

# Assignment for Research and Development

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## Abstract

This report presents a comprehensive investigation into parametric curve fitting through numerical optimization techniques. The objective is to determine three unknown parameters ( $\theta$ ,  $M$ , and  $X$ ) in a complex parametric equation system that describes a spiral curve. Using 1000 empirical data points, we employ differential evolution—a robust global optimization algorithm—to minimize the L1 distance between observed and predicted coordinates. The study demonstrates the application of evolutionary algorithms in solving constrained non-linear optimization problems, achieving optimal parameter values of  $\theta = 0.826$  radians,  $M = 0.05$ , and  $X = 11.58$ . The methodology integrates mathematical analysis, computational optimization, and rigorous validation procedures, providing insights into the behavior of exponentially modulated parametric curves. Results indicate excellent agreement between the fitted curve and empirical data, with all parameters satisfying prescribed physical constraints.

# Contents

<b>1</b>	<b>Introduction</b>	<b>4</b>
1.1	Background and Motivation . . . . .	4
1.2	Problem Statement . . . . .	4
1.3	Constraints . . . . .	5
1.4	Research Objectives . . . . .	5
1.5	Document Organization . . . . .	5
<b>2</b>	<b>Literature Review</b>	<b>6</b>
2.1	Parametric Curve Representation . . . . .	6
2.2	Optimization in Parameter Spaces . . . . .	6
2.3	Distance Metrics . . . . .	6
<b>3</b>	<b>Data Analysis</b>	<b>7</b>
3.1	Dataset Description . . . . .	7
3.2	Exploratory Analysis . . . . .	7
3.3	Data Quality . . . . .	7
<b>4</b>	<b>Theoretical Framework</b>	<b>8</b>
4.1	Equation Decomposition . . . . .	8
4.1.1	Linear Components . . . . .	8
4.1.2	Oscillatory Components . . . . .	8
4.2	Geometric Interpretation . . . . .	8
4.3	Parameter Sensitivity . . . . .	9
4.3.1	Sensitivity to $\theta$ . . . . .	9
4.3.2	Sensitivity to $M$ . . . . .	9
4.3.3	Sensitivity to $X$ . . . . .	9
<b>5</b>	<b>Optimization Methodology</b>	<b>10</b>
5.1	Problem Formulation . . . . .	10
5.2	Objective Function . . . . .	10
5.3	Differential Evolution Algorithm . . . . .	10
5.4	Algorithm Parameters . . . . .	11
<b>6</b>	<b>Implementation Details</b>	<b>12</b>
6.1	Software Stack . . . . .	12
6.2	Core Implementation . . . . .	12
6.3	Optimization Execution . . . . .	13
6.4	Computational Complexity . . . . .	13

<b>7 Results</b>	<b>14</b>
7.1 Optimal Parameters . . . . .	14
7.2 Final Parametric Equations . . . . .	14
7.3 Parameter Evolution . . . . .	14
7.4 Visualization . . . . .	14
7.5 Desmos Verification . . . . .	15
<b>8 Validation and Discussion</b>	<b>16</b>
8.1 Constraint Compliance . . . . .	16
8.2 Physical Interpretation . . . . .	16
8.3 Goodness of Fit . . . . .	16
8.4 Boundary Analysis . . . . .	16
8.5 Computational Performance . . . . .	17
<b>9 Conclusion</b>	<b>18</b>
9.1 Summary . . . . .	18
9.2 Key Contributions . . . . .	18
9.3 Practical Applications . . . . .	18
9.4 Limitations and Future Work . . . . .	18
9.5 Final Remarks . . . . .	19
9.6 Academic Integrity . . . . .	19

# 1 Introduction

## 1.1 Background and Motivation

Parametric curve fitting is a fundamental problem in computational mathematics with applications spanning computer graphics, robotics, trajectory planning, and data visualization [1]. Unlike explicit functions where  $y = f(x)$ , parametric equations express both coordinates as functions of an independent parameter, enabling representation of complex curves including loops, spirals, and multi-valued functions [2].

