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# $L_2$ and BIBO stability of systems with variable delays

Catherine Bonnet\* and Jonathan R. Partington†

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## Abstract

This paper considers  $L_2$  and BIBO stability and stabilization issues for systems with time-varying delays which can be of retarded or neutral type. An important role is played by a nominal system with fixed delays which are close to the time-varying ones. Under stability or stabilizability conditions of this nominal system, sufficient conditions are given in order to ensure similar properties for the system with time-varying delays.

**Keywords:** neutral delay systems, time-varying delays,  $L_2$ -stability, *BIBO*-stability

**In memory of Ruth Curtain.**

## 1 Introduction and notation

There has been a growing interest in systems with time-varying delays in recent years, in particular due to the study of large-scale networked systems where delays may have to be considered to be time-varying for better accuracy of the model. The presence of time-varying delays induces complex behaviours which have been pointed out and studied by many authors (see e.g. [14, 15, 21] the monograph [7] and the references therein). Although the case of autonomous systems has been widely studied, much less work has been dedicated to such systems submitted to arbitrary external inputs. Several studies, e.g. [2], consider the  $L^2$ -input-output norm of the time-varying delay operator, however to the best of our knowledge, no study has been made of the input–output stability of a standard feedback scheme involving a system with time-varying delays. We can find in [19] an input–output setting for determining rate-based flow controllers for communication networks in the presence of time-varying delays; however, an  $H_\infty$  optimization problem is considered here which deals with several types of perturbations acting on the state-space system including time-varying coefficients and time-varying delays and this renders the comparison with our work inappropriate. Several papers (for example [8, 9, 12, 20]) mention an input–output approach for systems with time-varying delays; however the input–output framework is not considered for the given system but is introduced once an initially autonomous system with time-varying delays has been transformed into a system with external input by means of the introduction of additional variables given in terms of the states.

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\*Inria Saclay - Ile-de-France, L2S-CentraleSupélec, 3 rue Joliot Curie 91192 Gif-sur-Yvette cedex, France  
Catherine.Bonnet@inria.fr

†School of Mathematics, University of Leeds, Leeds LS2 9JT, U.K. J.R.Partington@leeds.ac.uk

In our setting, the classical condition on the boundedness of the derivative of the time-varying delay by a constant strictly lesser than one is not necessary. Note that this is also the case in [22] where  $H_\infty$  state-feedback control of systems time-varying input delays is considered. Physical considerations (such as the order of events being preserved in the presence of a time-varying delay) may impose that for a time-varying delay  $\tau(t)$  the function  $t \mapsto t - \tau(t)$  is strictly increasing, but since this only implies that the derivative of  $\tau$  is bounded by one, a relaxation of the classical condition of boundedness is of use (*moderately varying delays* were first considered in [10]).

We consider two versions of input–output stability: so-called  $H_\infty$ -stability (a finite gain when the signals are measured in terms of energy, that is,  $L_2$  norm), and BIBO stability (bounded inputs give bounded outputs). Retarded and neutral type systems with pointwise or distributed delays are studied here. Note that in [8], the input-output approach to neutral systems has been presented, but the results were confined to slowly-varying delays.

The very general framework is introduced in Section 2, and the stability analysis is given in Section 3. Then, a discussion of feedback stabilization is given in Section 4. Finally, numerical examples appear in Section 5. The results we derive yield very explicit estimates for stability margins, as will be seen by considering the examples we present.

## Notation

$H_\infty$ , or  $H_\infty(\mathbb{C}_+)$ , denotes the space of bounded analytic functions on the complex right half-plane  $\mathbb{C}_+$ , with the supremum norm  $\|F\|_\infty = \sup_{s \in \mathbb{C}_+} |F(s)|$ . The  $H^\infty$  norm gives an explicit expression for the  $L_2$  input/output gain of a stable system.

In addition,  $\mathcal{A}$  denotes the space of distributions of the form

$$g(t) = g_a(t) + \sum_{i=0}^{\infty} g_i \delta(t - t_i),$$

where  $g_a \in L_1(0, \infty)$  and  $\sum_0^\infty |g_i| < \infty$ ; here,  $\delta(t - t_i)$  denotes a delay Dirac distribution,  $0 = t_0 < t_1, t_2, t_3 \dots$  the  $t_k$  being distinct. This is equipped with the norm

$$\|g\|_{\mathcal{A}} = \int_0^\infty |g_a(t)| dt + \sum_{i=0}^{\infty} |g_i|,$$

which gives an expression for the  $L_\infty$  input/output gain of a stable system. Then  $\hat{\mathcal{A}}$  is the space of Laplace transforms of functions in  $\mathcal{A}$ , which is a subalgebra of  $H^\infty$ .

