

N70 32577

NASA CR 110694

Slowly Varying Discrete System  $x_{i+1} = A_i x_i$ 

C. A. Desoer

Department of Electrical Engineering and Computer Sciences  
 Electronics Research Laboratory  
 University of California, Berkeley, California 94720

Abstract. If all eigenvalues of all matrices  $A_i$  ( $i = 0, 1, 2, \dots$ ) lie in a disk of radius  $< 1$  and if the matrices  $A_i$  vary sufficiently slowly, then the system  $x_{i+1} = A_i x_i$  is exponentially stable. An explicit upper bound on the variation rate is given.

The purpose of this note is to prove for the discrete case a result that has been established for the continuous case by Rosenbrock<sup>1</sup> and recently sharpened by Desoer<sup>2</sup>.

Consider the system

$$x_{i+1} = A_i x_i \quad i = 0, 1, 2, \dots \quad (1)$$

where  $x_i \in \mathbb{R}^n$  and  $A_i \in \mathbb{R}^{n \times n}$  for all  $i$ . ( $\mathbb{R}^{n \times n}$  denotes the class of all  $n \times n$  matrices with real elements). We assume that the sequence of matrices  $\{A_i\}_0^\infty$  is bounded, i.e. there is some finite  $a_M$  such that

$$\sup_i \|A_i\| = a_M < \infty, \quad (2)$$

and that for some  $\epsilon > 0$ ,

$$\max_j |\lambda_j(A_i)| \leq 1 - 2\epsilon < 1 \quad i = 0, 1, 2, \dots \quad (3)$$

i.e. all eigenvalues of all the matrices  $A_i$  are in the disk of radius  $1 - 2\epsilon < 1$ . Under these conditions, provided the sequence of matrices  $\{A_i\}$  varies sufficiently slowly, i.e.

Research sponsored by the National Aeronautics and Space Administration, Grant NGL-05-003-016(Sup 8).

CASE FILE  
 COPY

$\sup_i \|A_{i+1} - A_i\|$  is sufficiently small,  
the system (1) is exponentially stable.

It is well known that without the restriction on the rate of variation, the system may have exponentially increasing solutions.

As a first step in the proof, let us bound  $A_i^N$  where  $N$  is a positive integer. Calculate  $A_i^N$  by Dunford's integral<sup>3</sup> using the circle of radius  $\rho = 1 - \epsilon$  as contour,

$$A_i^N = \frac{1}{2\pi j} \int_C s^N (sI - A_i)^{-1} ds \quad (4)$$

Now Kato<sup>4</sup> has shown that if one uses the euclidian norms in  $R^n$  and the induced norm for matrices, then  $\|M^{-1}\| \leq \|M\|^{n-1} / |\det M|$ . So

$$\begin{aligned} \|A_i^N\| &\leq \frac{2\pi(1-\epsilon)}{2\pi} (1-\epsilon)^N \max_{|s|=1-\epsilon} \left[ \frac{\|sI - A_i\|^{n-1}}{|\det(sI - A_i)|} \right] \\ &\leq (1-\epsilon)^{N+1} \frac{(1-\epsilon) + (a_M)^{n-1}}{\epsilon^n} \end{aligned}$$

where we used (2) in the last step. Thus we obtain the bound

$$\|A_i^N\| \leq m \rho^N \quad \forall i, \forall N \quad (5)$$

where  $\rho = 1 - \epsilon$  and  $m$  depends on  $\epsilon$ ,  $n$  and  $a_M$ , but is independent of  $i$ .

Now, for the  $i^{\text{th}}$  sampling instant pick the Liapunov function

$$V_i(x) = x^T P_i x \quad (6)$$

Hence, by (1),

$$V_{i+1}(x_{i+1}) - V_i(x_i) = x_i^T [A_i^T P_{i+1} A_i - P_i] x_i \quad (7)$$

Pick  $P_{i+1}$  such that

$$A_i^T P_{i+1} A_i - P_{i+1} = -I \quad (8)$$

By direct substitution, the solution is the symmetric positive definite matrix

$$P_{i+1} = I + \sum_{k=1}^{\infty} (A_i^T)^k (A_i)^k \quad (9)$$

Note that the series (9) is absolutely convergent in view of (5), and

$$1 \leq \|P_{i+1}\| \leq \frac{m^2}{1-\rho^2} \quad \forall i,$$

where we observed that the induced euclidian norm of  $A^T$  was equal to that of  $A$ . Note that the upper bound does not depend on  $i$ ; therefore

$$\|x\|^2 \leq V_i(x) \leq \frac{m^2}{1-\rho^2} \|x\|^2 \quad \forall i \quad (10)$$

We are going to show that if  $\sup_i \|A_i - A_{i-1}\|$  is sufficiently small, then there is an  $\eta > 0$  such that

$$\|P_{i+1} - P_i\| \leq 1 - \eta < 1 \quad \forall i \quad (11)$$

so that

$$V_i(x_i) - V_{i+1}(x_{i+1}) \leq -\eta \|x_i\|^2 \quad \forall i. \quad (12)$$

If (12) holds, then, together with (10), they imply that (1) is exponentially stable.

By subtracting two consecutive instances of (8), we obtain

$$A_i^T (P_{i+1} - P_i) A_i - (P_{i+1} - P_i) = - [(A_i^T - A_{i-1}^T) P_i A_i + A_{i-1}^T P_i (A_i - A_{i-1})] \quad (13)$$

Call the right hand side  $-M_i$  and note that by (2) and (5)

$$\|M_i\| \leq 2 \|A_i - A_{i-1}\| \frac{m^2}{1-\rho^2} a_M$$

Solving (13),

$$P_{i+1} - P_i = M_i + \sum_{k=1}^{\infty} (A_i^T)^k M_i (A_i)^k$$

so

$$\|P_{i+1} - P_i\| \leq \|A_i - A_{i-1}\| \frac{2m^2 a_M}{1-\rho^2} \frac{m^2}{1-\rho^2} \quad (14)$$

Inequality (14) shows that if

$$\sup_i \|A_i - A_{i-1}\| \leq \frac{(1-\rho^2)^2}{2m^4 a_M} (1-\eta)$$

then (11) follows. This concludes the proof.

## References

- [1] Rosenbrock, H. H., "The Stability of Linear Time-dependent Control Systems," Jour. El. and Control, 15, 1, p. 73-80, July 1963.
- [2] Desoer, C. A., "Slowly Varying System  $\dot{x} = A(t)x$ ," Trans. IEEE CT-14, 6, p. 780-781, December 1969.
- [3] Dunford, N. and J. T. Schwartz, Linear Operators, vol. I. Interscience, New York, 1958. (see p. 568).  
  
Zadeh, L. A. and C. A. Desoer, Linear System Theory. McGraw-Hill, New York, 1963. (see p. 606).
- [4] Kato, T, "Estimation of Iterated Matrices, with Application to the Von Neumann Condition," Numer. Mathem., 2, p. 22-29, 1960.