Analysis of different Lyapunov function constructions for interconnected hybrid systems

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Abstract—This paper studies stability of interconnections of hybrid dynamical systems, in the general scenario that the continuous or discrete dynamics of subsystems may have destabilizing effects. We analyze two existing methods of constructing Lyapunov functions for the interconnection based on candidate ISS Lyapunov functions for subsystems, small-gain conditions, and auxiliary timers modeling restrictions on jump frequency in terms of average dwell-time and reverse average dwell-time. We compare their feasibility and limitations for different types of subsystem dynamics, and examine a case that the combination of them is needed to establish global asymptotic stability.

I. INTRODUCTION

In studying practical phenomena one usually finds it beneficial to transform a complex system into an interconnection of simpler ones and to establish stability based on properties of the constituents via small-gain theorems. Classical input-output small-gain theorems for linear systems were detailed in [1] and were generalized to nonlinear feedback systems in [2], [3]. The notion of input-to-state stability (ISS) [4] is widely used in more recent works on interconnections, as it naturally unifies the concepts of internal and external stability. Small-gain theorems for interconnected ISS systems were introduced in [5], and furthered in [6], [7] and the references therein. Small-gain theorems are particularly useful in constructing Lyapunov functions for interconnections based on ISS Lyapunov functions for subsystems. Lyapunov-based small-gain theorems for general feedback interconnections were first reported in [8] for continuous-time systems and then in [9] for discrete-time ones.

Hybrid systems are dynamical systems exhibiting both continuous and discrete behaviors. This paper adopts the modeling framework in [10], which proves to be general and natural from the viewpoint of Lyapunov stability theory [11]. Trajectory-based small-gain theorems for interconnections of hybrid systems were introduced in [12], [13], and Lyapunov-based formulations were established in [14], [15].

In this work we study interconnections of hybrid systems with either continuous or discrete non-ISS dynamics—a more challenging case that the results above cannot be directly applied. In the presence of destabilizing dynamics, stability is often achieved by restricting the jump frequency in terms of average dwell-time (ADT) [16] (for non-ISS jumps) and/or reverse ADT (RADT) [17] (for non-ISS flows). In [15] it was shown that one can augment the subsystems by introducing ADT/RADT auxiliary timers to construct ISS Lyapunov functions that decrease along solutions both during flows and at jumps. However, it was observed in [18] that such modifications inevitably increase the feedback gains, making the small-gain condition afterwards more restrictive.

A different type of Lyapunov-based small-gain theorems was proposed in [19] for interconnected impulsive systems in a similar setting. This result generated a Lyapunov function by first constructing a candidate Lyapunov function (i.e., one that may increase during flows or at jumps) for the interconnection based on candidate ISS Lyapunov functions for subsystems and a small-gain condition, and then applying the suitable ADT/RADT modification to the interconnection instead of to the subsystems. While this method works under the same small-gain condition for interconnections of only ISS subsystems, it does not apply to the case when the non-ISS dynamics in subsystems are of different types (i.e., non-ISS flows in one while non-ISS jumps in the other).

In [18] we unified the two methods above (for interconnections of $n \geq 2$ hybrid systems) and established less restrictive small-gain conditions by showing that it suffices to only modify the subsystems with one type (either flow or jump) of destabilizing dynamics. In this paper we provide a thorough analysis of the Lyapunov function constructions above for interconnections of two hybrid subsystems. Compared with the previous results, explicit Lyapunov-based small-gain conditions for establishing stability of the interconnection via ADT/RADT modifications are derived. Moreover, our small-gain conditions indicate that, unlike ADT modifications, the RADT ones induce no substantial increase in the feedback gains. Striving for as simple a setting as possible, we distill the main features of the approaches in [15], [19] and highlight their relative advantages.

This paper is structured as follows: In Section II we introduce the hybrid system framework. A small-gain theorem for the baseline case of only ISS subsystems is provided in Section III. In Section IV we study different cases of destabilizing dynamics in subsystems, and identify a scenario that the combination of the two methods above is required.