## 2 The class of systems studied

In this paper we shall consider the variable-delay input–output system

$$\begin{aligned} \dot{x}(t) + \sum_{\ell=1}^L A_{-\ell} \dot{x}(t - \gamma_\ell(t)) &= Ax(t) + \sum_{j=1}^J A_j x(t - \tau_j(t)) + \int_0^{\delta(t)} h(\theta) Ix(t - \theta) d\theta \\ &+ Bu(t) + \sum_{k=1}^K B_k u(t - \sigma_k(t)) d\theta, \quad (t > 0), \end{aligned} \quad (1)$$

where  $x(t) \in \mathbb{C}^n$  denotes the state and  $u(t) \in \mathbb{C}^p$  the input, both assumed zero for  $t \leq 0$ , the matrices  $A$ ,  $A_{-\ell}$ ,  $A_j$ ,  $B$ ,  $B_k$  and  $I$  (identity matrix) have the appropriate sizes, the function  $h(\theta)$  is of polynomial type and the delays  $\gamma_\ell(t)$ ,  $\tau_j(t)$ ,  $\sigma_k(t)$  and  $\delta(t)$  are positive (to ensure stability, further hypotheses will be required later).

Were the delays constant (say,  $\gamma_\ell(t) = H_\ell$ ,  $\tau_j(t) = h_j$ ,  $\delta(t) = D$ , and  $\sigma_k(t) = T_k$  for each  $j$ ,  $k$  and  $\ell$ ), then this system would have a transfer function given by

$$G(s) = \left( sI + \sum_{\ell=1}^L A_{-\ell} s e^{-H_\ell s} - A - \sum_{j=1}^J A_j e^{-h_j s} - \int_0^D h(\theta) e^{-s\theta} d\theta \right)^{-1} \left( B + \sum_{k=1}^K B_k e^{-T_k s} \right),$$

and  $H_\infty$  stability (bounded  $L_2$  gain) would correspond to  $G$  being analytic and bounded in the right half-plane  $\mathbb{C}_+$ .

Let us mention that the considered distributed delay will give rise only to polynomial and exponential terms in the transfer function allowing one to divide the considered class of systems into retarded and neutral type classes as in the generic (distributed delay free) case.

In [9], Fridman and Gil' considered an autonomous system with variable delays, given by

$$\dot{x}(t) = \sum_{j=1}^{\ell} A_j x(t - \tau_j(t)), \quad (t > 0),$$

with initial conditions specified on an interval  $[-\eta, 0]$ . They analysed its asymptotic stability using a frequency-domain approach.

It is our aim to analyse the  $H_\infty$  and BIBO stability of the system (1), using methods similar to those of [9] in a far more general context, assuming stability of the nominal system where the delays are fixed.

Consider the *nominal system* (as always, with zero initial conditions),

$$\dot{v}(t) + \sum_{\ell=1}^L A_{-\ell} \dot{v}(t - H_\ell) = Av(t) + \sum_{j=1}^J A_j v(t - h_j) + \int_0^D h(\theta) Iv(t - \theta) d\theta + Bu(t) + \sum_{k=1}^K B_k u(t - T_k), \quad (2)$$

for  $t > 0$ ,

Throughout the rest of the paper, we make the following hypothesis.

**Hypothesis (H):** we assume that  $\sum_{\ell=1}^L \|A_{-\ell}\| < 1$ .

If the  $L_2$  gain from  $u$  to  $v$  is finite we have that  $\dot{v}(t) + \sum_{\ell=1}^L A_{-\ell} \dot{v}(t - H_\ell)$  is in  $L_\infty$  and there exists a constant  $K$  such that

$$\left\| \dot{v}(t) + \sum_{\ell=1}^L A_{-\ell} \dot{v}(t - H_\ell) \right\|_\infty \leq K \|u\|_\infty.$$

From this inequality and the fact that  $\|\dot{v}(t - H)\|_\infty = \|\dot{v}(t)\|_\infty$ , we get that

$$\left(1 - \sum_{\ell=1}^L \|A_{-\ell}\|\right) \|\dot{v}\| \leq K \|u\|_\infty,$$

which means, as  $\sum_{\ell=1}^L \|A_{-\ell}\| < 1$ , that we also have a finite  $L_\infty$  gain from  $u$  to  $\dot{v}$ .

If the  $L_2$  gain from  $u$  to  $v$  is finite we have that the associated transfer function  $G_{nom}$  is in  $H_\infty$ , its denominator being

$$\det(sI + \sum_{\ell=1}^L A_{-\ell} s e^{-H_\ell s} - A - \sum_{j=1}^J A_j e^{-h_j s} - \int_0^D h(\theta) I e^{-\theta s} d\theta)$$

We can easily deduce from this that  $sG(s)$  is also in  $H_\infty$  as there is no problem with properness and no problem with boundedness on the imaginary axis. This means that there is a finite  $L_2$  gain from  $u$  to  $\dot{v}$ .

We shall need to consider the system

$$\dot{z}(t) + \sum_{\ell=1}^L A_{-\ell} \dot{z}(t - H_\ell) = Az(t) + \sum_{j=1}^J A_j z(t - h_j) + \int_0^D h(\theta) Iz(t - \theta) d\theta + w(t), \quad (t > 0).$$

For the same reasons as above, if the  $L_2$ -gain (from  $w$  to  $z$ ) is finite, we also have a  $L_2$  finite gain from  $w$  to  $\dot{z}$  and if the  $L_\infty$ -gain (from  $w$  to  $z$ ) is finite we also have a finite  $L_\infty$  gain from  $w$  to  $\dot{z}$ .

