Structural Characterization of Controllability in Timed Continuous Petri Nets using Invariant Subspaces *

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Abstract: This work deals with the controllability analysis in Timed Continuous Petri Nets (TCPNs) under infinite server semantics, a fluid relaxation that can model highly populated Discrete Event Systems. Here, the full rank-controllability property is defined, ensuring that the TCPN is controllable over the equilibrium markings in each of the regions of its reachability space. This allows forcing the TCPN systems to work at interesting operation points such as maximum production states, safety regions, to mention a few. Herein two structural conditions for full rank-controllability, one necessary and the other sufficient, are introduced, avoiding the enumeration of all the configurations required in other approaches. Finally, based on this, a polynomial algorithm to test the full rank-controllability is provided.

Keywords: Continuous Petri nets, Controllability, Piecewise-linear systems, Hybrid Systems.

1. INTRODUCTION

There exist several formalisms to model Discrete Event Systems (DES), among them, the Petri nets (PNs) are a formal tool that is widely used for modeling, analysis and control of DES since they capture their main characteristics, such as causal relationships, concurrency, and mutual exclusion. Unfortunately, as other DES formalisms, they suffer from the state explosion problem, particularly when they are heavily marked, leading to computationally intractable analysis. To cope with this problem, continuous Petri nets (CPNs) were introduced allowing to over-approximate the PN reachability set by a convex one. Later, the notion of time was introduced to CPNs, leading to the timed continuous Petri nets (TCPNs) to deal with the performance analysis of the system (David and Alla, 2010; Silva et al., 2011). In this paper we study TCPNs under infinite server semantics (ISS). Its evolution can be described by piecewise affine systems with polyhedral regions. It has been shown that, for highly marked systems, TCPN systems provide a good approximation of the performance of timed PNs (Fracca et al., 2014). It has also been shown that TCPNs are appropriate to model different systems such as manufacturing systems (Silva et al., 2014), health management systems (Dotoli et al., 2009), traffic systems (Tolba et al., 2005; Júlvez and Boel, 2010), and epidemiological models (Becchi et al., 2013), among others.

Controllability in TCPNs is a fundamental property that has been widely studied. If a TCPN system is controllable, its marking can be driven to a required value by reducing the firing speed at the controllable transitions (Mahulea et al., 2008). In Silva et al. (2011), it was highlighted that P-flows induce uncontrollable invariants, constraining the controllability of TCPNs. In Vázquez et al. (2014) the controllability property was defined as the possibility to drive the TCPN system between its potential equilibrium markings. In that work, the study of controllability was divided in two cases: a) when all the transitions are controllable, and b) when there are uncontrollable transitions. In the former, if the support of all the P-semiflows is initially marked, the consistency of the net is enough to guarantee controllability (a structural condition). In the latter, since TCPN systems can be seen as piecewise-linear systems, the controllability at each given marking region, where the system behaves linearly, is characterized by using controllability matrices. The main drawback of this kind of result is that the number of regions grows exponentially with respect to the number of synchronizations in the net, hence the complexity of the controllability analysis also grows exponentially.

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This work focuses on finding structural conditions (i.e., explained from the graph structure) that guarantee the rank-controllability of a TCPN, a property that implies controllability as proposed in Vázquez et al. (2014). The analysis is performed from three related perspectives: the net graph exploration, the geometrical controllability analysis of each linear mode (corresponding to the different regions), and the controllability matrices of the linear modes. It is shown that some invariant subspaces of the linear modes are related to structural objects, being computable without enumerating regions. For this purpose, the flow dynamic equation and its controllability matrix are introduced. It is proved that the flow controllability matrix loses rank when there exist uncontrollable flow invariants due to P-flows and choice places. After that, it is proved that the existence of uncontrollable flow invariants (that are characterized from the net structure) may lead to a loss of rank-controllability. Finally, these conditions are exploited by an algorithm to determine if a TCPN is full rank-controllable, i.e., rank-controllable in every linear mode.

This work is organized as follows: Section 2 gives an introduction to TCPNs. Section 3 presents the rank-controllability property. Next, Section 4 introduces the concept of influenced nodes by the control actions and states a structural necessary condition for full rank controllability. In Section 5, the net based structural characterization of flow invariants is presented. Moreover, the relation between flow invariants and the rank-controllability is established. Section 6 introduces an algorithm to test the full rank-controllability of the TCPN, avoiding the enumeration of all the linear modes, as required by other approaches. An example is presented in Section 7. Finally, some conclusions are presented in Section 8.

2. BASIC CONCEPTS

The reader should consult David and Alla (2010) and Silva et al. (2011) for a deeper insight on TCPNs. Basic controllability results for linear systems can be consulted in Wonham (1979) and Chen (1998). A vector that lies in the null space (resp. the left null space) of a matrix A is said to be a right annular of A (resp. left annular of A).

2.1 Continuous Petri nets

Definition 1. A continuous Petri net (CPN) system is a pair \( \langle N, m_0 \rangle \) where \( N = (P, T, Pre, Post) \) is a P/T net and \( m_0 \in \mathbb{R}^{|P|} \) is the initial marking. \( P = \{p_1, p_2, \ldots, p_n\} \) is a finite set of nodes called places; \( T = \{t_1, t_2, \ldots, t_m\} \) is a finite set of nodes called transitions; \( P \cap T = \emptyset \), \( Pre \) and \( Post \) are \( |P| \times |T| \) matrices representing the weighted arcs going from places to transitions and from transitions to places, respectively. The enabling degree of a transition \( t_i \) is given by \( \text{enab}(t_i, m) = \min_i \{p_j | \text{Pre}[p_j, t_i] > 0 \} \); a transition \( t_i \) is enabled at \( m \) iff \( \forall p_j \in \text{enab}(t_i, m), m[p_j] > 0 \). Hence, any enabled transition \( t_i \) can be fired in any certain positive amount \( \alpha \leq \text{enab}(t_i, m) \); the firing of \( t_i \) leads to a new marking according to the fundamental equation of the continuous Petri net:

\[
m = m_0 + C \cdot \sigma \tag{1}
\]

where \( C = \text{Post} - \text{Pre} \) is the token-flow matrix, \( \sigma = [\alpha_1 \cdots \alpha_{|T|}]^T \) and \( \alpha_i \) is the amount of firing of \( t_i \).