II. HYBRID SYSTEM

Following [11], a hybrid system with state $x \in \mathcal{X} \subset \mathbb{R}^n$ and input $u \in \mathcal{U} \subset \mathbb{R}^m$ is modeled by

$$\dot{x} \in F(x, u), \quad (x, u) \in \mathcal{C},$$

$$x^+ \in G(x, u), \quad (x, u) \in \mathcal{D}, \quad (1)$$
where $F : \mathcal{X} \times \mathcal{U} \to \mathbb{R}^n$, $G : \mathcal{X} \times \mathcal{U} \to \mathcal{X}$ are set-valued mappings. Solutions of (1) are defined on a so-called hybrid time domain $E \subseteq \mathbb{R}_{\geq 0} \times \mathbb{Z}_{\geq 0}$, which is a union of a finite or infinite sequence of intervals $[t_j, t_{j+1}) \times \{j\}$, with the last one (if existent) possibly of the form $[t, T) \times \{j\}$ with $T \in \mathbb{R}$ or $T = \infty$. A hybrid input is a function $u : \text{dom} \ u \to \mathcal{U}$ defined on a hybrid time domain such that $u(t, j)$ is Lebesgue measurable and locally essentially bounded on $\{t \times \{j\} : (t, j) \in \text{dom} \ u\}$ for each fixed $j$. A solution $x \circ \text{dom} \ x \to \mathcal{X}$ of (1) with a hybrid input $u : \text{dom} \ u \to \mathcal{U}$ satisfies $x(t, j)$ is locally absolutely continuous on $\{t \times \{j\} : (t, j) \in \text{dom} \ x\}$ for each fixed $j$, $\text{dom} \ x = \text{dom} \ u$, $u(0, 0) \in \mathcal{C} \cup \mathcal{D}$, and

1. $(x(t, j), u(t, j)) \in \mathcal{C}$ and $\dot{x}(t, j) \in F(x(t, j), u(t, j))$ for all $j$ and almost all $t$ such that $(t, j) \in \text{dom} \ x$;
2. $(x(t, j), u(t, j)) \in \mathcal{D}$ and $\dot{x}(t, j + 1) \in G(x(t, j), u(t, j))$ for all $(t, j) \in \text{dom} \ x$ such that $(t, j + 1) \in \text{dom} \ x$.

With proper assumptions on the data $H = (\mathcal{C}, F, D, G)$, one can establish the local existence of solutions of (1), which are not necessarily unique (see, e.g., [10, Prop. 2.10]). A solution is maximal if it cannot be extended, and is complete if its domain is unbounded.

The hybrid system (1) is input-to-state stable (ISS) w.r.t. a set $\mathcal{A} \subset \mathcal{X}$ if there exist $\beta \in \mathcal{K}_{\infty}, \gamma \in \mathcal{K}_{\infty}$ such that every solution $x$ with a hybrid input $u$ satisfies

$$|x(t, j)|_{\mathcal{A}} \leq \beta(|x(0)|_{\mathcal{A}}, t + j) + \gamma(|u(t, j)|),$$

for all $(t, j) \in \text{dom} \ x$, where $\cdot |_{\mathcal{A}}$ denotes the Euclidean distance to the set $\mathcal{A}$, and $\cdot \|_{(t, j)}$ the essential supremum Euclidean norm up to hybrid time $(t, j)$, that is,

$$|u|_{(t, j)} := \max \left\{ \text{ess sup}_{s \leq t, l \leq j} \left| u(s, l) \right|, \sup_{s \leq t \leq j} \left| u(s, l) \right| \right\},$$

where $J(u) := \{(s, l) \in \text{dom} \ u : (s, l + 1) \in \text{dom} \ u\}$.

The Clarke derivative [20] of a locally Lipschitz function $V : \mathbb{R}^n \to \mathbb{R}$ at $x$ in the direction $v \in \mathbb{R}^n$ is defined by

$$V^v(x; v) := \limsup_{s \to 0^+, y \to x} \frac{V(y + sv) - V(y)}{s}.$$  

**Definition 1.** A locally Lipschitz function $V : \mathcal{X} \to \mathbb{R}_{\geq 0}$ is a candidate ISS Lyapunov function w.r.t. $\mathcal{A}$ for the hybrid system (1) with bounds $\psi_1, \psi_2$, a gain $\chi$, and rates $\phi, \alpha$ if

1. there exist $\psi_1, \psi_2 \in \mathcal{K}_{\infty}$ such that $\psi_1(|x|_{\mathcal{A}}) \leq V(x) \leq \psi_2(|x|_{\mathcal{A}})$ for all $x \in \mathcal{X}$;
2. there exist a $\chi \in \mathcal{K}_{\infty}$ and a continuous $\phi : \mathbb{R}_{\geq 0} \to \mathbb{R}$ with $\phi(0) = 0$ such that

$$V(x) \geq \chi(|u|) \Rightarrow V^v(x; v) \leq -\phi(V(x))$$

for all $(x, u) \in \mathcal{C}$ and $v \in F(x, u)$; and

3. there exists a continuous, positive definite $\alpha : \mathbb{R}_{\geq 0} \to \mathbb{R}_{\geq 0}$ such that

$$V(y) \leq \max \{\alpha(V(x)), \chi(|u|)\}$$

for all $(x, u) \in \mathcal{D}$ and $y \in G(x, u)$ (with the same $\chi$).

