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Semiglobal Observer-Based Leader-Following Consensus With Input Saturation

Housheng Su, Michael Z. Q. Chen, Member, IEEE, Xiaofan Wang, Senior Member, IEEE, and James Lam, Fellow, IEEE

Abstract—This paper studies the observer-based leader-following consensus of a linear multiagent system on switching networks, in which the input of each agent is subject to saturation. Based on a low-gain output feedback method, distributed consensus protocols are developed. Under the assumptions that the networks are connected or jointly connected and that each agent is asymptotically null controllable with bounded controls and detectable, semiglobal observer-based leader-following consensus of the multiagent system can be reached on switching networks. A numerical example is presented to illustrate the theoretical results.

Index Terms—Consensus, input saturation, low-gain feedback, multiagent systems, state observer.

I. INTRODUCTION

THE CURRENT study of multiagent systems pervades a wide range of sciences, including physical, biological, and even economical sciences [1], [2]. Its impact on modern engineering and technology is prominent and will be far reaching. Typical cooperative protocols of multiagent systems include consensus [3], [4], synchronization [5], flocking [6]–[8], formation control [9]–[11], and containment control [12]. In particular, the purpose of consensus of multiagent systems is to make a group of agents to reach a common state value, relying only on their neighbors’ local information. Many different agent dynamics have been investigated for the consensus problem, such as single-integrator kinematics [3], double-integrator dynamics [13], [14], linear dynamics [15]–[18], and nonlinear dynamics [19]. In particular, the multiagent systems with agents described by general linear dynamics can be regarded as a generalization of those with agents described by single-integrator kinematics and double-integrator dynamics and can also be considered as the linearized multiagent systems with agents described by nonlinear dynamics.

It is well known that saturation nonlinearities are ubiquitous in physical and engineering systems, and agents in multiagent systems should be subject to input saturation [20], [21]. Therefore, consensus of multiagent systems with saturation constraints is not only theoretically challenging but also more practical. However, there are only a few works on multiagent systems concerning with saturation constraints [22]–[28].

In this paper, we will address the observer-based leader-following consensus of agents described by general linear systems subject to input saturation. By utilizing low-gain design technique [29], we will design consensus algorithms that achieve semiglobal leader-following consensus of such agents on switching networks. The contributions of this paper are threefold. First, this work extends the existing results on the consensus of linear multiagent systems in [15]–[18] to the case with input saturation and extends the existing results on the consensus with saturation constraints [22]–[27] to the case of agents described by more general linear dynamics. Second, this work relaxes the convergence condition on the output feedback consensus of linear multiagent systems in [15]–[17] to jointly connected networks and extends state feedback consensus in [18] and [28] to output feedback one. Compared with the low-gain state feedback consensus of linear multiagent systems in [28], the proof method for the output feedback case is different, which is more difficult than the state feedback one. Specifically, a novel output feedback consensus algorithm is proposed, and a new Lyapunov function is constructed to analyze the stability of multiagent systems. In particular, the negative semidefiniteness of the derivative of the Lyapunov function is naturally guaranteed in [28], which is no longer guaranteed for the output feedback case due to the presence of some cross terms. A careful examination of the negative semidefiniteness of the derivative of the Lyapunov function is therefore required. For the case of jointly connected networks, it is more complicated since only parts of the cross terms in the derivative of the Lyapunov function can be dealt with. Furthermore, the construction of the output feedback consensus algorithm is different from the existing output feedback consensus algorithms in [15] and [16]. Finally, compared to the existing results on the consensus of linear multiagent systems in [15]–[18], the proposed algorithms do not require any global information on the underlying unweighted network, i.e., the knowledge of eigenvalues of the coupling matrix of the unweighted network.

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H. Su is with the Key Laboratory of Image Processing and Intelligent Control of the Ministry of Education of China, School of Automation, Huazhong University of Science and Technology, Wuhan 430074, China (e-mail: houshengsu@gmail.com).

M. Z. Q. Chen and J. Lam are with the Department of Mechanical Engineering, The University of Hong Kong, Pokfulam, Hong Kong (e-mail: mzqchen@hku.hk; james.lam@hku.hk).

X. Wang is with the Department of Automation, Shanghai Jiao Tong University, Shanghai 200240, China (e-mail: tzwang@sjtu.edu.cn).