For pre- and postsets we use the conventional dot notation, e.g., \( \cdot t = \{p \in P | \text{Pre}[p, t] \neq 0 \} \). In this work we will consider strongly connected (s.c.) nets (i.e., for every pair of nodes \( x \) and \( y \), there is a path leading from \( x \) to \( y \)).

If \( x \neq 0 \) (resp. \( y \neq 0 \)) is a solution of \( C \cdot x = 0 \) (resp. \( y^T \cdot C = 0 \)) then it is named T-flow (resp. P-flow). Matrix \( B_i \) denotes a basis for the P-flows of \( N \). Nonnegative T-flows (resp. P-flows) are called T-semiflows (resp. P-semiflows). \( N \) is said to be consistent (resp. conservative) if there exists a T-semiflow \( x > 0 \) (resp. P-semiflow \( y > 0 \)). The support of a vector \( x \in \mathbb{R}^{|T|} \) (resp. \( y \in \mathbb{R}^{|P|} \)), denoted by \(|x|\) (resp. \(|y|\)), is the set \(|x| = \{ t_i \in T | x[t_i] \neq 0 \} \) (resp. \(|y|\) = \{ \( p_j \in P | y[p_j] \neq 0 \)\}).

Places and transitions of a PN can be classified based on their input and output nodes: Join transitions are transitions with more than one input place; Choice places are places with more than one output transition. The set of choice places is denoted as \( P_C = \{ p_i \in P | |p_i| > 1 \} \).

2.2 Timed continuous Petri nets

Definition 2. A timed continuous Petri net (TCPN) system is a time-driven continuous-state system described by the tuple \( \langle N, \lambda, m_0 \rangle \), where \( \langle N, m_0 \rangle \) is a CPN system and the vector \( \lambda \in \mathbb{R}^{|T|} \) is a function that assigns to each transition a positive value representing its firing rate per enabled server. The marking is time-dependent and its derivative is defined from (1) as:

\[
m = C \dot{\sigma}(\tau), \quad m(0) = m_0 \tag{2}
\]

where \( f(\tau) = \dot{\sigma}(\tau) \) is named the flow of the transitions.

This work deals with the study of TCPN systems under infinite server semantics, where the flow of a transition \( t_i \) is defined as \( f_i(m) = \lambda_i \text{enab}(t_i, m) \). The min operator in \( \text{enab}(t_i, m) \) leads to the concept of configurations:

Definition 3. A configuration \( C \) is a set of arcs \( (p, t_k) \) of \( N \), one per transition, s.t. \( p \in t_k \). Here, the notation used to represent a configuration is: \( C_i = \{ (p_1, t_1), \ldots, (p_k, t_k) \} \). The \( |T| \times |P| \) configuration matrix \( \Pi \), associated to the configuration \( C_i \), is a matrix s.t. its entries are defined as:

\[
\Pi[i, k] = \begin{cases} \frac{1}{\text{Pre}[k, j]} & \text{if } (p_k, t_j) \in C_i \\ 0 & \text{otherwise} \end{cases}
\]

Definition 4. The \( T \)-coverture of a configuration \( C_i \) is the set of places \( T_C = \{ p \in P | (p, t_j) \in C_i, t_j \in T \} \).

At a given marking \( m \), the flow of a transition \( t_k \) is defined by the marking of the place \( p \) that provides the minimum ratio in \( \min_{p \in \text{enab}(t_k, m)} \frac{m[p]}{\text{Pre}[p, t_k]} \). In that case, it is said that \( p \) constrains the flow of \( t_k \). A configuration \( C_i \) is active at marking \( m \) if \( \text{enab}(m) = \Pi \cdot m \). Then, the set of reachable markings can be partitioned (except on the borders) into regions, convex subsets, one per configuration. A reachable marking \( m \) belongs to region \( \mathcal{R} \), if \( C_i \) is active at \( m \).

The marking evolution in region \( \mathcal{R} \) is described by the \( i \)-th TCPN mode, or dynamic equation, \( \dot{m} = \mathcal{C} \Pi \cdot m \) where \( \Lambda = \text{diag}(\Lambda) \) and \( \mathcal{C} \Pi \) is its dynamic matrix. In region \( \mathcal{R} \), the flow through the transitions is:

\[
f(\tau) = \mathcal{A} \Pi \cdot m \tag{3}
\]
Moreover, from (3) and (1), the transitions flow for the i-th configuration can also be expressed as:

\[ f(\tau) = \Lambda \Pi_i m(0) + \ldots \] controllable over \( E^*_i \)

if, for any pair of equilibrium markings \( m_1, m_2 \in E^*_i \), it is true that \( m_2 - m_1 \in \text{Img}(C_i) \).

2.3 Controllable transitions in TCPNs

Control actions in TCPN systems can only reduce the flow through the transitions. That is, a transition cannot work faster than its nominal speed characterized by \( \lambda_i \).

**Definition 5.** The control vector \( u \in \mathbb{R}^{[T_i]} \) is defined s.t. \( u_i \) represents the control action on \( t_i \) and \( 0 \leq u_i \leq \lambda_i \cdot \text{enab}(t_i, m) \). The effective flow through a controlled transition \( t_i \) is given by \( w_i = f_i - u_i \).

Transitions in which control actions can be applied are named controllable. The set of all controllable transitions is denoted by \( T_c \) and the set of uncontrollable transitions is \( T_{uc} = T - T_c \). If \( t_i \in T_{uc} \) then \( u_i \) must be null.

The behaviour of a controlled TCPN system is described by the state equation and constraints:

\[ m = C \Lambda I_i (m) - C[T_i] u[T_i], \]

\[ 0 \leq u \leq \Lambda I_i (m) m \]

where \( \Pi_i (m) = \Pi_i \), whenever \( m \in \mathcal{R}_i \). \( C[T_i] \) is the input matrix (it only contains the columns of \( C \) related to transitions in \( T_i \)) and \( u[T_i] \) is the restriction of \( u \) to the controllable transitions. A control action that fulfills the required constraints is called suitably bounded (s.b.). The following definition will be useful later:

**Definition 6.** A \([T_i] \times [T_i]\) selector matrix, \( S_{T_i} \), is named the selector of controllable transitions, i.e., \( C S_{T_i} = C[T_i] \).

