Model reference adaptive control of piecewise affine systems with state tracking performance guarantees

Tong Liu | Martin Buss

Chair of Automatic Control Engineering, Technische Universität München, Munich, Germany

Correspondence
Tong Liu, Chair of Automatic Control Engineering, Technische Universität München, Munich 80333, Germany. Email: tong.liu@tum.de

Abstract
In this paper, we investigate the model reference adaptive control approach for uncertain piecewise affine systems with state tracking performance guarantees. The proposed approach ensures the error metric, defined as the weighted Euclidean norm of the state tracking error, to be confined within a user-defined time-varying performance bound. We introduce an auxiliary performance bound to construct a barrier Lyapunov function. This auxiliary performance bound is reset at each switching instant, which prevents the barrier transgression caused by the jumps of the error metric at switching instants. The dwell time constraints are derived such that the auxiliary performance bound resides within the user-defined performance bound. We prove that the Lyapunov function is nonincreasing at and in between the switching instants. Therefore, it does not impose extra dwell time constraints and ensures the error metric to fulfill the performance guarantees. Furthermore, we study the robust modification of the adaptive controller for the uncertain piecewise affine systems subject to unmatched disturbances. A numerical example validates the correctness of the proposed approach.

KEYWORDS
barrier Lyapunov function, piecewise affine systems, robust adaptive control, time-varying performance guarantees

1 | INTRODUCTION

The study of piecewise affine (PWA) systems has attracted significant interest due to their capability to approximate nonlinear systems and model hybrid systems. A PWA system consists of several linear subsystems. Each subsystem is associated with a certain region in the state space. Depending on in which region the state vector lies, the PWA system is governed by the associated subsystem dynamics. The switching from one subsystem to another subsystem is triggered, when the state trajectory goes through the boundary of two neighboring regions. Therefore, PWA systems represent a class of state-dependent switched systems. Early studies of PWA systems focus on the controllability and observability, convergence analysis, and control synthesis, where the system parameters and region partitions are exactly known.

In the physical world, an exact system model is mostly not accessible due to uncertainties and disturbances. Therefore, introducing the adaptive mechanism into the uncertain PWA systems has significant meaning, especially...
when the uncertainties and disturbances are so large that a single robust controller cannot stabilize the closed-loop system. Due to the hybrid nature of the PWA systems, not only the uncertain parameters need to be estimated by designing adaptation laws, but also the switching behavior of the closed-loop system needs to be carefully considered. In the last decade, model reference adaptive control (MRAC) approaches have been investigated for uncertain PWA systems. The methods proposed in the work of di Bernardo et al.\textsuperscript{6-8} rely on common Lyapunov functions, where the closed-loop systems are allowed to switch arbitrarily fast. MRAC for piecewise linear systems, a special version of PWA systems, are investigated in the work of Sang and Tao\textsuperscript{9,10} where dwell time constraints for switches are given to ensure the closed-loop stability. Its extension to PWA systems is reported recently,\textsuperscript{11} where the exponential decaying of the state tracking error is proved given that a persistently exciting (PE) condition and some dwell time constraints are fulfilled. To enhance the robustness of the adaptive switched systems against disturbances and time-delay, some robust MRAC approaches have been proposed for switched linear systems, whose formulation is similar to PWA systems but with switching signals given externally. These include robust MRAC with dead zone\textsuperscript{12} and leakage,\textsuperscript{13} robust $H_\infty$ MRAC\textsuperscript{14,15} as well as control approaches with asynchronous switching between subsystems and controllers.\textsuperscript{16,17}

Despite the aforementioned advances, the adaptive control for PWA systems fulfilling a user-defined performance guarantee (such as state constraints) is rarely studied. In light of the fact that a lot of systems in practice have state constraints like physical or operational boundaries, saturation, performance and safety specifications, we would like to explore the MRAC of generalized PWA systems with state tracking performance guarantees.

Notable progress has been made in the field of adaptive control with performance guarantees. These include funnel control,\textsuperscript{18,19} barrier Lyapunov function-based approach,\textsuperscript{20} and prescribed performance control.\textsuperscript{21,22} All of these methods are proposed to confine the output tracking error within the predefined constraints. Although some recent barrier Lyapunov function-based controllers achieve the full state constraints,\textsuperscript{23-26} they are built upon the backstepping structure, which requires the controlled system to be in strict feedback form or pure feedback form. Thus, they cannot be applied to generalized PWA systems. Recently, a set-theoretic MRAC for linear systems is developed.\textsuperscript{27} It uses the barrier Lyapunov function concept to confine the weighted Euclidean norm of the state tracking error within a predefined bound. The controller does not rely on the backstepping-type analysis and therefore does not impose restrictions on the system structure. This method is extended to the cases with time-varying performance bounds,\textsuperscript{28} systems with actuator faults,\textsuperscript{29} and systems with unstructured uncertainties.\textsuperscript{30} However, applying this method to switched systems is nontrivial and challenging. If the barrier Lyapunov function is constructed with the user-defined performance bound being the barrier, as it is done in the linear system case, then the discontinuity of the weighted Euclidean norm of the tracking error at switching instants may cause transgression of the barrier, which makes the barrier Lyapunov function invalid. Besides, only matched uncertainties (uncertainties, which can be compensated with an additional input term) are addressed in the work of set-theoretic MRAC approaches. Since the PWA systems are mostly approximations of nonlinear systems, their approximation errors are not necessarily matched, let alone other kinds of external disturbances. How to enhance the robustness against unmatched uncertainties/disturbances when applying the set-theoretic MRAC to PWA systems is still open.

The main contribution of this paper is twofold. First, a set-theoretic MRAC approach for uncertain PWA systems with state tracking performance guarantees is developed. Second, a robust modification of this method is proposed for PWA systems subject to unmatched disturbances. Specifically, we impose an auxiliary performance bound with a state reset map to construct the barrier Lyapunov function, which bypasses the barrier transgression problem. The dwell time constraints are derived based on the auxiliary performance bound and the user-defined performance bound. The Lyapunov function is nonincreasing, even at switching instants, and therefore, does not impose extra dwell time constraints. Furthermore, a projection-based robust modification of the proposed approach is developed to enhance the robustness against disturbances. Compared with the state-of-the-art set-theoretic MRAC approaches, the disturbances are not required to be matched. This allows broader applications of the proposed method.

The paper is structured as follows. The definition of PWA systems, MRAC, and the performance function are revisited in Section 2. The proposed method is explained in Section 3, in which the stability analysis is also provided. The robust modification is shown in Section 3.4. A numerical example is illustrated in Section 4.

Notations: In this paper, $\mathbb{R}$, $\mathbb{R}^+$, $\mathbb{N}$ and $\mathbb{N}^+$ denote the set of real numbers, positive real numbers, natural numbers, and positive natural numbers, respectively. $\text{tr}(\cdot)$ represents the trace of a matrix. The Euclidean norm is denoted by $\| \cdot \|_2$. $\lambda_{\text{max}}(P)$ and $\lambda_{\text{min}}(P)$ represent the maximal and minimal eigenvalues of matrix $P$, respectively. $\|e\|_P = (e^TPe)^{\frac{1}{2}}$ represents the weighted Euclidean norm of $e \in \mathbb{R}^n$ with the weighting matrix $P \in \mathbb{R}^{n \times n}$.\textsuperscript{12,16,17}
2 | PRELIMINARIES AND PROBLEM STATEMENT

Let the state space be partitioned into \( s \in \mathbb{N}^+ \) convex regions \( \{\Omega_i\}_{i=1}^s \) without overlaps, that is, \( \Omega_i \cap \Omega_j = \emptyset \) for \( i \neq j \) and \( i, j \in I \triangleq \{1, 2, \ldots, s\} \). The PWA system is of the form

\[
\dot{x} = A_ix(t) + B_iu(t) + f_i, \quad x(t) \in \Omega_i,
\]

where \( A_i \in \mathbb{R}^{nxn} \) and \( B_i \in \mathbb{R}^{nsp} \) and \( f_i \in \mathbb{R}^n \). \( x \in \mathbb{R}^n \) and \( u \in \mathbb{R}^p \) denote its state and control input signal. To characterize in which region the state vector locates, we define the following indicator function

\[
\chi_i(t) = \begin{cases} 
1, & \text{if } x(t) \in \Omega_i \\
0, & \text{otherwise} 
\end{cases}
\]

Since the regions \( \{\Omega_i\}_{i=1}^s \) have no overlaps, we have \( \sum_{i=1}^s \chi_i = 1 \) and \( \prod_{i=1}^s \chi_i = 0 \). Thus, the PWA system can be written as

\[
\dot{x}(t) = A(t)x(t) + B(t)u(t) + f(t),
\]

with \( A(t) = \sum_{i=1}^s \chi_i(t)A_i, B(t) = \sum_{i=1}^s \chi_i(t)B_i \) and \( f(t) = \sum_{i=1}^s \chi_i(t)f_i \).

