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Stability Analysis of Gradient-Based Distributed Formation Control With Heterogeneous Sensing Mechanism: The Three Robot Case

Nelson P. K. Chan , Bayu Jayawardhana , and Hector Garcia de Marina 

Abstract—This article focuses on the stability analysis of a formation shape displayed by a team of mobile robots that uses a heterogeneous sensing mechanism. For the setups consisting of three robots, we show that the use of heterogeneous gradient-based control laws can give rise to undesired invariant sets where a distorted formation shape is possibly moving at a constant velocity. We guarantee local asymptotic stability for the correct and desired formation shape. For the setup with one distance and two bearing robots, we identify the conditions such that an incorrect moving formation is locally attractive.

Index Terms—Formation control, gradient-based control design, heterogeneous sensing.

I. INTRODUCTION

Over the years, a rich body of work has been developed on realizing a formation shape by a team of mobile robots. The use and active maintenance of a common type of constraint (distance, bearing, angle, and relative position) between two neighboring robots have been the basis for achieving robust formation shape [1]–[5]. However, neighboring robots controlling constraints using nonreliable sensors lead to unstable formations [6], [7]. If a sensor failure occurs, then one solution might be to withdraw the nonreliable information and consider a heterogeneous sensing setting for a pair of neighboring robots. For instance, in the case of a partial failure of a LIDAR sensor, which can normally provide relative position information, we may still measure bearing information with nonaccurate distance information. In this case, it is possible to define heterogeneous constraints on the same edge that still define the same shape (e.g., one robot controls relative position while the other one controls bearing). However, it remains an open problem whether the application of the local gradient-based control law based on the (heterogeneous) information available to each robot can still maintain the formation. Note that communication between robots to recover full information might not be possible by design. Indeed, the aforementioned works on formation with homogeneous

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information require only local sensing without information exchange between robots. The answer to this problem can open the way to the design of more robust strategies since distance-based/bearing-based controllers are more robust to nonaccurate bearing/distance measurements [8], [9]. For example, instead of just controlling relative positions, the bearing measurement becomes less sensitive when the robots move in a large formation shape, or the robots carrying multiple distance and bearing sensors can control the most relevant constraint depending on the accuracy or reliability of the equipped sensor for a given situation (e.g., far versus near, wide-angle versus small-angle, etc.). Intuitively, the gradient-based control law will steer each robot to the direction that minimizes the local potential function and reaches the desired constraints. However, as different types of potential function may be defined for the same edge due to the heterogeneous sensing mechanisms between the robots, the direction that is taken by each robot may not coincide anymore with the minimization of the combined potential functions.

In this article, we consider the formation stabilization problem in which the desired formation shape is specified by a mixed set of distance and bearing constraints. In [9], the authors divide the edges of formation graph into two sets where one set is associated to the distance constraints while the other one corresponds to the bearing constraints. Consequently, there are nodes that are involved in both types of edges, in which case the robots will be equipped with both types of sensor systems. In contrast to [9], we consider instead two disjoint sets of nodes where one set uses distance information while the other one employs bearing information. Analogous to the previous case, there are edges that are defined by both distance and bearing constraints. The presence of multiple constraints in these edges may lead to some robustness issues when each pair of nodes employs different control laws associated to these different constraints. In this article, we study the robustness of formation keeping in a heterogeneous network where minimal number of sensor systems for formation keeping are deployed per node. Particularly, each robot within the team has the task of maintaining a subset of either the distance or bearing constraints. For this particular work, we focus on teams consisting of three robots. Using standard gradient-based control laws specific to the constraints each robot has to maintain, we analyze the stability property, particularly, the local asymptotic stability of the desired and incorrect formation shapes. It is of interest to study the applicability of these control laws without modifying their local potential functions to incorporate the different constraints on the edges since it allows us to design distributed control laws that are completely dependent on the available local information to the robot and are independent of the eventual deployment of the robot in the formation.

The rest of this article is organized as follows. In Section II, preliminary material and problem formulation are presented. In Sections III and IV, we show that the deployment of heterogeneous gradient-based control laws can result in incorrect formation shapes, possibly moving at a constant velocity. Numerical results are given in Sections V. Finally, Section VI concludes this article.

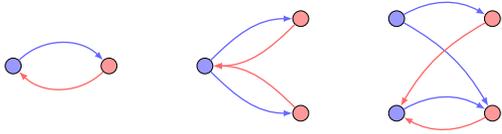


Fig. 1. Examples of complete bipartite digraphs for $n = 2$ and 3 vertices and a bipartite digraph for $n = 4$ vertices. Without loss of generality, \bullet represents an element of \mathcal{V}_1 while \bullet represents \mathcal{V}_2 . Correspondingly, the blue arrows represent $\mathcal{V}_1 \times \mathcal{V}_2$ while the red arrows represent elements of $\mathcal{V}_2 \times \mathcal{V}_1$.

II. PRELIMINARIES

A. Graph Theory

A *directed graph* (in short, *digraph*) \mathcal{G} is a pair $(\mathcal{V}, \mathcal{E})$, where $\mathcal{V} = \{1, 2, \dots, n\}$ is the *vertex set* and $\mathcal{E} \subseteq \mathcal{V} \times \mathcal{V}$ is the *edge set*. For $i, j \in \mathcal{V}$, the ordered pair (i, j) represents an edge pointing from i to j . We assume that \mathcal{G} does not have self-loops, i.e., $(i, i) \notin \mathcal{E}$ for all $i \in \mathcal{V}$ and $\text{card}(\mathcal{E}) = m$. The set of neighbors of vertex i is denoted by $\mathcal{N}_i = \{j \in \mathcal{V} \mid (i, j) \in \mathcal{E}\}$. The digraph \mathcal{G} is *bipartite* if the vertex set \mathcal{V} can be partitioned into two subsets \mathcal{V}_1 and \mathcal{V}_2 with $\mathcal{V}_1 \cap \mathcal{V}_2 = \emptyset$ and the edge set is $\mathcal{E} \subseteq (\mathcal{V}_1 \times \mathcal{V}_2) \cup (\mathcal{V}_2 \times \mathcal{V}_1)$. We assume $\text{card}(\mathcal{V}_1) = n_1$ and hence $\text{card}(\mathcal{V}_2) = n_2 = n - n_1$. For a *complete bipartite digraph*, $\mathcal{E} = (\mathcal{V}_1 \times \mathcal{V}_2) \cup (\mathcal{V}_2 \times \mathcal{V}_1)$ and $\text{card}(\mathcal{E}) = 2n_1n_2$. Fig. 1 depicts complete bipartite digraphs for $n = 2$ and 3 vertices and a bipartite digraph for $n = 4$ vertices.

