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Hybrid Control of Formations of Robots

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Hybrid Control of Formations of Robots

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Abstract
We describe a framework for controlling a group of nonholonomic mobile robots equipped with range sensors. The vehicles are required to follow a prescribed trajectory while maintaining a desired formation. By using the leader-following approach, we formulate the formation control problem as a hybrid (mode switching) control system. We then develop a decision module that allows the robots to automatically switch between continuous-state control laws to achieve a desired formation shape. The stability properties of the closed-loop hybrid system are studied using Lyapunov theory. We do not use explicit communication between robots; instead we integrate optimal estimation techniques with nonlinear controllers. Simulation and experimental results verify the validity of our approach.

1 Introduction
Research activity in multi-robotic systems has increased substantially in the last few years. Topics include cooperative manipulation [9], multi-robot motion planning, collaborative mapping and exploration [2], software architectures for multi-robotic systems [12], and formation control [6]. Areas of application include, undersea and space exploration, surveillance, target acquisition, and service robotics for mention just a few. Researchers in multi-robotic systems are facing new challenges and open issues that require deeper investigation. For instance, we need to address stability and robustness of multi-agent hybrid systems and develop the methodology and the software that will enable robots to exhibit deliberative and reactive behaviors, and to learn and adapt to unstructured, dynamic environments and new tasks, while providing performance guarantees.

This work considers the problem of formation control. Formation control of multiple autonomous vehicles arises in many scenarios of current interest. For example, in military applications and intelligent vehicle highway systems (IVHS) vehicles need to maneuver while keeping a prescribed formation. To be more specific, we consider a team of robots that are required to follow a prescribed trajectory while maintaining a desired formation. A robot designated as the reference robot follows a trajectory generated by a high-level planner. By using the leader-following approach, we split the formation control problem into:

Continuous-state robot control: Control algorithms are designed based on I/O feedback linearization. Each robot can maintain a prescribed separation and bearing from its adjacent neighbors. Explicit inter-robot communication is avoided by using optimal estimation techniques.

Discrete-state formation control: A desired formation is achieved by sequential composition of basic maneuvers (control algorithms). Switching rules are formulated based on sensor constraints.

The paper is organized as follows. In section 2, we provide some mathematical preliminaries and present a brief description of the set of controllers we use in our work. The sequential composition of behaviors and the formation switching strategy are addressed in section 3. Section 4 presents simulation and experimental results. Finally, some concluding remarks and future work ideas are given in section 5.

2 Formation Control
In this section, we describe a formation of robots as a tuple $F = (r, H)$ where $r$ is a set of variables describing the relative positions of the robots with respect to the reference robot, and $H$ is a formation graph describing the control strategy used by each robot. Thus, $F$ is a dynamical system evolving in continuous-time on the interval $T = [t_0, t_N] \subset \mathbb{R}^+$. The configuration space for $F$ is $C = SE(2)^n$.

A formation change can be accomplished by using the compositional control approach introduced in [3]. The main idea is to define a set of controllers $U = \{\xi_1, \ldots, \xi_p\}$ for each robot. Let $\Phi_j$ and $\Omega_j$ be the domain and goal of controller $\xi_j$, respectively. It is said that controller $\xi_j$ prepares controller $\xi_k$ (denoted $\xi_j \triangleright \xi_k$) if $\Omega_j \subseteq \Phi_k$. For a given suitably designed set of controllers $U$, a switching strategy can be found such that the team of robots achieves a
desired formation $F^d$ from any initial formation $F_0$. Thus, the control problem of formations of robots can be formulated as a hybrid system whose continuous dynamics change in a controlled fashion [7]. Let $g \in SE(2)$ denote the reference robot’s trajectory. The kinematics of the nonholonomic i-robot are given by

$$\dot{x}_i = v_i \cos \theta_i, \quad \dot{y}_i = v_i \sin \theta_i, \quad \dot{\theta}_i = \omega_i \quad (1)$$

In the next subsections we describe briefly three controllers used for formation control purposes. The first two are adopted from [6]. We derived here a third controller that takes into account obstacles.