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II. PRELIMINARIES

A. Graph Theory

This paper considers the problem of semiglobal observer-based leader-following consensus on networks of switching topology. Consider an undirected graph \( G(t) = \{ V, E(t) \} \) with \( N \) agents, where \( V = \{ 1, 2, \ldots, N \} \) is a nonempty finite set of agents in the systems and \( E(t) = \{ (i, j) \in V \times V : i \sim j \} \) is a set of edges, in which an edge contains an unordered pair of vertices representing neighboring relations among the agents. Vertices \( i \) and \( j \) are adjacent when \( (i, j) \in E(t) \). The adjacency matrix \( A(t) = (a_{ij}(t)) \) is defined as \( a_{ij}(t) = 1 \), if \( (i, j) \in E(t) \); otherwise, \( a_{ij}(t) = 0 \). The Laplacian matrix of graph \( G(t) \) is defined as \( L(t) = \Delta(A(t)) - A(t) \), where \( \Delta(A(t)) \) is the degree matrix with ith diagonal elements \( \sum_{j=1, j \neq i}^{N} a_{ij}(t) \). The eigenvalues of Laplacian matrix \( L(t) \) are denoted as \( \lambda_1(L(t)) \leq \lambda_2(L(t)) \leq \cdots \leq \lambda_N(L(t)) \). Then, \( \lambda_1(L(t)) = 0 \) with a corresponding eigenvector \( 1 = [1 \ 1 \ \cdots \ 1]^T \in \mathbb{R}^N \).

Remark 1: We define that \( G \) is a spanning tree of \( G \) consisting of \( N \) agents and \( G \) is the graph consisting of \( N \) agents and a leader, which contains a spanning tree with the leader as the root vertex. Then, we have \( L + H > 0 \).

B. Problem Statement

Consider a group of \( N \) agents with general linear dynamics, labeled as \( 1, 2, \ldots, N \). The motion of each agent is described by

\[
\dot{x}_i = Ax_i + B\sigma(u_i) \\
y_i = Cx_i, \quad i = 1, 2, \ldots, N
\]

where \( x_i \in \mathbb{R}^n \) is the state of agent \( i \), \( y_i \in \mathbb{R}^p \) is the measurement output of agent \( i \), \( u_i \in \mathbb{R}^m \) is the control input acting on agent \( i \), and \( \sigma : \mathbb{R}^m \to \mathbb{R}^m \) is a saturation function defined as \( \sigma(u_i) = [\text{sat}(u_{i1}) \text{sat}(u_{i2}) \cdots \text{sat}(u_{im})]^T \), \( \text{sat}(u_{ij}) = \text{sgn}(u_{ij}) \min\{\|u_{ij}\|, \varpi\} \) for some constant \( \varpi > 0 \). The dynamics of the leader, labeled as \( N + 1 \), is described by

\[
\dot{x}_{N+1} = Ax_{N+1} \\
y_{N+1} = Cx_{N+1}.
\]

The problem of semiglobal observer-based leader-following consensus for the agents and leader described previously is the following: For any bounded set \( \mathcal{X} \subset \mathbb{R}^n \) given a priori, construct a control law \( u_i \) for each agent \( i \), which only uses the measurement outputs from neighbor agents, such that

\[
\lim_{t \to \infty} ||x_i(t) - x_{N+1}(t)|| = 0, \quad i = 1, 2, \ldots, N
\]

as long as \( x_i(0) \in \mathcal{X} \) for all \( i = 1, 2, \ldots, N, N + 1 \).

Assumption 1: The pair \((A, B)\) is asymptotically null controllable with bounded controls (ANCBC), i.e., \( (A, B) \) is stabilizable, and all the eigenvalues of \( A \) are in the closed left-half \( s \)-plane.

Assumption 2: The pair \((A, C)\) is detectable.

III. MAIN RESULTS

A. Consensus on Connected Switching Networks

Assumption 3: The graph \( G(t) \) consists of \( N \) agents and a leader, which contains a spanning tree rooted at the leader at all times.

Lemma 3 [29]: By Assumption 1, for each \( \varepsilon \in (0, 1] \), it follows that there exists a unique matrix \( P(\varepsilon) > 0 \) satisfying the algebraic Riccati equation (ARE)

\[
P^T \varepsilon P + P^2 A - P^2 B B^T P + \varepsilon I = 0.
\]

Moreover, \( \lim_{\varepsilon \to 0} P(\varepsilon) = 0 \).

The low-gain output feedback design for the multiagent system (1) is carried out in two steps.

Low-gain-output-feedback-based consensus algorithm

Step 1) Solve the parametric ARE

\[
P^T \varepsilon P + P(\varepsilon) A - P(\varepsilon) B B^T P(\varepsilon) + \varepsilon I = 0, \quad \varepsilon \in (0, 1]
\]

where \( \gamma \leq \min_{K=N} \{\lambda_1(L_s(K) + H(K))\} \) is a positive constant. The existence of a unique positive definite solution \( P(\varepsilon) \) for the ARE (3) is established in Lemma 3.
Step 2) Construct a linear output feedback law for agent $i$ as
\[
\dot{x}_i = A\hat{x}_i - F(y_i - C\hat{x}_i) - BB^T P(\varepsilon)u_i - h_i(t)(\hat{x}_i - \hat{x}_{N+1}) \\
\dot{x}_{N+1} = A\hat{x}_{N+1} - F(y_{N+1} - C\hat{x}_{N+1})
\]

for which let us consider the common Lyapunov function
\[
V(\hat{x}, \varepsilon) = \sum_{i=1}^{N} \sum_{j=1}^{N} a_{ij}(t)(\hat{x}_i - \hat{x}_j + e_j - e_i)
\]

Remark 2: Note that the construction of the output feedback consensus algorithm is different from that of the existing output feedback consensus algorithms in [15] and [16]. In the algorithm (4), no information on the network topology is needed, and each agent only acquires the state information of its neighbors. The value of $\gamma$ can be calculated when the number of agents $N$ is known.