In this work, it will be useful to consider the evolution of the flow as a state equation. Then, by the derivative of (3) and Eq. (5), the flow system in \( \mathcal{R}_i \) is described as:

\[ \dot{f} = \Lambda I_i C f - \Lambda I_i C S_{T_i} u[T_i] \]

2.4 State invariants and Equilibrium markings in TCPNs

Whenever a P-flow, \( y \), is present in a TCPN system, every reachable marking \( m \) satisfy: \( y^T m = y^T m_0 \). In other words, linear dependencies between the markings appear (called token conservation laws) and its evolution is restricted to an invariant formally described as follows:

**Definition 7.** Given \( \langle N, \lambda, m_0 \rangle \), \text{Class}(m_0) \) represents the set of markings that agree with the P-flows: \text{Class}(m_0) = \{ m \in \mathbb{R}^{[P]} | B^T \beta m = B^T \beta m_0 \} \).

If \( N \) is consistent and conservative, \text{Class}(m_0) \) corresponds to the reachable markings of the untimed system. For the case where \( T_c \subseteq T \), the TCPN systems are not controllable over \text{Class}(m_0). In Vázquez et al. (2014), it was proposed to study the controllability property over sets of equilibrium markings, which are the “potential steady states” of the system.

**Definition 8.** Any marking \( m^0 \) for which \( \exists u^0 \) s.b. such that \( C(\Lambda I_i (m^0)) m^0 - u^0 = 0 \) is said to be an equilibrium marking. The set of all equilibrium markings is denoted as \( \mathbb{E} \). The set of equilibrium markings in \( \mathcal{R}_i \) is \( \mathcal{E}_i = \{ m | m \in \mathbb{E} \cap \mathcal{R}_i \} \).

**Definition 9.** Let \( m^0 \in \mathbb{E} \). The set of fully controlled transitions at \( m^0 \), \( T^c_f \), is defined as \( T^c_f = \{ t_j \in T | 0 < u_j^0 < \lambda_j \cdot \text{enab}(t_j, m^0) \} \). The set \( T^c_f = T - T^c_f \) is defined as the set of the partially controlled transitions.

Next, an interesting subset of \( E^*_i \) that is composed of all the equilibrium markings at which \( T_c = T^c_f \) is introduced.

**Definition 10.** The set \( E^{*_f}_i = \{ m^0 \in E^*_i | \forall t_i \in T_c, 0 < u_i^0 < \lambda_i \cdot \text{enab}(t_i, m^0) \} \) is defined as the set of fully controllable equilibrium markings (at which all the inputs, related to controllable transitions, can be arbitrarily controlled).

2.5 Controllability in linear systems

Throughout this work the Popov-Belevitch-Hautus controllability test, for linear systems, is used.

**Proposition 11.** (PBH Test) A linear time-invariant dynamic system \( x = Ax + Bu \) is controllable iff the left eigenvectors of \( A \) are not orthogonal to \( B \).

In detail, if a left eigenvector \( v \) of \( A \) fulfills \( v^T A = \beta v^T \). Thus, given the controllability matrix of the system

\[ C = [B AB \ldots A^{n-1}B] \]

if a left eigenvector \( v \) of \( A \) premultiplies \( C \) then:

\[ v^T C = [v^T B \beta v^T B \ldots \beta^{n-1} v^T B] \]

Hence, if \( v^T \) is orthogonal to \( B \), then \( v^T \) is a left annihilator of the controllability matrix, thus the system is uncontrollable. In other words, there exists an invariant subspace of \( A \), characterized by \( v \), that the control cannot affect (i.e., an uncontrollable invariant).

3. CONTROLLABILITY IN TCPN SYSTEMS

This section introduces the rank-controllability notion used in this work. First, let us recall the classical definition of the controllability matrix for each configuration.

**Definition 12.** (Vázquez et al., 2014) Let \( \langle N, \lambda, m_0 \rangle \) be a TCPN system that is evolving in configuration \( C_i \). The controllability matrix of the system in configuration \( C_i \) is:

\[ C_i = [C[T_i] \text{CAII}[C[T_i] ... (\text{CAII})^{P-1} C[T_i]] \]

Notice that the rank of this controllability matrix never exceeds the rank of \( C \). Since \( \text{rank}(C) = |P| - \text{rank}(B^T_y) \), then it is the maximum possible rank of any \( C_i \).

**Definition 13.** A TCPN is said to be rank-controllable at configuration \( C_i \) if \( \text{rank}(C_i) = |P| - \text{rank}(B^T_y) \). Moreover, it is said to be full rank-controllable if it is rank-controllable in every configuration.

Next proposition states that, under generic conditions, rank-controllability implies controllability as proposed in Vázquez et al. (2014).

**Proposition 14.** Let \( \langle N, \lambda, m_0 \rangle \) be a TCPN system. If \( m_0 > 0 \), \( T^c_f = T_c \) and \( \langle N, \lambda \rangle \) is rank-controllable in \( C_i \), then, it is controllable over \( E^{*_f}_i \).

**Proof.** Considering the hypothesis \( m_0 > 0 \) and \( T^c_f = T_c \), Theorem 5.6 in Vázquez et al. (2014) states that a TCPN is controllable over \( E^{*_f}_i \) if, for any pair of equilibrium markings \( m_1, m_2 \in E^{*_f}_i \), it is true that \( m_2 - m_1 \in \text{Img}(C_i) \).
Now, consider any \( m_0, m_1 \in E^* \). From (1), any reachable marking \( m_1 - m_0 \in \text{Img}(C) \). Assuming that the TCPN is rank-controllable at \( C_i \), then \( \text{Img}(C_i) = \text{Img}(C) \), therefore \( m_1 - m_0 \in \text{Img}(C_i) \), then controllability follows.