In this paper, the reference system is also chosen to be a PWA model, which provides more design flexibility for the user. Without loss of generality, we let the reference PWA system (4) and the controlled PWA system (3) have the same region partitions and therefore, the same indicator functions. The PWA reference system is given by

\[
\dot{x}_m(t) = A_m(t)x_m(t) + B_m(t)r(t) + f_m(t),
\]

where \( x_m \in \mathbb{R}^n \) and \( r \in \mathbb{R}^p \) denote the state and input of the reference system, \( A_m(t) = \sum_{i=1}^s \chi_i(t)A_{mi}, B_m(t) = \sum_{i=1}^s \chi_i(t)B_{mi}, f_m(t) = \sum_{i=1}^s \chi_i(t)f_{mi} \) with \( A_{mi} \in \mathbb{R}^{nxn}, B_{mi} \in \mathbb{R}^{nsp}, f_{mi} \in \mathbb{R}^n, i \in I \) being the parameters of the reference system. \( A_{mi} \) are Hurwitz matrices and there exists a set of positive definite matrices \( P_i \) and \( Q_i \in \mathbb{R}^{nxn} \) for each subsystem \( \forall i \in I \). Therefore, the controller takes the form

\[
u(t) = K^*_x x(t) + K^*_r r(t) + K^*_f,
\]

where \( K^*_x(t) = \sum_{i=1}^s \chi_i(t)K_{x,i}^*, K^*_r(t) = \sum_{i=1}^s \chi_i(t)K_{r,i}^*, K^*_f(t) = \sum_{i=1}^s \chi_i(t)K_{f,i}^* \). Taking (6) into (3) yields the closed-loop system. To obtain a closed-loop system having the same behavior as the reference system, we make the usual assumption that following matching equations hold:

\[
A_{mi} = A_i + B_iK_{x,i}, \quad B_{mi} = B_iK_{r,i}^*, \quad f_{mi} = f_i + B_iK_{r,i}^* \quad \forall i \in I.
\]

These are typical conditions for state feedback state tracking design. Note that not every system can satisfy such matching equations, some relaxation approaches (state feedback output tracking and output feedback output tracking) can be found in section 4 of Tao’s survey. Since \( A_i, B_i, f_i \) are unknown, the nominal controller gains \( K_{x,i}^*, K_{r,i}^*, K_{f,i}^* \) are not available. Let \( K_{x,i}(t) \in \mathbb{R}^{nxn}, K_{r,i}(t) \in \mathbb{R}^{nsp}, K_{f,i}(t) \in \mathbb{R}^p \) be the estimates of \( K_{x,i}^*, K_{r,i}^*, K_{f,i}^* \). We introduce the following adaptive controller

\[
u(t) = K_x(t)x(t) + K_r(t)r(t) + K_f(t),
\]

with \( K_x(t) = \sum_{i=1}^s \chi_i(t)K_{x,i}(t), K_r(t) = \sum_{i=1}^s \chi_i(t)K_{r,i}(t) \) and \( K_f(t) = \sum_{i=1}^s \chi_i(t)K_{f,i}(t) \). Inserting (8) into the controlled PWA system (3) and defining the state tracking error \( e(t) = x(t) - x_m(t) \), we have

\[
e(t) = A_me(t) + \sum_{i=1}^s \chi_iB_i(\dot{x}_i + \dot{K}_{x,i}x + \dot{K}_{r,i}r + \dot{K}_{f,i}).
\]
where $K_{sl} = K_{sl} - K_{sl}^*$, $K_{rl} = K_{rl} - K_{rl}^*$, $K_{r} = K_{r} - K_{r}^*$.

We define $t_0$ to be the initial time instant and the set $\{t_1, t_2, \cdots, t_k, \cdots | k \in \mathbb{N}^+ \}$ to be the set of switching time instants.

**Definition 1** (Dwell time\textsuperscript{12}). The switching of a switched system is said to be with dwell time if there exists a number $\tau_D > 0$ such that the time between every two consecutive switches is no smaller than $\tau_D$, that is, constraint $t_{k+1} - t_k \geq \tau_D$ holds for $\forall k \in \mathbb{N}^+$. Such positive number $\tau_D$ is called dwell time.

In this paper, we would like to design an adaptive controller for PWA systems such that the norm of the state tracking error $e$ is enforced within a predefined performance bound such that the closed-loop system has performance guarantees. The performance bound can be formulated by a performance function $\rho : \mathbb{R}^+ \to \mathbb{R}^+$, a smooth and decreasing function satisfying $\lim_{t \to \infty} \rho(t) = \rho_\infty > 0$. We adopt the following commonly used performance function\textsuperscript{21}

$$\rho(t) = (\rho_0 - \rho_\infty)e^{-(t-t_0)} + \rho_\infty, \quad (10)$$

where $\rho_0, \rho_\infty, l \in \mathbb{R}^+$ and $\rho_0 > \rho_\infty$. We can see that $\rho(t)$ is smooth and decreasing with the initial value $\rho(t = t_0) = \rho_0$ and the final value $\rho(t \to \infty) = \rho_\infty$. The initial value $\rho_0$ can be chosen such that the performance guarantee (introduced in (11)) can be satisfied at the initial time instant. The final value $\rho_\infty$ implies a steady-state error bound, while $l$ determines the convergence speed toward $\rho_\infty$. The performance guarantee to be satisfied can be formulated as

$$\|e(t)\|_P < \rho(t). \quad (11)$$

The error metric $\|e(t)\|_P$ serves as a performance measure reflecting the difference between the state of the controlled system and the reference system. $P$ is equal to $P_i$ if subsystem $i$ is activated, that is, $P = \sum_{i=1}^I x_i(t)P_i$, where the weighting matrices $P_i$ satisfy (5). So the error metric $\|e(t)\|_P$ and the system parameters switch synchronously.

**Remark 1.** Some questions may arise regarding (11): is it feasible to specify a global weighting matrix for the error metric instead of the switching one? What if the user would like to define a performance guarantee with an arbitrary weighting matrix, which does not necessarily satisfy the Lyapunov equation (5)? In fact, these requirements can be transformed into the formulation (11). We explain this point in the following.

Suppose that a global performance measure, which should hold for every subsystem, is desired by the user, that is, $\|e(t)\|_S < \rho^*(t)$, where $S \in \mathbb{R}^{n \times n}$ is an arbitrary user-defined positive definite matrix and $\rho^*(t)$ represents a user-defined performance function in form of (10). Then, we can choose $P_i, i \in I$ matrices based on (5). We know $\|e\|_S \leq \gamma \|e\|_P$ with $\gamma = \min_{i \in I} \sqrt{\frac{1}{\lambda_{\min}(P)}}$. To satisfy $\|e(t)\|_S < \rho^*(t)$, it suffices to let $\|e\|_P < \gamma \rho^*(t)$ hold, which is equivalent to (11) by letting $\rho(t) = \gamma \rho^*(t)$.

The problem to be studied in this paper is formulated as follows:

**Problem 1.** Given a performance function (10), a reference model (4) and a PWA system (3) with unknown subsystem parameters $A_i, B_i, f_i$ and known regions $\Omega_i$ (or equivalently, known indicator functions $x_i(t)$), design an adaptive control law $u(t)$ such that the state $x(t)$ of (3) tracks the state $x_m(t)$ of (4) with the tracking error $e(t)$ satisfying the performance guarantee (11).

3 | **ADAPTIVE CONTROL DESIGN**

In this section, we propose the adaptive controller to solve the given problem in the disturbance-free case and study its robust modification. First, we introduce the auxiliary performance bound and explain the solution concept. Then the proposed adaptation laws are presented, which are followed by the stability analysis of the closed-loop system.

3.1 | **Auxiliary performance bound**

We define a generalized restricted potential function (barrier Lyapunov function)\textsuperscript{28} $\phi : \mathbb{R}^+ \to \mathbb{R}^+$ on the set $D_\theta \triangleq \{e | \|e\|_P \in [0, \theta)\}$

$$\phi(\|e\|_P) = \frac{\|e\|_P^2}{\theta^2(t) - \|e\|_P^2}, \quad \|e\|_P < \theta(t). \quad (12)$$
Lemma 1. Given the performance function (10) and the auxiliary performance bound (14) with the reset map (15), if \( h > l \), \( \rho_\infty > \sqrt{\frac{\mu}{h}} \) and if the dwell time of \( c(t) \) satisfies

\[
\tau_D > \frac{1}{h - l} \ln \frac{\sqrt{\mu \rho_\infty} - \frac{g}{h} \sqrt{\mu}}{\rho_\infty - \frac{g}{h} \sqrt{\mu}}.
\]
for $\mu > 1$, then the following inequality holds
\[
\frac{g}{h} \leq e(t) < \rho(t), \quad \forall t \in [t_0, \infty). \tag{17}
\]

**Proof.** The initial value of $\epsilon$ satisfies $e(t_0) > \frac{g}{h}$, meaning that $e$ decreases exponentially toward $\frac{g}{h}$ if no switch occurs. Since $\sqrt{\mu} > 1$, $e$ increases at each switching time instant and $e(t_k) > \frac{g}{h}$ for $\forall k \in \mathbb{N}^+$. If the switch terminates from some time on, then $e > \frac{g}{h}$ for $t \to \infty$, otherwise, $e > \frac{g}{h}$ for $t \in [t_0, \infty)$. Therefore, we have $e(t) \geq \frac{g}{h}, \forall t \in [t_0, \infty)$.

Now, we explore the relationship between $e(t)$ and $\rho(t)$. We have for the time interval $[t_0, t_1)$
\[
e(t) = e(t_0)e^{-h(t-t_0)} + \int_{t_0}^{t} e^{-h(t-r)} dr = (e(t_0) - \frac{g}{h}) e^{-h(t-t_0)} + \frac{g}{h}. \tag{18}
\]

Since $e(t_0) \in \left( \frac{g}{h}, \rho_0 \right)$, $h > l$ and $\rho_\infty > \sqrt{\mu} \frac{g}{h}$, we have $e(t) < \rho(t)$ for $t \in [t_0, t_1)$. For $t = t_1$ it gives
\[
e(t_1) = \sqrt{\mu}e(t_1) = \sqrt{\mu} \left( e(t_0) - \frac{g}{h} \right) e^{-h(t_1-t_0)} + \sqrt{\mu} \frac{g}{h}. \tag{19}
\]

Let $\Delta t_1 = t_1 - t_0$, we have
\[
\rho(t_1) - e(t_1) = (\rho_0 - \rho_\infty) e^{-\Delta t_1} - \sqrt{\mu} \left( e(t_0) - \frac{g}{h} \right) e^{-h\Delta t_1} + \left( \rho_\infty - \sqrt{\mu} \frac{g}{h} \right)
\geq (\rho_0 - \rho_\infty) e^{-\Delta t_1} - \sqrt{\mu} \left( e(t_0) - \frac{g}{h} \right) e^{-h\Delta t_1} + \left( \rho_\infty - \sqrt{\mu} \frac{g}{h} \right) e^{-l\Delta t_1},
\]
\[
= (\rho_0 - \sqrt{\mu} \frac{g}{h}) e^{-\Delta t_1} - \sqrt{\mu} \left( e(t_0) - \frac{g}{h} \right) e^{-h\Delta t_1}
\geq \left( \rho_0 - \sqrt{\mu} \frac{g}{h} \right) e^{-\Delta t_1} - \sqrt{\mu} \left( \rho_0 - \frac{g}{h} \right) e^{-h\Delta t_1}. \tag{20}
\]