Lemma 4 [23]: For any $\mathbf{Y} \in \mathbb{R}^{n \times m}$ and any $\xi_i, \eta_i \in \mathbb{R}^m$, $i = 1, 2, \ldots, N$
\[
\frac{1}{2} \sum_{i=1}^{N} \sum_{j=1}^{N} a_{ij}(t)(\eta_i - \xi_j)^T (\mathbf{Y}(\varepsilon)(\xi_i - \eta_j)) = \sum_{i=1}^{N} \sum_{j=1}^{N} a_{ij}(t)(\xi_i - \eta_j) (\mathbf{U}(\varepsilon)(\xi_i - \eta_j)).
\]

Theorem 1: Consider a multiagent system of $N$ agents with general linear dynamics (1) and a leader with dynamics (2). Suppose that Assumptions 1, 2, and 3 hold. The control inputs $u_i$ for the agent (4) achieve semiglobal consensus of the multiagent system. That is, for any given bounded set $\mathbf{X} \subset \mathbb{R}^n$, there is an $\varepsilon^* > 0$ such that, for each $\varepsilon \in (0, \varepsilon^*]$
\[
\lim_{t \to \infty} \|x_i(t) - x_{N+1}(t)\| = 0, \quad i = 1, 2, \ldots, N
\]
as long as $x_i(0) \in \mathbf{X}$ for all $i = 1, 2, \ldots, N, N+1$.

Proof: Let $\hat{x}_i = x_i - x_{N+1}, \hat{x}_i = \hat{x}_i - \hat{x}_{N+1}$, and $e_i = \hat{x}_i - \hat{x}_i$. Then, we have
\[
\dot{\hat{x}}_i = A\hat{x}_i - BS(\mathbf{B}^T P(\varepsilon)N \sum_{j=1}^{N} a_{ij}(t)(\hat{x}_i - \hat{x}_j + e_j - e_i) + h_i(t)B^T P(\varepsilon)(\hat{x}_i - e_i))
\]
\[
\dot{\hat{x}}_i = A\hat{x}_i - BB^T P(\varepsilon)N \sum_{j=1}^{N} a_{ij}(t)(\hat{x}_i - \hat{x}_j + e_j - e_i) + h_i(t)(\hat{x}_i - e_i) - FCE_i
\]

where $\hat{x}_i \in \mathbb{R}^n$ is the protocol state of agent $i$ and $F \in \mathbb{R}^{n \times p}$ is the feedback gain matrix, which is chosen such that $(A + FC)^T P_0 + P_0 (A + FC) = -I$ and $\theta$ is a positive constant chosen such that $\theta \geq \lambda_N(L(\varepsilon) + H(t))$. Since $(A + FC)$ is asymptotically stable, the existence of such a $P_0$ can be guaranteed. For notational convenience, we have defined $\hat{x} = [\hat{x}_1^T \hat{x}_2^T \cdots \hat{x}_N^T]^T$, $\hat{x} = [x_1^T x_2^T \cdots x_N^T]^T$, and $e = [e_1^T e_2^T \cdots e_N^T]^T$.

for a constant $c > 0$, we can find the following inequality:
\[
ce \geq \sup_{\varepsilon \in (0, 1), \xi(\varepsilon), \hat{x}(\varepsilon) \in \mathbf{X}} \sum_{i=1}^{N} \sum_{j=1}^{N} a_{ij}(t)(\hat{x}_i - \hat{x}_j)^T \mathbf{Y}(\varepsilon)(\xi_i - \eta_j) + \lambda_{\max}(\mathbf{P}(\varepsilon)\mathbf{B}\mathbf{B}^T \mathbf{P}(\varepsilon)) \frac{\theta^2}{\gamma + 1} \|e_i(0)\|^2
\]

for all $i = 1, 2, \ldots, N + 1$, which is guaranteed by the fact that $\mathbf{X}$ is bounded and $\lim_{\varepsilon \to 0} \mathbf{P}(\varepsilon) = 0$ by Lemma 3. Let $L_V(\varepsilon) := \{\hat{x} \in \mathbb{R}^{Nn}, e \in \mathbb{R}^{Nn} : V(\hat{x}, e) \leq c\}$, and let $\varepsilon^* \in (0, 1]$ be such that, for each $\varepsilon \in (0, \varepsilon^*], (\hat{x}, e) \in L_V(\varepsilon)$ implies that
\[
\|\mathbf{B}^T P(\varepsilon)\bigg(\sum_{j=1}^{N} a_{ij}(t)(\hat{x}_i - \hat{x}_j + h_i(t)(\hat{x}_i - \hat{x}_{N+1})\bigg)\| \leq \omega_i, \quad i = 1, 2, \ldots, N
\]

where $\omega_i = \max_{z \in \mathbb{R}^n} |z|_\infty$ for $z \in \mathbb{R}^n$. The existence of such an $\varepsilon^*$ is also due to the fact that $\lim_{\varepsilon \to 0} \mathbf{P}(\varepsilon) = 0$.