Let us denote :

- $M_2^{nom}$  : the  $L_2$  gain from  $u$  to  $v$
- $M_\infty^{nom}$  : the  $L_\infty$  gain from  $u$  to  $v$
- $M_\infty^{nomd}$  : the  $L_\infty$  gain from  $u$  to  $\dot{v}$
- $M_2^{nomd}$  : the  $L_2$  gain from  $u$  to  $\dot{v}$
- $M_2$  : the  $L_2$  gain from  $w$  to  $z$
- $M_\infty$  : the  $L_\infty$  gains from  $w$  to  $z$
- $M_2^d$  : the  $L_2$  gain from  $w$  to  $\dot{z}$
- $M_\infty^d$  : the  $L_\infty$  gain from  $w$  to  $\dot{z}$

### 3 Stability analysis

Our standing assumptions, together with Hypothesis (H) are that

$$\begin{aligned} 0 &\leq H_\ell - \eta_\ell \leq \gamma_\ell(t) \leq H_\ell + \eta_\ell \\ 0 &\leq h_j - \mu_j \leq \tau_j(t) \leq h_j + \mu_j \\ 0 &\leq D - \epsilon \leq \delta(t) \leq D + \epsilon \\ 0 &\leq T_k - \nu_k \leq \sigma_k(t) \leq T_k + \nu_k \end{aligned}$$

for all  $t$  and for each  $j$ ,  $k$  and  $\ell$ , where  $\eta_\ell, \mu_j, \epsilon$ , and  $\nu_k$  are positive constants.

Writing  $y = x - v$  we have

$$\begin{aligned}
\dot{y}(t) + \sum_{\ell=1}^L A_{-\ell} \dot{y}(t - H_\ell) &= Ay(t) \\
&+ \sum_{j=1}^J A_j y(t - h_j) + \sum_{j=1}^J A_j [x(t - \tau_j(t)) - x(t - h_j)] \\
&+ \int_0^D h(\theta) Iy(t - \theta) d\theta + \int_D^{\delta(t)} h(\theta) Ix(t - \theta) d\theta \\
&+ \sum_{\ell=1}^L A_{-\ell} [\dot{x}(t - H_\ell) - \dot{x}(t - \gamma_\ell(t))] \\
&+ \sum_{k=1}^K B_k [u(t - \sigma_k(t)) - u(t - T_k)], \quad (t > 0).
\end{aligned}$$

We may write this as

$$\begin{aligned}
\dot{y}(t) + \sum_{\ell=1}^L A_{-\ell} \dot{y}(t - H_\ell) &= Ay(t) + \sum_{j=1}^J A_j y(t - h_j) + \int_0^D h(\theta) Iy(t - \theta) d\theta \\
&+ \sum_{j=1}^J A_j f_j(t) + \sum_{\ell=1}^L A_{-\ell} \tilde{f}_\ell(t) + \int_D^{\delta(t)} h(\theta) Ix(t - \theta) d\theta + \sum_{k=1}^K B_k g_k(t)
\end{aligned} \tag{3}$$

with

$$\begin{aligned}
f_j(t) &= x(t - \tau_j(t)) - x(t - h_j), \\
\tilde{f}_\ell(t) &= \dot{x}(t - H_\ell) - \dot{x}(t - \gamma_\ell(t)), \\
\text{and } g_k(t) &= u(t - \sigma_k(t)) - u(t - T_k).
\end{aligned}$$

We now need supplementary conditions to ensure that the functions  $\tilde{f}$ ,  $f_j$  and  $g_k$  lie in  $L_2(0, \infty)$  or  $L_\infty(0, \infty)$ .

### 3.1 The special case of retarded type systems

We begin with the case that all  $A_{-\ell} = 0$ , since the system is then more robust to perturbations. The equations under consideration are

$$\dot{x}(t) = Ax(t) + \sum_{j=1}^J A_j x(t - \tau_j(t)) + \int_0^{\delta(t)} h(\theta) Ix(t - \theta) d\theta + Bu(t) + \sum_{k=1}^K B_k u(t - \sigma_k(t)) \quad (t > 0), \tag{4}$$

$$\dot{v}(t) = Av(t) + \sum_{j=1}^J A_j v(t - h_j) + \int_0^D h(\theta) Iv(t - \theta) d\theta + Bu(t) + \sum_{k=1}^K B_k u(t - T_k), \quad (t > 0) \tag{5}$$

$$\dot{y}(t) = Ay(t) + \sum_{j=1}^J A_j y(t-h_j) + \int_0^D h(\theta) Iy(t-\theta) d\theta + \sum_{j=1}^J A_j f_j(t) + \int_D^{\delta(t)} h(\theta) Ix(t-\theta) d\theta + \sum_{k=1}^K B_k g_k(t), \quad (6)$$

and

$$\dot{z}(t) = Az(t) + \sum_{j=1}^J A_j z(t-h_j) + \int_0^D h(\theta) Iz(t-\theta) d\theta + w(t), \quad (t > 0). \quad (7)$$

**Theorem 3.1.** 1) Suppose that the system (5) is BIBO-stable.

If  $M_\infty^d \sum_{j=1}^\ell \mu_j \|A_j\| < 1$  and  $M_\infty \epsilon \|h\|_\infty \left( \sum_{j=1}^\ell M_\infty^d \mu_j \|A_j\| (1-M)^{-1} + 1 \right) < 1$ , then the system (4) is BIBO-stable.

