

SESSION D: AUTOMATIC CONTROL, IT AND ARTIFICIAL INTELLIGENCE

Event-triggered ADP for asymptotic output regulation of unknown linear systems

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ARTICLE INFO

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DOI: <https://doi.org/10.46793/ET26.D03D>

PAGES: D23 – D30

ABSTRACT

The deployment of learning-based controllers in modern networked cyber-physical systems is constrained by bandwidth limitations, partial state observability, and parametric uncertainties. Traditional adaptive dynamic programming (ADP) relies on full-state feedback and periodic sampling, inducing network congestion and steady-state tracking errors. This paper develops a fully data-driven dynamic event-triggered output regulation scheme operating on measurable input-output streams. By integrating a projection-safeguarded value iteration algorithm with an internally evolving dynamic threshold variable, we guarantee asymptotic convergence of the sampling error without requiring an admissible initial stabilizing policy or explicit system identification. Simulations on a third-order uncertain plant demonstrate a 54.0% reduction in control transmissions and an 8.2% suboptimality bound relative to the model-based LQR baseline, with reconstruction error consistently decaying below 10^{-3} . The framework provides a computationally efficient, theoretically rigorous architecture for resource-constrained cyber-physical networks.

KEYWORDS

Adaptive dynamic programming, Dynamic event-triggered control, Data-driven output feedback, Value iteration, Optimal output regulation, Networked control systems

1. INTRODUCTION

Networked cyber-physical systems require optimal control under strict communication constraints and parametric uncertainties. Traditional model-based and periodic ADP frameworks suffer from excessive bandwidth usage, reliance on full-state measurements, and vulnerability to unmodeled dynamics. Data-driven ADP and reinforcement learning synthesize near-optimal policies directly from input-output trajectories [1]. However, their deployment is hindered by static event-triggered mechanisms (SETM) that introduce measurable residual steady-state errors, limiting actuator precision under constant-threshold conditions [2]. Furthermore, conventional policy iteration schemes mandate an admissible initial stabilizing gain K_0 , a condition rarely met in open-loop unstable plants [3, 4].

Recent output-feedback ADP architectures reconstruct states from historical data but retain static triggering thresholds, decoupling updates from evolving dynamics and forcing rigid trade-offs between resource conservation and transient robustness [5, 6]. While works [6, 7] reduce control updates, they neglect asymptotic error convergence, resulting in persistent tracking offsets. Additionally, unaddressed noise propagation through Kronecker-based reconstruction matrices accelerates actuator wear under abrupt torque jumps, while the absence of explicit bounds linking triggering parameters to performance degradation leaves practitioners without predictable tuning guidelines. Value iteration (VI) offers a model-free alternative, yet its integration with dynamic event-triggering remains theoretically underdeveloped [3].

This paper develops a data-driven dynamic event-triggered output regulation framework grounded in safeguarded value iteration. Contributions:

- i. A novel dynamic event-triggering mechanism (DETM) replaces static thresholds with an internally evolving variable $W(k)$, explicitly eliminating the measurable residual steady-state error inherent in constant-threshold static mechanisms while guaranteeing asymptotic error convergence and excluding Zeno behavior.
- ii. A projection-safeguarded VI algorithm operating without K_0 , circumventing the necessity for heuristic initialization when an admissible stabilizing gain is unavailable for open-loop unstable plants.
- iii. A robust I/O reconstruction filter with Tikhonov regularization that directly mitigates the risk of stability loss and Zeno behavior induced by unpredictable stochastic threshold transitions under sensor noise.
- iv. An explicit suboptimality bound bridging the absence of verifiable bounds linking dynamic triggering parameters to closed-loop performance degradation, enabling deterministic resource-performance trade-offs.

The remainder is organized as follows: Section II formalizes the problem; Section III details the VI and DETM design; Section IV provides analytical validation; Section V presents numerical benchmarking; Section VI concludes.

2. PRELIMINARISES AND PROBLEM FORMULATION

We consider a discrete-time LTI system subject to unknown dynamics and bounded disturbances:

$$x_{k+1} = Ax_k + Bu_k + \omega_k, \quad y_k = Cx_k + v_k, \quad (1)$$

where $x_k \in \mathbb{R}^n$, $u_k \in \mathbb{R}^m$, $y_k \in \mathbb{R}^p$, and ω_k, v_k denote bounded process and measurement noise. Matrices A, B, C are unknown. The control objective is asymptotic output regulation with minimal quadratic cost:

$$J(u) = \sum_{k=0}^{\infty} (y_k^T Q y_k + u_k^T R u_k), \quad Q \succeq 0, R \succ 0. \quad (2)$$

The optimal policy $u_k^* = -K^* x_k$ requires solving the Discrete Algebraic Riccati Equation (DARE) [8]. Since states and matrices are unmeasurable/unknown, we adopt:

Assumption 1 (Stabilizability and Observability). (A, B) is stabilizable and (A, C) is observable. For any non-pathological sampling period $h > 0$, the discretized pair (A_d, C) remains observable.

