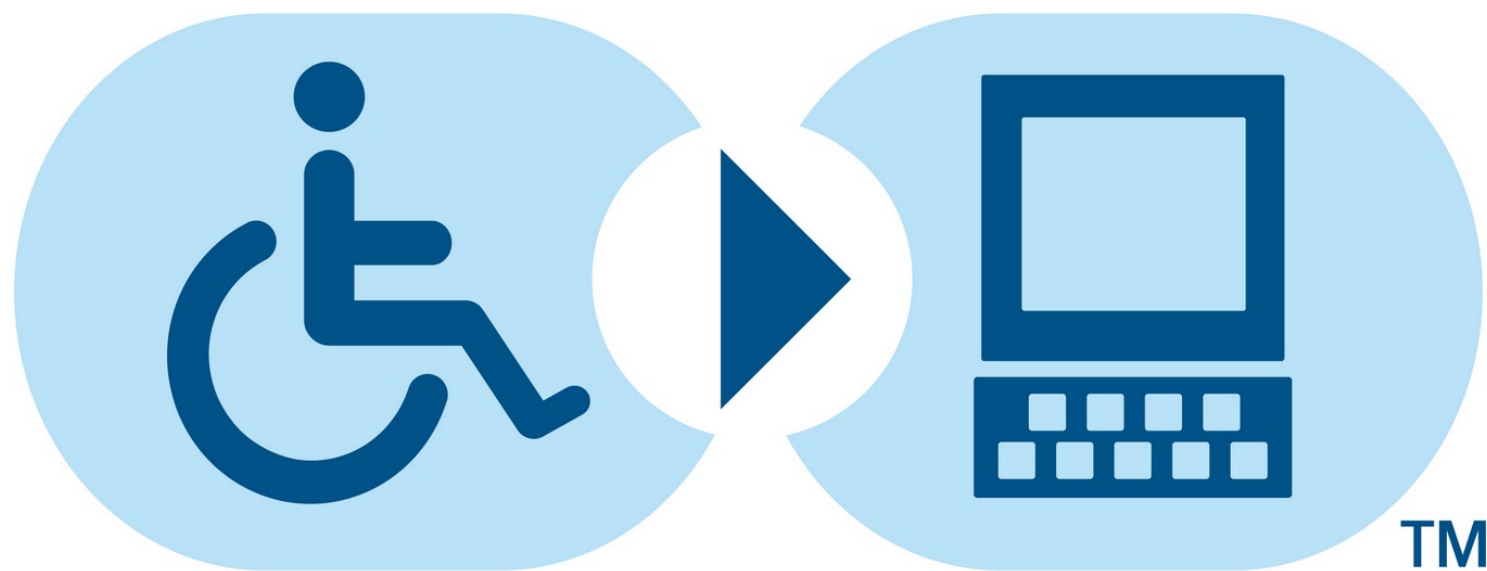








...from an engineering/science
perspective...



Collect data +
Develop models

If we have data, let's look at data.
If all we have are opinions, let's go with mine.

– Jim Barksdale, former Netscape CEO

In God we trust; all others must bring data

**– W. Edwards Deming, statistician, professor,
author, and consultant**

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Everybody thinks they are right[†]. Use technology and learn from data + models.