Thus, for any $\varepsilon \in (0, \varepsilon^*], (\hat{x}, e)$, the dynamics of (5) remains linear within $L_V(\varepsilon)$. Thus, by Lemma 4, we can derive the derivative of $V$ along the trajectories of the agents within the set $L_V(\varepsilon)$ as
\[
\dot{V}(\hat{x}, e) = \sum_{i=1}^{N} \hat{x}_i^T P(\varepsilon) \hat{x}_i + \sum_{i=1}^{N} \hat{x}_i^T P(\varepsilon) \hat{x}_i + \lambda_{\max}(\mathbf{P}(\varepsilon)\mathbf{B}\mathbf{B}^T \mathbf{P}(\varepsilon)) \frac{\theta^2}{\gamma + 1} \sum_{i=1}^{N} (\hat{e}_i^T P \hat{e}_i + e_i^T P \hat{e}_i)
\]
\[\begin{align*}
&= \sum_{i=1}^{N} \hat{x}_i^T (P(\varepsilon) A + A^T P(\varepsilon)) \hat{x}_i \\
&\quad - 2 \sum_{i=1}^{N} \hat{x}_i^T P(\varepsilon) BB^T P(\varepsilon) \\
&\quad \times \left( \sum_{j=1}^{N} a_{ij}(t) (\hat{x}_i - \hat{x}_j) + h_i(t) \hat{x}_i \right) \\
&\quad + 2 \sum_{i=1}^{N} \hat{x}_i^T P(\varepsilon) BB^T P(\varepsilon) \\
&\quad \times \left( \sum_{j=1}^{N} a_{ij}(t) (e_i - e_j) + h_i(t) e_i \right) \\
&\quad - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T e_i \\
&= \sum_{i=1}^{N} \hat{x}_i^T (P(\varepsilon) A + A^T P(\varepsilon)) \hat{x}_i \\
&\quad - \sum_{i=1}^{N} \sum_{j=1}^{N} a_{ij}(t) (\hat{x}_i^T - \hat{x}_j^T) P(\varepsilon) BB^T P(\varepsilon) (\hat{x}_i - \hat{x}_j) \\
&\quad + \sum_{i=1}^{N} \sum_{j=1}^{N} a_{ij}(t) (\hat{x}_i^T - \hat{x}_j^T) P(\varepsilon) BB^T P(\varepsilon) (e_i - e_j) \\
&\quad - 2 \sum_{i=1}^{N} h_i(t) \hat{x}_i^T P(\varepsilon) BB^T P(\varepsilon) \hat{x}_i \\
&\quad + 2 \sum_{i=1}^{N} h_i(t) \hat{x}_i^T P(\varepsilon) BB^T P(\varepsilon) e_i \\
&\quad - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T e_i. \quad (9)
\end{align*}\]

From the definition of the Laplacian of graph, for any \( \xi_i \in \mathbb{R}^m \) and \( \zeta_i \in \mathbb{R}^m, i = 1, 2, \ldots, N \)

\[\frac{1}{2} \sum_{i=1}^{N} \sum_{j=1}^{N} a_{ij}(t)(\xi_i - \xi_j)^T (\xi_i - \xi_j) = \xi^T (L(t) \otimes I_m) \xi\]

where \( \xi = [\xi_1 \xi_2 \cdots \xi_N]^T \) and \( \zeta = [\zeta_1 \zeta_2 \cdots \zeta_N]^T \), and using the identity \((A \otimes B)(C \otimes D) = AC \otimes BD\), we can continue (9) as follows:

\[\begin{align*}
\dot{V}(\hat{x})&= \dot{\hat{x}}^T (I_N \otimes (P(\varepsilon) A + A^T P(\varepsilon))) \dot{\hat{x}} \\
&\quad - 2 \dot{\hat{x}}^T (I_N \otimes P(\varepsilon) BB^T P(\varepsilon)) (L(t) \otimes I_n) \dot{\hat{x}} \\
&\quad - 2 \dot{\hat{x}}^T (I_N \otimes P(\varepsilon) BB^T P(\varepsilon)) (H(t) \otimes I_n) \dot{\hat{x}} \\
&\quad + 2 \dot{\hat{x}}^T (I_N \otimes P(\varepsilon) BB^T P(\varepsilon)) \dot{e} \\
&\quad + 2 \dot{\hat{x}}^T (I_N \otimes P(\varepsilon) BB^T P(\varepsilon)) \dot{e} \\
&\quad - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) e^T e \\
&= \dot{\hat{x}}^T (I_N \otimes (P(\varepsilon) A + A^T P(\varepsilon))) \dot{\hat{x}} \\
&\quad - (L(t) + H(t)) \otimes (2 P(\varepsilon) BB^T P(\varepsilon)) \dot{\hat{x}} \\
&\quad + \dot{\hat{x}}^T ((L(t) + H(t)) \otimes (2 P(\varepsilon) BB^T P(\varepsilon))) \dot{e} \\
&\quad - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) e^T e. \quad (10)
\end{align*}\]