If the inequality
\[
\left( \rho_0 - \sqrt{\mu} \frac{g}{h} \right) e^{-\Delta t_1} > \sqrt{\mu} \left( \rho_0 - \frac{g}{h} \right) e^{-h\Delta t_1}, \tag{21}
\]
holds, we will immediately have $\rho(t_1) > e(t_1)$. Since $\rho_0 > \rho_\infty > \sqrt{\mu} \frac{g}{h} > \frac{g}{h}$, we have $\rho_0 - \sqrt{\mu} \frac{g}{h} > 0$ and $\sqrt{\mu} (\rho_0 - \frac{g}{h}) > 0$. Therefore, (21) is equivalent to
\[
\frac{\rho_0 - \sqrt{\mu} \frac{g}{h}}{\sqrt{\mu} (\rho_0 - \frac{g}{h})} > e^{-(h-l)\Delta t_1}. \tag{22}
\]

Taking the logarithm of both sides we obtain
\[
\Delta t_1 > \frac{1}{h-l} \ln \frac{\sqrt{\mu} \rho_0 - \frac{g}{h} \sqrt{\mu}}{\rho_0 - \frac{g}{h} \sqrt{\mu}}. \tag{23}
\]

Following the above analysis we can obtain $e(t) < \rho(t)$ for $t \in [t_{k-1}, t_k)$ and $e(t_k) < \rho(t_k)$ for $k \in \mathbb{N}^+$ if
\[
\Delta t_k > \frac{1}{h-l} \ln \frac{\sqrt{\mu} \rho(t_{k-1}) - \frac{g}{h} \sqrt{\mu}}{\rho(t_{k-1}) - \frac{g}{h} \sqrt{\mu}} = \frac{1}{h-l} \ln \left( \frac{\sqrt{\mu} + (\mu - \sqrt{\mu}) \frac{g}{h}}{\rho(t_{k-1}) - \frac{g}{h} \sqrt{\mu}} \right). \tag{24}
\]

If the dwell time $\tau_D$ is no smaller than the maximal required interval length $\max \{ \Delta t_k \}$, then $e(t) < \rho(t)$ holds for $\cup [t_{k-1}, t_k), k \in \mathbb{N}^+$. Because $\rho(t_{k-1}) \geq \rho_\infty$ for $k \in \mathbb{N}^+$, we have
\[
\tau_D \geq \max \{ \Delta t_k \} > \frac{1}{h-l} \ln \frac{\sqrt{\mu} \rho_\infty - \frac{g}{h} \sqrt{\mu}}{\rho_\infty - \frac{g}{h} \sqrt{\mu}}. \tag{25}
\]
So we can conclude that if (16) holds, then $\epsilon(t) < \rho(t)$ for $t \in [t_0, \infty)$.

Lemma 1 tells the dwell time constraint to be fulfilled. We will further discuss how this dwell time constraint can be satisfied later following Remark 4. Since $\epsilon$, the reference system (4) and the closed-loop system share the same switching signal, the first question to ask is, if the reference system is stable with the dwell time constraint (16)? This is answered by the following lemma.

**Lemma 2.** The reference system (4) satisfying (5) is stable with the dwell time constraint (16) and $h$ satisfying (28).

The proof of Lemma 2 can be seen in Appendix A.1.

### 3.2 Adaptation laws

Based on the auxiliary performance bound proposed in Section 3.1, we define the following generalized restricted potential function (barrier Lyapunov function) $\phi : \mathbb{R}^+ \to \mathbb{R}^+$

$$
\phi(||e||_P) = \frac{||e||_P^2}{\epsilon^2(t) - ||e||_P^2}, \quad ||e||_P < \epsilon(t).
$$

(26)

with $P = \sum_{i=1}^r \chi_i(t)P_i$. Since $||e||_P^2$ and $\epsilon^2(t)$ are piecewise continuous and piecewise differentiable, the partial derivative of $\phi$ with respect to $||e||_P^2$ over the time interval $[t_k, t_{k+1})$, $k \in \mathbb{N}^+$ takes the form $\phi_d \triangleq \partial \phi / \partial ||e||_P^2 = \epsilon^2(t)/(\epsilon^2(t) - ||e||_P^2)^2 > 0$. $\phi$ and $\phi_d$ have the property that $2\phi_d(||e||_P)||e||_P - \phi > 0$.

The adaptation laws of the estimated controller gains are given as

$$
K_{xi} = -\chi_i \Gamma_{xi} \phi_d S_i^T B_m^T P_1 e x^T, \quad K_{ri} = -\chi_i \Gamma_{ri} \phi_d S_i^T B_m^T P_1 e r^T, \quad K_{fi} = -\chi_i \Gamma_{fi} \phi_d S_i^T B_m^T P_1 e,
$$

(27)

where $\Gamma_{xi}, \Gamma_{ri}, \Gamma_{fi} \in \mathbb{R}^+$ are positive scaling factors. $S_i \in \mathbb{R}^{p \times p}$ is a matrix such that there exists a symmetric and positive definite matrix $M_i \in \mathbb{R}^{p \times p}$ with $(K_i^T S_i)^{-1} = M_i$. Here we make the usual assumption in multivariable adaptive control$^{31}$ that $S_i$ is known. The use of the indicator functions $\chi(t)$ in the adaptation laws (27) implies that the controller gains associated with a certain subsystem are updated only when this subsystem is activated. Their adaptation terminates and their values stay unchanged during the inactive phase of the corresponding subsystem. Note that $\phi_d$ in (27) can also be viewed as an error-dependent gain, whose effect can be weakened or amplified by tuning the constant gains $\Gamma_{xi}, \Gamma_{ri}, \Gamma_{fi}$. They are chosen by trial and error in the simulation. If $\Gamma_{xi}, \Gamma_{ri}, \Gamma_{fi}$ are too small, the effect of $\phi_d$ on the adaptation speeds $K_{xi}, K_{ri}, K_{fi}$ is weakened. Consequently, $\phi$ and $\phi_d$ may have every small denominators and become ill-conditioned. If $\Gamma_{xi}, \Gamma_{ri}, \Gamma_{fi}$ are too large, the differential equations may become “stiff” and difficult to solve numerically.

### 3.3 Stability analysis

The tracking performance and the stability of the closed-loop system are summarized in the following theorem.

**Theorem 1.** Given the reference PWA system (4) and the predefined performance function (10), let the PWA system (3) with known regions $\Omega_i$, $i \in T$ and unknown subsystem parameters $A_i, B_i, f_i$, $i \in T$ be controlled by the feedback controller (8) with the adaptation laws (27). Let the initial state of $e$ satisfy $||e(t_0)||_P < \epsilon(t_0)$. The closed-loop system is stable and the state tracking error $e(t)$ fulfills the prescribed performance guarantees (11) if the time constant $h$ in (14) satisfies

$$
h < \frac{1}{2} \min_{i \in T} \frac{\lambda_{\text{min}}(Q_i)}{\lambda_{\text{max}}(P_i)},
$$

(28)

and if the switching signal of the controlled PWA system obeys the dwell time constraint $\tau_D$ in (16).

**Proof.** Without loss of generality, we let the scaling factors in (27) be 1. Consider the following Lyapunov function

$$
V = \phi(||e||_P) + \sum_{i=1}^r \left( \text{tr} \left( \tilde{K}_{xi}^T M_i \tilde{K}_{xi} \right) + \text{tr} \left( \tilde{K}_{ri}^T M_i \tilde{K}_{ri} \right) + \text{tr} \left( \tilde{K}_{fi}^T M_i \tilde{K}_{fi} \right) \right).
$$

(29)
The time-derivative of $V$ gives

$$V = \phi(||e||_{P_i}) + 2\sum_{i=1}^{s} \left( \text{tr} \left( \tilde{K}_{xi}^T M_i \dot{K}_{xi} \right) + \text{tr} \left( \tilde{K}_{ni}^T M_i \dot{K}_{ni} \right) + \tilde{K}_{i}^T M_i \dot{K}_{i} \right).$$  

(30)

First, we simplify the second term of $V$. Taking the adaptation laws (27) into the first summand of the second term of $V$ gives

$$\text{tr} \left( \tilde{K}_{xi}^T M_i \dot{K}_{xi} \right) = -\chi_i \phi_d \text{tr} \left( \tilde{K}_{xi}^T M_i S_i^T B_m^T P_i e x^T \right)$$

(31)

Since $\left( K_{ri}^* S_i \right)^{-1} = M_i$ and $B_i K_{ri}^* = B_{mi}$, we have $M_i S_i^T B_m^T = M_i S_i^T (B_i K_{ri}^*)^T = M_i M_i^{-1} B_i^T = B_i^T$, which further gives

$$\text{tr} \left( \tilde{K}_{xi}^T M_i \dot{K}_{xi} \right) = -\chi_i \phi_d \text{tr} \left( x e^T P_i B_i \tilde{K}_{xi} \right) = -\chi_i \phi_d \text{tr} \left( e^T P_i B_i \tilde{K}_{xi} x \right) = -\chi_i \phi_d e^T P_i B_i \tilde{K}_{xi} x.$$  

(32)

Doing the same simplification for $\text{tr} \left( \tilde{K}_{ri}^T M_i \dot{K}_{ri} \right)$ and $\tilde{K}_{i}^T M_i \dot{K}_{i}$ we have

$$2\sum_{i=1}^{s} \left( \text{tr} \left( \tilde{K}_{xi}^T M_i \dot{K}_{xi} \right) + \text{tr} \left( \tilde{K}_{ni}^T M_i \dot{K}_{ni} \right) + \tilde{K}_{i}^T M_i \dot{K}_{i} \right) = -2\sum_{i=1}^{s} \chi_i \phi_d e^T P_i B_i (\tilde{K}_{xi} x + \tilde{K}_{ni} r + \tilde{K}_{i}).$$  