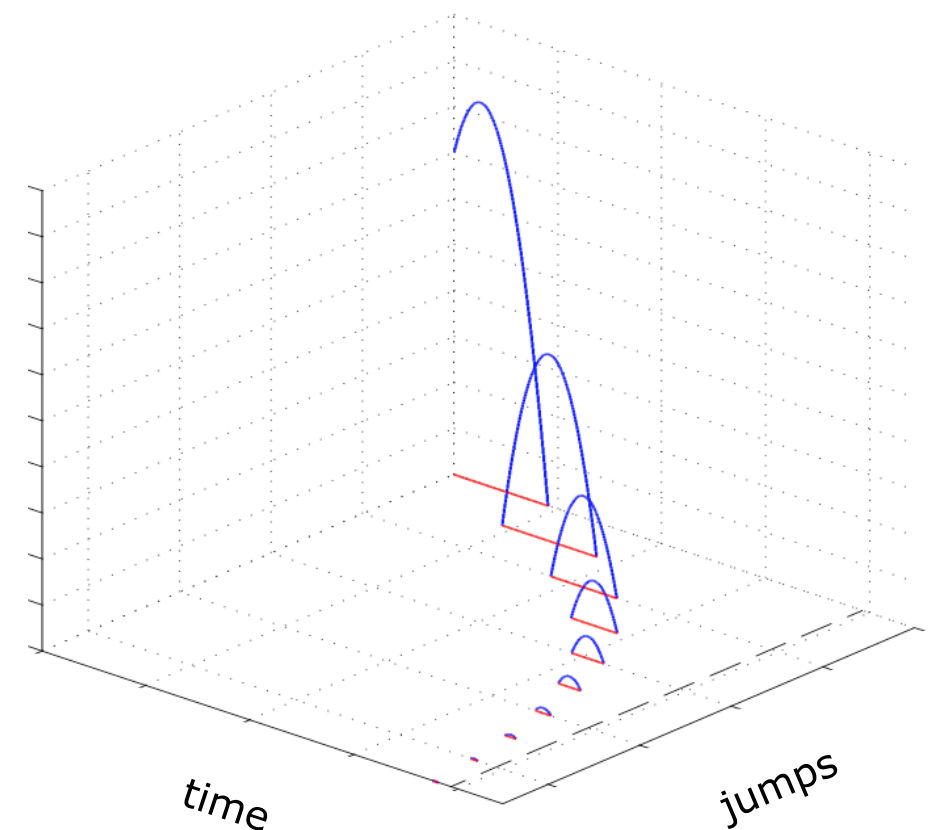
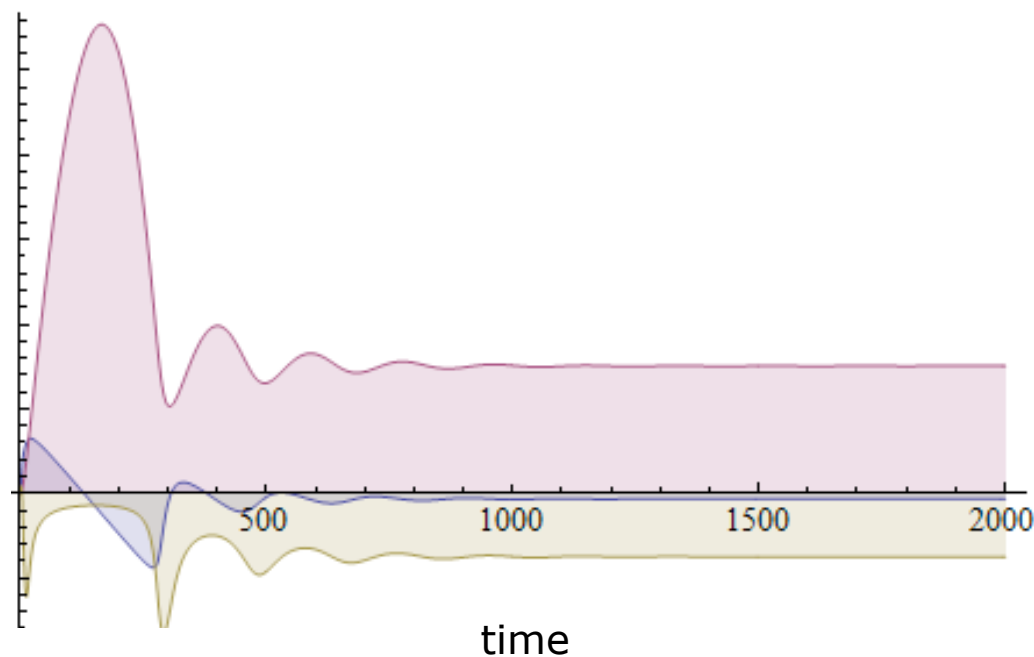
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Review