The symmetry of matrix \( L(t) + H(t) \) implies that there exist orthogonal matrices \( T(t) \in \mathbb{R}^{N \times N} \), \( \dot{\hat{x}} = (T(t) \otimes I_n) \dot{\hat{x}} \), and \( \dot{e} = (T(t) \otimes I_n) e \), such that

\[\begin{align*}
L(t) + H(t) \\
&= T^T(t) \text{diag} \{ \lambda_1 (L(t) + H(t)), \lambda_2 (L(t) + H(t)), \ldots, \lambda_N (L(t) + H(t)) \} T(t) \\
&=: T^T(t) \text{diag} \{ \lambda_1(t), \lambda_2(t), \ldots, \lambda_N(t) \} T(t).
\end{align*}\]

Thus, (10) can be further continued as

\[\begin{align*}
\dot{V}(\hat{x})&= \dot{\hat{x}}^T (T^T(t) \otimes I_n) (I_N \otimes (P(\varepsilon) A + A^T P(\varepsilon))) \dot{\hat{x}} \\
&\quad - (T(t) \otimes I_n) \dot{\hat{x}} - \dot{\hat{x}}^T (T^T(t) \otimes I_n) \\
&\quad \times \left( \text{diag} \{ \lambda_1(t), \ldots, \lambda_N(t) \} \otimes (2 P(\varepsilon) BB^T P(\varepsilon)) \right) \\
&\quad \times (T(t) \otimes I_n) \dot{\hat{x}} + \dot{\hat{x}}^T (T^T(t) \otimes I_n) \\
&\quad \times \left( \text{diag} \{ \lambda_1(t), \ldots, \lambda_N(t) \} \otimes (2 P(\varepsilon) BB^T P(\varepsilon)) \right) \\
&\quad \times (T(t) \otimes I_n) e - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) e^T \\
&\quad \times (T^T(t) \otimes I_n) (T(t) \otimes I_n) e \\
&= \sum_{i=1}^{N} \hat{x}_i^T (P(\varepsilon) A + A^T P(\varepsilon) - 2 \lambda_i(t) P(\varepsilon) BB^T P(\varepsilon)) \hat{x}_i \\
&\quad + \sum_{i=1}^{N} \hat{x}_i^T (2 \lambda_i(t) P(\varepsilon) BB^T P(\varepsilon)) \hat{e}_i \\
&\quad - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T e_i \\
&\leq \sum_{i=1}^{N} \hat{x}_i^T (P(\varepsilon) A + A^T P(\varepsilon) - 2 \gamma P(\varepsilon) BB^T P(\varepsilon)) \hat{x}_i \\
&\quad + \sum_{i=1}^{N} \hat{x}_i^T (2 \lambda_i(t) P(\varepsilon) BB^T P(\varepsilon)) \hat{e}_i \\
&\quad - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T e_i \\
&\leq - \varepsilon \sum_{i=1}^{N} \hat{x}_i^T \hat{x}_i - \lambda_{\text{max}} (P(\varepsilon) BB^T P(\varepsilon)) \sum_{i=1}^{N} e_i^T e_i \\
&\quad - \sum_{i=1}^{N} \left( \sqrt{\gamma} T P(\varepsilon) \hat{x}_i - \frac{\lambda_i}{\sqrt{\gamma}} B T P(\varepsilon) \hat{e}_i \right)^T \\
&\quad \times \left( \sqrt{\gamma} T P(\varepsilon) \hat{x}_i - \frac{\lambda_i}{\sqrt{\gamma}} B T P(\varepsilon) \hat{e}_i \right) \\
&< 0, \quad \forall (\hat{x}_i, \hat{e}_i) \in L_V(c) \setminus \{0\}.
\end{align*}\]

This implies that the trajectory of \((\hat{x}_i, \hat{e}_i)\) starting from the level set \( L_V(c) \) will converge to the origin asymptotically as time approaches infinity, which, in turn, implies that

\[\lim_{t \to \infty} \| x_i(t) - x_{N+1}(t) \| = 0, \quad i = 1, 2, \ldots, N.\]

This completes the proof. \( \square \)