(33)

$\phi$ can be further simplified as

$$\phi = \frac{\partial \phi}{\partial||e||_{P_i}} \frac{d||e||_{P_i}^2}{dt} + \frac{\partial \phi}{\partial e} \dot{e} = 2\phi_d(||e||_{P_i}) e^T P_i e + \frac{\partial \phi}{\partial e} \dot{e}.$$  

(34)

Substituting $\dot{e}$ with (9) yields

$$\dot{\phi} = \phi_d (e^T (A_m P_i + P_i A_m) e + 2 e^T P_i \sum_{i=1}^{s} \chi_i B_i (\tilde{K}_{xi} x + \tilde{K}_{ni} r + \tilde{K}_{i})) + \frac{\partial \phi}{\partial e} \dot{e}$$

$$= -\phi_d e^T Q_i e + 2 \sum_{i=1}^{s} \chi_i \phi_d e^T P_i B_i (\tilde{K}_{xi} x + \tilde{K}_{ni} r + \tilde{K}_{i}) + \frac{\partial \phi}{\partial e} \dot{e}.$$  

(35)

Therefore, $\dot{V}$ can be simplified as

$$\dot{V} = -\phi_d e^T Q_i e + \frac{\partial \phi}{\partial e} \dot{e},$$  

(36)

with

$$\frac{\partial \phi}{\partial e} \dot{e} = \frac{-2\epsilon e^2}{(\epsilon^2 - ||e||_{P_i})^2} \dot{e} = -2\phi_d(||e||_{P_i}) ||e||_{P_i}^2 \dot{e} \leq 2\phi_d(||e||_{P_i}) ||e||_{P_i}^2 \frac{\dot{e}}{e}.$$  

(37)

Invoking Lemma 1, we have $\epsilon(t) \geq \frac{\dot{\epsilon}}{\epsilon}, \forall t \in [t_0, \infty)$. Therefore,

$$\frac{|\dot{e}|}{e} = \frac{h \epsilon - g}{e} = h - \frac{g}{e} \leq h,$$

(38)
which leads to
\[ \frac{\partial \phi}{\partial e} e \leq 2h \phi_d(\|e\|_p)\|e\|_p^2. \]  
(39)

Taking this into (36) yields
\[ \dot{V} \leq -\phi_d(\|e\|_p^2)\lambda_{\text{max}}(Q_I) + 2h \phi_d(\|e\|_p^2)\lambda_{\text{max}}(P_I) = -\phi_d(\|e\|_p^2)(\lambda_{\text{max}}(Q_I) - 2h \lambda_{\text{max}}(P_I)). \]  
(40)

From the condition (28) it follows \( \lambda_{\text{min}}(Q_I) - 2h \lambda_{\text{max}}(P_I) > 0 \), which together with the property \( 2\phi_d(\|e\|_p)\|e\|_p^2 - \phi > 0 \) gives
\[ \dot{V} \leq -\frac{\lambda_{\text{min}}(Q_I) - 2h \lambda_{\text{max}}(P_I)}{2\lambda_{\text{max}}(P_I)} \phi \leq 0. \]  
(41)

The fact \( \dot{V} \leq 0 \) in intervals \([t_k, t_{k+1}), k \in \mathbb{N}^+ \) implies that the Lyapunov function decreases between two consecutive switches. \( \phi_d \) and \( \phi_d \) are bounded in \([t_k, t_{k+1}) \). Since \( \|e(t_k)\|_p < e(t_k) \), we have \( \|e(t)\|_p < e(t) \) for \( \forall t \in [t_k, t_{k+1}) \).

The property \( \dot{V} \leq 0 \) for each \([t_k, t_{k+1}) \) does not imply the global stability of the closed-loop system over the whole \( t \in [t_0, \infty) \). It is necessary to evaluate the discontinuity of \( V \) at each switching instant (phase 2): *jump at switch instant \( t_k, k \in \mathbb{N}^+ \).

Now we analyse the behavior of the Lyapunov function at the switching time instants. Suppose that \( i \)-th subsystem is activated in \([t_{k-1}, t_k) \) and \( j \)-th subsystem is activated in \([t_k, t_{k+1}) \), where \( i, j \in I, i \neq j \). From the adaptation laws of the estimated controller gains (27), we see that the estimated controller gains are continuous, that is, \( \tilde{K}_x(t_k) = \tilde{K}_x(t_k^-) \), \( \tilde{K}_x(t_k) = \tilde{K}_x(t_k^-) \) and \( \tilde{K}_y(t_k) = \tilde{K}_y(t_k^-) \) for \( \forall k \in I \), from which it follows \( V_o(t_k^-) = V_o(t_k) \). To study the relationship between \( V(t_k^-) \) and \( V(t_k) \), it remains to analyse \( \phi(\|e(t_k^-)\|) \) and \( \phi(\|e(t_k)\|) \). Since \( e(t) \) is also continuous, \( e(t_k^-) = e(t_k^-) \). This results in
\[ \|e(t_k^-)\|^2 = e^T(t_k^-)P_k e(t_k^-) \leq \lambda_{\text{max}}(P_k)\|e(t_k^-)\|^2 \leq \frac{\lambda_{\text{max}}(P_k)}{\lambda_{\text{min}}(P_k)} e^T(t_k^-)P_k e(t_k^-) = \frac{\lambda_{\text{max}}(P_k)}{\lambda_{\text{min}}(P_k)}\|e(t_k^-)\|^2 \leq \mu\|e(t_k^-)\|^2. \]  
(42)

From the analysis of phase 1, we already know that \( \|e(t_k^-)\| < e(t_k^-) \). \( e \) is reset at \( t_k \) and we have
\[ \|e(t_k)\|_p \leq \sqrt{\mu}\|e(t_k^-)\|_p < \sqrt{\mu e(t_k^-)} = e(t_k^-), \]  
(43)
which makes the potential function \( \phi(\|e(t_k)\|) \) also valid at \( t_k \). Recalling the dynamics of \( e \) (14) and the above inequalities (42), we have
\[ \phi(\|e(t_k)\|) = \frac{\|e(t_k^-)\|^2}{e^T(t_k^-) - \|e(t_k^-)\|^2} \leq \frac{\mu\|e(t_k^-)\|^2}{e^T(t_k^-)} = \mu\|e(t_k^-)\|^2 = \phi(\|e(t_k^-)\|). \]  
(44)

Combining the facts \( \phi(\|e(t_k)\|) \leq \phi(\|e(t_k^-)\|) \) and \( V_o(t_k^-) = V_o(t_k) \), we have
\[ V(t_k) = \phi(\|e(t_k)\|) + V_o(t_k) \leq \phi(\|e(t_k^-)\|) + V_o(t_k^-) = V(t_k^-). \]  
(45)

Therefore, the Lyapunov function is nonincreasing at every switching time instant. This together with the fact \( \dot{V} \leq 0 \) in \([t_k, t_{k+1}) \) for \( \forall k \in \mathbb{N} \) implies that \( V(t) \) is nonincreasing for \( \forall t \in [t_0, \infty) \). The discontinuity of the Lyapunov function does not introduce extra dwell time constraints.

Combining the analysis of phase 1 and phase 2, we have \( \phi, \tilde{K}_x, \tilde{K}_y, \tilde{K}_x, \tilde{K}_y, \tilde{K}_y \in \mathcal{L}_\infty \), which further leads to \( K_x, K_y, K_y \in \mathcal{L}_\infty \).

Besides, \( \|e(t)\|_p < \epsilon(t) < \rho(t) \) holds for \( \forall t \in [t_0, \infty) \). This gives \( \phi(t) \in \mathcal{L}_\infty \).

Invoking Lemma 2 we have \( x_m \in \mathcal{L}_\infty \). This property and \( \|e(t)\|_p < \epsilon(t) < \rho(t) \) lead to \( x \in \mathcal{L}_\infty \), which together with \( r, \phi_d \in \mathcal{L}_\infty \) implies \( K_x, K_y, K_y \in \mathcal{L}_\infty \).

Theorem 1 shows the tracking performance and the stability of the closed-loop system under the dwell time constraint (16). Now we study the case with arbitrary switching. For the PWA reference systems with common Lyapunov matrix \( P \), that is, if positive definite matrices \( P \) and \( Q_i, i \in I \) exist such that
\[ A_{mi}^T P + P A_{mi} = -Q_i, \quad i \in I, \]  
(46)
the error metric \( ||e(t)||_p \) exhibits no jumps at the switching instants. We can construct the potential function with the user-defined performance function directly

\[
\phi_0(||e||_p) = \frac{||e||_p^2}{\rho^2(t) - ||e||_p^2}, \quad ||e||_p \leq \rho(t).
\]

(47)

**Corollary 1.** For the reference PWA system (4) with a common Lyapunov matrix \( P \), if the adaptation laws

\[
\dot{K}_{\alpha} = -\chi_i \phi_{d0} S_i^T B_{m_i}^T P_{ex} x^T, \quad \dot{K}_{r_i} = -\chi_i \phi_{d0} S_i^T B_{m_i}^T P_{er} x^T, \quad \dot{K}_{\beta} = -\chi_i \phi_{d0} S_i^T B_{m_i}^T P_{e} x,
\]

(48)

are used with \( \phi_{d0} = \frac{\partial \phi_0}{\partial ||e||_p} \), and if the decaying rate of \( \rho \) satisfies

\[
l < \frac{1}{2} \min_{i \in I} \lambda_{\min}(Q_i), \nonumber\]

(49)

the closed-loop system is stable under arbitrary switching and the state tracking error \( e(t) \) satisfies the prescribed performance guarantees (11).

