

#### E 4.1 · Hybrid Automata to Hybrid Program Translation for LINCÉ

For further training in the usage of LINCÉ for simulation, recapitulate the derivation of LINCÉ hybrid programs required based on the example of the two-tank system on worksheet 3.

#### E 4.2 · Discrete Dynamic Programming of an Inverted Pendulum

Implement the numerical approach to dynamic programming (DP) ('Dynamic Programming' slide 8) for the linear-quadratic (LQ) regulator (LQR) problem discussed in Exercise 2.3. Assume a maximum time span of 2 seconds for the inverted pendulum controller to achieve its goal, that is,  $\mathbf{x}(2) = 0$ , penalise all states at  $t_f = 2$  with  $30000 \phi^2(2)$ , and define the admissible states and inputs to be  $\mathcal{X} = [-1, 1] \times [-2, 1]$  and  $\mathcal{U} = [-60, 10]$ , respectively. Use  $\Delta t = 0.1$ ,  $\Delta u = 2$ , and  $\Delta \phi = \Delta \dot{\phi} = 0.05$  for the sampling resolutions of time, inputs, and state parameters. For approximation, you can discretise the system dynamics according to the pattern  $x_{k+1} = x_k + \dot{x}_k \cdot \Delta t$ .

### Assessed Assignments

#### H 4.3 · Dynamic Programming of Two Heated Tanks

(30 points)

Replace the LQR law(s) in the two-tank system (2.2/3.2) by two controllers, one for each tank, computed separately via discrete dynamic programming (DDP) according to the algorithm for value iteration ('Dynamic Programming' slide 9).

[**Note:** For the sake of simplicity, you can assume to have only one mode (i.e., no hybrid automaton (HA)) where both controllers are working simultaneously on their tanks.]

[**Note:** Optionally and for comparison, you can compute a single controller for heating both tanks.]

[**Note:** Optionally, you can model the two-tank system abstracting the heat transfer into a disturbance input applied by the other tank and the environment, and solve a zero-sum differential games (DGs) ('Differential Games' slide 6) for the two players to obtain your two controllers.]