2) Suppose that the system (5) is  $H_\infty$ -stable and that  $\dot{u} \in L_2$ .

If  $M = M_2^d \sum_{j=1}^\ell \mu_j \|A_j\| < 1$  and  $M_2 \epsilon \|h\|_\infty \left( \sum_{j=1}^\ell \mu_j \|A_j\| (1-M)^{-1} + 1 \right) < 1$ , then the system (4) is  $H_\infty$ -stable in the sense that there is a finite  $L^2$  gain between  $(u, \dot{u})$  and  $x$ .

*Proof.* 1) The basic calculation is as follows:

$$\begin{aligned} \|\dot{x}\|_\infty &\leq \|\dot{v}\|_\infty + \|\dot{y}\|_\infty \\ &\leq \|\dot{v}\|_\infty + M_\infty^d \left( \sum_{j=1}^\ell \|A_j\| \|f_j\|_\infty + \epsilon \|h\|_\infty \|x\|_\infty + \sum_{k=1}^m \|B_k\| \|g_k\|_\infty \right) \end{aligned}$$

and then we shall bound  $\|f_j\|_\infty$  in terms of  $\|\dot{x}\|_\infty$ .

We have

$$\|f_j\|_\infty = \sup_t \left\| \int_{t-\tau_j(t)}^{t-h_j} \dot{x}(s) ds \right\| \leq \mu_j \|\dot{x}\|_\infty$$

and

$$\|g_k\|_\infty = \sup_t \| [u(t - \sigma_k(t)) - u(t - T_k)] \| \leq 2\|u\|_\infty$$

So that, provided that  $M := M_\infty^d \sum_{j=1}^\ell \mu_j \|A_j\| < 1$ , we have

$$\|\dot{x}\|_\infty \leq \|\dot{v}\|_\infty + M \|\dot{x}\|_\infty + M_\infty^d \epsilon \|h\|_\infty \|x\|_\infty + M_\infty^d \sum_{k=1}^m 2 \|B_k\| \|u\|_\infty,$$

or

$$\|\dot{x}\|_\infty \leq (1-M)^{-1} \left( M_\infty^{nomd} \|u\|_\infty + M_\infty^d \epsilon \|h\|_\infty \|x\|_\infty + M_\infty^d \sum_{k=1}^m 2 \|B_k\| \|u\|_\infty \right),$$

Now  $x = v + y$  and so by (5) and (6) we have

$$\begin{aligned} \|x\|_\infty &\leq \|v\|_\infty + \|y\|_\infty \\ &\leq M_\infty^{nom} \|u\|_\infty + M_\infty \left( \sum_{j=1}^\ell \|A_j\| \|f_j\|_\infty + \epsilon \|h\|_\infty \|x\|_\infty + \sum_{k=1}^m \|B_k\| \|g_k\|_\infty \right) \\ &\leq M_\infty^{nom} \|u\|_\infty + M_\infty \left( \sum_{j=1}^\ell \mu_j \|A_j\| \|\dot{x}\|_\infty + \sum_{k=1}^m 2 \|B_k\| \|u\|_\infty + \epsilon \|h\|_\infty \|x\|_\infty \right) \end{aligned}$$

Let  $\tilde{M} := M_\infty \epsilon \|h\|_\infty \left( 1 + \sum_{j=1}^{\ell} \mu_j \|A_j\| \|M_\infty^d (1 - M)^{-1}\right)$ , we have

$$(1 - \tilde{M}) \|x\|_\infty \leq M_\infty^{nom} \|u\|_\infty + M_\infty \left( \sum_{j=1}^{\ell} \mu_j \|A_j\| (1 - M)^{-1} (M_\infty^{nomd} + M_\infty^d \sum_{k=1}^m 2 \|B_k\|) + \sum_{k=1}^m 2 \|B_k\| \right) \|u\|_\infty$$

which under the condition  $\tilde{M} < 1$  gives a finite  $L_\infty$  gain from  $u$  to  $x$ .