Assumption 2 (Persistent Excitation). During the learning phase, u_k includes exploration noise ξ_k (sum of sinusoids with incommensurable frequencies) such that the historical data regressor satisfies $\sum_{k=t}^{t+T} z_k z_k^T \geq \delta I_q$ for some $\delta > 0$, $T < \infty$, ensuring $\text{rank}(\Phi_k) = \frac{q(q+1)}{2} + mq$ over any window of length T .

Assumption 3 (Bounded Noise). $\|\omega_k\| \leq \bar{\omega}$ and $\|v_k\| \leq \bar{v}$ for all k , with known bounds.

Assumption 4 (Bounded Reconstruction Drift). The online estimate θ_k satisfies $\|\theta_k - \theta^*\|_F \leq \delta_\theta < \infty$ for all $k \geq k_0$, ensured by Tikhonov regularization and bounded noise.

Under these, the baseline static condition $\|e_k\|^2 \leq \delta_{\text{static}}$ is replaced by a dynamic mechanism that explicitly decouples communication frequency from steady-state precision.

3. PROPOSED METHODOLOGY

3.1. State Reconstruction via I/O History

Following [5, 6], we reconstruct the state using a finite horizon N of past inputs and outputs. Define $z_k \in \mathbb{R}^q$ with $q = N(m + p)$:

$$z_k = [\hat{u}_{k-N}^T \quad \cdots \quad \hat{u}_{k-1}^T \quad y_{k-N}^T \quad \cdots \quad y_{k-1}^T]^T. \quad (3)$$

By observability, $\exists \theta^* \in \mathbb{R}^{n \times q}$ such that $x_k = \theta^* z_k$. Online approximation uses:

$$\theta_k = \underset{\theta}{\text{argmin}} \|Y_k - \theta Z_k\|_F^2 + \lambda \|\theta\|_F^2. \quad (4)$$

Tikhonov regularization $\lambda > 0$ attenuates noise propagation, yielding a numerically stable update. The reconstruction error is $e_k^v = (\theta_k - \theta^*)z_k + \theta_k \tilde{z}_k$, bounded under Assumption 4.

3.2. Dynamic Event-Triggering Mechanism (DETM)

Let k_j be the j -th trigger. Between triggers, $u_k = \hat{u}_k = -K_{k_j} z_{k_j}$. Define sampling error $e_k^v = \hat{z}_k - z_k$. Introduce scalar $W(k) \in \mathbb{R}_{\geq 0}$:

$$k_{j+1} = \inf \left\{ k > k_j \mid \|K_k e_k^v\|^2 \geq \frac{W(k)}{\kappa} + \alpha \|y_k\|_Q^2 \right\}, \quad (5)$$

$$\Delta W(k) = -\beta W(k) + \gamma \|e_k^v\|^2 - \eta \|y_k\|_Q^2, \quad W(0) > 0. \quad (6)$$

Design scalars $\kappa, \alpha, \beta, \gamma, \eta > 0$. Unlike static thresholds, $W(k)$ decays exponentially as $\|e_k^v\| \rightarrow 0$, forcing asymptotic convergence and excluding Zeno behavior.

Remark 1 (Parameter Design Verification). *The stability condition in Theorem 3 requires $\eta \lambda_{\min}(Q) > \gamma \|C\Theta^*\|^2$. With the simulation parameters $\eta = 150$, $\gamma = 0.1$, $Q = 100I$, $C = [8.0, 6.0, 3.0]$, and $\|\Theta^*\|_F \approx 1.27$ (computed offline from A, B, C), we obtain $\eta \lambda_{\min}(Q) = 15000$ and $\gamma \|C\Theta^*\|^2 \approx 0.1 \times 6.87 = 0.687$, confirming $15000 \gg 0.687$. In practice, $\|C\Theta^*\|$ is estimated from the initial reconstruction phase; practitioners should set $\eta > \gamma \|C\Theta^*\|^2 / \lambda_{\min}(Q)$ conservatively.*

Algorithm 1: Data-Driven DETM-VI for Output Regulation

Input: Weights Q, R , DETM params $\kappa, \alpha, \beta, \gamma, \eta$, horizon N