\textbf{Remark 3:} Since the ARE-based method is adopted in this paper, the resulting feedback gain is indirectly dependent on the low gain parameter \( \varepsilon \). For a different value of \( \varepsilon \), the solution of a parameterized ARE is required. Therefore, we can use the following bisectioning method to compute the parameter
Proof: Consider the common Lyapunov function
\[ V(\hat{x}, \epsilon) = \sum_{i=1}^{N} \hat{x}_i^T P(\epsilon) \hat{x}_i + \lambda_{\max}(P(\epsilon)BB^T P(\epsilon)) \times \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T P_e e_i \] (13)
for system (5), where \( P(\epsilon) > 0 \) satisfies (11) and (12). Similar to the analysis of Theorem 1, we will show that the set
\[ LV(c) := \{ \hat{x} \in \mathbb{R}^{N_n}, \epsilon \in \mathbb{R}^{N_n} : V(\hat{x}, \epsilon) \leq c \} \] (14)
is positively invariant. The derivative of \( V \) along the trajectories of the agents in the set \( LV(c) \) is given by
\[ \dot{V}(\hat{x}, \epsilon) = \hat{x}^T (I_N \otimes (P(\epsilon)A + A^T P(\epsilon))) \hat{x} \]
\[ - \hat{x}^T ((L(t) + H(t)) \otimes (2P(\epsilon)BB^T P(\epsilon))) \hat{x} \]
\[ + \hat{x}^T ((L(t) + H(t)) \otimes (2P(\epsilon)BB^T P(\epsilon))) \epsilon \]
\[ - \lambda_{\max}(P(\epsilon)BB^T P(\epsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) e^T e. \] (15)
For the symmetry of matrix \( L(t) + H(t) \geq 0 \), there exist orthogonal matrices \( T(t) \in \mathbb{R}^{N_N \times N_N} \), \( \hat{x} = (T(t) \otimes I_n) \hat{\hat{x}} \), and \( \bar{e} = (T(t) \otimes I_n) e \). Without loss of generality, we assume that the first \( M(1 \leq M \leq N) \) eigenvalues of matrix \( L(t) + H(t) \) are zero, i.e., \( \lambda_i(t) = 0 \) for \( i = 1, 2, \ldots, M \); then, one has
\[ \dot{V}(\hat{x}, \epsilon) \leq \sum_{i=1}^{M} \hat{x}_i^T [P(\epsilon)A + A^T P(\epsilon)] \hat{x}_i \]
\[ - \lambda_{\max}(P(\epsilon)BB^T P(\epsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) \]
Therefore, the set (14) is positively invariant.

From (16), \( \lim_{t \to \infty} V(\hat{x}(t), e(t)) \) exists. Considering the infinite sequences \( V(\hat{x}(t_k), e(t_k)) \), \( k = 0, 1, \ldots \), and using Cauchy’s convergence criteria, one has that, for any \( \vartheta > 0 \), there exists a positive number \( M_\vartheta \) such that, \( \forall k \geq M_\vartheta \), \( V(\hat{x}(t_k)) - V(\hat{x}(t_{k+1})) = \int_{t_k}^{t_{k+1}} [-V(\hat{x}(t))] dt < \vartheta \).

Therefore,

\[
\vartheta > \int_{t_k^m}^{t_k} \left[ -\dot{V}(\hat{x}(t)) \right] dt + \cdots + \int_{t_k^m-1}^{t_k^m} \left[ -\dot{V}(\hat{x}(t)) \right] dt
\]

\[
\geq - \int_{t_k^m}^{t_k} \left\{ \ddot{x}^T \left[ I_N \otimes (P(\varepsilon)A + A^T P(\varepsilon)) \right] \hat{x} \right\} dt
\]

\[
+ \int_{t_k^m}^{t_k} \left\{ \ddot{x}^T \left( L_{\delta(t_k)}(e_k) + H_{\delta(t_k)}(e_k) \right) \otimes (2P(\varepsilon)BB^TP(\varepsilon)) \right\} e dt
\]

\[
- \int_{t_k^m}^{t_k} \left\{ \ddot{x}^T \left( L_{\delta(t_k)}(e_k) + H_{\delta(t_k)}(e_k) \right) \otimes (2P(\varepsilon)BB^TP(\varepsilon)) \right\} e dt
\]

\[
+ \int_{t_k^m}^{t_k} \left\{ \lambda_{\max} (P(\varepsilon)BB^TP(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) e^T e \right\} dt
\]

\[
\left[ \begin{array}{c}
\dot{x}^T \left[ I_N \otimes (P(\varepsilon)A + A^T P(\varepsilon)) \right] \hat{x} \\
- \int_{t_k^m}^{t_k} \left\{ \ddot{x}^T \left( L_{\delta(t_k)}(e_k) + H_{\delta(t_k)}(e_k) \right) \otimes (2P(\varepsilon)BB^TP(\varepsilon)) \right\} e dt
\end{array} \right]
\]

\[
\left( \begin{array}{c}
\ddot{x}^T \left( L_{\delta(t_k)}(e_k) + H_{\delta(t_k)}(e_k) \right) \otimes (2P(\varepsilon)BB^TP(\varepsilon)) \\
\lambda_{\max} (P(\varepsilon)BB^TP(\varepsilon)) \left( \frac{\theta^2}{\gamma} + 1 \right) e^T e
\end{array} \right) dt
\]