B. Formations and Gradient-Based Control Laws

We consider a team consisting of n robots in which R_i is the label assigned to robot i . The robots are moving in the plane according to the single integrator dynamics, i.e.,

$$\dot{p}_i = u_i, \quad i \in \{1, \dots, n\} \quad (1)$$

where $p_i \in \mathbb{R}^2$ (a point in the plane) and $u_i \in \mathbb{R}^2$ represent the position of and the control input for R_i , respectively. For convenience, all spatial variables are given relative to a global coordinate frame Σ^g . The group dynamics is obtained as $\dot{p} = u$ with the stacked vectors $p = [p_1^\top \dots p_n^\top]^\top \in \mathbb{R}^{2n}$ representing the team *configuration* and $u = [u_1^\top \dots u_n^\top]^\top \in \mathbb{R}^{2n}$ being the collective input. The interactions among the robots are described by a fixed graph $\mathcal{G}(\mathcal{V}, \mathcal{E})$ with \mathcal{V} representing the team of robots and \mathcal{E} containing the neighboring relationships. We embed \mathcal{G} into the plane by assigning to each robot $i \in \mathcal{V}$, a point $p_i \in \mathbb{R}^2$. The pair $\mathcal{F}_p = (\mathcal{G}, p)$ denotes a *framework* (or equivalently a *formation*). We assume $p_i \neq p_j$ if $i \neq j$, i.e., two robots cannot be at the same position. We introduce the following notation prior to providing details on the *distance-based* and *bearing-only* formation control approaches. For points p_i and p_j , we define, relative to Σ^g , the relative position as $z_{ij} = p_j - p_i \in \mathbb{R}^2$, the distance as $d_{ij} = \|z_{ij}\| \in \mathbb{R}_{>0}$, and the relative bearing as $g_{ij} = \frac{z_{ij}}{d_{ij}} \in \mathbb{R}^2$. It follows $z_{ji} = -z_{ij}$, $d_{ji} = d_{ij}$ and $g_{ji} = -g_{ij}$.

1) *Distance-Based Formation Control*: In *distance-based* formation control, a *desired formation* is characterized by a set of *inter-robot distance constraints*. Assume that the desired distance between a robot pair (i, j) of the formation is d_{ij}^* and let $d_{ij}(t)$ be the current distance at time t . Let us define the *distance error* signal as $e_{ijd}(t) = d_{ij}^2(t) - (d_{ij}^*)^2$. A distance-based potential function for (i, j) takes the form $V_{ijd}(e_{ijd}) = \frac{1}{4} e_{ijd}^2$. It has a minimum at the desired distance d_{ij}^* , i.e., $V_{ijd}(e_{ijd}) \geq 0$ and $V_{ijd}(e_{ijd}) = 0 \iff d_{ij} = d_{ij}^*$. In this case, the corresponding gradient-based control law for maintaining distance d_{ij}^*

for the robot pair (i, j) is $u_{ijd} = e_{ijd} z_{ij}$, where z_{ij} is the measurement that R_i obtains from its neighbor $j \in \mathcal{N}_i$. Thus, the distanced-based formation control law for robot R_i in (1) is given by

$$u_{id} = \sum_{j \in \mathcal{N}_i} e_{ijd} z_{ij}. \quad (2)$$

It is well studied in literature (e.g., [10]) that the abovementioned control law guarantees the local exponential stability of the desired formation shape when the desired shape is infinitesimally rigid.

2) *Bearing-Only Formation Control*: In *bearing-only* formation control, the desired formation is characterized by a set of *inter-robot bearing constraints*. Consider the i th robot (with label R_i) in this setup. Robot R_i is able to obtain the bearing measurement $g_{ij}(t)$ from its neighbors $j \in \mathcal{N}_i$ and its goal is to achieve desired bearings g_{ij}^* with all neighbors $j \in \mathcal{N}_i$. In this case, the *bearing error* signal for a robot pair (i, j) can be defined by $e_{ijb}(t) = g_{ij}(t) - g_{ij}^*$. The corresponding potential function is $V_{ijb}(e_{ijb}) = \frac{1}{2} d_{ij} \|e_{ijb}\|^2$. Note that $V_{ijb}(e_{ijb}) \geq 0$ and it is only zero when $d_{ij} = 0$ or $e_{ijb} = \mathbb{0}_2 \iff g_{ij} = g_{ij}^*$. (In forthcoming analysis, we will show that $d_{ij} = 0$, where robots R_i and R_j are at the same position, is not a viable option.) It can be verified that $u_{ijb} = e_{ijb}$ is the gradient-based control law derived from $V_{ijb}(e_{ijb})$ for the robot pair (i, j) . The bearing-only formation control law for R_i in (1) is then given by

$$u_{ib} = \sum_{j \in \mathcal{N}_i} e_{ijb}. \quad (3)$$

In [4], it has been shown that the above control law ensures the global asymptotic stability of the desired formation shape provided that the formation shape is infinitesimally bearing rigid.

C. Cubic Equations

Lemma 1: Consider the reduced cubic equation $y^3 + cy + d = 0$ with coefficients $c < 0$ and $d > 0$. The discriminant is $\Delta := -4c^3 - 27d^2 \geq 0$. Then, two positive real roots exist with these values

$$\begin{aligned} y_{p1} &= 2 \sqrt[3]{r_v} \cos\left(\frac{1}{3} \varphi_v\right) && \in [1, \sqrt{3}] \sqrt[3]{r_v} \\ y_{p2} &= 2 \sqrt[3]{r_v} \cos\left(\frac{1}{3} \varphi_v - 120^\circ\right) && \in (0, 1] \sqrt[3]{r_v} \end{aligned} \quad (4)$$

where $r_v = \sqrt{-\left(\frac{c}{3}\right)^3}$ and $\varphi_v = \tan^{-1}\left(\frac{-2}{d} \sqrt{-R}\right) \in (90^\circ, 180^\circ]$. When $\Delta = 0$, the two positive real roots are equal and have value $y_{p1} = y_{p2} = \sqrt[3]{r_v} = \sqrt[3]{\frac{d}{2}}$.

The proof of Lemma 1 can be found in [11].

D. Problem Formulation

As discussed in Section I, we study the setup in which the robots possess heterogeneous sensing, and each robot, depending on its own local information, maintains the prescribed distance or bearing with its neighbors using the aforementioned distance-based or bearing-only formation control law. Thus, in the current setup, each robot fulfills either a *distance task* or a *bearing task*. As before, consider a pair of robots with labels R_i and R_j . In case R_i is assigned a distance task, its goal is to maintain a desired distance d_{ij}^* with R_j . To attain this goal, it makes use of the distance-based control law $u_{ijd} = e_{ijd} z_{ij}$, with z_{ij} being the obtained relative position measurement relative to a local coordinate frame Σ^i . Note that Σ^i is *not necessarily aligned* with Σ^j or Σ^g . On the other hand, when R_j is assigned a bearing task, its goal is to maintain a desired bearing g_{ji}^* with R_i . It reaches this goal by employing the bearing-only control law $u_{ijb} = e_{ijb}$ based on

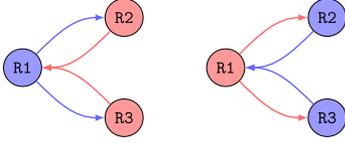


Fig. 2. Setups for the three robot case; \bullet represents a distance robot and \circ represents a bearing robot. Correspondingly, blue arrows represent sensing carried out by the distance robots while red arrows represent the edges from the bearing robots. From left to right, we have the **(1D2B)** and **(1B2D)** setup.

the obtained relative bearing measurement g_{ij} relative to Σ^j , which is aligned with Σ^s . For the interconnection topology, we assume that each robot has only neighbors of the opposing category, i.e., a distance robot can only have edges with bearing robot(s) and vice versa. As a result, the team of n robots can be partitioned into two sets, namely, the set of distance robots \mathcal{D} and the set of bearing robots \mathcal{B} , with $\mathcal{D} \neq \emptyset$ and $\mathcal{B} \neq \emptyset$. The edge set is given by $\mathcal{E} \subseteq (\mathcal{D} \times \mathcal{B}) \cup (\mathcal{B} \times \mathcal{D})$; the underlying graph structure is that of a bipartite digraph.