**Proof.** We propose the following common Lyapunov function

\[
V = \phi_0(||e||_p) + \sum_{i=1}^{s} \left( \text{tr} \left( K_{\alpha}^T M_i K_{\alpha} \right) + \text{tr} \left( K_{r_i}^T M_i K_{r_i} \right) + K_{\beta i}^T M_i K_{\beta i} \right).
\]

(50)

\( V \) is continuous not only within each interval \([t_k, t_{k+1})\), \( k \in \mathbb{N} \) but also at switch instants \( t_k, k \in \mathbb{N}^+ \). Taking its time derivative and inserting (48) and (9), we obtain

\[
\dot{V} = -\phi_{d0} e^T \left( \sum_{i=1}^{s} \chi_i Q_i \right) e + \frac{\partial \phi_0}{\partial \rho} \dot{\rho}.
\]

(51)

Since \( \frac{\partial \phi_0}{\partial \rho} \dot{\rho} \leq 2 \phi_{d0}(||e||_p)||e||_p^2 \frac{\rho}{\rho} \) and \( \frac{\rho}{\rho} \leq l \), we have

\[
\dot{V} \leq -\phi_{d0} ||e||_p^2 \lambda_{\min}(Q_i) + 2 \phi_{d0} ||e||_p^2 \lambda_{\max}(P) \leq \frac{\min_{i \in I} \lambda_{\min}(Q_i) - 2 \lambda_{\max}(P)}{2 \lambda_{\max}(P)} \phi_0 \leq 0,
\]

(52)

given that (49) holds. \( \dot{V} \leq 0 \) is negative semidefinite. Therefore, we have \( \phi_0, \dot{K}_{\alpha}, \dot{K}_{r_i}, \dot{K}_{\beta} \in \mathcal{L}_\infty \) for arbitrary switching. The boundedness of \( \dot{K}_{\alpha}, \dot{K}_{r_i}, \dot{K}_{\beta} \) implies \( K_{\alpha}, K_{r_i}, K_{\beta} \in \mathcal{L}_\infty \). Furthermore, \( ||e(t)||_p < \rho(t) \) holds for all \( t \in [t_0, \infty) \). This leads to \( x \in \mathcal{L}_\infty \) and \( \phi_{d0} \in \mathcal{L}_\infty \), which together with \( r \in \mathcal{L}_\infty \) implies that \( K_{\alpha}, K_{r_i}, K_{\beta} \in \mathcal{L}_\infty \).

It is worth comparing the proposed method with other control approaches for switched systems with performance guarantees. The bang-bang funnel controller\(^{33}\) enforces the output tracking error of systems, which can be transformed into Byrnes–Isidori normal form, within a predefined funnel. The backstepping-based approaches can achieve output tracking with performance guarantees for systems with special structures (strict-feedback form\(^{34,35}\) and non-strict-feedback form\(^{36}\)). In contrast, our approach achieves performance-guaranteed full state tracking without special structural requirements provided that the matching conditions (7) hold. Nevertheless, extra efforts are needed in our case for the design of auxiliary performance bound to bypass the barrier transgression problem. The fault-tolerant approach\(^{37}\) solves the barrier transgression problem by modifying the performance function when actuator failure occurs. Compared to this concept, our method imposes the auxiliary performance bound with certain dwell time constraints such that the modification of the original performance function \( \rho(t) \) is not necessary.

**Remark 2.** The classical MRAC approaches for switched systems\(^{10,11,14}\) suggest using \( e^T \left( \sum_{i=1}^{s} \chi_i P_i \right) e \) as the error-related term (the first summand) of the Lyapunov function \( V \). This leads to potential increases of \( V \) at switching instants. The dwell time constraints are then derived by formulating an inequality in form of \( \dot{V} < -\alpha V + \beta \) for some constant \( \alpha, \beta > 0 \) to keep \( V \) exponentially decreasing in between the switches. To achieve this, the projection operator needs to be introduced.
(see work by Sang and Tao\textsuperscript{10} as well as Wu and Zhao\textsuperscript{14}) or the input signal must be PE (see work by Kersting and Buss\textsuperscript{11}) in the disturbance-free case. One key feature of our approach is that the Lyapunov function $V$ is nonincreasing even at the switching instants and does not impose extra dwell time constraints. This omits the need for introducing projection or the PE condition in the disturbance-free case.

Remark 3. The nonincreasing property at switching instants of Lyapunov functions is also achieved in the recently proposed adaptive control approaches for switched systems,\textsuperscript{38,39} which employ time-varying gains for adaptation laws. These time-varying gains are either obtained by interpolating a set of precalculated $P_{ik}$ matrices satisfying certain linear matrix inequalities\textsuperscript{38} or generated by an auxiliary piecewise continuous dynamical system.\textsuperscript{39} Compared to these approaches, our method can be viewed as an error-dependent dynamic gain approach (see $\phi_d$ in adaptation laws (27)) and endows the closed-loop system with a user-defined performance guarantee.

Remark 4. Introducing the auxiliary performance bound $\epsilon$ has the advantage that the barrier transgression problem can be avoided. Nevertheless, this imposes one technical challenge: how its parameters are related to the dwell time constraint and the system stability. We resolve this challenge by deriving a novel dwell time constraint in terms of the parameters of $\epsilon$ in Lemma 1, which differs from the existing dwell time constraints\textsuperscript{40,41} and proving that the resulted Lyapunov function does not impose extra dwell time constraints.

So far, the theoretical results are obtained with the assumption that the reference PWA system (4) and the controlled PWA system (3) switch synchronously, where the switches depend on the state of the controlled PWA system. To show how the dwell time constraint (16) can be satisfied, we consider a more general case, where the reference PWA system switches based on its own state space partitions $x_m \in \{\Omega_i^m\}_{i=1}^n$. For $x \in \Omega_i$ and $x_m \in \Omega_i^m$, a set of controllers $K_{dij}, K_{rij}, K_{rif}$ is activated for adaptations, whose nominal values $K_{dij}^*, K_{rij}^*, K_{rif}^*$ satisfy the matching equations for $\{A_i, B_i, f_i\}$ and $\{A_{mj}, B_{mj}, f_{mj}\}$. At the switching instants $\{i_k\}_{k \in \mathbb{N}^+}$ of the reference PWA system, that is, $x(i_k)$ and $x(i_k) \in \Omega_i, x_m(i_k) \in \Omega_i, x_m(i_k) \in \hat{\Omega}_j, j \neq i$, we have $P(i_k) = P_j(i_k) = P_i$. The reset of $\epsilon$ is triggered; At the switching instants $\{i_k\}_{k \in \mathbb{N}^+}$ of the controlled PWA system, i.e., $x(i_k) \in \Omega_i, x_m(i_k) \in \hat{\Omega}_i, i \neq j, x_m(i_k) \in \Omega_j$, we have a common $P(i_k^+) = P(i_k) = P_j$. $\epsilon$ is not reset at $i_k$. So within each interval $[i_{k-1}, i_k)$, the analysis follows a common Lyapunov setting shown in Corollary 1; Over the whole time interval $\cup [i_{k-1}, i_k)$, the stability argumentation follows Theorem 1. The above analysis shows that only $\{i_k\}_{k \in \mathbb{N}^+}$ of the reference system have to satisfy the dwell time constraint. Since the reference PWA system is designed by the user, the dwell time constraint can be fulfilled by properly designing the reference input and the reference PWA system offline and can be checked in advance.

### 3.4 Robust modification

We now study the robust modification of the proposed method to extend it to the case with disturbances and unmodeled dynamics. Consider

$$\dot{x}(t) = A(t)x(t) + B(t)u(t) + f(t) + d(x, u, t),$$  \hspace{1cm} (53)

where $d(x, u, t) \in \mathbb{R}^n$ can denote the approximation error of the linearization, unmodeled dynamics or external disturbances. $d$ is continuous and its norm is upper bounded, that is, $\|d\|_2 \leq \bar{d}$, where $\bar{d}$ is known.

We propose the following robust adaptation laws

$$K_{dx} = -\chi_1 \phi_d S^T B_{m1} P_{e1} x^T + \chi_1 F_{dx}, \quad K_{ri} = -\chi_1 \phi_d S^T B_{m1} P_{e1} x^T + \chi_1 F_{ri}, \quad K_{fl} = -\chi_1 \phi_d S^T B_{m1} P_{e1} x + \chi_1 F_{fl},$$  \hspace{1cm} (54)

where $F_{dx} \in \mathbb{R}^{p \times n}, F_{ri} \in \mathbb{R}^{p \times p}, F_{fl} \in \mathbb{R}^{p}$ represent the projection terms to confine the estimated controller gains $K_{dx}, K_{ri}, K_{fl}$ within some given bounds. The projection terms have no effect on the adaptation if $K_{dx}, K_{ri}, K_{fl}$ are within their bounds, otherwise, the adaptation terminates. Here we make the assumption that a known matrix $S_i \in \mathbb{R}^{p \times p}$ as well as an unknown diagonal and positive definite matrix $M_i \in \mathbb{R}^{p \times p}$ exist such that $(K_{ri}^* S_i)^{-1} = M_i$.

Remark 5. For the robust adaptive control design, more prior information is required compared with the disturbance-free case. For our projection-based approach, $M_i$ must be diagonal and the element-wise bounds of $K_{dx}, K_{ri}, K_{fl}$ need to be known (see also work by Sang and Tao\textsuperscript{9}). The leakage-based approach proposed by Yuan et al.\textsuperscript{12} requires $M_i$ to be completely known because they are used in the leakage terms. The follow-up work\textsuperscript{42} requires $\lambda_{max}(M_i^{-1})$ to satisfy some constraints associated with the leakage rates.
Remark 6. Regarding the input matrix, there is another popular formulation \( \dot{x} = A_p x + B_p \Delta u \) for linear systems appearing in many works inspired by aerospace applications, where \( B_p \) is known and \( \Delta \) is an unknown diagonal matrix with strictly positive diagonal elements. Such arrangement of the input matrix is equivalent to our formulation. Specifically, \( B = B_m S M \) (we remove the subscript \( i \)) in our notations. The unknown diagonal matrix \( \Lambda \) with strictly positive diagonal elements corresponds to the diagonal and positive definite matrix \( M \) in our case, while the known control direction \( B_p \) corresponds to the multiplication \( B_m S \).