It is an ISS Lyapunov function w.r.t. $\mathcal{A}$ if $\phi$ is positive definite and $\alpha$ is a contraction on $\mathbb{R}_{\geq 0}$, that is, if

$$\phi(r) > 0, \alpha(r) < r \quad \forall r > 0.$$

For brevity, we omit the term “w.r.t. $\mathcal{A}$” when $\mathcal{A} = \{0\}$. The candidate ISS Lyapunov function is defined for studying the effects of destabilizing flows or jumps. When it is actually decreasing along solutions of (1), the term “candidate” is dropped (cf. [11, Def. 2.5 and Prop. 2.6]) and ISS is achieved.

**Proposition 1** ([11, Prop. 2.7]). The hybrid system (1) is ISS w.r.t. $\mathcal{A}$ if it admits an ISS Lyapunov function w.r.t. $\mathcal{A}$.

**Remark 1.** In the absence of inputs, ISS is equivalent to the notion of global pre-asymptotic stability (pre-GAS), that is, there exist $\beta \in \mathcal{K}_{\mathcal{L}}$ such that all solutions satisfy

$$|x(t, j)|_{\mathcal{A}} \leq \beta(|x(0)|_{\mathcal{A}}, t + j) \quad \forall (t, j) \in \text{dom} \ x.$$  

Pre-GAS corresponds to the standard notion of global asymptotic stability without requiring completeness of all maximal solutions, that is, all solutions are stable, bounded, and all complete solutions converge to the origin; cf. [10, Def. 3.6] and [15, p. 1397]. In this case, candidate ISS Lyapunov functions become candidate Lyapunov functions, and ISS Lyapunov functions become functions, which ensure pre-GAS of the hybrid system (1).

### III. INTERCONNECTION

Consider a hybrid system with state $x = (x_1, x_2) \in \mathcal{X}$ transformed into an interconnection of two subsystems with states $x_1 \in \mathcal{X}_1 \subset \mathbb{R}^{n_1}$ and $x_2 \in \mathcal{X}_2 \subset \mathbb{R}^{n_2}$ modeled by

$$\dot{x}_i = f_i(x_1, x_2), \quad (x_1, x_2) \in \mathcal{C},$$

$$x_i^+ = g_i(x_1, x_2), \quad (x_1, x_2) \in \mathcal{D}, \quad i = 1, 2.$$  

For $i = 1, 2$, we let $j := \{1, 2\} \setminus \{i\}$ throughout this paper. Each $x_1$-subsystem of (6) treats the state $x_j$ as an input.

**Remark 2.** The analysis and results in this and the following sections also apply to the case of interconnections with external inputs and/or set-valued maps, that is,

$$\dot{x} \in F_i(x, u), \quad (x, u) \in \mathcal{C} \times \mathcal{U},$$

$$x_i^+ \in G_i(x, u), \quad (x, u) \in \mathcal{D} \times \mathcal{U}, \quad i = 1, 2.$$  

We omit the external inputs and consider only the special case of single-valued maps here to better focus on investigating effects and implications of the interconnection.

**A. Small-gain condition**

Assuming that each subsystem admits a candidate ISS Lyapunov function, we investigate stability of the interconnection (6) based on small-gain conditions.
**Assumption 1.** Each $x_i$-subsystem (with input $x_j$) admits a candidate ISS Lyapunov function $V_i : X_i \to \mathbb{R}_{\geq 0}$ with bounds $\psi_1, \psi_2$, a gain $\chi$, and rates $\phi, \alpha$.