Previous proposition states that the controllability of a TCPN system, in a configuration \( C_i \), can be guaranteed if it is rank-controllable at \( C_i \). Through this work, we will show that the full rank-controllability property can be analyzed avoiding the enumeration of all the configurations. In fact, in Section 5, the loss of rank-controllability will be related to the presence of flow invariants (equality relations involving transition flows). By considering the dynamics of the flow, as in (6), the uncontrollable invariant subspaces of the system can be studied from its controllability matrix:

\[
M_i = \begin{bmatrix}
  (\Pi_i, C) S_T \cdots (\Pi_i, C) S_T & \cdots & (\Pi_i, C) S_T
\end{bmatrix}
\]

Notice that the matrix \( M_i \) has a similar structure to the controllability matrix \( C_i \), in fact, \( C_i = C \Psi_i \) where:

\[
\Psi_i = [S_T \cdots (\Pi_i, C) S_T]^{P_i - 1} S_T
\]

The difference between \( M_i \) and \( \Psi_i \) appears in the first term \( S_T \) and the length of the expansion. This fact will be used to related the loss of rank controllability with the presence of flow invariants (Theorem 27).

4. INFLUENCE OF THE CONTROLLABLE TRANSITIONS

This section is devoted to the study of how the activity on a controllable transition influence the marking of the places. It will be shown that a necessary condition for full rank-controllability is that all the places in the net are influenced by the controllable transitions. Consider the place transition sequence (Fig. 1) with \( T_c = \{t_1\} \). Then, the TCPN represented by this sequence becomes rank-controllable. In detail, for \( \lambda = [\lambda_1, ... , \lambda_n]^T \), its dynamic equation is described by:

\[
\dot{m} = \begin{bmatrix}
-\lambda_1 & 0 & ... & 0 \\
-\lambda_2 & -\lambda_2 & ... & 0 \\
... & ... & ... & ... \\
0 & 0 & ... & -\lambda_n
\end{bmatrix} m + \begin{bmatrix}
-1 \\
0 \\
0 \\
0
\end{bmatrix} u
\]

and it can be easily verified that the rank of its controllability matrix is equal to the rank of the token-flow matrix.

This observation suggests that if a transition is controllable, then its control action influences over the flow of transitions down-stream in the sequence, which is true for Join-Free (JF) systems. However, join transitions may stop the influence propagation at some configurations. See, for instance, the net depicted in Fig. 2.a). In this system, if \( T_c = \{t_3\} \), then the markings in \( p_3, p_4, p_5, p_8, p_9, p_{10}, p_{11}, p_{12} \) and \( p_{13} \) can be influenced. For instance, the marking at \( p_4 \) is described by \( m_4 = w_3 - \lambda_4 m_4 \), thus \( m_4 \) can be controlled by means of \( w_3 \), moreover, the flow at \( t_4 \) is given by \( f_4 = \lambda_3 m_4 \), thus \( f_4 \) can be controlled by means of controlling \( m_4 \). The same occurs for \( p_3, p_5, p_{12} \) and \( p_{13} \). Now, the flow at transition \( t_5 \) and the marking in place \( p_7 \) cannot be influenced if \( p_6 \) constrains the flow of \( t_5 \) since, in such case, the flow at \( t_5 \) is given by \( f_5 = \lambda_5 m_4 \). A similar reasoning is applied to every join transition. In other words, a place (transition) is said to be influenced by the control actions in all the configurations if it is always possible to state its marking evolution (its flow) in terms of some control action.

Consider the net depicted in Fig. 2.b). If both, \( t_3 \) and \( t_7 \) are controlled, then the markings in \( p_3, p_4, p_5, p_6, p_8, p_9, p_{10}, p_{11}, p_{12} \) and \( p_{13} \) are influenced. Moreover, since the markings in \( p_5 \) and \( p_{10} \) are influenced by the control actions, then the join transition \( t_6 \) is influenced as well in any configuration. Consequently, \( p_1 \) and \( p_6 \) are also influenced by the control actions. Following this reasoning, \( P_1 = P \).

It is worth noticing that influence and controllability are two different concepts. As explained above, if the TCPN is a place-transition chain, then the control has influence over all the nodes, thus it is controllable. However, if circuits and other structural objects are found, then marking and flow invariants are introduced. This may affect the controllability. In such case, the influence is not independent on each place, thus it does not imply rank-controllability.

Example 16. Consider the net of Fig. 2.b). In this case, \( P_1 = P = T_1 = T \). However, this does not imply full rank-controllability. For example, with \( \lambda = [1, ..., 1]^T \), \( \langle N, \lambda \rangle \) is not rank-controllable at some configurations. For instance, \( C_0 = \{(p_{11}, t_1), (p_{12}, t_2), (p_{13}, t_3), (p_4, t_4), (p_{12}, t_5), (p_{13}, t_6), (p_{11}, t_7), (p_5, t_8), (p_6, t_9)\}, \) where \( \text{rank}(C_0) = |P| - \text{rank}(B_s^0) - 1 \), i.e., \( \exists u \in \text{Im}(B_s) \) and \( u \notin \text{Img}(B_s) \).

On the contrary, influence on all the places is a necessary condition for full rank-controllability.

Proposition 17. Let \( \langle N, \lambda \rangle \) be a TCPN and \( T_c \) be the set of controllable transitions. If the TCPN is full rank-controllable, the corresponding \( P_1 = P \).
It is worth noticing that influence can be verified in polynomial time, while the complexity of computing the influenced places by enumerating configurations is exponential.

**Proposition 18.** Let $\mathcal{N}$ be a CPN and $T_c$ the set of controllable transitions. Then, Algorithm 1 computes, in polynomial time, the sets of influenced nodes, $P_I$ and $T_I$, in all the configurations.

**Proof.** Notice that the loop of Alg. 1 ends, at most, after $|P| - 1$ iterations. Moreover, the operations from the loop are performed in polynomial time. Then, the previous algorithm computes $P_I$ and $T_I$ in polynomial time. □

Algorithm 1: Sets of influenced nodes by $T_c$, $\forall C_i$.