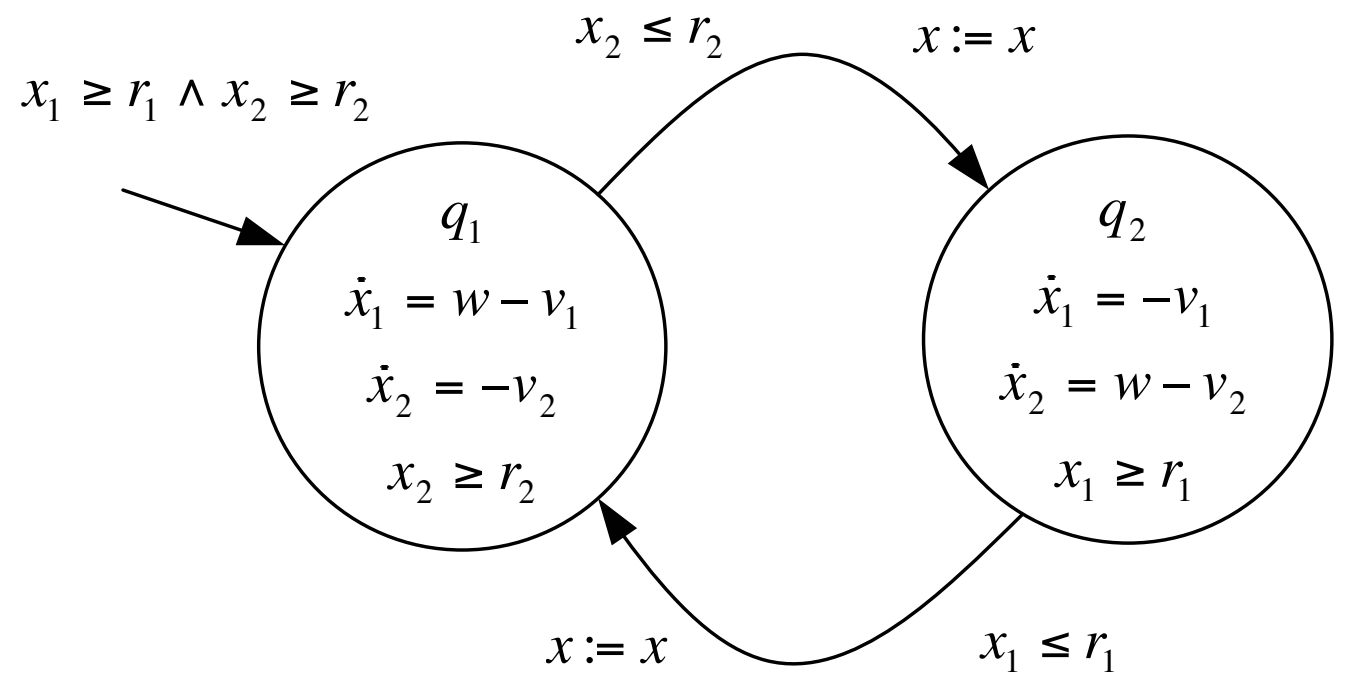
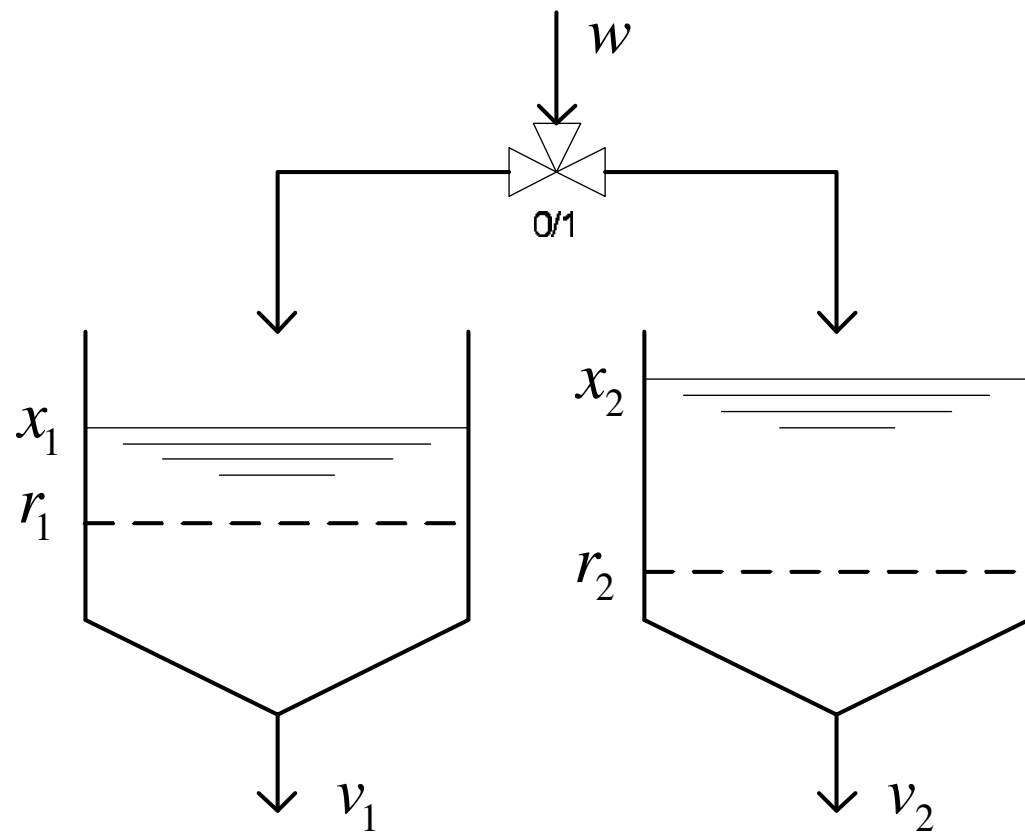
- State of the art modeling technique (characterize data on more sophisticated phenomena)
- Real love is hybrid! Stable? No! Why? Continuous + discrete dynamics.
- Other examples of hybrid systems
- Reality is less smooth than a set of differential eqs
- Notation, classification of dynamical systems

