

Consider the continuous-time state-space equations:

$$\dot{x}(t) = Ax(t) + Bu(t), \quad (1)$$

$$y(t) = Cx(t) + Du(t). \quad (2)$$

One simple way to do discretization is that we apply Euler method, i.e.,

$$x(t + T) = x(t) + Ax(t)T + Bu(t)T,$$

where  $T$  is the time interval for discretization. Then at time  $t = kT$ , we have

$$\begin{aligned} x((k+1)T) &= (I + TA)x(kT) + TBu(kT), \\ y(kT) &= Cx(kT) + Du(kT), \end{aligned}$$

where  $I$  represents identity matrix. This discretization is easy but not accurate especially when  $T$  is large, so we consider a different discretization.

For the discretization method to be discussed next, an assumption is made first. That is, in each time interval  $T$ , the input is assumed to be constant. This is not a strong assumption as this situation is very common in computer systems. Based on the assumption, we have for  $kT \leq t < (k+1)T$ ,

$$u(t) = u(kT) =: u[k].$$

For (1), its analytical solution at  $t = kT$  and  $t = (k+1)T$  is, respectively, [1]

$$x[k] = x(kT) = e^{AkT} x(0) + \int_0^{kT} e^{A(kT-\tau)} Bu(\tau) d\tau,$$

and

$$x[k+1] = x((k+1)T) = e^{A(k+1)T} x(0) + \int_0^{(k+1)T} e^{A((k+1)T-\tau)} Bu(\tau) d\tau,$$

which can be further written as

$$\begin{aligned} x[k+1] &= e^{AT} \left[ e^{AkT} x(0) + \int_0^{kT} e^{A(kT-\tau)} Bu(\tau) d\tau \right] + \int_{kT}^{(k+1)T} e^{A(kT+T-\tau)} Bu(\tau) d\tau, \\ &= e^{AT} x[k] + \left( \int_{kT}^{(k+1)T} e^{A(kT+T-\tau)} d\tau \right) Bu[k]. \end{aligned}$$

By introducing a new variable  $\alpha := kT + T - \tau$ , we have

$$x[k+1] = e^{AT} x[k] + \left( \int_0^T e^{A\alpha} d\alpha \right) Bu[k].$$

Therefore, (1) and (2) at time  $t = kT$  become

$$x[k+1] = A_d x[k] + B_d u[k], \quad (3)$$

$$y[k] = C_d x[k] + D_d u[k]. \quad (4)$$

with

$$\begin{aligned}A_d &= e^{AT}, \\B_d &= \left( \int_0^T e^{A\tau} d\tau \right) B, \\C_d &= C, \\D_d &= D.\end{aligned}$$

In this discretization there is no approximation involved, and (4) is the exact solution of (1) at  $t = kT$  if the input is piecewise constant.

## References

- [1] C.-T. Chen, *Linear System Theory and Design*. Oxford University Press, Inc., 1998.