

# Contents

<b>1</b>	<b>Introduction</b>	<b>1</b>
1.1	Motivation . . . . .	1
1.2	Distributed control and estimation . . . . .	3
1.3	Control of autonomous agents . . . . .	6
1.4	Contribution and Outline . . . . .	9
<b>2</b>	<b>Distributed <math>\mathcal{H}_\infty</math> State Estimation for Linear and Nonlinear Systems</b>	<b>13</b>
2.1	Linear Systems . . . . .	14
2.1.1	Observer scheme . . . . .	15
2.1.2	Centralized LMI-based solution . . . . .	19
2.1.3	Distributed LMI-based solution . . . . .	21
2.1.4	Relation to vector dissipativity . . . . .	23
2.2	Nonlinear Systems . . . . .	24
2.2.1	Observer scheme . . . . .	26
2.2.2	Observer design by vector storage functions . . . . .	28
2.2.3	Conservatism of the vector storage function . . . . .	30
2.2.4	Extended observer design . . . . .	33
2.2.5	Numerical calculation for the extended observer design . . . . .	39
2.2.6	Simulation example . . . . .	40
2.3	Summary and Discussion . . . . .	42
<b>3</b>	<b>Event-triggered Communication and Distributed Design</b>	<b>45</b>
3.1	Event-triggered Communication . . . . .	46
3.1.1	Observer scheme . . . . .	47
3.1.2	Observer design conditions . . . . .	48
3.1.3	Exclusion of Zeno-behaviour . . . . .	51
3.1.4	Simulation example . . . . .	53

3.2	Dual Decomposition and Iterative optimization . . . . .	55
3.2.1	Separation of the optimization problem . . . . .	56
3.2.2	Iterative optimization algorithm . . . . .	59
3.2.3	Simulation example . . . . .	63
3.3	Self-adapting solution with Ricatti-differential equations . . . . .	63
3.3.1	Simple coupling of RDEs . . . . .	66
3.3.2	Information weighted coupling of RDEs . . . . .	67
3.3.3	Simulation example . . . . .	69
3.4	Summary and Discussion . . . . .	69
<b>4</b>	<b>Distributed <math>\mathcal{H}_\infty</math> State Estimation-based Multi-Agent Coordination</b>	<b>73</b>
4.1	The Synchronization Problem . . . . .	74
4.1.1	Synchronization by model expansion . . . . .	75
4.1.2	Synchronization by distributed reference tracking . . . . .	83
4.2	Regional Estimation-based Synchronization . . . . .	85
4.2.1	Regional Estimation Scheme . . . . .	86
4.2.2	Proposed observer design . . . . .	89
4.2.3	Robustly synchronizing controllers . . . . .	93
4.2.4	Simulation example . . . . .	101
4.3	Extensions of Regional Estimation-based Control . . . . .	104
4.3.1	Physically interconnected agents . . . . .	104
4.3.2	Unknown neighbour models . . . . .	107
4.3.3	Regional estimation-based Distributed Output Regulation . . . . .	115
4.4	Summary and Discussion . . . . .	125
<b>5</b>	<b>Conclusions</b>	<b>129</b>
<b>A</b>	<b>Technical Preliminaries</b>	<b>133</b>
A.1	Observer design . . . . .	133
A.1.1	Undisturbed case . . . . .	133
A.1.2	$\mathcal{L}_2$ -integrable disturbances . . . . .	134
A.2	Graph Theoretic Preliminaries . . . . .	135
<b>B</b>	<b>Technical proofs</b>	<b>137</b>
B.1	Proof of Theorem 4.5 . . . . .	137
B.2	Proof of Theorem 4.7 . . . . .	139
B.3	Proof of Lemma 4.5 . . . . .	141

B.4 Proof of Theorem 4.10 . . . . . 143

**Bibliography** **145**