Besides, we assume that positive definite matrices \( P_i, Q_i, i \in I \) exist such that

\[
A_{mi}^T P_i P_i A_{mi} + P_i = -Q_i, \quad i \in I. \tag{55}
\]

Before we proceed with the robustness analysis, another property of the potential function, which is useful for the analysis in this paper, is given in the following lemma.

Lemma 3. For a positive constant \( c \in \mathbb{R}^+ \) and \( c < \min_i \varepsilon^2(t) \), the function \( \phi(||e||_p) \) defined in (26) and its partial derivative \( \phi_d \) with respect to \( ||e||_p^2 \) satisfy

\[
\begin{align*}
(1) & \quad 2\phi_d \cdot (||e||_p^2 - c) - \phi > 0 \text{ for } \zeta < ||e||_p^2 < \varepsilon^2 \\
(2) & \quad 2\phi_d \cdot (||e||_p^2 - c) - \phi \leq 0 \text{ for } ||e||_p^2 \leq \zeta
\end{align*}
\]

with \( \zeta \triangleq \frac{-\varepsilon^2 + \sqrt{\varepsilon^4 + 8c\varepsilon^2}}{2} \).

The proof of Lemma 3 can be seen in Appendix A.2.

The control performance and the closed-loop stability by using the robust adaptive controller are summarized in the following theorem.

Theorem 2. Given the reference PWA system (4) and the predefined performance function (10), let the PWA system (3) with known regions \( \Omega_i, i \in I \) and unknown subsystem parameters \( A_i, B_i, f_i, i \in I \) be controlled by the feedback controller (8) with the adaptation laws (54). Let the initial state of \( e \) satisfy \( ||e(t_0)||_p < \varepsilon(t_0) \). The closed-loop system is stable and the state tracking error \( e(t) \) satisfies the prescribed performance guarantees (11) if the time constant \( h \) in (14) satisfies

\[
h < \frac{1}{2} \min_{i \in I} \frac{\lambda_{\min}(Q_i)}{\lambda_{\max}(P_i)}, \quad \max_{i \in I} \frac{\lambda_{\max}(P_i) \bar{d}}{\sqrt{\lambda_{\min}(Q_i) - 2h \lambda_{\max}(P_i)}} < \frac{g}{\bar{h}}, \tag{56}
\]

and if the switching signal of the controlled PWA system obeys the dwell time constraint \( \tau_D \) in (16).

Proof. We propose the same Lyapunov function as (29). The stability analysis can also be divided into two phases as the one in Theorem 1.

phase 1: \( t \in [t_{k-1}, t_k), k \in \mathbb{N}^+ \)

Following the same steps from (30) to (35) as in Theorem 1, we have

\[
V = -\phi_d e^T (A_{mi}^T P_i + P_i A_{mi}) e + \phi_d (e^T P_i d + d^T P_i e) + \frac{\partial \phi}{\partial e} \dot{e} + 2\phi_d (\text{tr}(\bar{K}_{x_i}^T M_i F_{x_i}) + \text{tr}(K_{x_i}^T M_i F_{x_i}) + \bar{K}_{f_i}^T M_i F_{f_i})). \tag{57}
\]

Since \( M_i \) is diagonal, we have

\[
\phi_d (\text{tr}(\bar{K}_{x_i}^T M_i F_{x_i}) + \text{tr}(\bar{K}_n^T M_i F_{n_i}) + \bar{K}_{f_i}^T M_i F_{f_i})) = \phi_d \left( \sum_{j=1}^{p} \sum_{i=1}^{n_i} m_{i}^{(j)} \bar{K}_{x_i}^T f_{x_i}^{(j)} + \sum_{j=1}^{p} \sum_{i=1}^{n_i} m_{i}^{(j)} \bar{K}_{r_i}^T f_{r_i}^{(j)} + \sum_{j=1}^{p} m_{i}^{(j)} \bar{K}_{f_i}^T f_{f_i}^{(j)} \right) \tag{58}
\]

with \( \bar{K}_{x_i} = [\bar{K}_{x_i}^{(0)}], \bar{K}_n = [\bar{K}_n^{(0)}], \bar{K}_{f_i} = [\bar{K}_{f_i}^{(0)}], F_{x_i} = [f_{x_i}^{(0)}], F_{r_i} = [f_{r_i}^{(0)}], \) and \( F_{f_i} = [f_{f_i}^{(0)}] \). It can be verified that \( \bar{K}_{x_i}^T f_{x_i}^{(j)} \leq 0, \bar{K}_n^T f_{r_i}^{(j)} \leq 0 \) and \( \bar{K}_{f_i}^T f_{f_i}^{(j)} \leq 0 \), which together with the fact that \( m_{i}^{(j)} > 0, i \in I, j = 1, \ldots, p \) leads to

\[
V \leq -\phi_d e^T (A_{mi}^T P_i + P_i A_{mi}) e + \frac{\partial \phi}{\partial e} \dot{e} + \phi_d (e^T P_i d + d^T P_i e). \tag{59}
\]

\[
\begin{align*}
\text{for linearsystemsappearing}
\]
Since $P_1$ is positive definite, it can be written as $P_1 = H_i H_i^T$ with $H_i$ being a nonsingular matrix. The inequality (59) can be further transformed as

$$\dot{V} \leq -\phi_d e^T(A_{m_i}^T P_i + P_i \Lambda_{m_i}) e + \frac{\partial \phi}{\partial e} \dot{e} + 2 \phi_d \dot{e}^T H_i H_i^T d$$

$$\leq -\phi_d e^T(Q_i + P_i) e + \frac{\partial \phi}{\partial e} \dot{e} + \phi_d (e^T H_i H_i^T e + d^T H_i H_i^T d)$$

$$= -\phi_d e^T Q_i e + \frac{\partial \phi}{\partial e} \dot{e} + \phi_d d^T H_i H_i^T d$$

$$\leq -\phi_d \|e\|^2 Q_i + \phi_d d^T H_i H_i^T d$$

$$\leq -\phi_d \|e\|^2 \kappa_i + \phi_d \lambda_{\text{max}}(P_i) \zeta^2,$$

where $\kappa_i \triangleq \lambda_{\text{min}}(Q_i) - 2 \lambda_{\text{max}}(P_i)$. For $P_i, Q_i,$ and $h$ satisfying the condition (56), we have $\kappa_i > 0$. Further analysis can be divided into two cases: $\|e\|^2 > \zeta_i$ and $\|e\|^2 \leq \zeta_i$, where

$$\zeta_i = \frac{-e^2 + \sqrt{e^4 + 8e^2 \zeta_i}}{2}, \quad i \in I,$$

with $\zeta_i \triangleq \frac{\lambda_{\text{max}}(P_i)}{\kappa_i}$. From (56) we obtain

$$e(t)^2 \geq \frac{\zeta_i^2}{\lambda_{\text{min}}(Q_i)} = \frac{\lambda_{\text{max}}(P_i)}{\kappa_i} \implies \|e\|^2 \geq c_i,$$

which further leads to

$$\zeta_i < \frac{-e^2 + \sqrt{e^4 + 8e^2 \cdot e^2}}{2} = e^2.$$

**Case 1** $\|e\|^2 > \zeta_i$: invoking Lemma 3, inequality (60) can be further derived as

$$\dot{V} \leq -\frac{\kappa_i \phi_d}{\lambda_{\text{max}}(P_i)} \left(\|e\|^2 - \frac{\lambda_{\text{max}}^2(P_i)}{\kappa_i} \zeta^2\right) = -\frac{\kappa_i}{2 \lambda_{\text{max}}(P_i)} \phi < 0.$$

**Case 2** $\|e\|^2 \leq \zeta_i$: defining $\kappa \triangleq \min_{i \in I} \{\kappa_i\}$, $\alpha = \max_{i \in I} \lambda_{\text{max}}(P_i)$ and considering the property that $2 \phi_d(\|e\|^2) \|e\|^2 - \phi > 0$, we have

$$\dot{V} \leq -\frac{\kappa}{2 \alpha} \phi + \phi_d \dot{a}^2 = -\frac{\kappa}{2 \alpha} (\phi + V_\theta) + \frac{\kappa}{2 \alpha} V_\theta + \phi_d \dot{a}^2 \leq -\frac{\kappa}{2 \alpha} V + \frac{\kappa}{2 \alpha} V_\theta + \phi_{d\text{max}} \dot{a}^2,$$

with $\phi_{d\text{max}} = \max_{\|e\|^2 \leq \zeta} \phi_d(\|e\|^2) = \phi_d(\max_\zeta e) \in \mathcal{L}_\infty$ for $\zeta = \sum_{i=1}^i \chi_i \zeta_i$. $V_\theta$ is defined in (29). $\bar{K}_s, \bar{K}_n, \bar{K}_\beta$ are bounded due to the utilization of the projection, which leads to $V_\theta \in \mathcal{L}_\infty$. Suppose $\overline{V_\theta}$ to be the maximum of $V_\theta$ and let the positive number $B \in \mathbb{R}^+$ be defined as

$$B \triangleq \overline{V_\theta} + \frac{2 \phi_{d\text{max}}}{\kappa}.$$

For $V \leq B$, $V$ may increase. For $V > B$, we have $V < 0$ and therefore, $V$ is decreasing. Combining Case 1 and Case 2, we know that $V$ is bounded for the interval $[t_{k-1}, t_k)$.