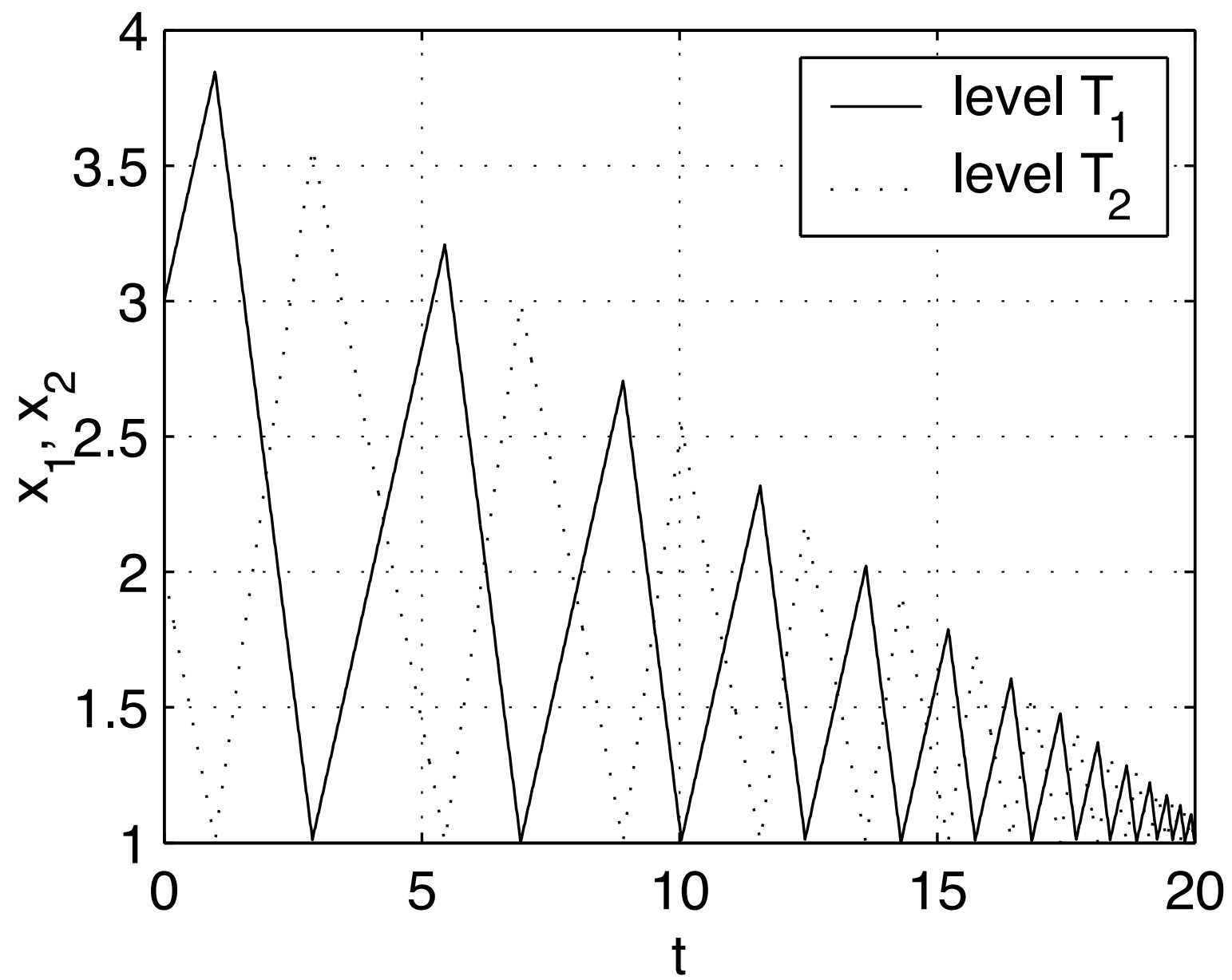


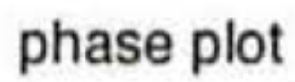
Today

- Hybrid automata (deterministic case)
 - Definitions
 - Time sets + Executions
- Classification of solutions
- Next class: existence of solutions

Tank example







Simulating Hybrid Systems

- MATLAB's Simulink
 - suitable for a small number of discrete modes
 - difficult to recover hybrid model
- Stateflow
 - good for large numbers of discrete modes and complex transitions
 - poor integration between continuous and discrete
- SHIFT
 - very good semantics (easily understandable), poor numerical algorithms
- Modelica
 - very good numerical algorithms
 - very convenient for large models with interconnected components
 - difficult to recover hybrid model

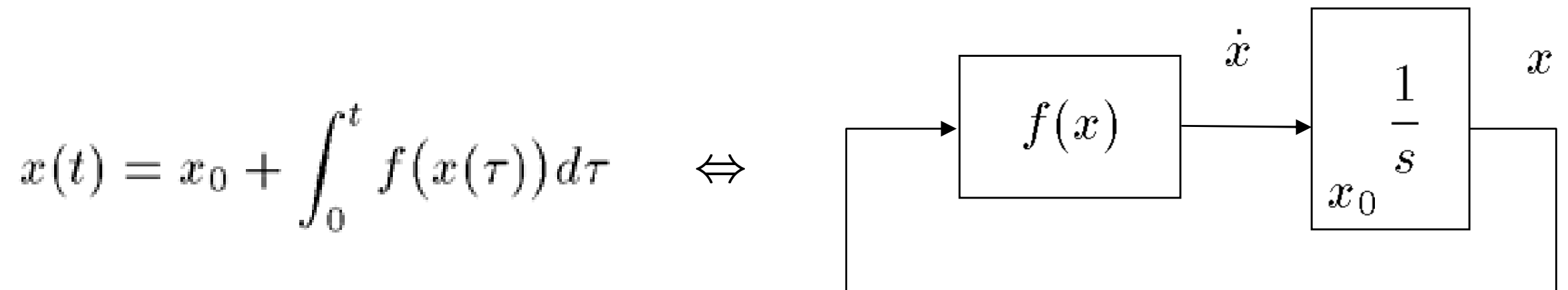
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MATLAB's Simulink

Simulink

$$\dot{x} = f(x) \quad x(0) = x_0$$

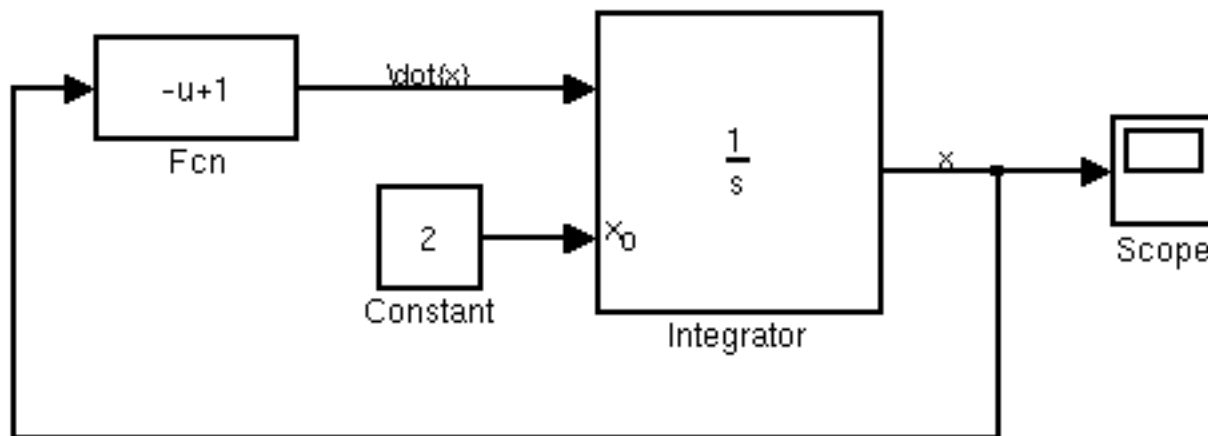
1. What you see: graphical user interface to build models of dynamical systems