2) In the case of  $L_2$ -stability, we start with the same inequality as above. First, similarly to [9], we have, recalling that  $x(t) = \dot{x}(t) = 0$  for  $t \leq 0$ ,

$$\begin{aligned} \|f_j\|_2^2 &= \int_0^\infty \left\| \int_{t-\tau_j(t)}^{t-h_j} \dot{x}(s) ds \right\|^2 dt \leq \int_0^\infty \mu_j \int_{t-h_j-\mu_j}^{t-h_j} \|\dot{x}(s)\|^2 ds dt \\ &\leq \mu_j^2 \int_0^\infty \|\dot{x}(r)\|^2 dr = \mu_j^2 \|\dot{x}\|_2^2. \end{aligned}$$

Then, to bound  $\|g_k\|_2$  requires some restrictive conditions on  $u$ . With the condition that  $\dot{u} \in L_2$ , we get  $\|g_k\|_2 \leq \nu_k \|\dot{u}\|_2$  and the stability result obtained in the case that there are input delays will take the form

$$\|x\|_2 \leq C_1 \|u\|_2 + C_2 \|\dot{u}\|_2.$$

Here again, provided that  $M' := M_2^d \sum_{j=1}^{\ell} \mu_j \|A_j\| < 1$ , we have

$$\|\dot{x}\|_2 \leq \|\dot{u}\|_2 + M' \|\dot{x}\|_2 + \epsilon \|h\|_\infty \|x\|_2 + M_2^d \sum_{k=1}^m \nu_k \|B_k\| \|\dot{u}\|_2,$$

or

$$\|\dot{x}\|_2 \leq (1 - M')^{-1} \left( M_2^{nomd} \|u\|_2 + \epsilon \|h\|_\infty \|x\|_2 + M_2^d \sum_{k=1}^m \nu_k \|B_k\| \|\dot{u}\|_2 \right),$$

By (5) and (6) we have

$$\|x\|_2 \leq M_2^{nom} \|u\|_2 + M_2 \left( \sum_{j=1}^{\ell} \mu_j \|A_j\| \|\dot{x}\|_2 + \epsilon \|h\|_\infty \|x\|_2 + \sum_{k=1}^m \nu_k \|B_k\| \|\dot{u}\|_2 \right),$$

that is,

$$\begin{aligned} &\left( 1 - M_2 \epsilon \|h\|_\infty \left( \sum_{j=1}^{\ell} \mu_j \|A_j\| (1 - M')^{-1} + 1 \right) \right) \|x\|_2 \\ &\leq \left( M_2^{nom} + M_2 M_2^{nomd} \sum_{j=1}^{\ell} \mu_j \|A_j\| (1 - M')^{-1} \right) \|u\|_2 + \left( M_2 \sum_{k=1}^m \nu_k \|B_k\| (M_2^d + 1) \right) \|\dot{u}\|_2, \end{aligned}$$

which gives, if  $M_2\epsilon\|h\|_\infty(\sum_{j=1}^\ell\mu_j\|A_j\|(1-M')^{-1}+1) < 1$ , a finite  $L_2$  gain from  $(u, \dot{u})$  to  $x$  if there are input delays.  $\square$

**Remark 3.1.** *If  $B_k = 0$  for all  $k$ , or if the  $\sigma_j$  are constant functions for all  $j$ , we do not need to impose the condition that  $\dot{u}$  lies in  $L_2$  in order to get  $H_\infty$ -stability.*

### 3.2 The general case of neutral systems

In general it is easier to destabilize a neutral delay system by a perturbation, and here we simply give a result for BIBO stability.

**Theorem 3.2.** *Suppose that the system (2) is BIBO-stable.*

*If  $M_\infty^d(\sum_{j=1}^\ell\mu_j\|A_j\| + 2\sum_{l=1}^L\|A_{-l}\|) < 1$  then the system (1) is BIBO-stable.*

*Proof.* As for retarded systems we start with the inequality

$$\|\dot{x}\|_\infty \leq \|\dot{v}\|_\infty + M_\infty^d \left( \sum_{j=1}^\ell \|A_j\| \|f_j\|_\infty + \sum_{k=1}^m \|B_k\| \|g_k\|_\infty + \sum_{l=1}^L \|A_{-l}\| \|\tilde{f}\|_\infty + \epsilon \|h\|_\infty \|x\|_\infty \right).$$

We have

$$\|\tilde{f}\|_\infty = \sup_t \|\dot{x}(t - \gamma(t)) - \dot{x}(t - H)\| \leq 2\|\dot{x}\|_\infty,$$

whereas

$$\|f_j\|_\infty \leq \mu_j \|\dot{x}\|_\infty$$

and

$$\|g_j\|_\infty \leq 2\|u\|_\infty$$

as in the retarded case.

Provided that  $M'' := M_\infty^d(\sum_{j=1}^\ell\mu_j\|A_j\| + 2\sum_{l=1}^L\|A_{-l}\|) < 1$ , we have

$$\|\dot{x}\|_\infty \leq (1 - M'')^{-1} \left( M_\infty^{nomd} \|u\|_\infty + M_\infty^d \sum_{k=1}^m 2\|B_k\| \|u\|_\infty + \epsilon \|h\|_\infty \|x\|_\infty \right),$$

From the relation  $x = v + y$ , we get a finite  $L_\infty$  gain from  $u$  to  $x$ .  $\square$

## 4 Stabilization properties

### 4.1 The case of retarded systems

We consider here the stabilization of system (4) through the following standard feedback scheme where  $r$  and  $d$  are external input signals.

