

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) <= 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] ;
    end
end
```

```

% 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
    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) <= 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

```