2. What's behind: numerical solver of ODEs with zero-crossing detection

ODEs with initial conditions

$$\dot{x} = -x + 1$$
$$x(0) = 2$$



Integrator

Continuous-time integration of the input signal.

Parameters

External reset: none

Initial condition source: external

☐ Limit output

Upper saturation limit: inf

Lower saturation limit: -inf

☐ Show saturation port

☐ Show state port

Absolute tolerance: auto

☐ Ignore limit and reset when linearizing

☒ Enable zero crossing detection

State Name: (e.g., 'position')

"

OK Cancel Help Apply

Fcn

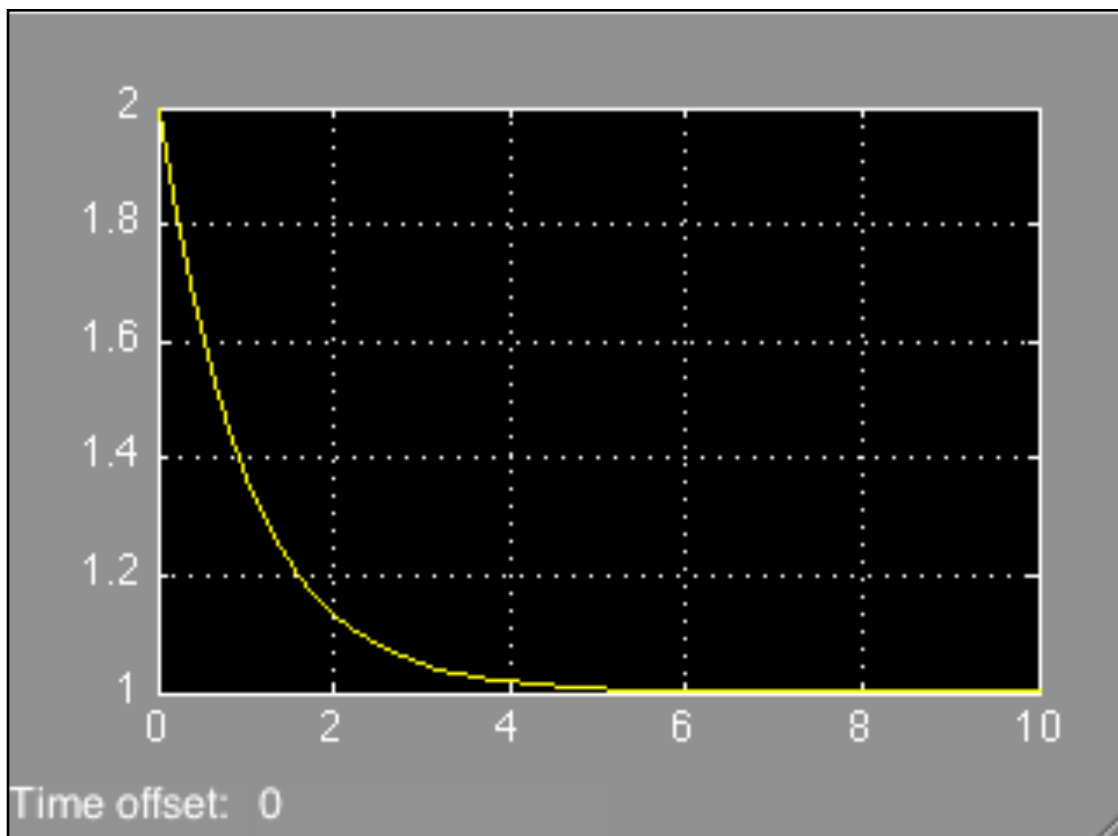
General expression block. Use "u" as the input variable name.
Example: sin(u[1] * exp(2.3 * -u[2]))