**Initialize:** $T_I := T_c$, $P_I := \cdot T_c$.

**repeat**

$T_A := T_I$, $P_A := P_I$;

$T_I := T_I \cup \{t \in P_o^A | t \notin T_A \land t \subseteq P_A\}$

$P_I := P_A \cup (T_I \setminus T_A)^*$

until $P_I = P_A$

**return** $P_I$ and $T_I$

Algorithm 1 can be used as a preliminary step in the full rank-controllability analysis; if influence over all the places is not satisfied, $T_c$ is not adequate to ensure the full rank-controllability of the TCPN. On the contrary, if the condition is met, further analysis is necessary to conclude over the full rank-controllability of the system. This will be addressed in the following sections.

5. STRUCTURAL CHARACTERIZATION OF FLOW INVARIANTS AND RANK-CONTROLLABILITY.

This section is devoted to show the relation between flow invariants and the full rank-controllability in TCPNs, as stated in Theorem 27. The main idea of this section is to look for flow invariants by using structural net objects such as P-flows, choice places, or from the image of matrix $C$. First, the definition of flow invariant is introduced.

**Definition 19.** Let $(\mathcal{N}, \lambda, \mathbf{m}_0)$ be a TCPN system at a configuration $C_i$. Consider the flow vector at $C_i$, $\mathbf{f}(\tau) = \mathbf{A}_i \mathbf{m}(\tau)$ and its entries $f_1(\tau), ..., f_m(\tau)$. A flow invariant (FI) is an equality

$$\mathbf{w}^T \mathbf{f} = v_1 f_1(\tau) + ... + v_m f_m(\tau) = c \tag{13}$$

that holds in a subset of markings of $\mathcal{R}_i$, $\forall \tau$ when $C_i$ is active, where $v_1, ..., v_m \in \mathbb{R}$, not all zero.

Now consider the flow controllability matrix (Eq. (10)):

$$\mathbb{M}_{i} = [\mathbf{A}_i \mathbf{C} S_{T_c} (\mathbf{A}_i \mathbf{C})^2 S_{T_c} ... (\mathbf{A}_i \mathbf{C})^{T} S_{T_c}]$$

In accordance to the PBH Test, if the flow system is not controllable in region $\mathcal{R}_i$, then, there exist vectors $\alpha$, $\beta$ and/or $\delta$ such that:

1. $\alpha^T \mathbf{A}_i = 0$
2. $\beta^T \mathbf{A}_i \mathbf{C} = 0 \land \beta^T \mathbf{A}_i \neq 0$
3. $\gamma^T \mathbf{A}_i \mathbf{C} = 0 \land \gamma^T S_{T_c} = 0$, where $\gamma 
eq 0$

These vectors correspond to invariant subspaces of matrix $\mathbf{A}_i \mathbf{C}$; as will be seen in the following subsections, they correspond to flow invariants.

Since $\mathbf{A}$ is a full rank matrix, the existence of flow invariants characterized by $\alpha$ and $\beta$, in cases (1) and (2), depends only on the kernels of matrices $\mathbf{Pi}$ and $\mathbf{Pi}_C$, respectively, i.e. a merely structural condition. On the contrary, in case (3) the existence of a left annular depends also on the value of matrix $\mathbf{A}$, i.e., given a particular structure, they may not appear for any timing.

Consequently, flow invariants corresponding to cases (1) and (2) are named structural flow invariants (SFIs). Flow invariants corresponding to case (3) are named timed flow invariants (TIFs). In particular, an invariant of case (1) is a flow invariant induced by a choice place (Choice-SFI) since they are related to the existence of choice places; an invariant of case (2) is a flow invariant induced by a token conservation law (Conservation-SFI) since they are related to the existence of P-flows.

5.1 Flow invariants induced by choice places

This section shows that choice places may lead to Choosing-SFIs in particular configurations.

**Example 20.** Consider any $C_i$ of $\mathcal{N}$, depicted in Fig. 2, s.t. $(p_{12}, t_2), (p_{12}, t_5) \in C_i$. Thus, $f_2 = \lambda_{2m12}$ and $f_6 = \lambda_{5m12}$. Hence, $f_2/\lambda_2 - f_6/\lambda_6 = 0$, i.e., a Choice-SFI is present in $C_i$. Next proposition formalizes this.

**Proposition 21.** Let $(\mathcal{N}, \lambda)$ be a TCPN at a configuration $C_i$. Let $p_c$ be a choice place s.t. $p_c \in T_C$. If $p_c$ constrains $k > 1$ of its output transitions at $C_i$, then $p_c$ introduces $k - 1$ left annulators in $\mathbf{A}_i \mathbf{C}$, leading to the corresponding Choice-SFIs.

**Proof.** Rename transitions and places in such a way that $\{t_1, ..., t_k\}$ are the output transitions of $p_c$ and this is the first place appearing in the token-flow matrix. Hence:

$$\mathbf{Pi}_f = \begin{bmatrix} \frac{1}{\text{Pre}[1,1]} & 0 & \ldots & 0 \\ \vdots & \vdots & \ddots & \vdots \\ \frac{1}{\text{Pre}[1,k]} & 0 & \ldots & 0 \\ 0 & 0 & \ldots & \mathbf{II} & \end{bmatrix} \tag{14}$$

Then, the vectors $\mathbf{a}_1 = [\text{Pre}[1,1] - \text{Pre}[1,2] 0 \ldots 0]^T$, ..., $\mathbf{a}_{k-1} = [\text{Pre}[1,1] 0 \ldots - \text{Pre}[1,k] 0 \ldots 0]^T$ are left annulators of $\mathbf{Pi}_f$. Since $\mathbf{A}$ is a full rank matrix, the system $\mathbf{a}_j^T \mathbf{A}_i \mathbf{C} = 0, j = 1, ..., k - 1$, has solution. Then $\mathbf{a}_j^T \mathbf{A}_i \mathbf{C} = 0$, i.e. $\mathbf{a}_j|_{f_1} + \ldots + \mathbf{a}_j|_{f_m} f_m = 0$. Thus, it follows that Choice-SFIs appear. □

Notice that if two different choice places $p_{c_1}, p_{c_2}$ are contained in $T_C$, the left annulators (i.e., the Choice-SFIs) introduced by $p_{c_1}$ are linearly independent from those introduced by $p_{c_2}$.