In the current article, we focus on the case in which the team of $n = 3$ robots has a *complete bipartite digraph* topology, i.e., the edge set is $\mathcal{E} = (\mathcal{D} \times \mathcal{B}) \cup (\mathcal{B} \times \mathcal{D})$. We distinguish two feasible robot setups, namely, the *one distance and two bearing (1D2B)* or the *one bearing and two distance (1B2D)* setup; see Fig. 2 for an illustration of these setups. For these setups, we are interested in studying the stability of the formation system employing the distance-based formation control law in (2) for the distance robot(s) and the bearing-only formation control law in (3) for the bearing robot(s). In this case, we do not modify the standard gradient-based control law for the different tasks. Consequently, we analyze whether

- 1) the equilibrium set contains undesired shape and/or group motion;
- 2) the desired shape is (exponentially) stable;
- 3) the undesired shape and/or group motion (if any) is attractive.

The first and last questions are motivated by the robustness issues of the distance- and displacement-based controllers as studied in [6], [7], [12], and [13] where a disagreement between neighboring robots about desired values or measurements can lead to an undesired group motion and deformation of the formation shape. Since we are considering heterogeneous sensing mechanisms with corresponding heterogeneous potential functions, it is of interest whether such undesired behavior can coexist. Such knowledge on the effect of heterogeneity in the control law can potentially be useful to design simultaneous formation and motion controller, as pursued recently in [14].

III. (1D2B) ROBOT SETUP

In this section, we consider the case of three robots with the partition $\mathcal{D} = \{1\}$ and $\mathcal{B} = \{2, 3\}$; the **(1D2B)** setup is shown in Fig. 2. Utilizing gradient-based control laws for each distance or bearing task, we obtain the following closed-loop dynamics:

$$\begin{bmatrix} \dot{p}_1 \\ \dot{p}_2 \\ \dot{p}_3 \end{bmatrix} = \begin{bmatrix} K_d e_{12d} z_{12} + K_d e_{13d} z_{13} \\ K_b e_{21b} \\ K_b e_{31b} \end{bmatrix} \quad (5)$$

where we assume that the distance robot R_1 has the control gain $K_d > 0$ and the bearing robots R_2 and R_3 the common control gain $K_b > 0$. It is of interest to note that when physical dimension is taken into account with [L] as the unit of length and [T] the unit of time, the control gain K_d has dimension $[L]^{-2}[T]^{-1}$ while K_b is expressed in $[L][T]^{-1}$. We define the relative position or link vector $z = [z_{12}^\top \ z_{13}^\top]^\top \in \mathbb{R}^4$. The

link dynamics \dot{z} evaluates to

$$\begin{bmatrix} \dot{z}_{12} \\ \dot{z}_{13} \end{bmatrix} = - \begin{bmatrix} K_b e_{12b} + K_d e_{12d} z_{12} + K_d e_{13d} z_{13} \\ K_b e_{13b} + K_d e_{12d} z_{12} + K_d e_{13d} z_{13} \end{bmatrix}. \quad (6)$$

For a triangle, $z_{12} + z_{23} - z_{13} = \mathbb{0}_2$ holds. Hence, the dynamics related to link z_{23} evaluates to $\dot{z}_{23} = -K_b(e_{13b} - e_{12b})$.

In the following sections, we rigorously analyze the closed-loop formation system (5) and link dynamics (6).

A. Equilibrium Configurations

Proposition 1 ((1D2B) Equilibrium Configurations): The equilibrium configurations corresponding to the closed-loop formation system (5) belong to the set

$$\mathcal{S}_p = \{p \in \mathbb{R}^6 \mid e = \mathbb{0}_6\} \quad (7)$$

where $e = [e_{12d} \ e_{13d} \ e_{12b}^\top \ e_{13b}^\top]^\top \in \mathbb{R}^6$.

Proof: Setting the left-hand side (LHS) of each equation in (5) to the zero vector, we immediately obtain that the bearing constraints for robots R_2 and R_3 are satisfied since $e_{21b} = -e_{12b} = \mathbb{0}_2$ and $e_{31b} = -e_{13b} = \mathbb{0}_2$. This implies that $d_{21} = d_{12} \neq 0$ and $d_{31} = d_{13} \neq 0$. It remains to solve for $\dot{p}_1 = \mathbb{0}_2$. With the gathered insights, we obtain $e_{12d} d_{12} g_{12}^* = -e_{13d} d_{13} g_{13}^*$. Since $g_{12}^* \neq \pm g_{13}^*$ (the robots are colinear when $g_{12} = \pm g_{13}$), the expression is satisfied when $e_{12d} d_{12} = 0$ and $e_{13d} d_{13} = 0$. Because $d_{12} \neq 0$ and also $d_{13} \neq 0$, we require $e_{12d} = 0$ and $e_{13d} = 0$ to hold.

B. Moving Configurations

During the analysis of the **(1D1B)** setup (see [11] for details), we observed that robots may move with a common velocity w while the predefined constraints are not met. For the **(1D2B)** setup, we explore whether conditions exist such that the formation may move with a common velocity w .

Proposition 2 ((1D2B) Moving Configurations): The closed-loop formation system (5) moves with a constant velocity $w = K_b b_{\text{sum}}^*$ with $b_{\text{sum}} = g_{12} + g_{13}$ when the error vector e satisfies

$$e = - \begin{bmatrix} \frac{1}{d_{12}} R_{bd} & \frac{1}{d_{13}} R_{bd} & b_{\text{sum}}^{*\top} & b_{\text{sum}}^{*\top} \end{bmatrix}^\top. \quad (8)$$

Proof: First, we solve for $\dot{z} = \mathbb{0}_4$. Since $\dot{z}_{12} = \mathbb{0}_2 = \dot{z}_{13}$, it follows $\dot{z}_{23} = \mathbb{0}_2$. This expression evaluates to $g_{12} - g_{13} = g_{12}^* - g_{13}^*$. Define $b_{\text{diff}} = g_{12} - g_{13}$ and let $\angle g_{12} = \alpha$ be the angle enclosed by vector g_{12} and the positive x -axis of Σ^s . Similarly, let $\angle g_{13} = \beta$. We can rewrite b_{diff} as

$$b_{\text{diff}} = 2 \cos \left(\frac{1}{2} (\alpha - \beta_\pi) \right) \begin{bmatrix} \cos \left(\frac{1}{2} (\alpha + \beta_\pi) \right) \\ \sin \left(\frac{1}{2} (\alpha + \beta_\pi) \right) \end{bmatrix} \quad (9)$$

where $\beta_\pi = \beta + \pi \pmod{2\pi}$. The expression $\dot{z}_{23} = \mathbb{0}_2$ can be transformed to the following set of angle constraints, namely:

$$\begin{cases} \alpha + \beta_\pi = \alpha^* + \beta_\pi^* \\ \alpha - \beta_\pi = \alpha^* - \beta_\pi^* \end{cases} \iff \begin{cases} \alpha = \alpha^* \\ \beta = \beta^* \end{cases} \quad (10)$$

and

$$\begin{cases} \alpha + \beta_\pi = \alpha^* + \beta_\pi^* \\ -(\alpha - \beta_\pi) = \alpha^* - \beta_\pi^* \end{cases} \iff \begin{cases} \alpha = \beta^* + \pi \\ \beta = \alpha^* - \pi \end{cases} \quad (11)$$

From (10), we obtain $(g_{12}, g_{13}) = (g_{12}^*, g_{13}^*)$ corresponding to the equilibrium configurations in \mathcal{S}_p while the solution in (11) corresponds to $(g_{12}, g_{13}) = (-g_{13}^*, -g_{12}^*)$. Subsequently, we obtain $e_{12b} = e_{13b} =$

$-(g_{12}^* + g_{13}^*) =: b_{\text{sum}}^*$; it is sufficient to consider one of the equations in (6). This leads to $(-K_d e_{13d} d_{13})g_{12}^* + (-K_d e_{12d} d_{12})g_{13}^* = K_b g_{12}^* + K_b g_{13}^*$. For it to hold, we require $-K_d e_{13d} d_{13} = K_b \iff e_{13d} = -\frac{K_b}{d_{13}} R_{bd}$ and $-K_d e_{12d} d_{12} = K_b \iff e_{12d} = -\frac{K_b}{d_{12}} R_{bd}$ with the gain ratio $R_{bd} = \frac{K_b}{K_d}$. Collecting the error constraints, we obtain (8). By an immediate substitution, we obtain for the dynamics of the bearing robot R_2 , $\dot{p}_2 = K_b b_{\text{sum}}^* =: w$.