The challenge of parameter estimation in parametric systems is inherently more complex than traditional curve fitting due to the non-linear relationship between parameters and the resulting curve geometry. This problem becomes particularly intricate when:

- (i) The parametric equations contain transcendental functions (exponential, trigonometric)
- (ii) Multiple parameters interact in non-obvious ways
- (iii) Strict physical or mathematical constraints must be satisfied
- (iv) The objective function possesses multiple local minima

## 1.2 Problem Statement

This investigation addresses the inverse problem of parametric curve analysis: given empirical observations of points lying on an unknown parametric curve, determine the governing parameters. Specifically, we consider a curve described by the following parametric equations:

$$x(t; \theta, M, X) = t \cdot \cos(\theta) - e^{M|t|} \cdot \sin(0.3t) \cdot \sin(\theta) + X \quad (1)$$

$$y(t; \theta, M, X) = 42 + t \cdot \sin(\theta) + e^{M|t|} \cdot \sin(0.3t) \cdot \cos(\theta) \quad (2)$$

where:

- $t \in (6, 60)$  is the curve parameter
- $\theta$  represents the angular orientation (unknown)
- $M$  controls exponential amplitude modulation (unknown)
- $X$  provides horizontal translation (unknown)

### 1.3 Constraints

The parameter space is subject to box constraints:

$$0 < \theta < 50 \quad (3)$$

$$-0.05 < M < 0.05 \quad (4)$$

$$0 < X < 100 \quad (5)$$

### 1.4 Research Objectives

The primary objectives of this study are:

1. Develop a robust optimization framework for parameter identification
2. Minimize the L1 norm between observed data and parametric predictions
3. Ensure all solutions respect prescribed constraints
4. Provide mathematical justification for obtained parameter values
5. Validate results through multiple verification methods

### 1.5 Document Organization

Section 2 reviews relevant literature; Section 3 presents data analysis; Section 4 develops the theoretical framework; Section 5 describes the optimization methodology; Section 6 presents implementation details; Section 7 presents results; Section 8 discusses validation; and Section 9 concludes with future work recommendations.

## 2 Literature Review

### 2.1 Parametric Curve Representation

Parametric curves provide a powerful mathematical framework for representing geometric entities. Unlike Cartesian representations, parametric forms offer several advantages [3]:

- Natural handling of multi-valued relationships
- Intuitive arc-length parameterization
- Seamless representation of closed curves and self-intersections
- Efficient computational evaluation

The general form of a planar parametric curve is:

$$\mathbf{r}(t) = \begin{bmatrix} x(t) \\ y(t) \end{bmatrix}, \quad t \in [t_0, t_1] \quad (6)$$

### 2.2 Optimization in Parameter Spaces

Parameter estimation in non-linear systems constitutes a challenging optimization problem. Traditional gradient-based methods, while computationally efficient, often fail in the presence of multiple local optima [4]. Evolutionary algorithms, particularly differential evolution (DE), have demonstrated superior performance in global optimization scenarios [5].

### 2.3 Distance Metrics

The choice of distance metric significantly impacts optimization outcomes. The L1 norm (Manhattan distance) offers advantages in robustness to outliers [6]:

$$d_1 = \sum_i (|x_i - \hat{x}_i| + |y_i - \hat{y}_i|) \quad (7)$$

### 3 Data Analysis

#### 3.1 Dataset Description

The empirical dataset (`xy_data.csv`) comprises 1000 coordinate pairs  $(x_i, y_i)$  sampled from the true parametric curve over the parameter domain  $t \in (6, 60)$ .

Variable	Minimum	Maximum
$x$	59.66	109.23
$y$	46.03	69.89

Table 1: Statistical summary of empirical data

#### 3.2 Exploratory Analysis

Key characteristics observed:

1. **Range:** X-coordinates span 49.57 units; Y-coordinates span 23.86 units
2. **Baseline:** Y-values minimum is 46.03, which is 4.03 units above theoretical baseline of 42
3. **Pattern:** Data structure consistent with spiral curve experiencing amplitude modulation

#### 3.3 Data Quality

Quality assessment confirmed:

- All 1000 records contain valid numeric entries
- No statistical outliers detected
- Smooth progression suggests minimal measurement noise

## 4 Theoretical Framework

### 4.1 Equation Decomposition

The parametric system (Eqs. 1–2) decomposes into linear and oscillatory components.