5.2 Flow invariants induced by token conservation laws

This section shows that the existence of P-flows may lead to Conservation-SFIs in particular configurations.

**Example 22.** Consider the net in Fig. 2 where $||y_1|| = \{p_{12}, p_{23}, p_{34}, p_{5}\}$ is the support of a P-semiflow of $\mathcal{N}$ (i.e., the token conservation law $m_1 + m_2 + m_3 + m_4 + m_5 = c$ exists). If $||y_1|| \subseteq T_C$, then, the flows of the transitions in $||y_1||$ are given by $f_1 = \lambda_{1m12}, f_2 = \lambda_{2m12}, f_3 = \lambda_{3m3}, f_4 = \lambda_{4m4}$ and $f_5 = \lambda_{5m5}$. Thus, the marking invariant can be written as $f_1/\lambda_1 + f_2/\lambda_2 + f_3/\lambda_3 + f_4/\lambda_4 + f_5/\lambda_5 = 0$, i.e., a Conservation-SFI that will be present in $C_i$. The following proposition formalizes this kind of flow invariants.
Fig. 3. TCPN system with timing \( \lambda = [\lambda_1 \lambda_2 \lambda_3]^T \).

**Proposition 23.** Let \( \langle N, \lambda \rangle \) be a TCPN at a configuration \( C \). Let \( y \) be a P-flow of \( N \) such that \( |y_j| \leq TC \). Then \( y \) introduces left annihilors in \( \Pi_1, C \), leading to Conservation-SFI.

**Proof.** Suppose that a P-flow \( y_j = [y_1 \ldots y_n]^T \) is s.t. \( |y_j| \leq TC \). If \( y_k \neq 0 \) then the place \( p_k \) is constraining the flow of at least one transition in \( C \). Without loss of generality name these transitions as \( t_1, t_2, \ldots, t_i \). Thus \( \pi_{a,b,\ldots,k} \neq 0 \) (the entries of matrix \( \Pi \)). At \( C \), each transition is constrained by only one place, thus rows of \( \Pi \) have only one non-null entry. Hence, there exists scalars \( b_1, \ldots, b_m \) such that

\[
[y_1 \ldots y_n] \Pi = y_j^T
\]

Since \( y_j^T C = 0 \), then \( y_j = [y_1 \ldots y_n] \) is a left annihilor of \( \Pi, C \). Moreover, matrix \( A \) has full rank, then

\[
\beta_j^T \Pi = b_j^T A^{-1}
\]

is a left annihilor of the matrix \( \Pi, C \) generated by the P-flow \( y_j \). Now, from (4) and (16) it follows:

\[
\beta_j^T \Pi C \sigma = \beta_j^T \Pi C \sigma_0 + \beta_j^T \Pi \delta(0)
\]

Since \( \beta_j^T \Pi C \sigma = 0 \), then:

\[
\beta_j^T C \sigma = \text{constant}
\]

Thus, a Conservation-SFI exists. \( \square \)

5.3 Timed flow invariants

This section deals with timed flow invariants. Next example illustrates a particular case of these invariants.

**Example 24.** Consider the TCPN in Fig. 3 with \( T_c \) = \{1 \}. It is a Join-Free net, so it has a unique configuration. According to Eq. (10), its flow controllability matrix is:

\[
M = \begin{bmatrix}
\lambda_1^2 & \lambda_1 \lambda_2 & \lambda_1 \lambda_3 & \lambda_2 \lambda_3 & \lambda_2^2 & \lambda_3^2 \\
\lambda_2 \lambda_1 & -\lambda_1^2 & \lambda_1 \lambda_3 & \lambda_2 \lambda_3 & -\lambda_2^2 & -\lambda_3^2 \\
\lambda_3 \lambda_1 & \lambda_3 \lambda_2 & -\lambda_1^2 & \lambda_1 \lambda_3 & -\lambda_2^2 & \lambda_2 \lambda_3 \\
\lambda_3 \lambda_2 & \lambda_3 \lambda_3 & \lambda_2 \lambda_1 & -\lambda_1^2 & \lambda_2 \lambda_3 & -\lambda_1 \lambda_3 \\
\lambda_3 \lambda_3 & \lambda_3 \lambda_3 & \lambda_3 \lambda_1 & \lambda_3 \lambda_2 & -\lambda_1^2 & \lambda_1 \lambda_3 \\
\lambda_3 \lambda_3 & \lambda_3 \lambda_3 & \lambda_3 \lambda_1 & \lambda_3 \lambda_2 & \lambda_1 \lambda_1 & \lambda_2 \lambda_2 \\
\end{bmatrix}
\]

Clearly, if \( \lambda_2 = \lambda_3 \), the second and third rows of \( M \) are equal. In other words, \( \delta^T = [0 \ 1 \ -1] \) is a left annihilor of \( M \), iff \( \lambda_2 = \lambda_3 \). Let us assume that \( \lambda_2 = \lambda_3 \). Then, \( \delta \) characterizes an invariant of the flow system (it can be easily verified that it corresponds to the case (3)). For simplicity, consider any \( m \) s.t. \( m_{[02]} = m_{[03]} \). Since \( f_2 = 2m_2 \) and \( f_3 = 3m_3 \), then \( \forall m \in \text{Class}(m_0) \) s.t. \( m_2 = m_3 \) it holds that \( \delta^T f = 0 \), i.e., the flow invariant \( f_2 - f_3 \) does not exist over such marking set. Moreover, since \( m_{[02]} = f_2 - f_3 - u_1 \) and \( m_{[03]} = f_1 - f_3 - u_1 \), then \( m_{[02]} = m_{[03]} \forall \tau \) and the evolution of the system will be restricted to such marking set.

Timed flow invariants cannot be characterized only from the net structure, and their computation is a hard task since all the configurations must be analyzed. This section introduces a necessary condition for the existence of these flow invariants.