Remark 1: The signed area for a triangle can be obtained using the expression $S_A = z_{12}^\top [0 \ 1] z_{13}$ [15], [16]. The signed area of the desired formation shape evaluates to $S_A^* = d_{12}^* d_{13}^* g_{12}^{\top*} [0 \ 1] g_{13}^*$. The signed area of the moving formation shape is $S_{A_M} = d_{12} d_{13} g_{12}^{\top*} [0 \ 1] g_{13}^* = -d_{12} d_{13} g_{12}^{\top*} [0 \ 1] g_{13}^* = -\frac{d_{12} d_{13}}{d_{12}^* d_{13}^*} S_A^*$. Since the distance error signals in (8) are negative, it follows $d_{ij} < d_{ij}^*$. Hence, $|S_{A_M}| < |S_A|$ and the cyclic ordering of the robots is opposite to that of the desired formation shape.

Following Proposition 2, a characterization of the moving set \mathcal{T}_p in terms of the error vector e is

$$\mathcal{T}_p = \{p \in \mathbb{R}^6 \mid e \text{ satisfies (8)}\}. \quad (12)$$

An equivalent characterization of \mathcal{T}_p can be provided in terms of the inter-robot relative position vectors z_{12_M} and z_{13_M} where subscript M refers to ‘‘moving’’. In fact, the inter-robot bearing vectors g_{12_M} between R_1 and R_2 and g_{13_M} between robots R_1 and R_3 are known from the proof of Proposition 2. It remains to obtain feasible values for the inter-robot distances d_{12_M} and d_{13_M} . To this end, we find the roots satisfying the expressions for the distance error signals e_{12d} and e_{13d} in (8). Expanding the expressions leads to the following cubic equation:

$$d_{ij}^3 - (d_{ij}^*)^2 d_{ij} + R_{bd} = 0, \quad ij \in \{12, 13\}. \quad (13)$$

Compared with Lemma 1, we have $c = -(d_{ij}^*)^2 < 0$ and $d = R_{bd} > 0$. We obtain that the discriminant corresponding to (13) is $\Delta = 4(d_{ij}^*)^6 - 27R_{bd}^2$ and the threshold value for the desired distance d_{ij}^* such that positive roots exist is $\hat{d} = \sqrt[3]{\frac{3R_{bd}}{2}} \approx 1.3747 \sqrt[3]{R_{bd}}$. We infer that if one of (or both) the desired distances d_{12}^* or (and) d_{13}^* has (have) a value less than \hat{d} , then no feasible value for d_{12} or (and) d_{13} satisfies $e_{12d} d_{12} = -R_{bd}$ or (and) $e_{13d} d_{13} = -R_{bd}$, implying the infeasibility of moving formations. We conclude the set \mathcal{S}_p containing equilibrium configurations with one of (or both) $d_{12}^* < \hat{d}$ or (and) $d_{13}^* < \hat{d}$ is globally asymptotically stable.

When the desired distances d_{ij}^* s satisfy $d_{ij}^* \geq \hat{d}$, we obtain that feasible distances d_{ij} to (13) are given by Lemma 1 with the values $r_v = \sqrt{\frac{(d_{ij}^*)^6}{27}}$ and $\varphi_v = \tan^{-1}(-2R_{bd}^{-1} \sqrt{-R})$. Since we have two desired distances d_{12}^* and d_{13}^* and we have either one or two feasible value(s) d_{ij} to the cubic equation (13), it follows that different feasible combinations (d_{12_M}, d_{13_M}) exist. We have the following cases:

- 1) $(d_{12}^*, d_{13}^*) = (\hat{d}, \hat{d})$; 1 combination for (d_{12_M}, d_{13_M}) ;
- 2) $(d_{12}^*, d_{13}^*) = (\hat{d}, > \hat{d})$; 2 combinations for (d_{12_M}, d_{13_M}) ;
- 3) $(d_{12}^*, d_{13}^*) = (> \hat{d}, \hat{d})$; 2 combinations for (d_{12_M}, d_{13_M}) ;
- 4) $(d_{12}^*, d_{13}^*) > (\hat{d}, \hat{d})$; 4 combinations for (d_{12_M}, d_{13_M}) .

We conclude the set \mathcal{T}_p is a nonempty set when the additional constraints $d_{12}^* \geq \hat{d}$ and $d_{13}^* \geq \hat{d}$ are satisfied.

Recall the common velocity $w = K_b b_{\text{sum}}$ for the robots in Proposition 2. We want to write b_{sum} in the form $b_{\text{sum}} = d_{\text{sum}} g_{\text{sum}}$ with d_{sum} being the magnitude and g_{sum} the orientation of b_{sum} relative to Σ^g . By

the sum-to-product identities for cosine and sine, we obtain

$$b_{\text{sum}} = 2 \cos\left(\frac{1}{2}(\alpha - \beta)\right) \begin{bmatrix} \cos\left(\frac{1}{2}(\alpha + \beta)\right) \\ \sin\left(\frac{1}{2}(\alpha + \beta)\right) \end{bmatrix}. \quad (14)$$

Depending on the value of the angle difference $|\alpha - \beta|$, we have different expressions for d_{sum} and g_{sum} . When $|\alpha - \beta| < \pi$, we set $d_{\text{sum}} = 2 \cos(\frac{1}{2}|\alpha - \beta|)$ and $g_{\text{sum}} = \frac{1}{2}(\alpha + \beta)$ while for $|\alpha - \beta| > \pi$, we set $d_{\text{sum}} = 2 \cos(\pi - \frac{1}{2}|\alpha - \beta|)$ and $g_{\text{sum}} = \frac{1}{2}(\alpha + \beta) + \pi \pmod{2\pi}$. Note that $d_{\text{sum}} \in (0, 2)$ for $|\alpha - \beta| \geq \pi$. If $|\alpha - \beta| = 0^\circ$, then $g_{12} = g_{13}$ and $b_{\text{sum}} = 2g_{12}$, and finally, $|\alpha - \beta| = \pi$ implies $g_{12} = -g_{13}$ and $b_{\text{sum}} = 0_2$. Since $g_{12}^* \neq \pm g_{13}^*$, the last two mentioned cases do not occur; therefore, the magnitude of w is $0 < \|w\| < 2K_b$.

C. Local Stability Analysis of the Equilibrium and Moving Formations

Assume that the desired distances satisfy $d_{12}^* \geq \hat{d}$ and $d_{13}^* \geq \hat{d}$. In this case, both the equilibrium configurations in (7) and moving configurations in (12) satisfy $\dot{z} = 0_4$ and are feasible. We are interested in determining the local stability around these formations. To this end, we consider the linearization of the z -dynamics (6); this results in the Jacobian matrix $A \in \mathbb{R}^{4 \times 4}$ as

$$A = - \begin{bmatrix} K_b A_{12b} + K_d A_{12d} & K_d A_{13d} \\ K_d A_{12d} & K_b A_{13b} + K_d A_{13d} \end{bmatrix} \quad (15)$$

where $A_{ijd} = e_{ijd} I_2 + 2z_{ij} z_{ij}^\top$ and $A_{ijb} = \frac{1}{d_{ij}} P_{g_{ij}}$, with $P_{g_{ij}} = I_2 - g_{ij} g_{ij}^\top$ and $ij \in \{12, 13\}$.