Retarded systems are  $H_\infty$ -stabilizable (see [3]) and so strongly stabilizable (see [18]). They are also *BIBO*-stabilizable (see [3]) and those with commensurate delays are strongly *BIBO*-stabilizable (see [16]).

Therefore, we may consider here only strong stabilization of system (4) by a controller  $K$ , with convolution kernel  $\mathcal{K}$ . In this case, instead of studying the stability of the four matrix

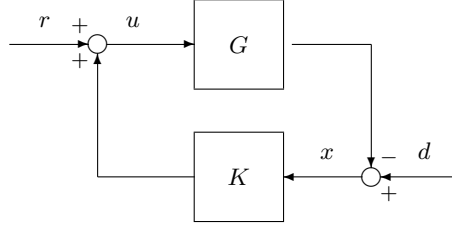


Figure 1: Standard Feedback Configuration

entries between  $(r, d)^T$  and  $(x, u)^T$ , it becomes sufficient to only study the stability of that between  $r$  and  $x$ . In the following, the control law  $u$  is then taken of the type  $u = \mathcal{K} * x + r$ .

The closed-loop has the following equation

$$\begin{aligned} \dot{x}(t) = & Ax(t) + \sum_{j=1}^{\ell} A_j x(t - \tau_j(t)) + \int_0^{\delta(t)} h(\theta) x(t - \theta) d\theta + B(\mathcal{K} * x)(t) + \sum_{k=1}^m B_k (\mathcal{K} * x)(t - \sigma_k(t)) \\ & + Br(t) + \sum_{k=1}^m B_k r(t - \sigma_k(t)), \quad (t > 0), \end{aligned} \quad (8)$$

Consider the system

$$\begin{aligned} \dot{v}(t) = & Av(t) + \sum_{j=1}^{\ell} A_j v(t - h_j) + \int_0^D h(\theta) v(t - \theta) d\theta + B(\mathcal{K} * v)(t) + \sum_{k=1}^m B_k (\mathcal{K} * v)(t - T_k) \\ & + Br(t) + \sum_{k=1}^m B_k r(t - T_k), \quad (t > 0), \end{aligned} \quad (9)$$

and let us denote:

- $M_{\infty}^{cl}$  : the  $L_{\infty}$ -gain of the closed-loop
- $M_{\infty}^{cl,d}$  :  $L_{\infty}$ -gain between input and derivative of the state of the closed-loop
- $M_2^{cl}$  : the  $L_2$ -gain of the closed-loop
- $M_{\infty}^{cl,nom,d}$  :  $L_{\infty}$ -gain between input  $r$  and  $\dot{v}$

**Theorem 4.1.** 1) Let us suppose that the nominal system (5) has commensurate delays. Let  $K$  be a stable controller which BIBO-stabilizes the nominal system (5), the  $L_{\infty}$ -gain of  $K$  being denoted  $M_{\infty}^K$ .

If  $M_{\infty}^{cl}(\sum_{j=1}^{\ell} \mu_j \|A_j\| + \sum_{k=1}^m \nu_k \|B_k\| M_{\infty}^K + \epsilon \|h\|_{\infty}) < 1$  then the controller  $K$  stabilizes system (4) in a BIBO sense.

2) Let  $K$  be a stable controller which  $H_{\infty}$ -stabilizes the nominal system (5), the  $L_2$ -gain of  $K$  being denoted  $M_2^K$ . Let us suppose that  $\dot{r}$  is in  $L_2$ .

If  $M_2^{cl}(\sum_{j=1}^{\ell} \mu_j \|A_j\| + \sum_{k=1}^m \nu_k \|B_k\| M_2^K) < 1$  then the controller  $K$  stabilizes system (4) in the sense that there is a finite  $L_2$  gain between  $r$  and  $x$ .

*Proof.* 1) Let  $\tilde{K}$  be a stable BIBO-stabilizing controller of system (5) with convolution kernel  $\mathcal{K}$ .

Considering the stabilization of (4) and (5) we deal with the following equations, where as before  $y = x - v$ :

and

$$\begin{aligned} \dot{y}(t) &= Ay(t) + \sum_{j=1}^{\ell} A_j y(t - h_j) + \sum_{j=1}^{\ell} A_j f_j(t) \\ &\quad + B(\mathcal{K} * y)(t) + \int_D^{\delta(t)} h(\theta) x(t - \theta) d\theta \\ &\quad + \sum_{k=1}^m B_k (\mathcal{K} * \tilde{f}_k)(t) + \sum_{k=1}^m B_k (\mathcal{K} * \tilde{r})(t), \quad (t > 0), \end{aligned}$$

with  $f_j(t) = x(t - \tau_j(t)) - x(t - h_j)$ ,  $\tilde{f}_k(t) = x(t - \sigma_k(t)) - x(t - T_k)$  and  $\tilde{r}(t) = r(t - \sigma_k(t)) - r(t - T_k)$ .