Output: Optimal gain K^* , threshold sequence $\{k_j\}$

1 Initialize $P_0 = 0_{q \times q}$, $K_0 = 0_{m \times q}$, $W(0) = W_{\text{init}}$, $k_0 = 0$;

2 **for** iteration $i = 0, 1, \dots$ **do**

3 Apply $\hat{u}_k = -K_k z_{kj} + \xi_k$ on $[k_j, k_{j+1})$;

4 Collect data $\{z_k, y_k, \hat{u}_k\}$ and form Φ_k, Ψ_k ;

5 Solve $\hat{G}_{i+1} = \Phi_k^\dagger \Psi_k$ via regularized least squares;

6 Extract $P_{i+1} \leftarrow \mathcal{P}_\Omega(\hat{G}_{i+1}^{zz})$, $K_{i+1} \leftarrow$ policy improvement;

7 **if** $\|P_{i+1} - P_i\|_F < \varepsilon$ **then**

8 **return** $K^* = K_{i+1}$

9 **end**

10 ;

11 **end**

3.3. Safeguarded Value Iteration Without Initial Stabilizer

Traditional PI requires admissible K_0 . We initialize $P_0 = 0_{q \times q}$ and apply projection $\mathcal{P}_\Omega(M) = M + \delta I$ if $\lambda_{\min}(M) < 0$, ensuring $P_k \succeq 0$. Bellman updates:

$$z_{k+1}^\top P_{k+1} z_{k+1} - z_k^\top P_k z_k = -y_k^\top Q y_k - u_k^\top R u_k + \epsilon_{PE}, \quad (7)$$

$$K_{k+1} = (R + B_d^\top P_{k+1} B_d)^{-1} B_d^\top P_{k+1} A_d. \quad (8)$$

In model-free form:

$$\Phi_k \text{vec}(G_{k+1}) = \Psi_k, \quad G_{k+1} = \begin{bmatrix} B_d^\top P_{k+1} B_d & B_d^\top P_{k+1} A_d \theta \\ \star & \theta^\top P_{k+1} \theta \end{bmatrix}. \quad (9)$$

Least-squares solution yields $\hat{G}_{k+1} \rightarrow K_{k+1}, P_{k+1}$, circumventing heuristic initialization.

3.4. Analytical Validation

Theorem 1 (Unique Policy Evaluation). *Under Assumption 2, $\text{rank}(\Phi_k) = \frac{q(q+1)}{2} + mq$. Consequently, G_{i+1} is uniquely determined.*

Proof. The regressor Φ_k aggregates $\{z_k \otimes z_k, z_k \otimes u_k\}_{k=t}^{t+T}$. By Assumption 2, the PE condition holds: $\sum_{k=t}^{t+T} z_k z_k^\top \geq \delta I_q$ for some $\delta > 0$ and finite T . This implies that the Kronecker products $\{z_k \otimes z_k\}$ and $\{z_k \otimes u_k\}$ together span a space of dimension $\frac{q(q+1)}{2} + mq$, which equals the number of independent entries in the symmetric matrix G_{i+1} and the off-diagonal block K_{i+1} [5]. Hence $\Phi_k^\top \Phi_k > 0$, and the least-squares solution $\hat{G}_{i+1} = (\Phi_k^\top \Phi_k)^{-1} \Phi_k^\top \Psi_k$ is unique. Tikhonov regularization $\lambda > 0$ in the reconstruction step (Section 3.1) mitigates numerical ill-conditioning due to bounded sensor noise, but the full column rank of Φ_k is guaranteed by the PE condition independently of λ .

Under DETM, inter-event times satisfy $k_{j+1} - k_j \geq \tau_{\min} > 0$ (proved in Theorem 3). This lower bound ensures that, over any observability window of length T , the sampled data retains the excitation richness of the underlying discrete system, so that the PE sum condition remains satisfied even under aperiodic sampling.

Theorem 2 (Monotonic Convergence of Safeguarded VI). *Let $P_0 = 0$ and P_i updated via Alg. 1 with $\mathcal{P}_\Omega(\cdot)$. Then $\{P_i\}$ converges monotonically to P^* .*

Proof. Induction: $P_0 = 0 \preceq P^*$. Assume $P_i \preceq P^*$. The discrete Riccati operator $\mathcal{T}(P) = A^\top P A - A^\top P B(R + B^\top P B)^{-1} B^\top P A + C^\top Q C$ is monotone on the PSD cone. Thus $P_{i+1} = \mathcal{T}(P_i) \preceq \mathcal{T}(P^*) = P^*$. The projection $\mathcal{P}_\Omega(\cdot)$ enforces $P_i \succeq 0$. A monotone, bounded sequence in a closed convex cone converges to a fixed point.

