

Consensus Problems in Networks of Agents with Switching Topology and Time-Delays

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分享暨个人总结

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- 4 Algebraic Graph Theory: Properties of Laplacians
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- 9 Simulation Results

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Some Basic Notations

- adjacency matrix
- neighbors nodes
- decision value
- χ -Consensus Problem
- Ave/Max/Min Consensus
- $\mathcal{A} = [a_{ij}]$
- N_i
- $\alpha(x^*)$
- χ
- Ave(x)/Max(x)/Min(x)

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Model Consensus Protocols

CT Model

$$\dot{x}_i = u_i(t)$$

DT Model

$$x_i(k+1) = x_i(k) + \epsilon u_i(k), \epsilon > 0$$

A1 Zero Communication Time-Delay

$$u_i = \sum_{j \in N_i} a_{ij}(x_j - x_i)$$

A2 Communication Time-Delay $\tau_{ij} > 0$

$$u_i(t) = \sum_{j \in N_i} a_{ij}[x_j(t - \tau_{ij}) - x_i(t - \tau_{ij})]$$

Consensus Problems:

1. Dynamic Networks
2. Consensus Protocols

Laplacians

$$l_{ij} = \begin{cases} \sum_{k=1, k \neq i}^n a_{ik}, & j = i \\ -a_{ij}, & j \neq i \end{cases}$$

A1 State Evolves

$$\dot{x}(t) = -Lx(t)$$

A1 State Evolves with Switchin Topology

$$\dot{x}(t) = -L_k x(t), \quad k = s(t)$$

A1 DT

$$x(k+1) = P_\epsilon x(k), \quad P_\epsilon = I - \epsilon L$$

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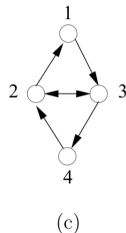
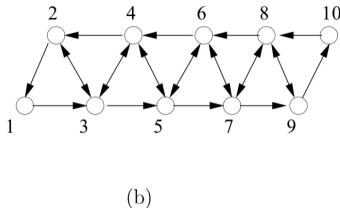
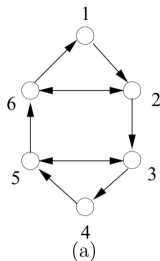
Balanced Graph

Balanced Node

$$\deg_{out}(v_i) = \deg_{in}(v_i)$$

Balanced Graph

$$\deg_{in}(v_i) = \sum_{j=1}^n a_{ji}, \quad \deg_{out}(v_i) = \sum_{j=1}^n a_{ij}$$



Laplacians

$$L = \mathcal{L}(G) = \Delta - \mathcal{A}$$

Δ (degree matrix) $\rightarrow \text{diag}(\text{deg}_{out}(v_i))$

\mathcal{A} (adjacency matrix) $\in \{0,1\}$

$w_r : L w_r = \lambda w_r$

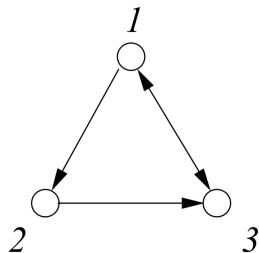
$w_l : w_l L = w_l \lambda$

SC (Strongly Connected)

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Counterexample



$$D = \begin{bmatrix} 2 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}, A = \begin{bmatrix} 0 & 1 & 1 \\ 0 & 0 & 1 \\ 1 & 0 & 0 \end{bmatrix}$$

$$L = \begin{bmatrix} 2 & -1 & -1 \\ 0 & 1 & -1 \\ -1 & 0 & 1 \end{bmatrix}$$

$$\mathcal{V} = \{1, 2, 3\}, \quad \mathcal{E} = \{12, 23, 31, 13\}.$$

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$$x^* = \lim_{t \rightarrow +\infty} x(t) = Rx_0 = w_r(w_L^T x_0) = \frac{1}{\sqrt{n}}(w_l^T x_0)\mathbf{1}$$

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$$\dot{x}_i(t) = \sum_{j \in N_i} a_{ij} [x_j(t - \tau_{ij}) - x_i(t - \tau_{ij})].$$