We first consider the stability analysis around the equilibrium configurations.

Theorem 1: Consider a team of three robots arranged in the **(1D2B)** setup with closed-loop dynamics given by (5). Assume that the desired distances satisfy $d_{12}^* \geq \hat{d}$ and $d_{13}^* \geq \hat{d}$ with $\hat{d} = \sqrt[3]{\frac{3R_{bd}}{2}}$ and the bearing vectors satisfy $g_{12}^* \neq \pm g_{13}^*$. Given an initial configuration $p(0)$ that is close to the desired formation shape, then the robot trajectories asymptotically converge to a point $\hat{p} \in \mathcal{S}_p$.

Proof: Evaluating the Jacobian matrix (15) at the equilibrium configurations results in

$$A_E = - \begin{bmatrix} x^* & 0 \\ 0 & p^* \end{bmatrix} \otimes I_2 - \begin{bmatrix} m^* g_{12}^* g_{12}^{\top*} & q^* g_{13}^* g_{13}^{\top*} \\ y^* g_{12}^* g_{12}^{\top*} & n^* g_{13}^* g_{13}^{\top*} \end{bmatrix} \quad (16)$$

where we define the variables

$$\begin{aligned} x &= K_b d_{12}^{-1}, & y &= 2K_d d_{12}^2, & m &= y - x \\ p &= K_b d_{13}^{-1}, & q &= 2K_d d_{13}^2, & n &= q - p \end{aligned} \quad (17)$$

and the matrices

$$g_{12}^* g_{12}^{\top*} = \begin{bmatrix} a^2 & ab \\ ab & b^2 \end{bmatrix}, \quad g_{13}^* g_{13}^{\top*} = \begin{bmatrix} c^2 & cd \\ cd & d^2 \end{bmatrix}. \quad (18)$$

The starred version for x , p , y , q , m , and n is used here since we have $d_{12} = d_{12}^*$ and $d_{13} = d_{13}^*$. The characteristic polynomial $\chi_E(\lambda)$ corresponding to matrix A_E is obtained as

$$\begin{aligned} \chi_E(\lambda) &= (\lambda + x^*)(\lambda + p^*) \dots \\ &\quad (\lambda^2 + (y^* + q^*)\lambda + y^* q^* \sin^2 \theta^*) \end{aligned} \quad (19)$$

where $\sin \theta = g_{12}^{\top*} [0 \ 1] g_{13}^*$. The roots of (19) are

$$\begin{aligned} \lambda_1 &= -x^*, & \lambda_2 &= -p^* \\ \lambda_{3,4} &= -\frac{1}{2}(y^* + q^*) \pm \frac{1}{2} \sqrt{(y^* + q^*)^2 - 4y^* q^* \sin^2 \theta^*}. \end{aligned} \quad (20)$$

It can be verified that $0 < 4y^*q^*\sin^2\theta^* \leq (y^* + q^*)^2$; all roots are real. Moreover, $-(y^* + q^*) + \sqrt{(y^* + q^*)^2 - 4y^*q^*\sin^2\theta^*} < 0$ and we conclude all λ s are negative; matrix A_E is Hurwitz. This implies that the link trajectories asymptotically converge to the desired relative positions z^* as $t \rightarrow \infty$. It also means that the robots accomplish their individual tasks since $z_{ij}^* = d_{ij}^*g_{ij}^*$, so $p(t) \rightarrow \mathcal{S}_p$ when $p(0)$ is close to the desired formation shape.

We continue with determining the stability of the moving formations in the set \mathcal{T}_p . Based on the characterization in (8), we obtain the Jacobian matrix

$$A_M = - \begin{bmatrix} 0 & p \\ x & 0 \end{bmatrix} \otimes I_2 - \begin{bmatrix} m g_{13}^* g_{13}^{*\top} & q g_{12}^* g_{12}^{*\top} \\ y g_{13}^* g_{13}^{*\top} & n g_{12}^* g_{12}^{*\top} \end{bmatrix} \quad (21)$$

where the variables are defined as in (17) and (18). The corresponding characteristic polynomial $\chi_M(\lambda)$ is the quartic polynomial

$$\chi_M(\lambda) = \lambda^4 + c_1\lambda^3 + c_2\lambda^2 + c_3\lambda + c_4 \quad (22)$$

with the coefficients

$$\begin{aligned} c_1 &= m + n, & c_2 &= qy\sin^2\theta^* - px, & c_4 &= pxmn\sin^2\theta^* \\ c_3 &= xm(q\sin^2\theta^* - p) + pn(y\sin^2\theta^* - x). \end{aligned} \quad (23)$$

Recall that depending on the value of d_{12}^* and d_{13}^* , we can obtain more than one feasible combination (d_{12M}, d_{13M}) for the moving configurations. Under certain conditions, we have the following result on the eigenvalues of the matrix A_M .

Lemma 2: Assume that the desired distances satisfy $d_{12}^* > \hat{d}$ and $d_{13}^* > \hat{d}$ and the desired bearing vectors are not perpendicular, i.e., $g_{12}^* \not\perp g_{13}^*$. Consider the combination $(d_{12M}, d_{13M}) = (y_{p1}(d_{12}^*), y_{p1}(d_{13}^*))$ with y_{p1} given in Lemma 1. Then, all eigenvalues of the matrix A_M have a negative real part if the following inequality holds:

$$\cos^2\theta^* < \frac{mn \left((mq - ny)^2 + mn(m + n)(x + p) \right)}{(m^2q + n^2y)(mqx + nyp)}. \quad (24)$$

Proof: Assuming that the bearing vectors are not perpendicular, we obtain that $0 < \sin^2\theta^* < 1$. Also, since $d_{12M} = y_{p1}(d_{12}^*)$ and $d_{13M} = y_{p1}(d_{13}^*)$, and $d_{12}^* > \hat{d}$ and $d_{13}^* > \hat{d}$, we verify that $m > 0$ and $n > 0$. We employ the Routh–Hurwitz stability criterion. The first column of the Routh–Hurwitz table, which is the column of interest, contains the following values:

$$\begin{bmatrix} 1 & c_1 & \frac{c_1c_2 - c_3}{c_1} & \frac{(c_1c_2 - c_3)c_3 - c_1^2c_4}{(c_1c_2 - c_3)} & c_4 \end{bmatrix}. \quad (25)$$

For all roots λ to have negative real parts, all values in (25) need to be positive. With $m > 0$ and $n > 0$, the coefficients c_1 and c_4 are positive. It remains to show that the third and fourth entries in (25) are positive. In fact, it is sufficient to show that the numerators are both positive. They evaluate to

$$\begin{aligned} c_1c_2 - c_3 &= \sin^2\theta^* (m^2q + n^2y) > 0 \\ (c_1c_2 - c_3)c_3 - c_1^2c_4 &= \\ &= \sin^2\theta^* \left(\left((mq - ny)^2 + mn(m + n)(x + p) \right) mn \right. \\ &\quad \left. - (m^2q + n^2y)(mqx + nyp) \cos^2\theta^* \right). \end{aligned} \quad (26)$$

Provided (24) holds, it follows $(c_1c_2 - c_3)c_3 - c_1^2c_4 > 0$. Since the entries in (25) are all positive, we conclude all eigenvalues of the matrix A_M have negative real parts.