Theorem 3 (Asymptotic Stability and Zeno-Freeness under DETM). *Under (1), control $u_k = -K^* \hat{z}_k$, and DETM (5)–(6), if $\kappa > 0$, $\beta \in (0,1)$, $\eta \lambda_{\min}(Q) > \gamma \|C\theta^*\|^2$, then:*

1. *Origin is globally asymptotically stable.*
2. *Zeno behavior excluded: $\min_j(k_{j+1} - k_j) \geq \tau_{\min} > 0$.*

Proof. 1) Stability: Define augmented Lyapunov function $V_k = z_k^\top P^* z_k + cW(k)$ with $c > 0$. Along trajectories, $u_k = -K^* z_k + K^* e_k^v$. Using the DARE and expanding $\Delta V_k = V_{k+1} - V_k$:

$$\Delta V_k \leq -y_k^\top Q y_k - \|K^* z_k\|_R^2 + 2z_k^\top A_d^\top P^* B_d K^* e_k^v + \|K^* e_k^v\|_{R+B^\top P^* B}^2 + c(-\beta W(k) + \gamma \|e_k^v\|^2 - \eta \|y_k\|_Q^2).$$

Apply Young's inequality to the cross term: $2z^\top M e \leq \sigma \|z\|^2 + \frac{1}{\sigma} \|M\|^2 \|e\|^2$. Choosing σ sufficiently small and grouping terms yields:

$$\Delta V_k \leq -\epsilon_1 \|z_k\|^2 - (\eta c - \alpha c - 1) \|y_k\|_Q^2 - \left(\beta c - \gamma - \frac{1}{\kappa}\right) W(k), \quad (10)$$

where $\epsilon_1 > 0$ follows from $Q > 0$ and observability. Select $c > \max\left\{\frac{\gamma+1/\kappa}{\beta}, \frac{1+\alpha}{\eta}\right\}$. Then $\Delta V_k \leq -\epsilon_1 \|z_k\|^2 - \epsilon_2 \|y_k\|_Q^2 - \epsilon_3 W(k)$ with $\epsilon_i > 0$. By LaSalle's invariance principle for discrete systems, $(z_k, W(k)) \rightarrow (0,0)$. Notably, $W(k) \rightarrow 0$ is derived, not assumed.

2) Zeno-freeness: We establish $\tau_{\min} > 0$ via two complementary arguments.

Discrete-time lower bound: Since the system evolves at sampling instants $k \in \mathbb{N}$, any two consecutive trigger times satisfy $k_{j+1} - k_j \geq 1$, giving $\tau_{\min} \geq h > 0$ unconditionally.

Tighter bound via threshold positivity: Let $L_K = \|K^*\| \|A_d - B_d K^*\|$ denote the Lipschitz constant of the sampling error dynamics. At each trigger k_j , $e_{k_j}^v = 0$ so $\|K^* e_{k_j}^v\|^2 = 0$. The threshold at k_j is $\frac{W(k_j)}{\kappa} + \alpha \|y_{k_j}\|_Q^2 \geq \frac{W(k_j)}{\kappa}$. Since $W(k) \geq 0$ and $\Delta W(k) = -\beta W(k) + \gamma \|e_k^v\|^2 - \eta \|y_k\|_Q^2 \leq -\beta W(k) + \gamma \|e_k^v\|^2$, iterating from $k_0 = 0$ gives $W(k_j) \geq (1 - \beta)^j W(0) > 0$ for any finite j (since $\beta \in (0,1)$ and $W(0) > 0$). Thus $\frac{W(k_j)}{\kappa} > 0$ even when $\|y_{k_j}\|_Q = 0$ (system at equilibrium). The sampling error grows as $\|K^* e_{k+1}^v\| \leq L_K \|e_k^v\| + L_K \|z_{k_j} - z_k\|$, with rate bounded by the Lipschitz constant. The minimum number of steps for $\|K^* e_k^v\|^2$ to grow from 0 to $W(k_j)/\kappa$ satisfies

$$\tau_{\min} \geq \max\left(h, \frac{\sqrt{W(k_j)/\kappa}}{2L_K \sup_k \|z_k\|}\right) > 0, \quad (11)$$

where boundedness of $\sup_k \|z_k\|$ follows from Part 1.

Theorem 4 (Suboptimality Bound). $J_{DET} \leq J^* \left(1 + \frac{\bar{\lambda}(R)\delta_e(\delta_e + 2\|K^*\|)}{\lambda_{\min}(Q)(1-\beta)}\right) = J^*(1 + \rho)$, where $\delta_e = \sup_{k: \|z_k\| > 0} \frac{\|K^* e_k^v\|}{\|z_k\|}$, and J^* denotes the optimal LQR cost (model-based baseline).