$$\tau \leq \frac{\pi}{4d_{\max}(G)}$$

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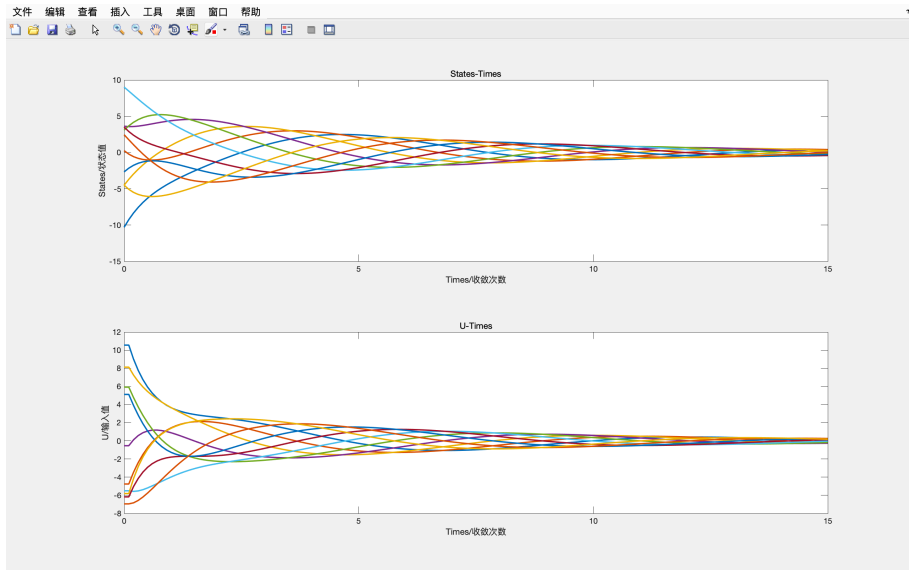
$$x_i(k+1) = \max(x_i(k), u_i(k))$$

$$x_i(k+1) = \frac{1}{2}(x_i(k) + u_i(k) + |x_i(k) - u_i(k)|) \quad u_i(k) = \max_{j \in N_i} x_j$$

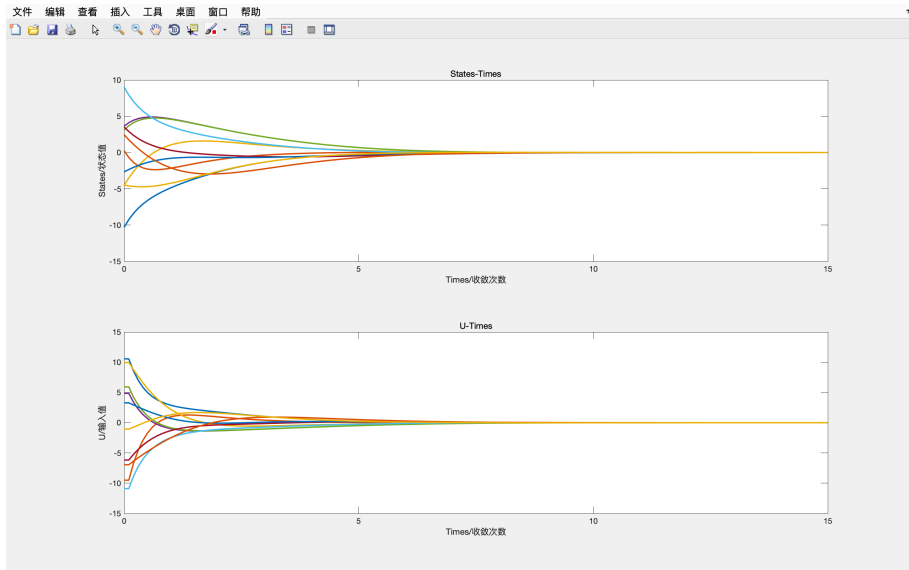
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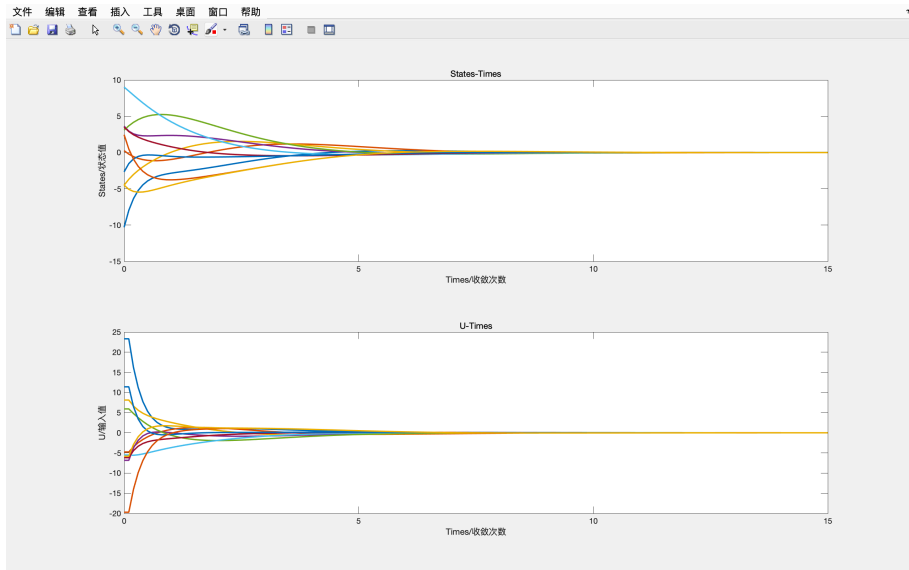
Simulation



Simulation



Simulation



Simulation