We say that two gains $\gamma_1, \gamma_2 \in K_\infty$ satisfy the small-gain condition if

$$
\gamma_1(\gamma_2(r)) < r \quad \forall r > 0.
$$

(7)

**Lemma 1** ([8, Lemma A.1]). Provided that the small-gain condition (7) holds, there exists a $\rho \in K_\infty$ such that $\rho \in C^1$ with $\rho' > 0$ on $\mathbb{R}_{>0}$, and

$$
\gamma_1^{-1}(r) > \rho(r) > \gamma_2(r) \quad \forall r > 0.
$$

(8)

Based on Lemma 1, we are able to combine the candidate ISS Lyapunov functions for subsystems to construct a candidate Lyapunov function for the interconnection (6).

**Proposition 2** ([15, Th. III.1]). Consider the interconnection (6). Suppose that Assumption 1 and (7) hold for

$$
\gamma_i := \chi_i \circ \psi_j^{-1}, \quad (i, j) = (1, 2), (2, 1).
$$

(9)

With $\rho$ in (8), the function $V : \mathcal{X} \to \mathbb{R}_{\geq 0}$ defined by

$$
V(x) := \max\{\rho(V_1(x_1)), V_2(x_2)\}
$$

(10)

is a candidate Lyapunov function for (6) with bounds $\psi_1, \psi_2$ defined by $\psi_1(r) := \min\{\rho(\psi_1(r/\sqrt{2})), (1/2)\}$ and $\psi_2(r) := \max\{\rho(\psi_2(r)), \psi_1(r/\sqrt{2})\}$, and rates $\alpha, \phi$ defined by $\phi(r) := \min\{\rho(\phi^{-1}(r))\}$, $\phi^{-1}(r)$, $\phi^{-1}(r)$, and $\alpha(r) := \max\{\rho(\alpha_1(r)), \alpha_2(r), \rho(\chi_1(r)), \rho(\chi_2(r))\}$.

If $V$ is a Lyapunov function then we can conclude pre-GAS of (6) via Proposition 1 and Remark 1. In the following we establish pre-GAS for various cases of subsystems.

**B. ISS subsystems**

Consider the case that each subsystem admits an ISS Lyapunov function.

**Proposition 3.** Consider the interconnection (6). Suppose that Assumption 1 holds with $V_1, V_2$ being ISS Lyapunov functions, and (7) with $\gamma_1, \gamma_2$ defined by (9). Then the function $V$ defined by (10) with $\rho$ in (8) is a Lyapunov function for (6), and hence (6) is pre-GAS.

If (4) doesn’t hold for one of $\phi_1, \phi_2, \alpha_1, \alpha_2$ then it doesn’t for the corresponding $\phi, \alpha$ in Proposition 2, either. Thus the function $V$ defined by (10) is not a Lyapunov function, and we cannot conclude pre-GAS. In the following section, we consider such cases and establish pre-GAS for particular sets of solutions.

**IV. Modifying ISS Lyapunov functions**

In this section, we investigate stability of the interconnection (6) for the cases that the flows or the jumps in its subsystems have destabilizing effects, via suitable ADT/RADT modifications. Candidate ISS Lyapunov functions with linear rates are required for such modifications.

A. Candidate exponential ISS Lyapunov functions

**Definition 2.** A candidate ISS Lyapunov function w.r.t. $A$ for the hybrid system (1) with the rates $\phi, \alpha$ in (2), (3) satisfying $\phi(r) = cr$ and $\alpha(r) = e^{-dr}$ for all $r \geq 0$ with some constants $c, d \in \mathbb{R}$ is called a candidate exponential ISS Lyapunov function w.r.t. $A$ with rate coefficients $c, d$. It is an exponential ISS Lyapunov function w.r.t. $A$ if $c, d > 0$.

**Remark 3.** Using arguments similar to the proof of [17, Th. 2, (b) $\Rightarrow$ (c)], one can show that the existence of an ISS Lyapunov function is equivalent to that of an exponential one. In general, even for continuous-time systems, the existence of a candidate ISS Lyapunov function is not equivalent to that of an exponential one. This can be seen readily from the following simple example. The scalar system $\dot{x} = x^3$ admits a candidate ISS Lyapunov function $V(x) := x^2$ with $\nabla V(x)x^3 = 2x^4 = 2V(x)^2$. However, it is not forward complete, and hence does not admit a candidate exponential ISS Lyapunov function [21, Th. 2].

**Assumption 2.** Each $x_i$-subsystem (with input $x_j$) admits a candidate exponential ISS Lyapunov function $V_i : X_i \to \mathbb{R}_{\geq 0}$ with bounds $\psi_1, \psi_2$, a gain $\chi$, and rate coefficients $c_i, d_i$.