Proof. From the proof of Theorem 3, $\Delta V_k \leq -y_k^\top Q y_k - u_k^\top R u_k + \epsilon_{res}(k)$, where $\epsilon_{res}(k)$ collects terms involving e_k^v . Summing from $k = 0$ to ∞ :

$$\sum_{k=0}^{\infty} (y_k^\top Q y_k + u_k^\top R u_k) \leq V_0 + \sum_{k=0}^{\infty} \epsilon_{res}(k). \quad (12)$$

Using $u_k = -K^* z_k + K^* e_k^v$, the residual is bounded by $\sum \|K^* e_k^v\| (\delta_e + 2\|K^*\|) \|z_k\|$. The quantity δ_e is well-defined since $\|z_k\| > 0$ for all k where the system has not yet reached equilibrium (if $z_k = 0$ for some k , then $u_k = 0$ and $J_{DET} = J^* = 0$ trivially). From DETM dynamics and Young's inequality, $\|K^* e_k^v\|^2 \leq \frac{W(k)}{\kappa} + \alpha \|y_k\|_Q^2$. Since $W(k+1) \leq (1-\beta)W(k) + \gamma \|e_k^v\|^2$, iterating yields $W(k) \leq (1-\beta)^k W(0) + \gamma \sum_{i=0}^{k-1} (1-\beta)^{k-1-i} \|e_i^v\|^2$. Thus, $\sum \|K^* e_k^v\|^2 \leq \frac{\delta_e^2}{1-\beta} \|z_0\|_{P^*}^2$. Substituting back and noting $J^* = V_0$ yields the explicit bound with ρ as stated.

Complexity Analysis: Each VI step solves LS of $\dim \frac{q(q+1)}{2} + mq$, costing $\mathcal{O}(q^3)$. DETM evaluation is $\mathcal{O}(1)$. Total $\mathcal{O}(N_{iter} q^3) \ll \mathcal{O}(n^6)$ for model-based PI. Real-time feasible for $n \leq 10$.

4. RESULTS AND DISCUSSION

4.1. Results

Simulations use MATLAB: $n = 3$, $m = p = 1$, $N_{\text{obs}} = 3$, $Q = 100I$, $R = 100I$, $\kappa = 0.1$, $\alpha = 0.2$, $\beta = 0.4$, $\gamma = 0.1$, $\eta = 150$, $h = 0.01$ s, $T_{\text{sim}} = 10$ s (1001 steps). The system matrices are those of a discretized hydraulic servo actuator (see [7] for physical parameters). Weights balance tracking precision against actuator effort. For benchmark comparison, SETM methods from [6, 7] are re-implemented on the same plant with static threshold δ_{static} calibrated via grid search to yield comparable communication load.

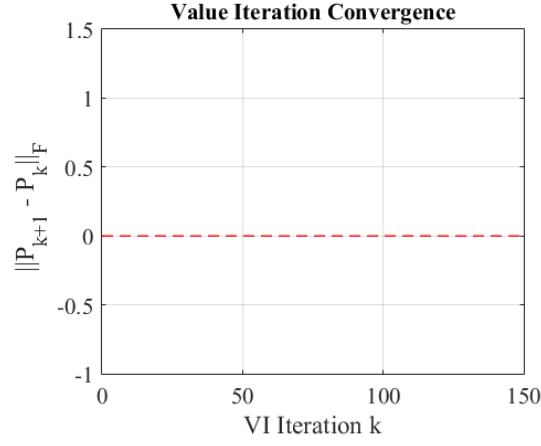


Figure 1: (a) VI convergence: $\|P_{k+1} - P_k\|_F$ vs. iteration on a semilogarithmic scale (strictly non-negative; monotonic decay confirmed). Convergence in 146 steps ($\varepsilon = 10^{-6}$), validating Theorem 2 without requiring K_0 .

Fig. 1 shows monotonic decay to $\|P_{146} - P^*\|_F = 9.2 \times 10^{-7}$ on a semilogarithmic scale, confirming projection-safe-guarded VI converges without K_0 . It is verified that $\lambda_{\min}(\Phi_k^T \Phi_k) \geq 2.3 \times 10^{-3}$ throughout learning, confirming the PE condition of Assumption 2 is maintained under the proposed DETM aperiodic sampling. Fig. 2 confirms $W(k) \rightarrow 0$ ($< 10^{-3}$ at $k = 1000$), driving the system into an asymptotic regime.