Parameters

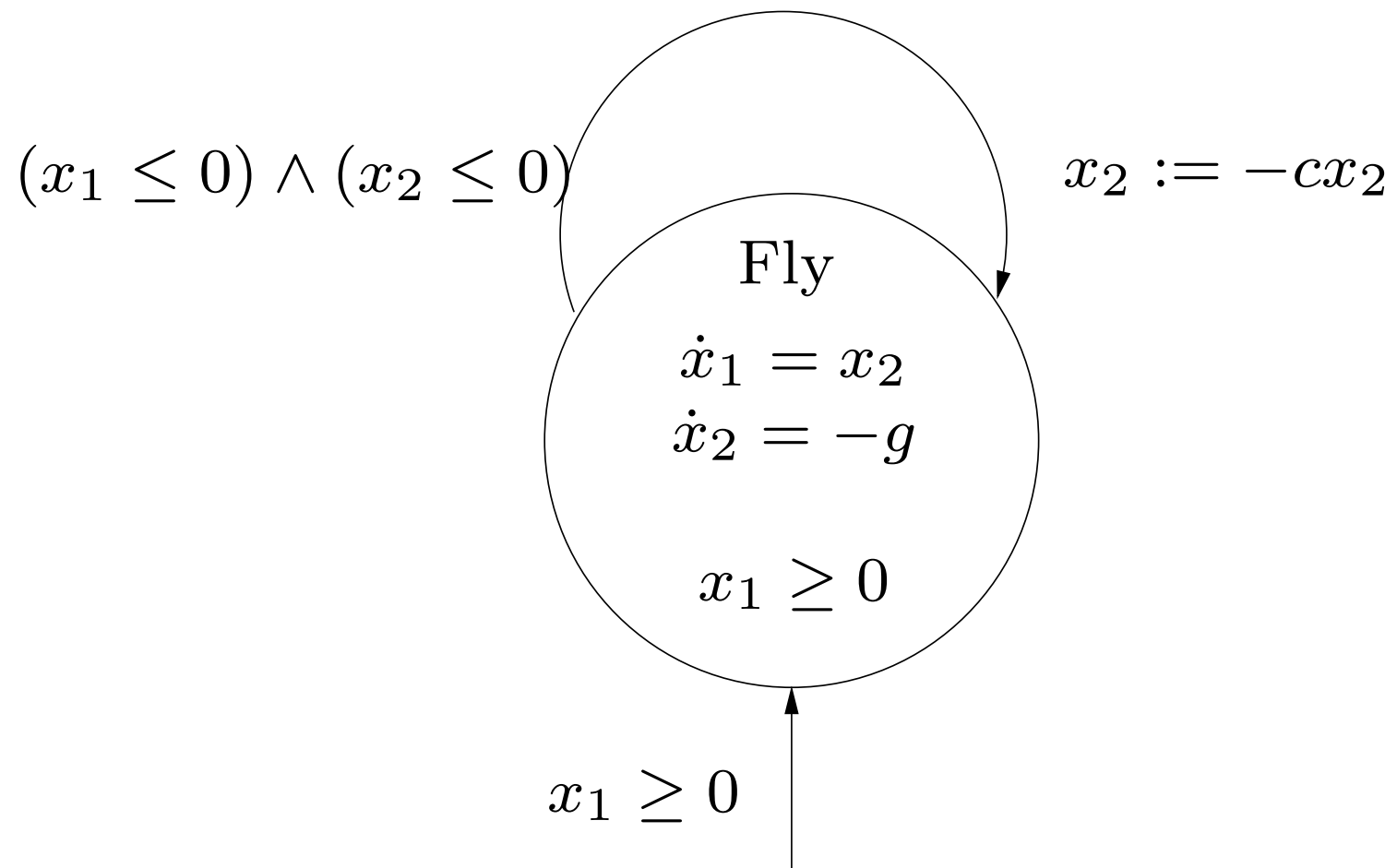
Expression: -u+1

Sample time (-1 for inherited): -1

OK Cancel Help Apply



Bouncing ball



ODEs with resets

Integrator

Continuous-time integration of the input signal.