### 2.1 Separation Bearing Control

In the Separation Bearing Controller (denoted $SB_{ij}C$), robot $R_j$ follows $R_i$ with a desired separation $l_{ij}^d$ and a desired relative bearing $\psi_{ij}^d$, see Figure 1. The control velocities for the follower are given by

$$v_j = s_{ij} \cos \gamma_{ij} - l_{ij} \sin \gamma_{ij} \left( b_{ij} + \omega_i \right) + v_i \cos (\theta_i - \theta_j) \quad (2)$$

$$\omega_j = s_{ij} \sin \gamma_{ij} + l_{ij} \cos \gamma_{ij} \left( b_{ij} + \omega_i \right) + v_i \sin (\theta_i - \theta_j) \quad (3)$$

where

$$\gamma_{ij} = \theta_i + \psi_{ij} - \theta_j, \quad v_{ij} = k_1(l_{ij}^d - l_{ij}), \quad b_{ij} = k_2(\psi_{ij}^d - \psi_{ij}) \quad (4)$$

The closed-loop linearized system becomes

$$\dot{l}_{ij} = k_1(l_{ij}^d - l_{ij}), \quad \psi_{ij} = k_2(\psi_{ij}^d - \psi_{ij}), \quad \dot{\theta}_j = \omega_j \quad (5)$$

### 2.2 Separation Separation Control

In the Separation Separation Controller (denoted $SS_{ij}C$), robot $R_j$ follows $R_i$ and $R_k$ with desired separations $l_{ik}^d$ and $l_{jk}^d$, respectively. See Figure 2.

In this case, the control velocities for the follower become

$$v_k = \frac{s_{jk} \sin \gamma_{jk} - s_{ik} \sin \gamma_{ik} + v_i \cos \psi_{ik} \sin \gamma_{jk}}{\sin(\gamma_{jk} - \gamma_{ik})} - \frac{v_i \cos \psi_{jk} \sin \gamma_{ik}}{\sin(\gamma_{jk} - \gamma_{ik})} \quad (6)$$

$$\omega_k = \frac{-s_{ik} \cos \gamma_{ik} + s_{jk} \cos \gamma_{ik} - v_i \cos \psi_{ik} \cos \gamma_{jk}}{d \sin(\gamma_{jk} - \gamma_{ik})} + \frac{v_j \cos \psi_{jk} \cos \gamma_{ik}}{d \sin(\gamma_{jk} - \gamma_{ik})} \quad (7)$$

### 2.3 Separation Distance-To-Obstacle Control

In the Separation Distance-To-Obstacle Controller (denoted $SDO_{ij}C$), the outputs of interest are the separation $l_{ij}$ between the follower robot and leader, and the distance $\delta$ from an obstacle to the follower. We define a virtual robot $R_0$, as shown in Figure 3, which moves on the obstacle’s boundary with linear velocity $v_0$ and orientation $\theta_0$.

For this case the kinematics of $R_0$ become

$$\gamma_{0j} = \theta_0 - \theta_j \quad (9)$$

$$\dot{l}_{ij} = v_j \cos \gamma_{ij} - v_i \cos \psi_{ij} + dw_j \sin \gamma_{ij} \quad (10)$$

$$\delta = v_j \sin \gamma_{0j} - dw_j \cos \gamma_{0j} \quad (11)$$

$$\dot{\theta}_j = \omega_j \quad (12)$$

where $\gamma_{ij}$ is given in (4) and $\delta = \inf \|x_j - x_{obs}\|$. Feedback I/O linearization is possible as long as
whether \( d \cos(\gamma_{ij} - \gamma_{k}) \neq 0 \), i.e., the controller is not defined whether \( d = 0 \) or \( \gamma_{ij} = \pm k \frac{\pi}{2} \). The latter occurs when vectors \( \delta \) and \( \hat{I}_{ij} \) are collinear. The velocity inputs for \( R_j \) are given by

\[
v_j = \frac{s_{ij} \cos \gamma_{ij} + s_{ij} \sin \gamma_{ij} + v_i \cos \psi_{ij} \cos \gamma_{ij}}{d \cos(\gamma_{ij} - \gamma_{ij})}
\]

\[
\omega_j = \frac{s_{ij} \sin \gamma_{ij} - s_{ij} \cos \gamma_{ij} + v_i \cos \psi_{ij} \sin \gamma_{ij}}{d \cos(\gamma_{ij} - \gamma_{ij})}
\]

Thus, the linearized kinematics become

\[
\dot{i}_{ij} = k_i (\hat{I}_{ij} - i_{ij}) \equiv s_{ij}
\]

\[
\delta = k_0 (\delta_0 - \delta) \equiv s_{ij}
\]

\[
\dot{\theta}_j = \omega_j
\]

where \( k_i, k_0 \) are positive controller gains, and \( \delta_0, \hat{I}_{ij} \) are desired distances to the obstacle and reference robot, respectively.

### 2.4 Stability Analysis

In this section, we provide stability results for the SBC and SSC, respectively. Proofs are omitted here due to space constraints. Details are discovered in [8].