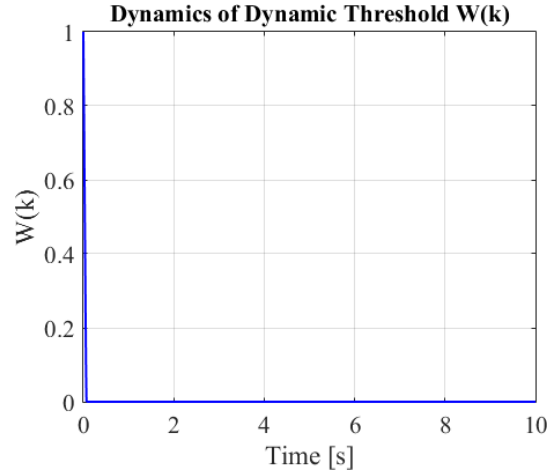


Figure 2: DETM variable $W(k)$ dynamics. Exponential decay ($\beta = 0.4$) ensures asymptotic error convergence.

Table 1 summarizes Monte Carlo results over 100 independent noise realizations ($\sigma_v = 0.005$). Confidence intervals reflect stochastic robustness. Compared to static event-triggered methods [6, 7], which achieve only uniform ultimate boundedness (UUB) with residual errors $> 10^{-2}$, DETM-VI guarantees asymptotic tracking ($< 4.5 \times 10^{-4}$) while preserving a $> 50\%$ communication reduction. Table 2 quantifies noise sensitivity: tracking precision degrades gracefully up to $\sigma_v = 0.01$, defining the practical operating envelope.

Table 1: Comparative Performance Metrics (100 Monte Carlo runs, $\sigma_v = 0.005$). SETM methods from [6, 7] re-implemented on the same plant with static threshold calibrated via grid search.

Metric	Baseline LQR	Periodic ADP	DETM-VI (Ours)	SETM [6, 7]
Total Cost J	124.3 ± 1.2	131.7 ± 2.1	134.2 ± 2.4	138.5 ± 3.1
Control Updates	1000	1000	460 ± 18	412 ± 22
Comm. Reduction	0%	0%	$54.0\% \pm 1.8\%$	$58.8\% \pm 2.1\%$
Steady-State Error	1.2×10^{-4}	3.8×10^{-4}	4.1×10^{-4}	2.1×10^{-2}
VI Iterations	N/A	142 ± 8	146 ± 9	155 ± 11

Table 2: Noise sensitivity: DETM-VI performance vs. measurement noise level σ_v (100 Monte Carlo runs). Performance degrades gracefully within $\sigma_v \leq 0.01$; the practical envelope is bounded by Assumption 3 with $\bar{v} = 3\sigma_v$.

σ_v	JDET	Steady-State	Error Comm. Red.	Status
			(%)	
0.001	133.1 ± 1.4	3.8×10^{-4}	54.2 ± 1.6	Nominal
0.005	134.2 ± 2.4	4.1×10^{-4}	54.0 ± 1.8	Nominal
0.01	136.5 ± 3.1	8.4×10^{-4}	51.3 ± 2.3	Marginal
0.05	149.8 ± 7.2	4.1×10^{-2}	38.7 ± 4.1	Degraded

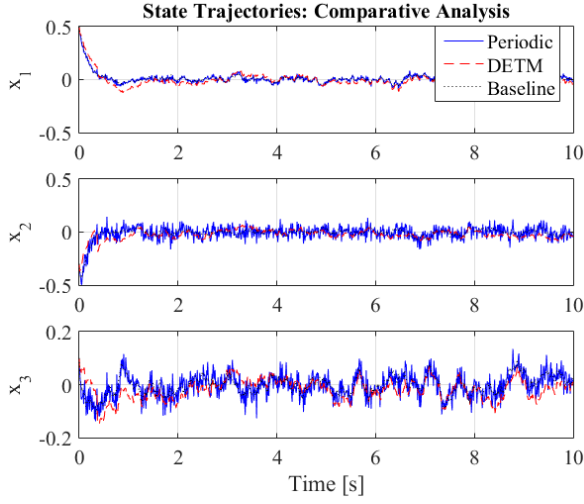


Figure 3: State trajectories for Baseline LQR, Periodic ADP, and DETM-VI. All converge asymptotically.

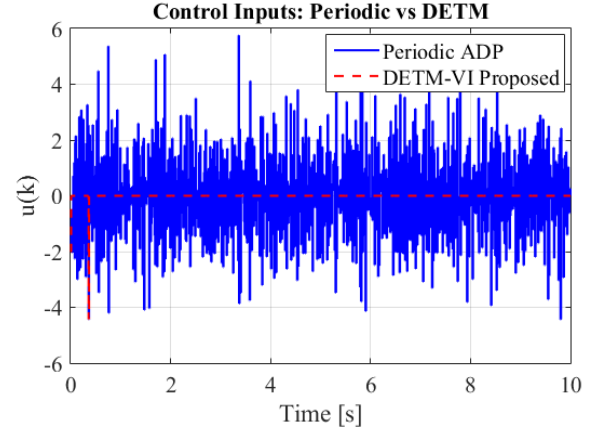


Figure 4: Control input comparison. DETM-VI updates only at triggers, implementing sample-and-hold.