Using the same arguments as in section 3, we get

$$\|\dot{x}\|_{\infty} \leq \|\dot{v}\|_{\infty} + M_{\infty}^{cld} \left( \sum_{j=1}^{\ell} \mu_j \|A_j\| \|\dot{x}\|_{\infty} + \sum_{k=1}^m \nu_k \|B_k\| M_{\infty}^K \|\dot{x}\| + 2 \sum_{k=1}^m \|B_k\| M_{\infty}^K \|r\|_{\infty} + \epsilon \|h\|_{\infty} \|x\|_{\infty} \right).$$

If  $1 - M_{\infty}^{cld} (\sum_{j=1}^{\ell} \mu_j \|A_j\| + \sum_{k=1}^m \nu_k \|B_k\| M_K) > 0$ , the above inequality gives us:

$$(1 - M_{\infty}^{cld} (\sum_{j=1}^{\ell} \mu_j \|A_j\| + \sum_{k=1}^m \nu_k \|B_k\| M_K)) \|\dot{x}\| \leq (M_{\infty}^{cld} + 2M_{\infty}^{cld} \sum_{k=1}^m \|B_k\| M_{\infty}^K) \|r\|_{\infty} + \epsilon \|h\|_{\infty} \|x\|_{\infty}$$

As before writing  $x = y + v$  we get a  $L_{\infty}$ -bound between  $r$  and  $x$ .

2) Taking  $\dot{r}$  in  $L_2$  enables us, as in the Proof of Theorem 3.1, to bound  $\|\dot{r}\|_2$ , which proves the result. □

## 4.2 The case of neutral systems

**Proposition 4.1.** *Let us suppose that there exists a stable controller  $K$  which BIBO-stabilizes the nominal system (2), the  $L_{\infty}$ -gain of  $K$  being denoted  $M_{\infty}^K$ , the  $L_{\infty}$ -gain of the closed-loop being denoted  $M_{\infty}^{cl}$  and the  $L_{\infty}$ -gain between the input and the derivative of the state of the closed-loop being denoted  $M_{\infty}^{cld}$ .*

*If  $M_{\infty}^{cld} (\sum_{j=1}^{\ell} \mu_j \|A_j\| + \sum_{k=1}^m \nu_k \|B_k\| M_{\infty}^K + 2 + \sum_{l=1}^L \|A_{-l}\|) < 1$  then  $K$  BIBO-stabilizes system (1).*

*Proof.* For neutral systems, we deal with equations

$$\begin{aligned} \dot{v}(t) + \sum_{l=1}^L A_{-l} \dot{v}(t - H_l) &= Av(t) + \sum_{j=1}^{\ell} A_j v(t - h_j) + B\mathcal{K} * v(t) + \sum_{k=1}^m B_k \mathcal{K} * v(t - T_k) \\ &\quad + \int_0^D h(\theta) v(t - \theta) d\theta + Br(t) + \sum_{k=1}^m B_k r(t - T_k), \quad (t > 0), \end{aligned}$$

and

$$\begin{aligned}
\dot{y}(t) + \sum_{l=1}^L A_{-l} \dot{v}(t - H_l) &= Av(yt) + \sum_{j=1}^{\ell} A_j y(t - h_j) + \sum_{j=1}^{\ell} A_j f_j(t) \\
&+ \sum_{l=1}^L A_{-l} (x(t - H_l) - x(t - \gamma(t))) + \int_0^D h(\theta) y(t - \theta) d\theta \\
&+ \int_D^{\delta(t)} h(\theta) x(t - \theta) d\theta \\
&+ B(K * y)(t) + \sum_{k=1}^m B_k (\mathcal{K} * y)(t - T_k) + Br(t) + \sum_{k=1}^m B_k r(t - T_k) \\
&+ \sum_{k=1}^m B_k (\mathcal{K} * \tilde{f}_k) + \sum_{k=1}^m B_k \mathcal{K} * (r(t - \sigma_k(t)) - r(t - T_k)), \quad (t > 0),
\end{aligned}$$

from which we get

$$\begin{aligned}
\|\dot{x}\|_{\infty} &\leq \|\dot{v}\|_{\infty} + M_{\infty}^{cld} \left( 2 \sum_{l=1}^L \|A_{-l}\| \|\dot{x}\|_{\infty} \sum_{j=1}^{\ell} \|A_j\| \mu_j \|\dot{x}\|_{\infty} \right. \\
&\quad \left. + \sum_{k=1}^m \|B_k\| \nu_k M_{\infty}^K \|\dot{x}\| + 2 \sum_{k=1}^m \|B_k\| M_{\infty}^K \|r\|_{\infty} + \epsilon \|h\|_{\infty} \|x\|_{\infty} \right).
\end{aligned}$$

□

Although the existence of a stable controller cannot be guaranteed in the general case, let us mention that the existence of a stabilizing controller can be indeed guaranteed in the particular case of systems with commensurate delays.