Remark 2: The implication of Lemma 2 is that under certain conditions on the distance and bearing constraints, a subset of the moving

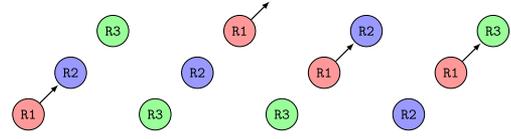


Fig. 3. Robot ordering for the moving configurations in the (1B2D) setup; the black arrow is the bearing vector g_{sum}^* . From left to right, we have ordering I to IV. Despite the different colors, both R_2 and R_3 are distance robots.

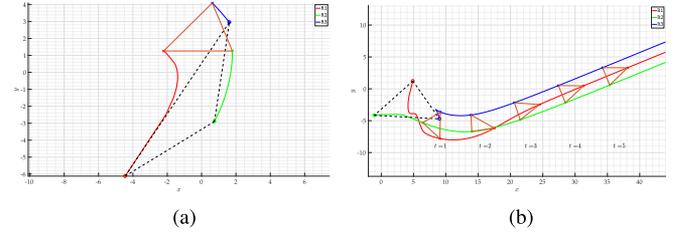


Fig. 4. Robot trajectories for the (1D2B) setup; (■, ■, ■) = (R_1 , R_2 , R_3), \circ represents the initial and \times is the final position. On the left panel, we have an initial configuration (dashed lines) where robots converge to the correct formation shape (solid lines) while the right panel illustrates an instance of convergence to the moving configuration with velocity $w = K_b b_{\text{sum}}^*$.

set \mathcal{T}_p is locally asymptotically stable. Hence, initializing the robots close to the conditions for the moving formation is not desirable. An illustration of this behavior is shown in Fig. 4(b).

Lemma 2 also holds when the desired bearing vectors are perpendicular, i.e., $g_{12}^* \perp g_{13}^* \iff \sin^2\theta^* = 1$. In this case, the coefficients in (23) and also all entries in (25) are positive; therefore, the matrix A_M will only have eigenvalues with negative real parts.

A full characterization of the remaining cases can be found in [11]. In almost all cases, the matrix A_M is not Hurwitz.

IV. (1B2D) ROBOT SETUP

In this section, the formation setup with one bearing and two distance robots (1B2D) is considered. Without loss of generality, we assume that robot R_1 is the bearing robot while robots R_2 and R_3 are distance robots. The right graph in Fig. 2 depicts the interconnection structure from which the closed-loop dynamics is obtained as

$$\begin{bmatrix} \dot{p}_1 \\ \dot{p}_2 \\ \dot{p}_3 \end{bmatrix} = \begin{bmatrix} K_b e_{12b} + K_b e_{13b} \\ K_d e_{21d} z_{21} \\ K_d e_{31d} z_{31} \end{bmatrix}. \quad (27)$$

The corresponding link dynamics evaluates to

$$\begin{bmatrix} \dot{z}_{12} \\ \dot{z}_{13} \end{bmatrix} = - \begin{bmatrix} K_d e_{12d} z_{12} + K_b e_{12b} + K_b e_{13b} \\ K_d e_{13d} z_{13} + K_b e_{12b} + K_b e_{13b} \end{bmatrix}. \quad (28)$$

Furthermore, the dynamics of the link z_{23} is found to be $\dot{z}_{23} = -K_d(e_{13d}z_{13} - e_{12d}z_{12})$. In the following, we follow similar steps to those described in Section III for analyzing (27) and (28), focusing on equilibrium configurations, possible moving formations, and their (local) stability analysis.

A. Equilibrium Configurations

Proposition 3 ((1B2D) Equilibrium Configurations): The equilibrium configurations corresponding to the closed-loop formation system

(27) belong to $\mathcal{S}_p^C \cup \mathcal{S}_p^F$, where

$$\begin{aligned} \mathcal{S}_p^C &= \{p \in \mathbb{R}^6 \mid e = \mathbb{O}_6\} \text{ and} \\ \mathcal{S}_p^F &= \left\{ p \in \mathbb{R}^6 \mid e = \begin{bmatrix} 0 & 0 & -b_{\text{diff}}^{\star\top} & b_{\text{diff}}^{\star\top} \end{bmatrix}^\top \right\} \end{aligned} \quad (29)$$

with $e = [e_{12d} \ e_{13d} \ e_{12b}^\top \ e_{13b}^\top]^\top \in \mathbb{R}^6$ and $b_{\text{diff}}^* = g_{12}^* - g_{13}^*$.

Proof: Setting the LHS of each equation of (27) to the zero vector, we obtain for robot R_2 that $-K_d e_{12d} z_{12} = \mathbb{O}_2 \iff e_{12d} = 0 \vee z_{12} = \mathbb{O}_2$ and similarly, we have $-K_d e_{13d} z_{13} = \mathbb{O}_2 \iff e_{13d} = 0 \vee z_{13} = \mathbb{O}_2$ for R_3 . The expression for R_1 evaluates to $g_{12} + g_{13} = g_{12}^* + g_{13}^*$. Defining $\angle g_{12} = \alpha$, $\angle g_{13} = \beta$ as before, and recalling the RHS of (14), we can write the following set of angle constraints, namely:

$$\begin{cases} \alpha + \beta = \alpha^* + \beta^* \\ \alpha - \beta = \alpha^* - \beta^* \end{cases} \iff \begin{cases} \alpha = \alpha^* \\ \beta = \beta^* \end{cases} \quad (30)$$

and

$$\begin{cases} \alpha + \beta = \alpha^* + \beta^* \\ -(\alpha - \beta) = \alpha^* - \beta^* \end{cases} \iff \begin{cases} \alpha = \beta^* \\ \beta = \alpha^* \end{cases} \quad (31)$$

Equation (30) translates to $(g_{12}, g_{13}) = (g_{12}^*, g_{13}^*)$, implying robot R_1 satisfies its bearing tasks while (31) translates to the *flipped* formation shape with bearings satisfying $(g_{12}, g_{13}) = (g_{13}^*, g_{12}^*)$. It follows the bearing error signals are $e_{12b} = -e_{13b} = -b_{\text{diff}}^*$. With both g_{12} and g_{13} defined, we obtain $d_{12} \neq 0$ and $d_{13} \neq 0$; hence, $z_{12} = \mathbb{O}_2$ and $z_{13} = \mathbb{O}_2$ are both infeasible. Robots R_2 and R_3 will stop moving when $e_{12d} = 0$ and $e_{13d} = 0$ holds, i.e., when they accomplished their individual distance task irrespective of R_1 .

It can be verified that the signed area of the flipped formation satisfies $S_{A_f} = -S_A^*$.

B. Moving Configurations

Proposition 4 ((IB2D) Moving Configurations): The moving configurations occur when the robots are colinear, i.e., $g_{12} = \pm g_{13}$ and oriented in the direction of $b_{\text{sum}}^* = g_{12}^* + g_{13}^*$.