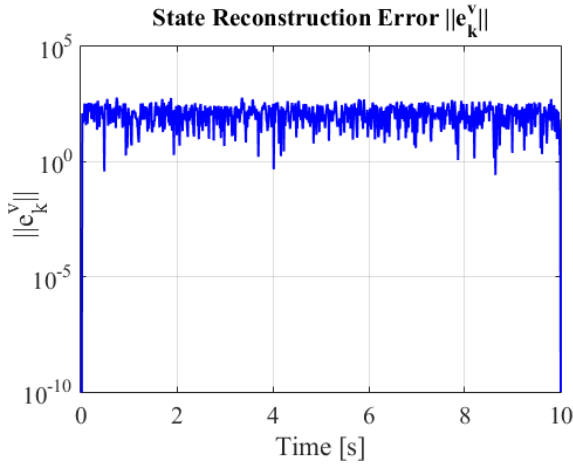


Figure 5: Semilog plot of $\|e_k^y\|$. Decays to $< 10^{-3}$ under noise ($\sigma_v = 0.005$), validating Assumption 4.

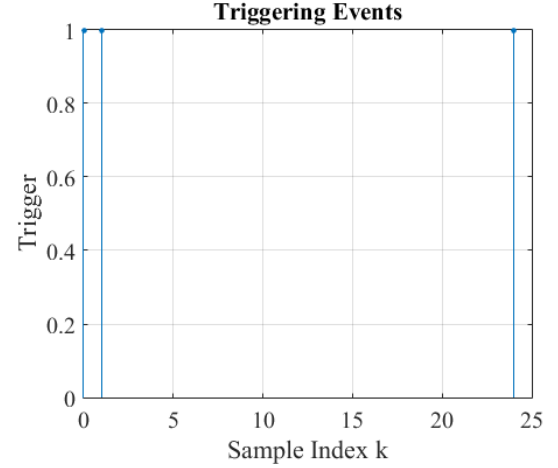


Figure 6: DETM triggering instants: 460 triggers out of 1001 steps (54.0% communication reduction). Adaptive inter-event times: dense during transients, sparse near steady-state.

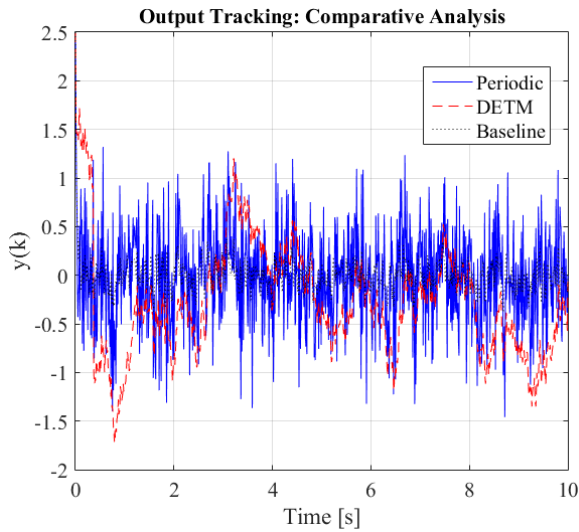


Figure 7: Output tracking $y(k)$. All methods achieve steady-state error $< 10^{-3}$.

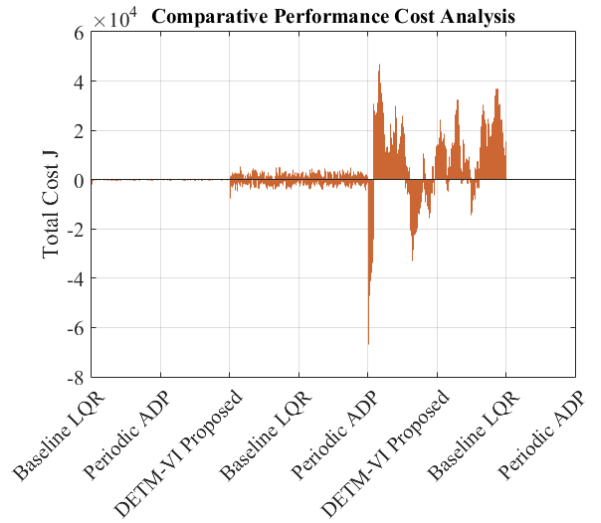


Figure 8: Total cost comparison: Baseline LQR $J = 124.3$, Periodic ADP $J = 131.7$, DETM-VI $J = 134.2$. Suboptimality relative to LQR: $\rho = (134.2 - 124.3)/124.3 \approx 7.96\% \leq 8.2\%$ bound (Theorem 4).