It has been shown in [5] that neutral systems with commensurate delays and a finite number of poles in  $\{\operatorname{Re} s > a\}$  with  $a < 0$  are stabilizable in an  $H_{\infty}$ -sense: coprime factorizations over  $H_{\infty}$  have been determined and the set of all stabilizing controllers was given. It is not difficult to see that the coprime factorizations are also in  $\hat{\mathcal{A}}$ , inducing BIBO-stabilizability as well.

The next Proposition shows that, under hypothesis (H) systems (2) with commensurate delays fall into the study of [5].

**Proposition 4.2.** *If the system (2) has commensurate delays, then there exists  $a < 0$  such that system (2) only has a finite number of poles in  $\{\operatorname{Re} s > a\}$ .*

*Proof.* It is well-known [1] that the location of chains of poles of system (2) can be determined from the denominator of its transfer function, more precisely from the coefficient (containing exponential terms) of the term  $s^n$ .

Considering  $\det(sI - A + \sum_{\ell=1}^L A_{\ell} s e^{-s\ell H} - \sum_{j=1}^J A_j e^{-sh_j} - \int_0^D h(\theta) I e^{-\theta s} d\theta)$  we notice that it is sufficient to look at  $\det(sI + \sum_{\ell=1}^L A_{-\ell} s e^{-s\ell})$  as other terms do not contribute to the coefficient of the term  $s^n$ .

Letting  $z = e^{-s\ell}$ , we get  $\det(sI + \sum_{\ell=1}^L A_{-\ell} s e^{-s\ell}) = s^n \det(I + \sum_{\ell=1}^L A_{-\ell} z^{\ell})$ .

Now, assume that there is  $z \in \mathbb{C}$  such that  $|z| \leq 1$  and  $\det(I + \sum_{\ell=1}^L A_{-\ell} z^{\ell}) = 0$ . Then there exists  $x^* \in \mathbb{C}^n \setminus 0$  with  $\|x^*\| = 1$  such that  $x^* = -(\sum_{\ell=1}^L A_{-\ell} z^{\ell}) x^*$ .

In this case, by hypothesis (H)

$$1 = \| -x^* \| = \left\| \sum_{\ell=1}^L A_{-\ell} z^\ell x^* \right\| \leq \sum_{\ell=1}^L \|A_{-\ell}\| \|x^*\| |z| \leq \left( \sum_{\ell=1}^L \|A_{-\ell}\| \right) |z| < 1$$

which is absurd so all roots of  $\det(I + \sum_{\ell=1}^L A_{-\ell} z^\ell) = 0$  are of modulus strictly greater than one entailing that all roots in  $s$  are strictly in the left half plane. All chains of poles of neutral system (2) are then asymptotic to vertical axes located in the open right half-plane ensuring a finite number of pole in  $\{\operatorname{Re} s > a\}$  with  $a < 0$ .  $\square$

## 5 Example

Consider the elementary delay system

$$\dot{x}(t) + x(t-h) = u(t),$$

with transfer function  $G_h(s) = 1/(s + e^{-sh})$ . This is  $H_\infty$  and BIBO stable provided that  $0 \leq h < \pi/2$  (see, for example, [17, Chap. 6]).

Now we consider the perturbed system

$$\dot{x}(t) + x(t - \tau(t)) = u(t), \tag{10}$$

with  $0 \leq h < \tau(t) \leq h + \mu$ .

By Theorem 3.1, we have  $H^\infty$  stability if  $\mu < M_2^{d-1}$ .

For  $h = 0, 0.5, 1$  and  $1.5$  these values are  $1, 0.63, 0.32$  and  $0.03$  respectively; naturally  $h + \mu < \pi/2$  in all cases.

For BIBO stability a similar result holds, except that we require the BIBO norm of  $sG_h(s) = 1 - e^{-sh}G_h(s)$ , which is not easy to calculate as we do not have an explicit form of the impulse response. One way round this is to use the Hardy–Littlewood inequality given in [11, p. 182] (see also [4]), namely that

$$\|G_h\|_{BIBO} \leq \frac{1}{2} \|G'_h\|_{L^1(i\mathbb{R})}.$$

Using this bound, we find that for  $h = 0, 0.5, 1$  and  $1.5$  the BIBO norm of  $G_h$  is at most  $1, 1.01, 2.96$  and  $39.1$  respectively, giving BIBO stability for  $\mu$  at most  $0.5, 0.50, 0.25$  and  $0.025$  respectively.

Now for  $h = 2$  the system  $G_h$  is not stable, but it is easily stabilized with the constant controller  $K = -1$ , giving a closed-loop transfer function of

$$G_{cl}(s) = \frac{s + e^{-2s}}{s + 1 + e^{-2s}}.$$

Calculations indicate that  $\|G_{cl}\|_\infty = 1.54$  and  $\|G_{cl}\|_{BIBO} \leq 3.89$ . We may therefore apply Theorem 4.1, and conclude that  $K$  stabilizes the system (10) provided that  $2 \leq \tau(t) \leq 2 + \mu$ , where  $\mu = 0.26$  in the BIBO case and  $\mu = 0.65$  in the  $H_\infty$  case.

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