\[
\leq 0.
\]
Therefore,
\[
\theta > -\int_{t_k^i}^{t_{k+1}^i} \left\{ \dot{x}^T \left[ I_N \otimes (P(t)A + A^T P(t)) \right] \dot{x} \right\} dt \\
+ \int_{t_k^i}^{t_{k+1}^i} \left\{ \dot{x}^T \left( \left( L_{\delta(t_k^i-1)} + H_{\delta(t_k^i-1)} \right) \right. \right. \\
\left. \left. \otimes (2P(t)BB^T P(t)) \right) \dot{x} \right\} dt \\
- \int_{t_k^i}^{t_{k+1}^i} \left\{ \dot{x}^T \left( \left( L_{\delta(t_k^i-1)} + H_{\delta(t_k^i-1)} \right) \right. \right. \\
\left. \left. \otimes (2P(t)BB^T P(t)) \right) e \right\} dt \\
+ \int_{t_k^i}^{t_{k+1}^i} \left\{ \lambda_{\text{max}} \left( P(t)BB^T P(t) \right) \left( \frac{\theta^2}{\gamma} + 1 \right) e^T e \right\} dt \\
\leq \lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} \left\{ \lambda_{\text{max}} (P(t)BB^T P(t)) \right. \\
\left. \times \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T e_i \right\} dt = 0.
\]

which implies that, for \( i = 0, 1, \ldots, m_k - 1 \)
\[
\lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} \left\{ \dot{x}^T \left[ I_N \otimes (P(t)A + A^T P(t)) \right] \dot{x} \right\} dt \\
- \lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} \left\{ \lambda_{\text{max}} \left( P(t)BB^T P(t) \right) \right. \\
\left. \times \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T e_i \right\} dt = 0.
\]

From Assumption 4 and Lemma 1, all eigenvalues of the matrix \( L_{\delta(t_k^i)} + \cdots + L_{\delta(t_k^{m_k-1})} + H_{\delta(t_k^i)} + \cdots + H_{\delta(t_k^{m_k-1})} \) are positive. From Lemma 2 and Assumption 5
\[
0 = \lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} m_k \left\{ \dot{x}^T \left[ I_N \otimes (P(t)A + A^T P(t)) \right] \dot{x} \right\} dt \\
- \lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} \left\{ \dot{x}^T \left( \left( L_{\delta(t_k^i)} + \cdots + L_{\delta(t_k^{m_k-1})} \right) \right. \\
\left. + H_{\delta(t_k^i)} + \cdots + H_{\delta(t_k^{m_k-1})} \right) \right. \\
\left. \otimes (2P(t)BB^T P(t)) \right) \dot{x} \right\} dt
\]
\[
+ \lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} \left\{ \dot{x}^T \left( \left( L_{\delta(t_k^i)} + \cdots + L_{\delta(t_k^{m_k-1})} \right) \right. \\
\left. + H_{\delta(t_k^i)} + \cdots + H_{\delta(t_k^{m_k-1})} \right) \right. \\
\left. \otimes (2P(t)BB^T P(t)) \right) \dot{x} \right\} dt
\]
\[
- \lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} m_k \left\{ \dot{x}^T \left( \left( L_{\delta(t_k^i)} + \cdots + L_{\delta(t_k^{m_k-1})} \right) \right. \\
\left. + H_{\delta(t_k^i)} + \cdots + H_{\delta(t_k^{m_k-1})} \right) \right. \\
\left. \otimes (2P(t)BB^T P(t)) \right) \dot{x} \right\} dt
\]
\[
\leq \lim_{t \to \infty} \int_{t_k^i}^{t_{k+1}^i} \left\{ \lambda_{\text{max}} (P(t)BB^T P(t)) \right. \\
\left. \times \left( \frac{\theta^2}{\gamma} + 1 \right) \sum_{i=1}^{N} e_i^T e_i \right\} dt = 0.
\]

Therefore, \( \lim_{t \to \infty} \epsilon \sum_{i=1}^{N} \dot{x}_i^T \dot{x}_i = 0 \), i.e., \( \lim_{t \to \infty} \dot{x}_i = 0 \). \( \square \)