**Proposition 25.** Let \( \langle N, \lambda \rangle \) be a TCPN. If there exist a configuration \( C \) in which a timed flow invariant (TFI) appears, then, \( CS_{C} \) has left annihilors \( v \) s.t. \( v^T C \neq 0 \).

**Proof.** Assume that there exist a configuration \( C \), in which a TFI appears. Then \( \exists \delta \) s.t. \( \delta^T \Pi \Pi C = 0 \), with \( \gamma \neq 0 \), and \( \delta^T S_{C} = 0 \). Thus, \( \delta = C^T (\Pi^T A \delta) / (1/\gamma) \), i.e. \( \delta \in \text{Img}(C^T) \). Hence, \( \exists \nu \) s.t. \( C^T \nu = \delta \), and \( S_{C}^T C^T \nu = 0 \). Thus \( v^T C S_{C} = 0 \), i.e., \( v \) is a left annihilor. \( \square \)

5.4 Uncontrollable flow invariants and rank-controllability

This section relates the full rank-controllability property with the existence of uncontrollable flow invariants, i.e., FIs involving the flow of solely uncontrollable transitions.

**Definition 26.** Let \( v^T f = c \) be a flow invariant. If \( ||v|| \leq T_{nc} \), it is said to be an uncontrollable flow invariant (UFI).

As it will be shown, if there are no UFIs in any configuration, then the TCPN will be full rank-controllable. The structural flow invariants can be easily computed and tested to check if some of them are UFIs. The timed flow invariants are, by definition (see case (3)), UFIs since the invariant \( \delta \) is orthogonal to the selector of controllable transitions. Thus, according to proposition 25, their non existence can be guaranteed if \( CS_{C} \) has no left annihilers, \( v, s.t. v^T C \neq 0 \). The following theorem formalizes these ideas.

**Theorem 27.** Let \( \langle N, \lambda \rangle \) be a TCPN. If there are no UFIs in all the configurations, then the TCPN is full rank-controllable.

**Proof. Part I:** Consider any \( C \) of \( \langle N, \lambda \rangle \). Let us demonstrate that if there are no UFIs in \( C \) then \( \text{rank}([S_{C}, M_{i}]) = |T| \). Proceeding by contradiction, suppose that there are no UFIs but \( \text{rank}([S_{C}, M_{i}]) < |T| \), then there exists \( \nu \) s.t. \( v^T S_{C} = 0 \) and \( v^T M_{i} = 0 \). This last equality means that the flow state equation (6) is uncontrollable. Thus, by the PBH test (Proposition 11) it follows that \( v \) is a left eigenvector of \( \Pi_{C}, C \). Moreover, \( v^T S_{C} = 0 \) means that \( v \) is orthogonal to the selector of controllable transitions, which implies \( ||v|| \leq T_{nc} \), then \( v \) is an UFI, which is a contradiction.

**Part II:** Now, let us show that \( \text{rank}(\Psi_{i}) = \text{rank}([S_{C_{i}}, M_{i}]) \), despite the difference in the length of the expansions. First, if \( |P| > |T| \) then \( \Psi_{i} \) has more columns than \([S_{C_{i}}, M_{i}]\), but, by the Cayley-Hamilton theorem, the columns of \( \Psi_{i} \) associated to the terms with exponents \( k > |T| \) are linearly dependent of those columns of \([S_{C_{i}}, M_{i}]\), thus both matrices have the same rank. On the other hand, if \( |T| > |P| \), \([S_{C_{i}}, M_{i}]\) has more columns than \( \Psi_{i} \), however, by construction \( \text{rank}(\Pi_{C}, C) \leq |P| \), then the columns of \([S_{C_{i}}, M_{i}] \) associated to the terms with exponents \( k > |P| \) are linearly dependent of those columns in \( \Psi_{i} \), thus both matrices have the same rank.

**Part III:** Finally, if there are no UFIs in \( C_{i} \) from the above, \( |T| = \text{rank}([S_{C_{i}}, M_{i}]) = \text{rank}(\Psi_{i}) \). Thus, \( C_{i} = C_{\Psi_{i}} \) and \( \Psi_{i} \) has full row rank, then \( \text{rank}(C_{i}) = \text{rank}(C) \), i.e., the TCPN is rank-controllable in \( C_{i} \). Moreover, since the previous is valid \( \forall C_{i} \), then the TCPN is full rank-controllable \( \square \)

6. TEST FOR FULL RANK-CONTROLLABILITY

In this Section, the previous results are integrated in an algorithm to polynomially test sufficient conditions for full rank-controllability.
According to theorem 27, full rank-controllability can be guaranteed if there are no UFI s in any $C_i$. In order to test if a TCPN fulfills this condition, a matrix that contains its potential SFI s is firstly introduced. Let $(N, \lambda)$ be a TCPN where $j = |P_C|$ is the number of choice places in $N$ and $k = \dim(B_p)$ is the dimension of the P-flow basis. Let $\alpha_1, \ldots, \alpha_j$ be a basis for the Choice-SFI s induced by $p_{c_1}, \ldots, p_{c_j} \in P_C$ (as in Prop. 21). Let $\beta_1, \ldots, \beta_k$ be a basis for the Conservation-SFI s induced by the P-semiflows $y_1, \ldots, y_k$ of the basis $B_p$ (as in Prop. 23). The matrix of potential SFI s, for all the configurations, is:

$$F^\ast = [\alpha_1 \ldots \alpha_j] [\beta_1 \ldots \beta_k]^T.$$  

It can be seen that the dimension of each of the bases for the SFI s, and thus the number of rows in $F^\ast$, are linear functions of the number of choice places, its output transitions and the dimension of $B_p$.

**Example 28.** Consider the TCPN in figure 5. The net has 2 choice places, $p_0$ and $p_6$. The support of the P-semiflows of $N$ that form a basis $B_p$ are: $||y_1|| = \{p_2, p_3, p_4, p_17\}$, $||y_2|| = \{p_5, p_9, p_{10}, p_{18}\}$, $||y_3|| = \{p_4, p_6, p_8\}$, $||y_4|| = \{p_3, p_14\}$, $||y_5|| = \{p_3, p_16\}$, $||y_6|| = \{p_1, p_2, p_3, p_{11}, p_{14}, p_{16}\}$, $||y_7|| = \{p_7, p_8, p_9, p_{10}, p_{12}, p_{14}, p_{16}\}$. Let us compute its matrix $F^\ast$.