Parameters

External reset: rising

Initial condition source: external

☐ Limit output

Upper saturation limit: inf

Lower saturation limit: -inf

☐ Show saturation port

☒ Show state port

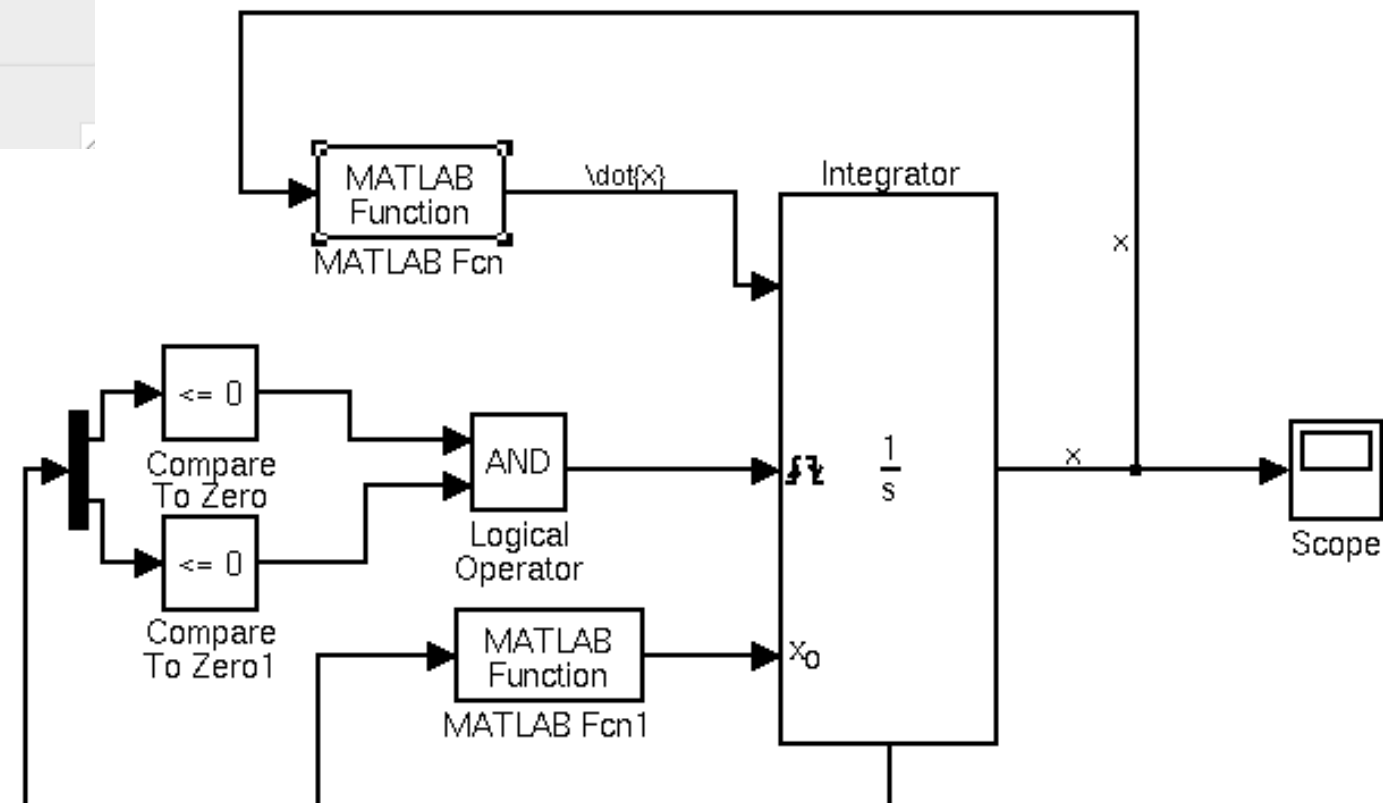
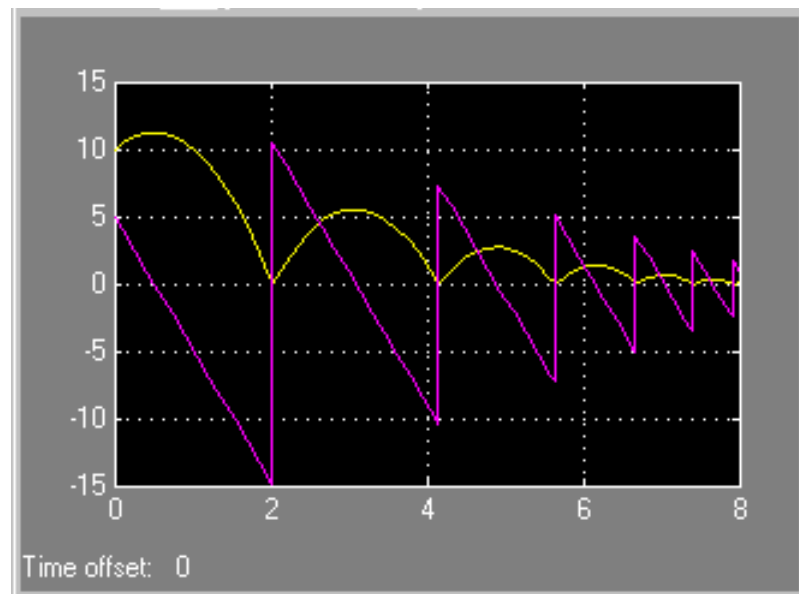
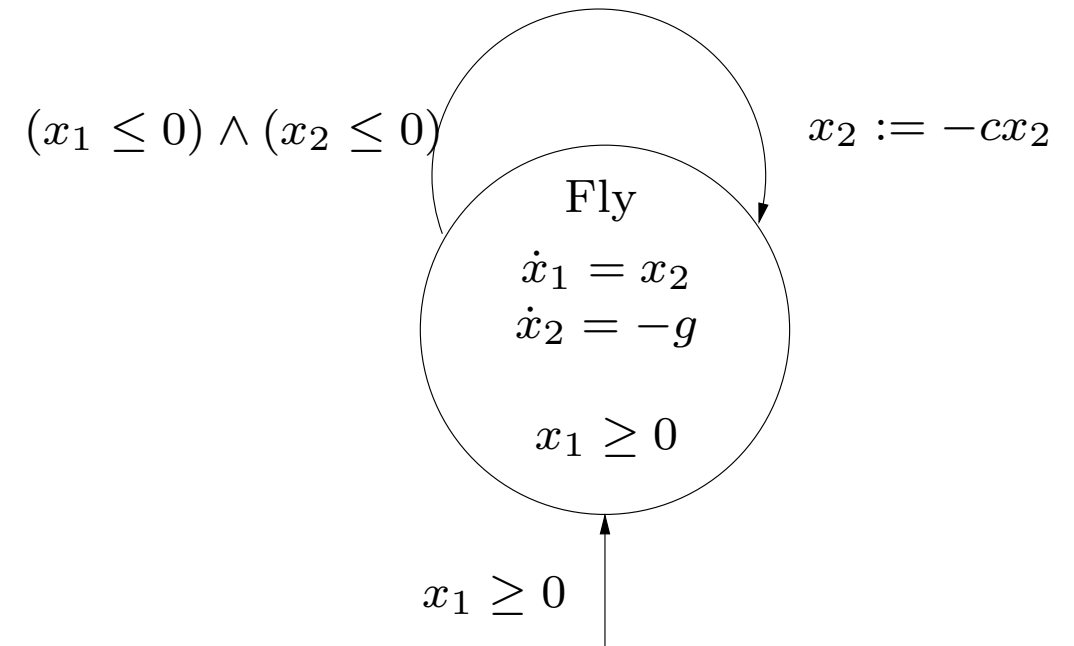
Absolute tolerance: auto