Proof: Expanding (28) yields

$$\begin{aligned} (K_d e_{12d} d_{12} + K_b) g_{12} + K_b g_{13} &= K_b b_{\text{sum}}^* \\ K_b g_{12} + (K_d e_{13d} d_{13} + K_b) g_{13} &= K_b b_{\text{sum}}^*. \end{aligned} \quad (32)$$

Solving for $z_{23} = \mathbb{O}_2$, we obtain $e_{12d} d_{12} g_{12} = e_{13d} d_{13} g_{13}$. Two vectors are equal when they have the same magnitude and direction or opposite signs in both the magnitude and direction. Hence, we distinguish the cases $g_{12} = g_{13} \wedge e_{12d} d_{12} = e_{13d} d_{13}$ and $g_{12} = -g_{13} \wedge e_{12d} d_{12} = -e_{13d} d_{13}$. Since $g_{12} = \pm g_{13}$, we conclude the robots are colinear. Substituting this in (32), we obtain expressions of the form $h g_{12} = K_b d_{\text{sum}}^* g_{\text{sum}}^*$ where $h = K_d e_{12d} d_{12} + 2K_b$ when $g_{12} = g_{13}$ and $h = K_d e_{13d} d_{13} + 2K_b$ when $g_{12} = -g_{13}$. From this, we infer $g_{12} = \pm g_{\text{sum}}^*$, implying the orientation of the formation is in the direction of b_{sum}^* .

In light of Proposition 4, we can obtain *four* different ordering of the robots, as depicted in Fig. 3. To provide a full characterization of the moving configurations, it remains to obtain the inter-robot distances for the different ordering. We first derive expressions for the distance error corresponding to the different ordering from the general expression $h g_{12} = K_b d_{\text{sum}}^* g_{\text{sum}}^*$. Define $e_{12d} = \frac{s}{d_{12}} R_{\text{bd}}$ and $e_{13d} = \frac{t}{d_{13}} R_{\text{bd}}$. For the different robot orderings in Fig. 3, we have the following for s and t :

- 1) $g_{12} = g_{13} = g_{\text{sum}}^*$; $s = t = -2 + d_{\text{sum}}^*$;
- 2) $g_{12} = g_{13} = -g_{\text{sum}}^*$; $s = t = -2 - d_{\text{sum}}^*$;
- 3) $g_{12} = -g_{13} = g_{\text{sum}}^*$; $s = -t = d_{\text{sum}}^*$;
- 4) $g_{12} = -g_{13} = -g_{\text{sum}}^*$; $s = -t = -d_{\text{sum}}^*$.

When expanded, we obtain the cubic expression in Lemma 1 with coefficients $c = -d_{12}^*$ and $d = -s R_{\text{bd}}$ when solving for feasible distance d_{12} while $c = -d_{13}^*$ and $d = -t R_{\text{bd}}$ when we are considering distance d_{13} . Since $d_{\text{sum}}^* \in \{0, 2\}$, it follows that the value for s and t can be positive or negative and, hence, also the coefficient d of the cubic equation. In turn, this may impose a condition on the desired distances d_{12}^* and d_{13}^* for obtaining positive values for d_{12} and d_{13} , as discussed in Section II-C. In particular, we can verify that coefficient d has range $d \in (-2, 4) R_{\text{bd}}$. Taking $d = 4R_{\text{bd}}$, we obtain that all four robot orderings in Fig. 3 can occur when the desired distances satisfy $d_{ij}^* \geq \sqrt[3]{2R_{\text{bd}}}$.

In Section IV-C, we will show that the colinear moving formations are unstable.

C. Local Stability Analysis of the Equilibrium and Moving Formations

We have characterized the equilibrium configurations and the moving configurations. It is of interest to study the local stability property of these different sets. Similar to the stability analysis for the (1D2B) setup, we will use Lyapunov's indirect method. The Jacobian matrix corresponding to the z -dynamics (28) results in

$$A = - \begin{bmatrix} K_b A_{12b} + K_d A_{12d} & K_b A_{13b} \\ K_b A_{12b} & K_b A_{13b} + K_d A_{13d} \end{bmatrix} \quad (33)$$

with A_{ijd} and A_{ijb} as defined earlier.

We first consider equilibrium configurations (29).

Lemma 3: The Jacobian matrix A_E at the equilibrium configurations in $\mathcal{S}_p^C \cup \mathcal{S}_p^F$ is Hurwitz.

Proof: For the correct and desired equilibrium configurations in \mathcal{S}_p^C , the Jacobian matrix (33) evaluates to

$$A_E^C = - \begin{bmatrix} x^* & 0 \\ 0 & p^* \end{bmatrix} \otimes I_2 - \begin{bmatrix} m^* g_{12}^* g_{12}^{\star\top} & p^* J g_{13}^* (J g_{13}^*)^\top \\ x^* J g_{12}^* (J g_{12}^*)^\top & n^* g_{13}^* g_{13}^{\star\top} \end{bmatrix} \quad (34)$$

where x, y, p, q, m, n , and the bearing matrices are previously defined in (17) and (18). Also, for the flipped equilibrium configurations in \mathcal{S}_p^F , we obtain

$$A_E^F = - \begin{bmatrix} x^* & 0 \\ 0 & p^* \end{bmatrix} \otimes I_2 - \begin{bmatrix} m^* g_{13}^* g_{13}^{\star\top} & p^* J g_{12}^* (J g_{12}^*)^\top \\ x^* J g_{13}^* (J g_{13}^*)^\top & n^* g_{12}^* g_{12}^{\star\top} \end{bmatrix}. \quad (35)$$

The characteristic polynomial $\chi_E(\lambda)$ corresponding to the Jacobian matrices A_E^C and A_E^F is the same, namely

$$\begin{aligned} \chi_E(\lambda) &= (\lambda + q^*)(\lambda + y^*) \dots \\ &(\lambda^2 + (p^* + x^*)\lambda + p^* x^* \sin^2 \theta^*). \end{aligned} \quad (36)$$

The roots of (36) are

$$\begin{aligned} \lambda_1 &= -q^*, \quad \lambda_2 = -y^* \\ \lambda_{3,4} &= -\frac{1}{2}(p^* + x^*) \pm \frac{1}{2} \sqrt{(p^* + x^*)^2 - 4p^* x^* \sin^2 \theta^*}. \end{aligned} \quad (37)$$

We can verify that $0 < 4p^* x^* \sin^2 \theta^* \leq (p^* + x^*)^2$. This implies that all λ s are real. Also, $-(p^* + x^*) + \sqrt{(p^* + x^*)^2 - 4p^* x^* \sin^2 \theta^*} < 0$, and hence, we conclude that all roots are negative real.

This leads to the following main result.

Theorem 2: Consider a team of three robots arranged in the (1B2D) setup with closed-loop dynamics given by (27). Given an initial configuration $p(0)$ that is close to the desired formation shape, the robot trajectories asymptotically converge to a point $\hat{p} \in \mathcal{S}_p^C$.

Proof: Following Lemma 3, we obtain that link trajectories locally asymptotically converge to the desired relative positions z^* when they

are initialized in the neighborhood of it. With $z_{ij}^* = d_{ij}^* g_{ij}^*$, it follows that the robots also converge to a point $\hat{p} \in \mathcal{S}_p^C$.

Employing Lyapunov's indirect method to the moving colinear formations yields the following statement.

Theorem 3: Let $p \in \mathbb{R}^6$ be a configuration yielding a colinear formation as depicted in Fig. 3. Then, p is unstable.