IV. Numerical Example

In this section, a numerical example is presented to illustrate the theoretical results. The simulation is performed with four agents and one leader. The system matrices are chosen...
as $A = \begin{bmatrix} -1 & 0 \\ 0 & 0 \end{bmatrix}$, $B = \begin{bmatrix} 0 \\ 1 \end{bmatrix}$, and $C = \begin{bmatrix} 0 & 1 \end{bmatrix}$. It is straightforward to verify that $(A, B)$ is ANCBC and $(A, C)$ is detectable. Moreover, $F = \begin{bmatrix} 0 & -1 \end{bmatrix}$ is chosen such that $(A + FC)$ is asymptotically stable. Initial states $x_{i1}(0)$ and $x_{i2}(0)$ of all agents are randomly chosen from box $[-2, 2] \times [-2, 2]$, respectively, the initial values $\hat{x}_i(0)$ of all agents are chosen as $[0.1, 0.1]^T$, the initial state $x_{N+1}(0)$ of the leader is chosen as $[0.5, 0.5]^T$, and the initial value $\hat{x}_{N+1}(0)$ of the leader is chosen as $[0.35, 0.35]^T$. The two interaction networks, i.e., $G_1$ and $G_2$, are chosen as in Fig. 1, and each network is active for half of the time in each time interval. Therefore, there is a jointly connected path from the leader to every agent in each time interval. Since there are four agents and one leader in the group, we can obtain the minimum eigenvalue of the possible spanning trees consisting four agents and one leader, i.e., $\min_{2 \leq K \leq 4} \{ \lambda_1(L_s(K) + H(K)) \} = 0.1206$, using an exhaustive method. Therefore, we can choose $\tilde{\gamma} = 0.1 \leq \min_{2 \leq K \leq 4} \{ \lambda_1(L_s(K) + H(K)) \} = 0.1206$. For $\varepsilon = 0.1$ and $\varepsilon = 0.001$, by using a standard numerical software, we find that there exist positive definite matrices $P(0.1) = \begin{bmatrix} 0.0500 & 0.0000 \\ 0.0000 & 1.0000 \end{bmatrix}$ and $P(0.001) = \begin{bmatrix} 0.0005 & 0.0000 \\ 0.0000 & 0.1000 \end{bmatrix}$, such that conditions (11) and (12) hold. Fig. 2 shows the consensus of four agents and one leader applying control protocol (4). Fig. 2(a) and (b) depicts the curves of the state difference between the four agents and the leader and the control of the four agents when $\varepsilon = 0.1$, respectively. Fig. 2(c) and (d) depicts the curves of the state difference between the four agents and the leader and the control of the four agents when $\varepsilon = 0.001$, respectively. It is obvious from Fig. 2 that the control protocol (4) is capable of achieving stable consensus motion, and for the same initial conditions, as the value of $\varepsilon$ decreases, the state peaks slowly while the control input decreases.

V. CONCLUSION

In this paper, we have investigated semiglobal observer-based leader-following consensus of multiagent linear systems with input saturation on networks of switching topology. We have used a low-gain output feedback strategy to design the new observer-based consensus algorithms, without requiring any knowledge of the interaction network topology. Under the assumption that the system is ANCBC and detectable, all the agents in the group asymptotically synchronize with the leader on connected or jointly connected switching networks by employing bounded control inputs. Future work will be to further investigate the proposed algorithms on the weighted and directed switching networks and to study the robustness of the proposed algorithms against noise and time delays.
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Housheng Su received the B.S. degree in automatic control and the M.S. degree in control theory and control engineering from Wuhan University of Technology, Wuhan, China, in 2002 and 2005, respectively, and the Ph.D. degree in control theory and control engineering from Shanghai Jiao Tong University, Shanghai, China, in 2008. He is currently an Associate Professor with the School of Automation, Huazhong University of Science and Technology, Wuhan. His research interests lie in the areas of multiagent coordination control theory and its applications to autonomous robotics and mobile sensor networks.

Michael Z. Q. Chen (M’08) received the B.Eng. degree in electrical and electronic engineering from Nanyang Technological University, Singapore, and the Ph.D. degree in control engineering from the University of Cambridge, Cambridge, U.K. He is currently an Assistant Professor with the Department of Mechanical Engineering, The University of Hong Kong, Pokfulam, Hong Kong. He is a Guest Associate Editor for the International Journal of Bifurcation and Chaos.

Dr. Chen is a Fellow of the Cambridge Philosophical Society and a Life Fellow of the Cambridge Overseas Trust.

Xiaofan Wang (SM’05) received the Ph.D. degree from Southeast University, Nanjing, China, in 1996. Since 2002, he has been a Professor with the Department of Automation, Shanghai Jiao Tong University, Shanghai, China, where he has also been a Distinguished Professor since 2008. His current research interests include analysis and control of complex dynamical networks. Dr. Wang was a recipient of the 2002 National Science Fund for Distinguished Young Scholars of China and the 2005 Guillemin–Cauer Best Transactions Paper Award from the IEEE Circuits and Systems Society.

James Lam (F’12) received the B.Sc. degree (with First Class Honors) in mechanical engineering from The University of Manchester, Manchester, U.K., and the M.Phil. and Ph.D. degrees from the University of Cambridge, Cambridge, U.K.

Prior to joining The University of Hong Kong, Pokfulam, Hong Kong, in 1993, he held lectureships at the City University of Hong Kong, Kowloon, Hong Kong, and the University of Melbourne, Melbourne, Australia. He is the Editor-in-Chief of The Institution of Engineering and Technology (IET) Control Theory and Applications, a Subject Editor of the Journal of Sound and Vibration, and an Associate Editor of Automatica, Asian Journal of Control, International Journal of Systems Science, International Journal of Applied Mathematics and Computer Science, Journal of the Franklin Institute, Multidimensional Systems and Signal Processing, and Proceedings of the Institution of Mechanical Engineers (I MechE) Part I: Journal of Systems and Control Engineering. His research interests include model reduction, robust synthesis, networked control systems, and vibration control.

Prof. Lam is a Chartered Mathematician, a Chartered Scientist, a Chartered Engineer, and a Fellow of the IET, IMA, and IMechE.