**phase 2:** jump at switch instant $t_k$, $k \in \mathbb{N}^+$ Following the same steps as shown in Theorem 1 and we have $V(t_k) \leq V(t_{k-1}).$

Based on the analysis of phase 1 and phase 2, we can conclude that

$$V(t) \leq \max\{V(t_0), B\}, \forall t \in [t_0, \infty),$$

from which we obtain $\phi, \phi_d \in \mathcal{L}_\infty$. The projection leads to $\bar{K}_s, \bar{K}_n, \bar{K}_\beta \in \mathcal{L}_\infty$, which further leads to $K_{s'i}, K_{n'i}, K_{\beta'i} \in \mathcal{L}_\infty$. Besides, $\|e(t)\|_p < c(t) < \rho(t)$ holds for $\forall t \in [t_0, \infty)$. The prescribed performance guarantee (11) is satisfied.

With similar steps in the proof of Lemma 2, one can prove the stability of the reference system with (55), so we have $x_m \in \mathcal{L}_\infty$. This leads to $x \in \mathcal{L}_\infty$, which together with $r, \phi_d \in \mathcal{L}_\infty$ implies $K_{s'i}, K_{n'i}, K_{\beta'i} \in \mathcal{L}_\infty$.  

Remark 7. The leakage-based robust MRAC approach for switched linear systems\textsuperscript{13} obtains the boundedness of the Lyapunov function \( V \) by formulating the inequality \( V \leq -\alpha V + \beta \), where \( \alpha > 0 \) and \( \beta \) is a disturbance-related term. This, however, does not apply to our approach, because the disturbance-related term in our case has a time-varying coefficient \( \phi_d \) (see the term \( \phi_d \lambda_{\text{max}}(P)\overline{d}^2 \) in (60)). The boundedness of \( \phi_d \) cannot be concluded without proving the boundedness of \( V \), while the boundedness of \( V \) requires \( \phi_d \lambda_{\text{max}}(P)\overline{d}^2 \) to be bounded. This potential circular reasoning constitutes one of the main technical challenges of the robust modification. Our solution concept is employing the property of \( \phi \) shown in Lemma 3 to discuss the stability in two separate cases. When \( \| \epsilon(t) \|_F > \zeta \), \( V \) may increase with \( \phi_d \) and \( V \) upper bounded. \( V \) is strictly decreasing if \( \| \epsilon(t) \|_F < \zeta \) for \( \zeta = \sum_{i=1}^{14} \zeta_i \).

Remark 8. In work about set-theoretic MRAC by Arabi and Yucelen,\textsuperscript{27,28,30} disturbances flow into the system through the same input matrix as the control signal. The fault-tolerant set-theoretic MRAC approach proposed by Xiao and Dong\textsuperscript{29} also assumes the actuator fault and external disturbances to be matched, that is, they can be compensated by designing additive terms in the control signal. Compared with these works, a distinctive feature of our approach is that the disturbance term \( d \) is also allowed to be unmatched.

Remark 9. According to (16), the length of the dwell time is governed by \( \sqrt{\mu} \), the reset map of the auxiliary performance signal \( \epsilon(t) \) (see (15)). By reducing \( \sqrt{\mu} \), a less-conservative dwell time constraint can be obtained. In both the adaptive controller (27) and the robust adaptive controller (54), the reset map is defined with \( \mu = \max_{i \in I} \frac{\lambda_{\text{max}}(P_i)}{\lambda_{\text{min}}(P_i)} \), which indicates the maximal possible jump of \( \| \epsilon(t) \|_F^2 \) at each switching instant. Since the current activated subsystem is known (supposed to be \( p \)), the maximal jump of \( \| \epsilon(t) \|_F^2 \) at next switching instant is \( \mu_p = \max_{i \in I} \frac{\lambda_{\text{max}}(P_i)}{\lambda_{\text{min}}(P_i)} \leq \mu \). For the case where both current subsystem (supposed to be \( p \)) and the next subsystem to be switched on (supposed to be \( q \)) are known in advance, the maximal jump of \( \| \epsilon(t) \|_F^2 \) at this switching instant is \( \mu_{pq} = \frac{\lambda_{\text{max}}(P_p)}{\lambda_{\text{min}}(P_q)} \leq \mu \). Adopting \( \sqrt{\mu_p} \) or \( \sqrt{\mu_{pq}} \) instead of \( \sqrt{\mu} \) as the reset map of \( \epsilon \) yields a less conservative dwell time constraint. The corresponding stability properties of the reference system (4) and the closed-loop system are still retained. Such dwell time constraints are known as mode-dependent dwell time\textsuperscript{44} (when \( \mu_p \) is adopted) and mode-mode-dependent dwell time\textsuperscript{13} (when \( \mu_{pq} \) is utilized).

4 | NUMERICAL VALIDATION

In this section, the proposed MRAC approach is validated through a numerical example modified based on the example in the literature,\textsuperscript{11} a mass-spring-damper system, which is shown in Figure 2. The displacement of the mass is denoted by \( p \) and the force operated on the mass is \( F \), respectively. The mass is \( m = 1 \) kg and the damping factor is \( d = 1 \) N s/m. The mass is connected to the static wall with the spring \( c_x \) and the damper \( d \). For \( |p| \leq 0.1 \) m, the spring factor \( c_x = 10 \) N/m. If it is extended beyond \( 0.1 \) m, the spring factor \( c_x \) is reduced to \( c_x = 1 \) N/m. The spring \( c_y = 90 \) N/m is a floating spring with one end connected to the wall. The distance between the mass and the tip of the spring \( c_y \) is \( \gamma \) when \( c_x \) is in its resting position. The system is equivalent to a classical mass-spring-damper system with the spring exhibiting a PWA stiffness characteristics:

\[
F_c(p) = \begin{cases} 
  c_1 = 10 \text{ N/m,} & \text{if } |p| \leq 1 \text{ m} \\
  c_2 = 1 \text{ N/m,} & \text{if } p > 1 \text{ m} \\
  c_3 = 100 \text{ N/m,} & \text{if } p < -1 \text{ m}
\end{cases}
\]  

(68)

FIGURE 2 The mass-spring-damper system
Let the state $x = [x_1, x_2]^T = [p, \dot{p}]^T$ and the input $u = F$. The system dynamics can be described by a PWA system in form of

$$\dot{x} = \begin{bmatrix} 0 & 1 \\ -\frac{c_i}{m} & -\frac{d}{m} \end{bmatrix} x + \begin{bmatrix} 0 \\ \frac{1}{m} \end{bmatrix} u + \begin{bmatrix} 0 \end{bmatrix}, \quad i \in \{1, 2, 3\},$$  

(69)

with $f_1 = 0, f_2 = (c_2 - c_1)/m, f_3 = (c_1 - c_3)/m$. The region partitions are given as

$$\Omega_1 = \{ x \in \mathbb{R}^2 | |x_1| \leq 1 \}, \quad \Omega_2 = \{ x \in \mathbb{R}^2 | x_1 > 1 \}, \quad \Omega_3 = \{ x \in \mathbb{R}^2 | x_1 < -1 \}.$$

The reference system is a PWA system with the following subsystem matrices

$$A_{m1} = \begin{bmatrix} 0 & 1 \\ -25 & -10 \end{bmatrix}, \quad B_{m1} = \begin{bmatrix} 0 \\ 25 \end{bmatrix}, \quad f_{m1} = \begin{bmatrix} 0 \end{bmatrix},$$  

(70)

$$A_{m2} = \begin{bmatrix} 0 & 1 \\ -16 & -8 \end{bmatrix}, \quad B_{m2} = \begin{bmatrix} 0 \\ 16 \end{bmatrix}, \quad f_{m2} = \begin{bmatrix} 0 \\ 5 \end{bmatrix},$$  

(71)

$$A_{m3} = \begin{bmatrix} 0 & 1 \\ -49 & -14 \end{bmatrix}, \quad B_{m3} = \begin{bmatrix} 0 \\ 49 \end{bmatrix}, \quad f_{m3} = \begin{bmatrix} 0 \\ -10 \end{bmatrix}. $$  

(72)

**Ideal case:**

The adaptive controller in the ideal case with the adaptation laws (27) is tested. The $P_i$ and $Q_i$ matrices satisfying (5) are chosen as

$$P_1 = \begin{bmatrix} 140 & 2 \\ 2 & 5.2 \end{bmatrix}, \quad P_2 = \begin{bmatrix} 121.25 & 3.125 \\ 3.125 & 6.64 \end{bmatrix}, \quad P_3 = \begin{bmatrix} 182.857 & 1.02 \\ 1.02 & 3.644 \end{bmatrix}, \quad Q_i = \begin{bmatrix} 100 & 10 \\ 10 & 100 \end{bmatrix} \quad \text{for } i \in \{1, 2, 3\},$$  

(73)

which gives $\sqrt{\mu} = 7.1$. The scaling factors are $\Gamma_{xi}, \Gamma_{ti}, \Gamma_{i} = 0.1$. The performance function is designed with $\rho_0 = 10, \rho_{\infty} = 1.5, l = 0.02$. We choose $e(t_0) = 9, h = 0.12$, and $g = 0.01$ such that the condition (28) and further conditions stated in Lemma 1 hold. Let the initial values of the reference system and the controlled PWA system be $[2, 0]^T$. The initial values of the estimated controller gains are specified as $K_{r1}(t_0) = 0.5K_{x1}^*, K_{r2}(t_0) = 0.5K_{x2}^*, K_{r3}(t_0) = 0.5K_{x3}^*, l \in \{1, 2, 3\}$. We use the following input signal $r$

$$r(t) = \begin{cases} 2 + 0.5 \sin(0.2 \pi t), & \text{for } 0 \leq t < 25 s \\ -0.08t + 2.8, & \text{for } 25 \leq t < 50 s \\ -2 + 0.8 \sin(2t - 100 - \pi), & \text{for } 50 \leq t < 75 s \\ 0, & \text{for } t \geq 75 s \end{cases}. $$  

(74)

The state-space trajectories of the reference system and the closed-loop system in the time interval $[23 s, 52 s]$ are displayed in Figure 3A with black dashed and red solid lines, respectively. The light blue, light green, and light yellow regions refer to $\Omega_2, \Omega_1$, and $\Omega_3$. The ellipses centered at the state trajectory of the reference system represent $\|e(t)\|_P = \varepsilon(t)$ and indicate the bounds of the state of the closed-loop PWA system. The colors of the ellipses distinguish $\|e(t)\|_{P_1}, \|e(t)\|_{P_2}$, and $\|e(t)\|_{P_3}$. We can observe that the state of the closed-loop system always stays within the auxiliary performance bound. For comparison, the state trajectory of the closed-loop system by using MRAC approach is displayed with blue solid lines in Figure 3B, from which the violation of the performance bound can be observed.