Proof: We first obtain the matrix A_M and the corresponding characteristic polynomial $\chi_M(\lambda)$. With $e_{12d} = \frac{s}{d_{12}^*} R_{bd}$, $e_{13d} = \frac{t}{d_{13}^*} R_{bd}$, and bearing vectors g_{12M} and g_{13M} oriented to g_{sum}^* , A_M takes the following form:

$$A_M = \begin{bmatrix} (s+1)x & 0 \\ 0 & (t+1)p \end{bmatrix} \otimes_{I_2} - \begin{bmatrix} m g_{sum}^* g_{sum}^{*\top} & p J g_{sum}^* (J g_{sum}^*)^\top \\ x J g_{sum}^* (J g_{sum}^*)^\top & n g_{sum}^* g_{sum}^{*\top} \end{bmatrix} \quad (38)$$

where the variables x , y , p , q , m , and n are defined in (17). The characteristic polynomial $\chi_M(\lambda)$ is

$$\chi_M(\lambda) = (\lambda + pt + q)(\lambda + xs + y)(\lambda^2 + \mathbb{B}\lambda + \mathbb{C}) \quad (39)$$

where the coefficients are $\mathbb{B} = (p(t+1) + x(s+1))$ and $\mathbb{C} = px((t+1)(s+1) - 1)$. We explore the nature of the roots, hereby focusing on the coefficients of the quadratic polynomial.

For the different orderings, we obtain the following:

- i) $\mathbb{B} = (p+x)(-1 + d_{sum}^*)$ and $\mathbb{C} = px((-1 + d_{sum}^*)^2 - 1) < 0$;
- ii) $\mathbb{B} = (p+x)(-1 - d_{sum}^*) < 0$ and $\mathbb{C} = px((-1 - d_{sum}^*)^2 - 1)$;
- iii) $\mathbb{B} = (p+x) + (x-p)d_{sum}^*$ and $\mathbb{C} = -(d_{sum}^*)^2 px < 0$;
- iv) $\mathbb{B} = (p+x) - (x-p)d_{sum}^*$ and $\mathbb{C} = -(d_{sum}^*)^2 px < 0$.

We infer that the quadratic polynomial in (39) contains at least a root with positive real part since for each ordering, either \mathbb{B} or \mathbb{C} is negative. This implies that matrix A_M is not Hurwitz; therefore, the colinear formations are unstable.

Remark 3: The bearing-only control law proposed in [17] can be obtained from the current control law by $P_{g_{ij}} e_{ijb} = -P_{g_{ij}} g_{ij}^*$. After following the steps as we have carried out for the gradient-based bearing control law, we infer that the closed-loop dynamics for the (1D2B) and (1B2D) robot setups contain only equilibrium configurations and no moving configurations. The incorrect equilibrium configurations, in which either one or both of the bearing vectors are incorrect, are found to be unstable after linearization; the desired equilibrium is almost globally stable.

V. NUMERICAL EXAMPLE

We consider two triangular formation shapes with the same distances d_{12}^* and d_{13}^* but different value for the internal angle θ^* (Note: $\theta^* = \cos^{-1}(g_{12}^{*\top} g_{13}^*)$). In particular, shape \mathbf{T}_1 has bearing vectors such that the internal angle is $\theta_{\mathbf{T}_1}^* = 15^\circ$ while for shape \mathbf{T}_2 , we take $\theta_{\mathbf{T}_2}^* = 45^\circ$. We set the gain ratio R_{bd} to a value 4. Taking the different setups into consideration, the threshold distance such that moving formations (stable or unstable) exist is $\hat{d} = 2\sqrt{3} \approx 3.4641$. We set the desired distances to $d_{12}^* = d_{13}^* = 4$ and assume $\angle g_{12}^* = 0^\circ$. Thus, shape \mathbf{T}_1 and \mathbf{T}_2 has the following desired constraints:

$$\begin{aligned} \mathbf{T}_1 : d_{12}^* = d_{13}^* = 4; \angle g_{12}^* = 0^\circ, \angle g_{13}^* = 15^\circ; \\ \mathbf{T}_2 : d_{12}^* = d_{13}^* = 4; \angle g_{12}^* = 0^\circ, \angle g_{13}^* = 45^\circ. \end{aligned} \quad (40)$$

For shape \mathbf{T}_1 , the moving formation for the (1D2B) setup is unstable, since $\cos^2(15^\circ) = 0.9330 > 0.9321$. Hence, the constraint in (24) is violated. For shape \mathbf{T}_2 , we obtain $\cos^2(15^\circ) = 0.5 < 0.9321$ satisfying constraint (24).

In the current example, we first intentionally set the gain ratio R_{bd} and then obtain desired distances d_{ij}^* s, in order to show the existence and local asymptotic stability of moving formations in the (1D2B) setup.

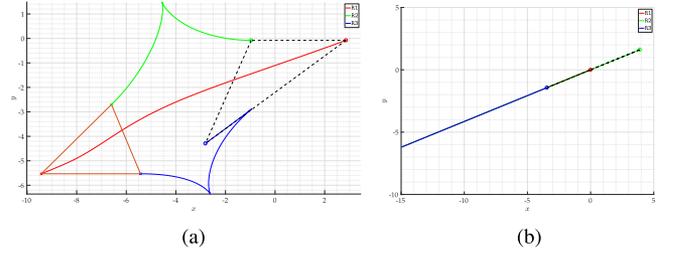


Fig. 5. Robot trajectories for the (1B2D) setup. On the left panel, we have an initial configuration where robots move and converge to the flipped formation shape while the right panel illustrates the evolution of the robots when the initial configuration satisfy conditions for ordering III in Fig. 3.

A. (1D2B) Simulation Results

For the three robots in the (1D2B) setup, we focus on the formation shape \mathbf{T}_2 . The Jacobian matrix A_M for the moving formation with distances $d_{12} = d_{13} \approx 3.8686$ is checked to be Hurwitz. Therefore, employing the closed-loop dynamics (5) can, depending on the initial configuration $p(0)$, lead to robot trajectories moving with a constant velocity. In Fig. 4(b), we show such an outcome for a specific $p(0)$. Fig. 4(a) depicts an initial $p(0)$ leading to convergence to the correct shape.

B. (1B2D) Simulation Results

For the three robots in the (1B2D) setup, we focus on the formation shape \mathbf{T}_1 . There are two equilibrium formations, namely, the correct and desired formation and the flipped formation satisfying only the distance constraints but not the bearing constraints. Fig. 5(a) depicts an initial configuration $p(0)$, which converges to this flipped formation. Notice that the signed area corresponding to $p(0)$ is positive (counterclockwise cyclic ordering of the robots) while the flipped formation has a negative signed area (clockwise cyclic ordering of the robots). Fig. 5(b) depicts an initial colinear configuration $p(0)$ leading to the robots to move with a constant velocity when employing the closed-loop dynamics (27). When perturbed, it will converge either to the correct or the flipped formation shape.

VI. CONCLUSION

In the current article, we have considered the formation shape problem for teams of three robots partitioned into two categories, namely: 1) distance and 2) bearing robots. Our aim was to employ gradient-based control laws in a heterogeneous setting and provide a systematic study on the stability of the possible formation shapes that arise as a result. We have shown that under certain conditions on the distance and bearing error signals, we obtain distorted formation shapes moving with a constant velocity w . For the (1B2D) robot setup, these undesired formation shapes are unstable while for the (1D2B) robot setup, we derive conditions such that one of the distorted moving formation shape is locally asymptotically stable. When the gains K_d and K_b are chosen such that the required desired distances d_{ij}^* s are smaller than a threshold distance $\hat{d}(K_b, K_d)$, then moving formation shapes do not exist. Depending on the setup considered, this may lead to global asymptotic stability of the desired formation shape.

We note that the moving configurations in the (1D2B) setup and the flipped equilibrium configuration in the (1B2D) setup both have a signed area that has an opposite sign compared to the signed area of the desired formation shape. Hence, the use of signed constraints

as introduced in [15] and [18] is a possible future direction. For the (1D2B) setup, the inclusion of the signed area constraint in [15] does not increase the sensing load of the distance robot while it can have the potential of mitigating the existence of distorted formation shapes.

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