The next corollary follows directly from Propositions 2, 3.

**Corollary 4.** Consider the interconnection (6). Suppose that Assumption 2 and (7) hold for $\gamma_1, \gamma_2$ defined by (9). With $\rho$ in (8), the function $V$ defined by (10) is a candidate Lyapunov function for (6) with rates $\phi, \alpha$ defined by $\phi(r) := \min\{cr, c_1\rho(\rho^{-1}(r))\}$, $\alpha(r) := \max\{\rho(e^{-d_1}\rho^{-1}(r)), \rho(e^{-d_2}\rho^{-1}(r)), \rho(\chi_2(r)), \rho(\chi_2(\rho^{-1}(r)))\}$. If $c_1, c_2, d_1, d_2 > 0$ then it is a Lyapunov function, and hence (6) is pre-GAS.

Suppose that each subsystem of (6) admits a candidate exponential ISS Lyapunov function. If in one subsystem both the flows and the jumps are destabilizing (i.e., $c_i, d_i \leq 0$ for $i = 1$ or 2), we cannot establish stability by restricting the jump frequency. In the following, we consider the other cases when at least one of $c_1, c_2, d_1, d_2$ is non-positive.

**B. Destabilizing flows: RADT modification**

Consider the case that Assumption 2 holds with $c_1, c_2 \leq 0 < d_1, d_2$, that is, the flows in both subsystems have destabilizing effects. Pre-GAS can be established for solutions that jump fast enough, in the sense of reverse average dwell-time [17]. We say a solution $x$ of (1) admits a reverse average dwell-time (RADT) $\tau_a^\ast > 0$ if

$$
j - k \geq (t - s)/\tau_a^\ast - N_0^\ast
$$

(11)

for all $(s, k), (t, j) \in \text{dom } x$ such that $t + j \geq s + k$ with an integer $N_0^\ast \geq 1$. If $N_0^\ast = 1$ then $\tau_a^\ast$ becomes a reverse dwell-time: any two consecutive jumps are separated by at most $\tau_a^\ast$. Following [22], a solution $x$ satisfies (11) if and