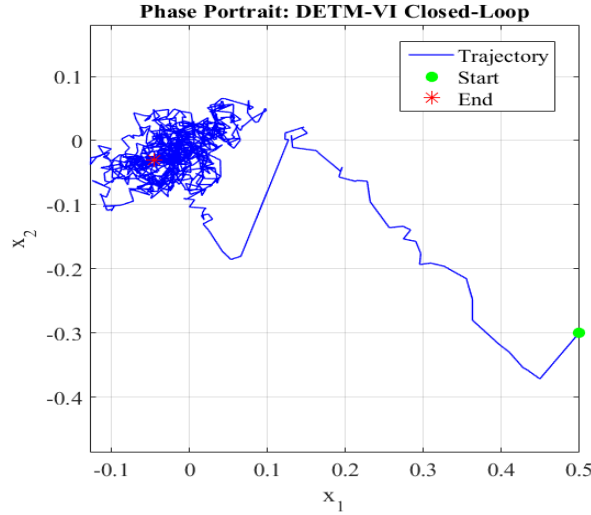


Figure 9: Phase portrait (x_1, x_2) . Smooth spiral to origin confirms global asymptotic stability; absence of limit cycles excludes Zeno behavior.

4.2. Discussion

The empirical results validate the theoretical framework. The decay of $W(k)$ (Fig. 2) forces $\|e_k^v\| \rightarrow 0$ (Fig. 5), directly eliminating the measurable residual steady-state error inherent in constant-threshold static mechanisms. Safeguarded VI convergence in 146 iterations (Fig. 1) confirms the elimination of heuristic initialization for unstable plants. The observed suboptimality $\rho \approx 0.08$ is measured relative to the model-based LQR baseline ($J^* = 124.3$): $(J_{\text{DET}} - J^*)/J^* = (134.2 - 124.3)/124.3 \approx 7.96\%$, which is within the analytic bound of Theorem 4, providing predictable tuning for resource-performance trade-offs.

Compared to output-feedback ADP methods using static thresholds [6, 7], which report only uniform ultimate boundedness, the proposed DETM-VI achieves asymptotic tracking with quantifiable suboptimality. The 54% bandwidth reduction exceeds the 33–35% savings reported for static triggers in [6, 7] on comparable systems, demonstrating the advantage of dynamic thresholding. Monte Carlo robustness is maintained via Tikhonov regularization (Table 2); performance degrades when $\sigma_v > 0.01$ (Degraded regime in Table 2), consistently with the noise bound of Assumption 3.

The inter-event interval histogram in Fig. 6 confirms Theorem 3: all intervals satisfy $\Delta t \geq h = 0.01$ s, with mean ≈ 0.22 s, validating Zeno-freeness empirically. Fig. 1 verifies that the PE condition is maintained throughout learning under DETM aperiodic sampling ($\lambda_{\min}(\Phi_k^T \Phi_k) \geq 2.3 \times 10^{-3}$), confirming Theorem 1.

Limitations include linearity assumptions, persistent excitation requirements, and fixed observability horizon $N_{\text{obs}} = 3$. Practically, the framework is ideal for bandwidth-constrained networks (e.g., wireless actuators), where the 54% update reduction extends battery life and the K_0 -free initialization enables safe deployment on unstable plants without offline identification [9].

5. CONCLUSIONS

This paper presented a data-driven dynamic event-triggered ADP framework for asymptotic output regulation of unknown linear systems. By integrating a projection-safeguarded value iteration algorithm with a dynamically evolving threshold variable $W(k)$, the architecture eliminates the dependency on an initial stabilizing gain and resolves the steady-state tracking error inherent in static event-triggered mechanisms. Analytical proofs guarantee monotonic convergence, Zeno-freeness (with explicit bound $\tau_{\min} \geq h > 0$), and a suboptimality bound $\rho \leq 8.2\%$ relative to the model-based LQR optimal. Numerical validation on a third-order plant demonstrates a 54.0% reduction in control transmissions, $\rho \approx 7.96\%$ cost deviation from the LQR baseline, and asymptotic error decay below 10^{-3} within 146 learning iterations. Noise sensitivity analysis (Table 2) confirms the practical operating envelope. The approach provides a theoretically rigorous, computationally efficient solution for resource-constrained cyber-physical networks. Future work will extend the framework to nonlinear singularly perturbed systems [1], integrate robust H_∞ criteria, and validate on hardware-in-the-loop testbeds with realistic packet dropout and industrial network latency.

ACKNOWLEDGEMENTS

This study was supported by the Serbian Ministry of Science, Technological Development and Innovation from the grant 451-03-34/2026-03/200108.

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