☐ Ignore limit and reset when linearizing

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State Name: (e.g., 'position') "

OK Cancel Help Apply

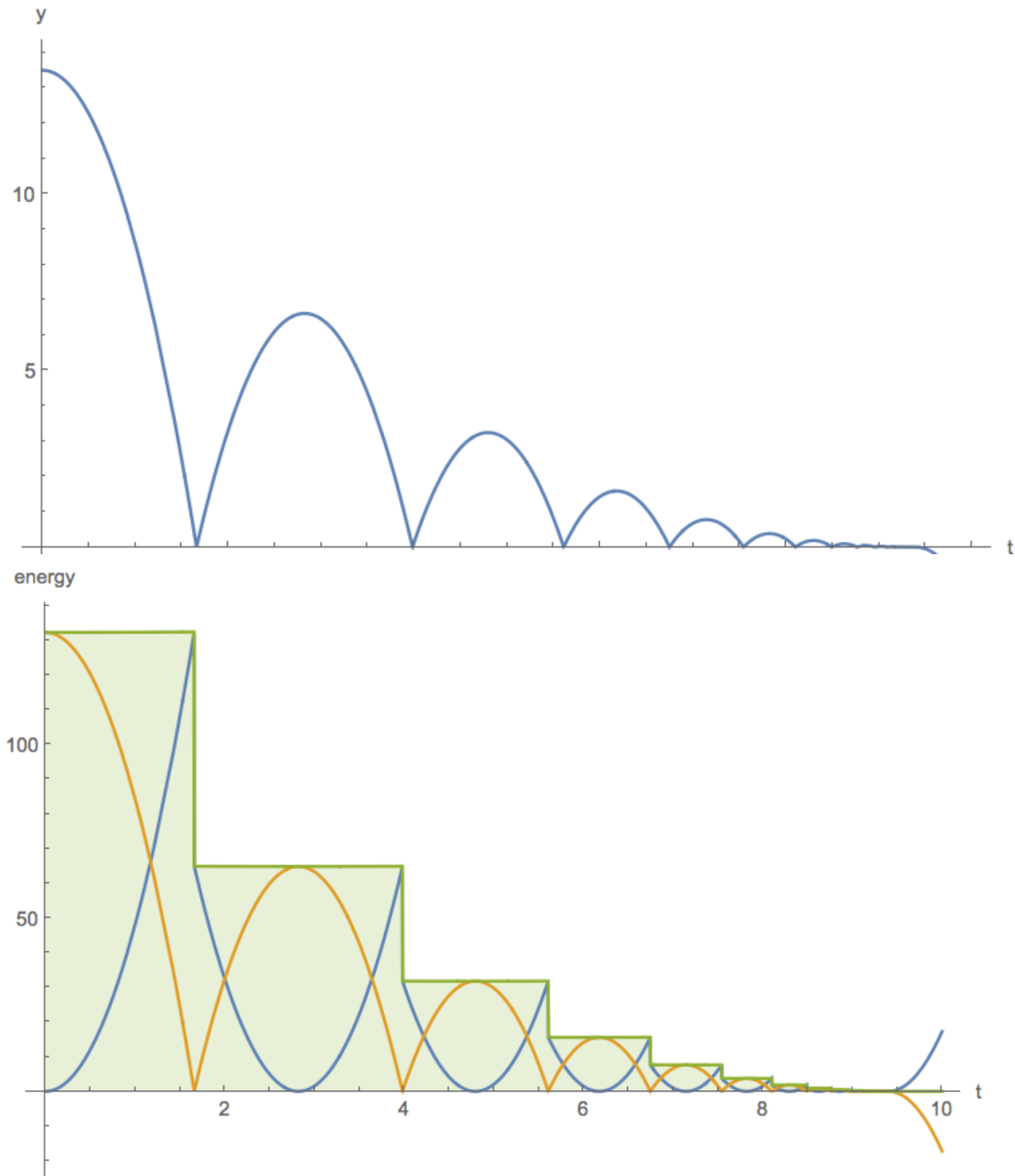


Mathematica

```

imagesize = 500;
ball =
  NDSolve[{y''[t] == -9.81, y[0] == 13.5,
    y'[0] == 0, WhenEvent[y[t] == 0,
      y'[t] → -0.7 y'[t]]}, y,
    {t, 0, 10}];
kin[v_] := .5 v^2;
pot[y_] := 9.8 y;
energy[y_, v_] := kin[v] + pot[y];
GraphicsGrid[
  {{Plot[y[t] /. ball, {t, 0, 10},
    AxesLabel → {"t", "y"},
    ImageSize → imagesize],
    Plot[Evaluate[
      {kin[y'[t]], pot[y[t]],
        energy[y[t], y'[t]] /. ball},
      {t, 0, 10}, Filling → {3 → 0},
      AxesLabel → {"t", "energy"}]}]}]}

```



What can go wrong?

- Problems in the continuous evolution
 - existence
 - uniqueness
 - finite escape
- Problems in the hybrid execution:
 - chattering
 - zeno
- Non-continuous dependency on initial conditions

...next class!