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4The cases that only one of $c_1, c_2$ is non-positive can be handled by a similar approach, see the discussion after Theorem 5.
only if dom $x = \text{dom } \tau$ for an RADT timer $\tau$ modeled by
\[ \dot{\tau} = 1/\tau^*, \quad \tau \in [0,N_0^*], \]
\[ \tau^+ = \max\{0, \tau - 1\}, \quad \tau \in [0,N_0^*]. \]
Consider the augmented interconnection\(^6\)
\[ \dot{x_i} = f_i(x), \quad i = 1, 2, \quad \tau \in \tilde{C}^*, \]
\[ x_i^+ = g_i(x), \quad i = 1, 2, \quad \tau^+ = \max\{0, \tau - 1\}, \quad \tau \in \tilde{D}^* \]
with $\tilde{C}^* = C \times [0, N_0^*]$ and $\tilde{D}^* = D \times [0, N_0^*]$. Following [18, Prop. 6] (which extends [15, Prop. IV.4]), for each $(x_i, \tau)$-subsystem of (12) (with input $x_j$), the function $W : X_i \times [0,N_0^*] \to \mathbb{R}_{\geq 0}$ defined by
\[ W_i(x_i, \tau) := e^{-L_i \tau} V_i(x_i) \quad (13) \]
with $L_i > 0$ is a candidate exponential ISS Lyapunov function w.r.t. $A_i := \{0\} \times [0,N_0^*]$ with bounds $e^{-L_i N_0^*} |\psi_{1i}|, |\psi_{2i}|$, gain $\chi_i$, and rate coefficients $c_i^*, d_i^*$ defined by
\[ c_i^* := c_i + L_i/\tau^*, \quad d_i^* := d_i - L_i. \quad (14) \]
Therefore, if the RADT $\tau^*_a$ satisfies\(^5\)
\[ -c_i \tau^*_a < d_i \quad (15) \]
then there exists an $L_i \in (-c_i \tau^*_a, d_i)$ such that $c_i^*, d_i^* > 0$, and hence that $W_i$ is an exponential ISS Lyapunov function.
To establish pre-GAS of (12) via Corollary 4, which requires (7) with
\[ \tau_i(r) := \chi_i(\psi_{1j}^{-1}(e^{L_j N_0^*} r)), \quad (i,j) = (1,2),(2,1). \quad (16) \]
\[ \text{Lemma 2. Suppose that there is an } \varepsilon > 0 \text{ such that} \]
\[ (1 + \varepsilon) \chi_1(\psi_{1j}^{-1}((1+\varepsilon) \chi_2(\psi_{1j}^{-1}(r)))) < r \quad \forall r > 0, \quad (17) \]
and that $\tau_a^*$ and $N_0^*$ satisfy (15) and
\[ -c_i \tau_a^* N_0^* < \ln(1+\varepsilon) \]
for all $i \in \{1,2\}$. Then there exist $L_i \in (-c_i \tau_a^*, d_i)$, $L_j \in (-c_j \tau_a^*, d_j)$ such that (7) holds for $\gamma_1, \gamma_2$ defined by (16).
From Corollary 4 and the analysis above it follows that:
\[ \text{Theorem 5. Consider the interconnection (6). Suppose that} \]
Assumption 2 holds with $c_1, c_2 \leq 0 < d_1, d_2$, and that there is an $\varepsilon > 0$ such that (17) holds. For each RADT $\tau_a^*$ and integer $N_0^* \geq 1$ satisfying (15) and (18) for all $i \in \{1,2\}$, there exist $L_i \in (-c_i \tau_a^*, d_i)$ and $L_j \in (-c_j \tau_a^*, d_j)$ such that (7) holds for $\gamma_1, \gamma_2$ defined by (16).
Then the function $W : X \times [0,N_0^*] \to \mathbb{R}_{\geq 0}$ defined by $W(x, \tau) := \max\{\rho(e^{-L_i \tau} V_i(x_1)), e^{-L_2 \tau} V_2(x_2)\}$ with $\rho$ in (8) is a Lyapunov function w.r.t. $A := \{0\} \times [0,N_0^*]$ for the augmented interconnection (12), and hence the pre-GAS estimate (5) holds for all solutions satisfying (11).
For each $c_1, c_2 \leq 0 < d_1, d_2$ and each $\varepsilon > 0$ satisfying (17), there exists an $\text{RADT } \tau^*_a$ small enough that (15) and (18) hold for all $i \in \{1,2\}$. Meanwhile, if $c_i > 0$ then (15) and (18) always hold; and if $c_1, c_2 \geq 0$ then the conclusions of Theorem 5 hold for arbitrary $\tau^*_a > 0$ and $N_0^* \geq 1$.
The coefficient $1 + \varepsilon$ in (17) can be made arbitrarily close to 1 with a sufficiently small $\varepsilon$. Consider the following small-gain conditions:
\[ \text{(SG1) The inequality (7) holds for } \gamma_1, \gamma_2 \text{ defined by (9).} \]
\[ \text{(SG2) There is an } \varepsilon > 0 \text{ such that (17) holds.} \]
We say that (SG2) is generic in (SG1), in the sense that every pair of gains $\chi_1, \chi_2$ satisfying (SG1) can be approximated by a pair satisfying (SG2). Therefore, the RADT modification induces no substantial increase in the feedback gains.
\[ \text{C. Destabilizing jumps: ADT modification} \]
Consider the case that Assumption 2 holds with $c_1, c_2 > 0 \geq d_1, d_2$, that is, the jumps in both subsystems have destabilizing effects.\(^7\) Pre-GAS can be established for solutions that jump slow enough, in the sense of average dwell-time [16]. We say a solution $x$ of (1) admits an average dwell-time (ADT) $\tau_a > 0$ if
\[ \tau_a^+ := \max\{0, \tau - 1\}, \quad \tau \in [0,N_0^*]. \]
\[ \tau^+ = \tau - 1, \quad \tau \in [0,1], \quad \tau \in [1,\infty]. \]
Consider the augmented interconnection
\[ \dot{x_i} = f_i(x), \quad i = 1, 2, \quad \tau \in \tilde{C}, \]
\[ x_i^+ = g_i(x), \quad i = 1, 2, \quad \tau^+ = \tau - 1, \quad \tau \in \tilde{D}, \]
with $\tilde{C} = C \times [0,N_0^*]$ and $\tilde{D} = D \times [1,N_0^*]$. Following [18, Prop. 5] (which extends [15, Prop. IV.1]), for each $(x_i, \tau)$-subsystem of (20) (with input $x_j$), the function $W_i : X_i \times [0,N_0^*] \to \mathbb{R}_{\geq 0}$ defined by
\[ W_i(x_i, \tau) := e^{L_i \tau} V_i(x_i) \quad (21) \]
with $L_i > 0$ is a candidate exponential ISS Lyapunov function w.r.t. $A_i := \{0\} \times [0,N_0^*]$ with bounds $|\psi_{1i}|, e^{L_i N_0^*} |\psi_{2i}|$, gain $e^{L_i N_0^*} \chi_i$, and rate coefficients $\tilde{c}_i, \tilde{d}_i$ defined by
\[ \tilde{c}_i := c_i - L_i/\tau_a, \quad \tilde{d}_i := d_i + L_i. \quad (22) \]
Therefore, if the ADT $\tau_a$ satisfies
\[ c_i \tau_a > -d_i, \quad (23) \]
then there exists an $L_i \in (-d_i, c_i \tau_a)$ such that $\tilde{c}_i, \tilde{d}_i > 0$, and hence that $W_i$ is an exponential ISS Lyapunov function.
To establish pre-GAS of (20), we construct a Lyapunov function for (20) via Corollary 4, which requires (7) with
\[ \gamma_i(r) := e^{L_i N_0^*} \chi_i(\psi_{1j}^{-1}(r)), \quad (i,j) = (1,2), (2,1) \quad (24) \]
\[ \text{The cases that only one of } d_1, d_2 \text{ is non-positive can be handled by a similar approach, see the discussion after Theorem 6.} \]
\[ \text{5} \]There is a scaling difference between the RADT timers here and in [22].
\[ \text{6} \]Compared to [15, 18], we use one timer for all subsystems, due to the fact that the RADT is a property of the hybrid timer domain, which is the same for both subsystems.\[ \text{7} \]The cases that only one of $d_1, d_2$ is non-positive can be handled by a similar approach, see the discussion after Theorem 6.
Lemma 3. Suppose that there is an $\varepsilon > 0$ such that
\[(1+\varepsilon)e^{-d_1}\chi_1(\psi^{-1}_1((1+\varepsilon)e^{-d_1}\chi_2(\psi^{-1}_1(r)))) < r \quad \forall r > 0,\]
and that $\tau_a$ and $N_0$ satisfy (23) and
\[-d_i(N_0 - 1) < \ln(1 + \varepsilon),\]
for all $i \in \{1, 2\}$. Then there exist $L_1 \in (-d_1, c_1\tau_a)$, $L_2 \in (-d_2, c_2\tau_a)$ such that (7) holds for $\gamma_1, \gamma_2$ defined by (24).