**Theorem 2.1** Assume that the reference linear velocity along the trajectory \( g(t) \in \text{SE}(2) \) is lower bounded i.e., \( v_i > V_{min} > 0 \), the reference angular velocity is also bounded i.e., \( |\omega_i| < \omega_{max} \), and the initial relative orientation \( |\theta_i(t_0) - \theta_j(t_0)| \) \( < \omega_0 C \) for some positive constant \( C \). If the control velocities (2)–(3) are applied to \( R_j \), then system (5) is stable and the output system error of the linearized system converges to zero exponentially.

**Remarks** The two output variables in (5) and (8) converge to the desired values arbitrarily fast (depending on \( k_1 \) and \( k_2 \)). The main difficulty arises in considering the internal dynamics, for instance \( \theta_j \) in (8), which depends on the controlled velocity \( \omega_k \).

The orientation error can be expressed as

\[
\dot{\theta}_j = \omega_j - \omega_k
\]

After some work, we have

\[
\dot{\theta}_j = -\frac{v_i}{d} \sin \theta_j + \eta(u, \epsilon_j)
\]

where \( u \) is a vector that depends on the output system error and reference angular velocity \( \omega_i, \eta(\cdot) \) is a nonvanishing perturbation for the nominal system in (14) which is (locally) exponentially stable. By using stability of perturbed systems [10], it can be shown that system (14) is stable, thus the stability results in Theorems 2.1 and 2.2 follow.

### 3 A 3-Robot Formation Control Case

We illustrate our approach using three nonholonomic mobile robots \( R_{1,2,3} \) moving in an obstacle-free environment. First, \( R_1 \), the reference robot, follows a given trajectory \( g(t) \in \text{SE}(2) \). Second, \( R_2 \), the leader robot, follows \( R_1 \) with \( SB_{12C} \). Finally, \( R_3 \), the follower, has to maintain a specified distance from \( R_1 \) and \( R_2 \), i.e., \( S_{13} S_{23} C \). However, \( R_3 \) may change its control behavior depending on its position with respect to \( R_1 \) and \( R_2 \). Thus, for any arbitrary initial configuration, \( R_3 \) may follow \( R_1 \) or \( R_2 \) with \( SB_{15C} \) or \( SB_{23C} \). Eventually, \( R_3 \) will switch between different control behaviors in order to reach the desired formation. The pallete of controllers becomes \( U = \{U_2 \cup U_3\} \), and \( U_2 = \{SB_{12C}\} \), \( U_3 = \{SB_{13C}, SB_{23C}, S_{13} S_{23} C\} \). The finite set of discrete formation modes \( Q = \{q_1, q_2, q_3\} \) is illustrated in Figure 4.

Assume that \( q_3 \in Q \) is the desired formation \( \mathcal{F}^d \), and \( \mathcal{F}_0 \) is an initial formation. The hybrid system is
designed using the compositional control approach outlined in section 2. Let \( \{\Phi_1, \Omega_1\}, \{\Phi_2, \Omega_2\}, \) and \( \{\Phi_3, \Omega_3\} \) be the \{domain, goal\} of \( S_{B13C}, S_{B23C}, S_{S13S23C}\), respectively. We design the controllers such that \( \Omega_1 \subseteq \Phi_1 \) and \( \Omega_2 \subseteq \Phi_2 \), then \( S_{B13C} > S_{S13S23C} \), similarly \( S_{B23C} > S_{S13S23C} \). In the next section, we formalize this approach by using Lyapunov stability theory to show that under reasonable assumptions \( F^d \) is achieved in a stable manner from any \( F_0 \).

3.1 Switching Strategy

Our robots are equipped with an on-board omni-directional vision system. The sensor constraints determine the switching sequence \( S_w \). \( R_0 \) may detect \( R_1, R_2 \) or both. In some cases, neither \( R_1 \) nor \( R_2 \) are within the field of view of \( R_3 \). Figure 5 depicts the switching boundaries in Cartesian space. Notice the triangle inequality \( l_{jk} + l_{jk} > l_{ij} \) should be satisfied. If \( R_i \) with \( i = 1, 2, 3 \) were collinear, \( SSC \) would not be defined, then a \( SBC \) should be utilized.

