Contents

- Hybrid Control Homework #2
- Problem 1 Spatial

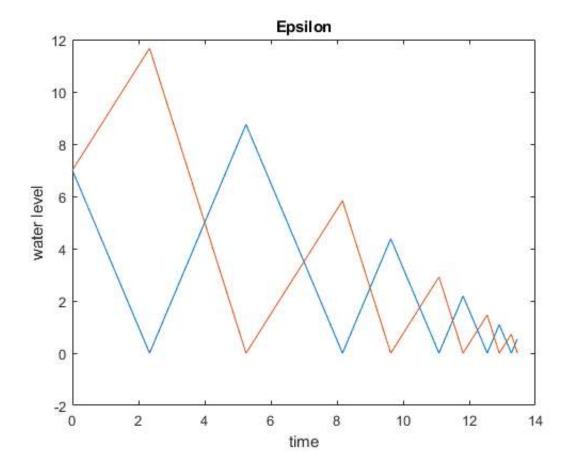
Hybrid Control Homework #2

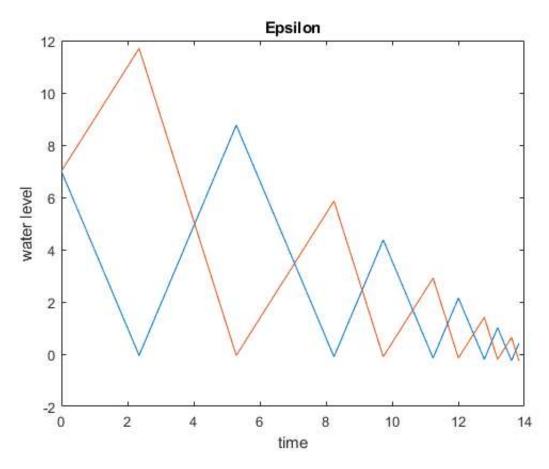
```
clc; clear; close all;
```

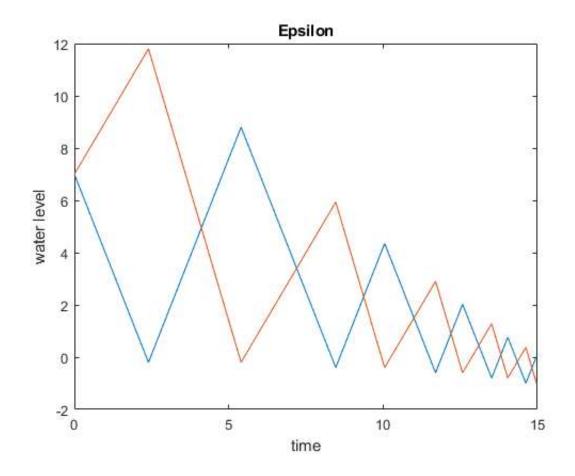
Problem 1 Spatial

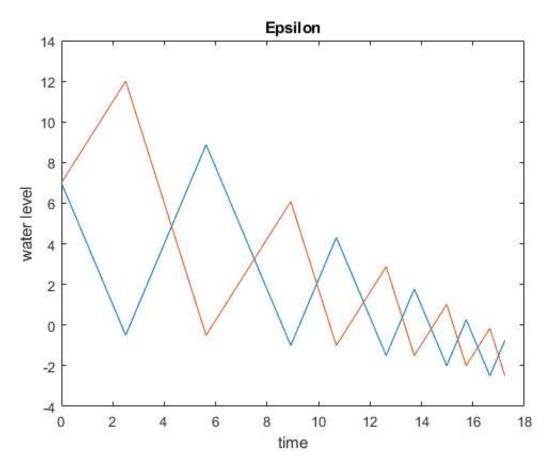
```
%%%%% Parameters
r1 = 5;
r2 = 5;
v1 = 3;
v2 = 4;
w = 6;
epsilon = [0, 0.05, 0.2, 0.5, 0.6];
for j = 1:length(epsilon)
   %%%%% Initial conditions
   x1 = 7;
   x2 = 7;
   x3 = 0;
   x4 = 0;
    x0 = [x1; x2; x3; x4];
   Tspan = [0 \ 10] ;
    t0 = 0 ; % Initial Time
    t_vec = [] ; x = [] ;
    q0 bool = false;
    q1_bool = false;
    if x0(1) \le x0(3) - epsilon(j)
        func = @(t,x) q1(t,x,w,v1,v2,r1,r2);
        options = odeset('Events',@(t,x) event_q1(t,x,w,v1,v2,r1,r2,epsilon(j)));
        q1 bool = true;
    else
        func = @(t,x) q0(t,x,w,v1,v2,r1,r2);
        options = odeset('Events',@(t,x) event_q0(t,x,w,v1,v2,r1,r2,epsilon(j)));
        q0 bool = true;
    end
    for i = 1:10
        % Continuous Dynamics
        [t,x_vec] = ode45(func, t0+Tspan, x0, options);
        % Save simulation data
        t_{vec} = [t_{vec}; t];
        x = [x; x_vec];
```

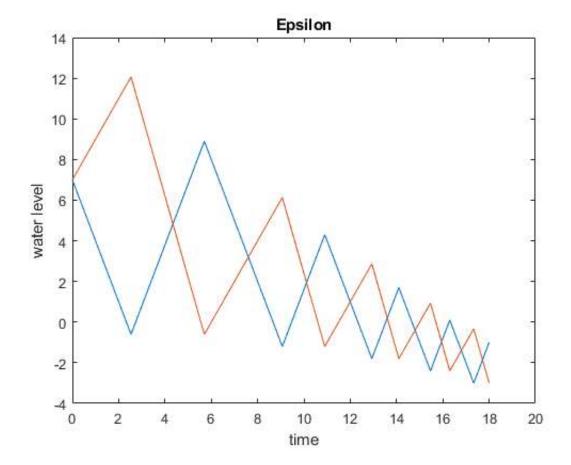
```
% Discrete Impact Dynamics
        x0 = x_vec(end,:);
        t0 = t_vec(end);
        % Simulate the system until event (water tank) occurs
        if x0(1) <= x0(3) - epsilon(j) && q0_bool</pre>
            func = @(t,x) q1(t,x,w,v1,v2,r1,r2);
            options = odeset('Events',@(t,x) event_q1(t,x,w,v1,v2,r1,r2,epsilon(j)));
            x0(3) = x0(1);
            q1 bool = true;
            q0 bool = false;
        elseif x0(2) \le x0(4) - epsilon(j) && q1 bool
            func = @(t,x) q0(t,x,w,v1,v2,r1,r2);
            options = odeset('Events',@(t,x) event_q0(t,x,w,v1,v2,r1,r2,epsilon(j)));
            x0(4) = x0(2);
            q0 bool = true;
            q1_bool = false;
        end
    end
   figure();
    plot(t_vec,x(:,1));
   hold on;
   plot(t_vec,x(:,2));
   xlabel("time");
   ylabel("water level");
    k = epsilon;
    title("Epsilon");
    hold off;
end
```











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