According to Lemma 1, the dwell time of the closed-loop system should satisfy $\tau_D > 24 s$. The small window of Figure 4A shows the mode information of the closed-loop system. We can observe that the dwell time constraint is satisfied. In Figure 4A, the prescribed performance bound $\rho(t)$, the auxiliary performance bound $e(t)$ and the weighted norm of the state tracking error $\|e(t)\|_P$ are displayed with the black dashed line, the blue solid line, and the red solid line, respectively. We can see that $\|e(t)\|_P < e(t) < \rho(t)$. The weighted norm of the state tracking error $\|e(t)\|_P$ and the auxiliary
**FIGURE 3**  Closed-loop system’s trajectory by applying proposed method and the classical model reference adaptive control (MRAC) approach. (A) Proposed approach; (B) Classical MRAC approach.

**FIGURE 4**  Tracking performance of the adaptive controller with adaptation laws (27). (A) State tracking error and performance bound. (B) Lyapunov function.

Performance bound $e(t)$ jump at the switching instants, where the relation $\|e(t)\|_P < c(t)$ is still satisfied. This guarantees the potential function $\phi(t)$ to be valid and the control objective (11) to be fulfilled.

The Lyapunov function $V$ is displayed in Figure 4B. We observe that the Lyapunov function $V$ is nonincreasing, also at the switching instants. This validates the theoretical statement given in Theorem 1.

**Robust case:**

Now we test the performance of the robust adaptive controller with the adaptation laws (54). The PWA system is subject to an unmatched disturbance term $d = [0.036 \cos(0.7t) + 0.072 \sin(0.2t) + 0.018 \sin(t), 0]^T$. The $P_i, Q_i$ matrices satisfying (55) are chosen as

$$P_1 = \begin{bmatrix} 0.7627 & 0.0353 \\ 0.0353 & 0.0458 \end{bmatrix}, P_2 = \begin{bmatrix} 0.6140 & 0.0504 \\ 0.0504 & 0.0601 \end{bmatrix}, P_3 = \begin{bmatrix} 0.7932 & 0.0183 \\ 0.0183 & 0.0236 \end{bmatrix}, Q_1 = Q_2 = \begin{bmatrix} 1 & 0.7 \\ 0.7 & 0.8 \end{bmatrix}, Q_3 = \begin{bmatrix} 1 & 0.6 \\ 0.6 & 0.6 \end{bmatrix}.$$  

(75)

which gives $\sqrt{\mu} = 5.86$. The scaling factors are $\Gamma_{xi}, \Gamma_{yi}, \Gamma_{fi} = 1$. The performance function is designed with $\rho_0 = 10, \rho_\infty = 3.2, l = 0.02$. The auxiliary performance signal is designed with $c(t_0) = 9, h = 0.08$ and $g = 0.04$ to fulfill the conditions in Lemma 1 and Theorem 2. The dwell time of the closed-loop system must satisfy $\tau_D > 67.7$ s. Let the initial values of the reference system and the controlled PWA system be $[0, 0]^T$. The initial values of the estimated controller gains are specified as $K_{xi}(t_0) = 0.5K_{xi}^*, K_{yi}(t_0) = 0.5K_{yi}^*, K_{fi}(t_0) = 0.5K_{fi}^*, i \in \{1, 2, 3\}$. The input signal $r$ is

$$r(t) = \begin{cases} 0, & \text{for } 0 \leq t < 70 \text{ s} + \frac{KT}{2} \\ 2, & \text{for } 70 \text{ s} + KT \leq t < 140 \text{ s} + KT \\ -2, & \text{for } 210 \text{ s} + KT \leq t < 280 \text{ s} + KT \end{cases}.$$  

(76)

with $K \in \mathbb{N}$ and $T = 280$ s.
FIGURE 5 Tracking performance of the adaptive controller with adaptation laws (54). (A) State tracking error and performance bound; (B) Lyapunov function; (C) state $x_1$; (D) state $x_2$

The small window of Figure 5A shows the switching information of the closed-loop system. It can be observed that the dwell time constraint $\tau_D > 67.7$ s is satisfied. In Figure 5A, the black dashed line, the blue solid line, and the red solid line represent the prescribed performance bound $\rho(t)$, the auxiliary performance bound $\varphi(t)$ and the weighted norm of the state tracking error $\|e(t)\|_P$, respectively. It can be seen that $\|e(t)\|_P < e(t) < \rho(t)$ holds. The element-wise tracking performance of the closed-loop system is displayed in Figure 5C,D, where the black dashed lines represent the reference signals and the red solid lines represent the state signals. Despite the existence of the disturbance, the closed-loop state tracks the one of the reference system with the prescribed performance.

The Lyapunov function $V$ is shown in Figure 5B. According to the proof of Theorem 2, $V$ may increase when $\|e\|_P \leq \zeta$. In Figure 5B, $V$ is shown in red for $\|e\|_P > \zeta$ and in blue for $\|e\|_P \leq \zeta$. We observe that $V$ is decreasing for $\|e\|_P > \zeta$ whereas it may increase (as shown in the small window) but remain bounded for $\|e\|_P \leq \zeta$. This validates the theoretical result given in Theorem 2.

5 | CONCLUSION

In this paper, we explored the MRAC approach for PWA systems with time-varying performance guarantees on the state tracking error. The proposed method is based on barrier Lyapunov functions. To solve the barrier transgression problem caused by the discontinuity of the weighted Euclidean norm of the state tracking error, we introduce an auxiliary performance bound with a state reset map at switching instants to construct the barrier Lyapunov function. This auxiliary performance bound resides within the user-defined performance bound if some dwell time constraints are satisfied. The Lyapunov function is nonincreasing at and in between the switching instants, which ensures the weighted Euclidean norm of the state tracking error to fulfill the performance guarantee. To enhance the robustness of the closed-loop system against unmatched disturbances, the projection-based robust modification of the proposed method is presented. Future work may include the extension to indirect MRAC approach and stability analysis when sliding mode on switching hyperplanes occurs. The current approach requires a proper initialization such that the error metric
locates within the performance bound at the initial instant. Extending this approach to a global setting is also of interest.

CONFLICT OF INTEREST
The authors declare no potential conflict of interests.

DATA AVAILABILITY STATEMENT
Data sharing not applicable to this article as no datasets were generated or analyzed during the current study

ORCID
Tong Liu https://orcid.org/0000-0001-7422-4312

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APPENDIX. PROOFS

A.1 Proof of Lemma 2
Consider the Lyapunov function $V_m = x_m^T \left( \sum_{i=1}^{s} \chi_i P_i \right) x_m$ for the homogeneous part of (4). The increment of $V_m$ at each switching instant satisfies $V_m(t_k) \leq \mu V_m(t_{k-1})$. In the interval $t \in [t_{k-1}, t_k)$, $k \in \mathbb{N}^+$, we have $\dot{V}_m \leq -a_m V_m$ with

$$a_m = \min_{i \in T} \frac{\lambda_{\min}(Q_i)}{\lambda_{\max}(P_i)}$$  \hspace{1cm} (A1)
If the switching satisfies $t_k - t_{k-1} > \frac{\ln \mu}{\alpha_m}, \forall k \in \mathbb{N}^+$, the homogeneous system $\dot{x}_m = A_m x_m$ is exponentially stable and the stability of the reference system (4) can be concluded for bounded input $r$. From (28) we have $h - l < h < \frac{1}{2} \alpha_m$. This together with $\mu > 1$ leads to

$$\tau_D > \frac{2}{\alpha_m} \ln \frac{\sqrt{\mu \rho_{\infty} - \frac{g}{h} \sqrt{\mu}}}{\rho_{\infty} - \frac{g}{h} \sqrt{\mu}} > \frac{2}{\alpha_m} \ln \frac{\sqrt{\mu (\rho_{\infty} - \frac{g}{h})}}{\rho_{\infty} - \frac{g}{h}} = \frac{\ln \mu}{\alpha_m}. \quad (A2)$$

So this tells that the reference system is stable and $x_m \in \mathcal{L}_\infty$ if the dwell time constraint $\tau_D$ in (16) is satisfied.

### A.2 Proof of Lemma 3

**Proof.** From the definition of $\phi$ given in (26) we have

$$2\phi_d \cdot (\|e\|^2_p - c) - \phi = \frac{\|e\|^4_p + e^2 \|e\|^2_p - 2ce^2}{(e^2 - \|e\|^2_p)^2}. \quad (A3)$$

The denominator of (A3) is positive and the sign of $2\phi_d \cdot (\|e\|^2_p - c) - \phi$ is determined by the numerator, which can be viewed as a quadratic function $f(z) = z^2 + c^2 z - 2ce^2$ with $z = \|e\|^2_p$. We have $f(z) \leq 0$ for $z \in \left[\frac{-c^2 - \sqrt{c^4 + 8c^2 e^2}}{2}, \frac{-c^2 + \sqrt{c^4 + 8c^2 e^2}}{2}\right]$ and $f(z) > 0$ otherwise. Since $\phi, \phi_d$ are defined over $\|e\|^2_p \in [0, e^2]$ and $\frac{-c^2 - \sqrt{c^4 + 8c^2 e^2}}{2} < 0$, it can be obtained that $2\phi_d \cdot (\|e\|^2_p - c) - \phi > 0$ for $\zeta < \|e\|^2_p < e^2$ and $2\phi_d \cdot (\|e\|^2_p - c) - \phi \leq 0$ for $\|e\|^2_p \leq \zeta$ with $\zeta = \frac{-c^2 + \sqrt{c^4 + 8c^2 e^2}}{2}$. \qed