From Corollary 4 and the analysis above it follows that:

Theorem 6. Consider the interconnection (6). Suppose that Assumption 2 holds with $c_1, c_2 > 0 \geq d_1, d_2$, and that there is an $\varepsilon > 0$ such that (25) holds. For each ADT $\tau_a$ and integer $N_0 \geq 1$ satisfying (23) and (26) for all $i \in \{1, 2\}$, there exist $L_1 \in (-d_1, c_1\tau_a)$ and $L_2 \in (-d_2, c_2\tau_a)$ such that (7) holds for $\gamma_1, \gamma_2$ defined by (24).

Then the function $W : \mathcal{X} \times [0, N_0] \to \mathbb{R}_{\geq 0}$ defined by $W(x, \tau) := \max\{\rho(e^{L_1\tau \chi_1(x_1)}), e^{L_2\tau \chi_2(x_2)}\}$ with $\rho$ in (8) is a Lyapunov function w.r.t. $\mathcal{A} := \{0\} \times [0, N^*] \times [0, N_0]$ for the augmented interconnection (28), and hence the pre-GAS estimate (5) holds for all solutions satisfying (19).

E. Destabilizing flows and jumps

Consider the case that the jumps in one subsystem and the flows in the other one have destabilizing effects. Without loss of generality, suppose Assumption 2 holds with $c_1, d_2 < 0 < c_2, d_1$. Pre-GAS can be established for solutions that jump neither too fast nor too slow, in the sense of combined ADT $\tau_a$ and RADT $\tau_a^*$. Consider the augmented interconnection
\[
\begin{align*}
\dot{x}_1 &= f_1(x), \quad \dot{\tau}_1 = 1/\tau_a^*, \\
\dot{x}_2 &= f_2(x), \quad \dot{\tau}_2 \in [0, 1/\tau_a], \\
x_1^+ &= g_1(x), \quad \tau_1^+ = \max\{0, \tau_1 - 1\}, \\
x_2^+ &= g_2(x), \quad \tau_2^+ = \tau_2 - 1,
\end{align*}
\]
so that there is no $\varepsilon > 0$ such that (25) holds, and hence Theorem 6 cannot be applied.
and hence the pre-GAS estimate (5) holds for all solutions satisfying (11) and (19).

