

Nonlinear
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Adaptation
and Self-
Organizing
Systems

Control of large 1D

networks
of double
integrator
agents:
role of
heterogeneity
and
asymmetry
on
stability

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margin

He Hao, Prabir

Barooah

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We
consider
the
distributed
control
of a
network
of
heterogeneous
agents
with
double
integrator
dynamics
to
maintain
a rigid
formation
in 1D
Euclidean
space.
The
control
signal at
a vehicle
is
allowed
to use

relative
position
and
velocity