![Figure 5: Switching boundaries based on sensor constraints.](image)

3.2 Stability Analysis

Since a palette of controllers and a switching strategy are given, we need to verify that the hybrid system is stable provided that each mode shares a common equilibrium point \( \bar{x}_0 \in \Omega_3 \). One way to solve this verification problem is to find a common Lyapunov function, thus the switched system is stable for any arbitrary fast switching sequence. This is in general a difficult task. A number of approaches have been proposed in the literature to confront this problem (see [11] and the references therein). In our 3-robot formation example, it turns out that under some reasonable assumptions, there may exist a common Lyapunov function. Therefore, the equilibrium point is stable, and the system error of the desired formation mode converges to zero. However, the property of exponential convergence is lost in the switching process. Let \( V_3(e) = V_3 + V_{12} \) be a Lyapunov function candidate for the desired formation...
\( F_3 \) in (17), and

\[
V_3 = \frac{1}{2} [e_1^2 + e_2^2 + e_3^2], \quad V_{12} = \frac{1}{2} [e_1^2 + e_2^2 + e_3^2]
\]

(18)

\( V_{12} \) is a Lyapunov function candidate for subsystem \( SB_{123} \) i.e., \( R_2 \) follows \( R_1 \) using a separation-bearing controller. If the assumptions in theorem 2.1 are satisfied, then \( V_{12} \leq 0 \). Moreover, if the assumptions in theorem 2.2 are satisfied for subsystem \( SB_{23} \), then \( \dot{V}_{3} \leq 0 \). We impose an additional constraint on our hybrid system which is \( R_3 \) has already reached its equilibrium point. Thus, we only need to consider \( V_3 \) in (18) for studying the stability of the switched system \( F_3 \). By definition \( V_3 \) is a Lyapunov function for \( F_3 \). We would like to show that, \( V_3 \) is also a Lyapunov function for \( F_1 \) and \( F_2 \).

Let us consider formation mode \( F_1 \), \( SB_{13} \) makes \( e_1 \rightarrow 0 \) and \( e_2 \rightarrow 0 \) exponentially as \( t \rightarrow \infty \). But we need to show that \( V_4 = e_4 \rightarrow 0 \) or \( (l_{12}^d - l_{13}^d)l_{13} > 0 \).

The main idea here is to pick \( \psi_{13}^d \) such that \( l_{23}^d \rightarrow l_{23}^d \) as \( e_2 \rightarrow 0 \). Then, we have

\[
\psi_{13}^d = \cos^{-1} \left( \frac{l_{12}^d + l_{13}^d - l_{23}^d}{2l_{12}^d l_{13}^d} \right) + \psi_{12}^d
\]

(19)

Using the inequality constraint imposed by the geometry of the problem i.e., \( l_{23}^d < l_{12}^d + l_{13}^d \), it is easy to show that \( V_4 = e_4 \rightarrow 0 \). Then \( V_3 \) is a Lyapunov function for \( F_1 \) (similarly for \( F_2 \)).

It is well known that Lyapunov methods provide conservative stability regions, since we always consider the worst case. Simulation results reveal that the desired formation is achieved even when some of the assumptions discussed here are not satisfied e.g., positions and orientation of \( R_2 \) and \( R_3 \) are randomly initialized.

4 Simulation and Experimental Results

We simulate the switching strategy outlined in section 3.1. As it can be seen in Figure 6, after some mode switching and obstacle avoidance the 3-Robot system reaches the desired formation. The parameters for simulation are: \( v_1 = 0.5 \text{ m/s}, R_1: (0, 0, 30\degree), R_2: (1.5, 0, 0\degree), R_3: (0.2, 2, 30\degree), \omega_1 = 0.1 \sin(0.2t), l_{12}^d = l_{13}^d = l_{23}^d = 1\text{m}, \) and \( \psi_{12}^d = 90\degree \).

4.1 The Experimental Setup

The mobile robots we use for the experiments are shown in Figure 7. Each robot has an onboard omni-directional vision system, a wireless video transmitter, and a battery pack. The receiver (located at the host NT computer) feeds the signal to a frame grabber that is able to capture video at full frame rate (30 Hz.) for image processing.

Figure 6: 3-Robot case formation control.

Figure 7: The experimental setup.
ified when we manually hold the follower for a few seconds at \( t = 65 \, s \).

![Figure 8: Measured separation and bearing.](image)

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**5 Conclusions**

In this paper, we have presented a hybrid system approach for formation control. We have designed a suite of controllers for leader following and obstacle avoidance. These individual controllers are sequentially composed in order to achieve a desired formation. Simulation and experimental results verify the validity of our approach. Velocity estimation techniques based on an EKF have been integrated in the closed loop system. Estimation of leader’s velocities is required, since there is no inter-agent communication. Experiments are being extended to more complex scenarios where robots need to exhibit a variety of behaviors such as localization, target acquisition, collaborative mapping and formation keeping. The controllers presented in this work are valid for \( SE(2) \).

Currently, we are investigating similar controllers for \( SE(3) \).

**References**