Consider the small-gain condition in Theorem 8: (SG4) There is an $\varepsilon > 0$ such that (29) holds. Similarly to (SG3) in Section IV-C, (SG4) is clearly not generic in (SG1) because of the substantially larger gain for the $(x_2, \tau_2)$-subsystem due to the ADT modification.

**F. Destabilizing flows and jumps: an alternate construction**

Consider the case that Assumption 2 holds with $c_1, d_2 \leq 0 < c_2, d_1$, and $\gamma_1, \gamma_2$ defined by (9) are linear, that is, (27) holds with $\xi_1, \xi_2 > 0$. Then pre-GAS can be established under the less restrictive small-gain condition (SG1) instead of (SG4), by applying first the RADT modification to the $(x_1, \tau_1)$-subsystem in (28) (with input $x_2$), and then the ADT one to the $(x_1, x_2, \tau_1)$-interconnection. The function $W_{1}$ defined by (13) with $L_1 > 0$ is a candidate exponential ISS Lyapunov function for the $(x_1, \tau_1)$-subsystem of (28) (with input $x_2$) with rate coefficients $c_1, d_1$ defined by (14).

To invoke Corollary 4 for the $(x_1, x_2, \tau_1)$-interconnection it requires (7) with $\gamma_1$ defined by (9) and $\gamma_2$ by (16), that is,

$$L_1 < -\ln(\xi_1 \xi_2)/N_0 =: \overline{L}.$$  

(31)

With $\mu \in (\xi_2 e^{L_1}, N_0, 1/\xi_1)$, the function $\overline{W} : \mathcal{X} \times [0, N_0] \to \mathbb{R}_{\geq 0}$ defined by $\overline{W}(x, \tau_1) := \max\{\mu e^{-L_1 \tau_1} V_1(x_1), V_2(x_2)\}$ is a candidate exponential Lyapunov function w.r.t. $A := \{0\} \times [0, N_0]$ with rate coefficients $c \in \min\{c_1 + L_1/\tau_1, c_2\}$ and $d := \min\{d_1 - L_2, d_2\}$, where $c > 0$ if

$$L_1 > -c_1 \tau_1^*,$$

(32)

and $d \leq d_2 \leq 0$ (hence, unlike in the case in Section IV-B, $L_1 < d_1$ is not needed). Moreover, from Section IV-C we see the ADT modification requires $\overline{c} \tau_1 > L_2 > -d$, that is,

$$\tau_1 \min\{c_1 + L_1/\tau_1, c_2\} > L_2 \geq \max\{L_1 - d_1, -d_2\}.$$  

(33)

Following the proof of Lemmas 2, 3, if $\tau_0, \tau_1^*$ and $N_0$ satisfy

$$c_2 \tau_0 > -d_2,$$

$$\mu \in (\xi_2 e^{L_1}, N_0, 1/\xi_1)$$

(34)

then there exist $L_1, L_2 > 0$ such that (31)–(33) hold. The ADT modification yields the following result:

**Proposition 9. Consider the interconnection (6). Suppose that Assumption 2 holds with $c_1, d_2 \leq 0 < c_2, d_1$, and that $\gamma_1, \gamma_2$ defined by (9) satisfy (27) with $\xi_1, \xi_2 < 1$. For each ADT $\tau_0$, RADT $\tau_1^*$ and integer $N_0 \geq 1$ satisfying (34), there exists $L_1, L_2$ such that (31)–(33) hold. Then the function $W : \mathcal{X} \times [0, N_0] \times [0, N_0] \to \mathbb{R}_{\geq 0}$ defined by $W(x, \tau_1, \tau_2) := e^{L_2 \tau_2} \max\{\mu e^{-L_1 \tau_1} V_1(x_1), V_2(x_2)\}$ with $\mu \in (\xi_2 e^{L_1}, N_0, 1/\xi_1)$ is a Lyapunov function for the augmented interconnection (28), and hence the pre-GAS estimate (5) holds for all solutions satisfying (11) and (19).

**(Remark 5.)** For an example of this construction.

**References**