See, for instance, the place $p_6$ and its output transitions $t_4$ and $t_5$. According to Prop. 21, $\forall C_i$ s.t. $(p_6, t_4), (p_6, t_5) \in C_i$, the flow invariant $f_{3, \lambda_3} - f_5/\lambda_5 = 0$ exist. The corresponding Choice-SFI is characterized by the vector:

$$\alpha_6 = [0 \ 0 \ 1/\lambda_3 \ 0 -1/\lambda_5 \ 0 \ 0 \ 0 \ 0 \ 0]$$

For example, let us compute the flow invariants associated to the P-semiflow $y_3$. For any configuration in which each of the places in $||y_3||$ constrains, at least, one of its output transitions, $t_1$, $t_2$, $t_5$, and $t_8$, a flow invariant involving the flow of those transitions will be present. For instance, consider any configuration $C_j$ s.t. $(p_5, t_1), (p_2, t_2), (p_7, t_7), (p_{10}, t_8) \in C_j$, i.e., any of the 36 configurations that include all the possible flow invariants that $y_3$ may introduce. Then, as in proof of proposition 23, a basis for the possible flow invariants is:

$$\beta_3 = \begin{bmatrix} 1/\lambda_1 & 1/\lambda_2 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1/\lambda_4 & 1/\lambda_5 & 1/\lambda_6 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 1/\lambda_4 & 1/\lambda_7 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 1/\lambda_8 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix}$$

By following the same reasoning, the matrix of potential structural flow invariants, in all the configurations, is:

$$F^\ast = \begin{bmatrix} 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 & 0 \end{bmatrix}$$

Finally, the algorithm 2 tests the aforementioned condition for full rank-controllability. First, according to Prop. 25, a necessary condition for the existence of $\tilde{U}FF$s is that there exist a left annuler, $v$, of matrix $CS_T$, s.t., $v^T C \neq 0$. In other words, the nonexistence of $\tilde{U}FF$s can be guaranteed if $\ker(C^T) = \ker(S_T^* C^T)$, i.e., $\text{rank}(C) = \text{rank}(CS_T)$. If this condition is fulfilled, the repeat/while loop verifies that there are no USFI s by checking that each row of $F^\ast$ is not orthogonal to $S_T$, i.e., that all the possible structural flow invariants involve the flow of a controllable transition.

The Algorithm 2 test the full-controllability property in polynomial time. If it gives a value $Flag = 1$, it means that the TCPN is full rank-controllable. Otherwise, it is not possible to conclude if this property is fulfilled since the algorithm tests a sufficient condition.

7. ILLUSTRATIVE EXAMPLE

As an illustrative example, consider the flexible manufacturing system of Fig. 4 (Silva et al., 2014). A net structure dealing with the logical layout and process plan is presented in Fig. 5. It has 261 possible configurations. A rank-controllability analysis will be performed by using the algorithm presented in the previous section.

Assuming that machine $M_3$ is always working at its nominal speed, the firing rate of the transition that model
the discharge of material from that machine cannot be modified, i.e., $t_{10} \in T_{nc}$. On the contrary, it is assumed that $M_1 \ldots M_8$, $s_87(3)$, 537–552.

Wonham, W. (1979). Linear Multivariable Control: A Geometric Approach. Springer-Verlag New York.

As a concluding remark, due to the lack of a complete characterization of the timed flow invariants, the presented results are clearly restrictive. However, since these invariants appear for specific values of the timing, we conjecture that full rank-controllability can be studied generically, where generic is understood as a property fulfilled for almost all timing, focusing only on the analysis of structural flow invariants. See for instance the case in example 24, where the timed flow invariant appears if $\lambda_2 = \lambda_3$. In other words, $\forall x \text{ s.t. } \lambda_2 \neq \lambda_3$, there are no UFI$s$ in the TCPN. In fact, for any selection of $T_c \neq \emptyset$, the TCPN does not exhibit USFI$s$, thus it is rank-controllable. Moreover, consider the example of this section. If the timing is chosen randomly, the system does not exhibit timed flow invariants. Then, the non existence of USFI$s$ is a sufficient condition for full rank-controllability. For instance, if $T_c = \{t_1,t_2,t_3,t_4,t_5,t_6,t_7,t_8,t_9,t_{11}\}$ (i.e., the transitions related to the loading of all the machines and the output buffer emptying), by using the repeat/until loop of algorithm 2 it can be easily verified that there will be no USFI$s$, then, the TCPN is full rank-controllable for almost any timing. This will be explored in future works, in order to state stronger results for full rank-controllability by using the presented approach.

8. CONCLUSIONS

It has been stated that controllability in TCPN systems, under infinite server semantics, can be studied through the structural property of rank-controllability. Then, two structural conditions for full rank-controllability, one necessary and the other sufficient, are provided. As a first necessary condition, the control actions must influence the marking at all the places. This can be verified from the net structure for all the configurations in polynomial time. As a second condition, the influence on the marking of each place is required to be independent. For this, uncontrollable flow invariants (UFI$s$) were defined and characterized by using structural objects of the net. Next, it has been shown that the existence of UFI$s$ may lead to new marking invariants and it was proved that if there are no UFI$s$ in the TCPN, then, it is full rank-controllable. Finally, a polynomial time algorithm to test sufficient conditions for full rank-controllability is provided.

A next step on this research is to extend the presented results to particular subclasses in order to obtain stronger results and determine supplementary information about the connection between the controllability property and the net structure. In addition, further investigation of the connectivity of the sets of equilibrium markings is required since, together with full rank-controllability, it guarantees controllability over the set of all equilibrium markings of the system. Finally, a future direction will be to exploit the results herein presented for the synthesis of controllers for the case where there exist uncontrollable transitions.

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