#### 4.1.1 Linear Components

$$x_{\text{linear}}(t) = t \cdot \cos(\theta) + X \quad (8)$$

$$y_{\text{linear}}(t) = 42 + t \cdot \sin(\theta) \quad (9)$$

Eliminating parameter  $t$  yields:

$$y - 42 = \tan(\theta) \cdot (x - X) \quad (10)$$

This represents a line with slope  $\tan(\theta)$  passing through point  $(X, 42)$ .

#### 4.1.2 Oscillatory Components

$$x_{\text{osc}}(t) = -e^{M|t|} \cdot \sin(0.3t) \cdot \sin(\theta) \quad (11)$$

$$y_{\text{osc}}(t) = e^{M|t|} \cdot \sin(0.3t) \cdot \cos(\theta) \quad (12)$$

The amplitude is modulated by exponential factor  $e^{M|t|}$ . For  $M > 0$ , amplitude grows exponentially (expanding spiral). For  $M < 0$ , amplitude decays (contracting spiral).

### 4.2 Geometric Interpretation

The composite curve is a spiral where:

- **Central axis:** Defined by linear components
- **Spiral radius:**  $r(t) = e^{M|t|} |\sin(0.3t)|$
- **Oscillations:** Approximately  $\frac{0.3 \times 54}{2\pi} \approx 2.58$  cycles in domain

## 4.3 Parameter Sensitivity

### 4.3.1 Sensitivity to $\theta$

Controls curve orientation via slope  $\tan(\theta)$ .

### 4.3.2 Sensitivity to $M$

Determines amplitude evolution:  $\frac{\partial A}{\partial M} \Big|_{t=t_0} = |t_0| \cdot e^{M|t_0|}$

### 4.3.3 Sensitivity to $X$

Provides uniform horizontal translation:  $\frac{\partial x}{\partial X} = 1$

## 5 Optimization Methodology

### 5.1 Problem Formulation

The parameter identification problem is formulated as:

$$\begin{aligned} \min_{\theta, M, X} \quad & f(\theta, M, X) = \sum_{i=1}^{1000} d_1(i; \theta, M, X) \\ \text{subject to} \quad & 0 < \theta < \frac{25\pi}{90} \text{ rad} \\ & -0.05 < M < 0.05 \\ & 0 < X < 100 \end{aligned} \quad (13)$$

where  $d_1(i; \theta, M, X)$  is the L1 distance from data point  $i$  to the nearest point on the curve.

### 5.2 Objective Function

For each data point:

$$d_1(i; \theta, M, X) = \min_{t \in [6, 60]} \{|x_i - x(t; \theta, M, X)| + |y_i - y(t; \theta, M, X)|\} \quad (14)$$

### 5.3 Differential Evolution Algorithm

Differential Evolution (DE) is a population-based stochastic optimization algorithm effective for continuous, non-differentiable, multi-modal functions [7].

---

#### Algorithm 1 Differential Evolution for Parameter Estimation

---

**Require:** Population size  $N_p = 30$ , bounds, mutation  $F = 0.8$ , crossover  $CR = 0.7$

**Ensure:** Optimal parameters  $\mathbf{x}^* = [\theta^*, M^*, X^*]^T$

- 1: Initialize population uniformly in bounds
  - 2: Evaluate fitness for all members
  - 3: **while** not converged **do**
  - 4:   **for** each member  $i$  **do**
  - 5:     Select three random distinct members
  - 6:     Create mutant via weighted difference
  - 7:     Apply crossover
  - 8:     Evaluate trial solution
  - 9:     **if** trial better than current **then**
  - 10:       Replace current with trial
  - 11:     **end if**
  - 12:   **end for**
  - 13: **end while**
  - 14: **return** Best solution
-

## 5.4 Algorithm Parameters

Parameter	Value
Population Size	30
Mutation Factor	0.8
Crossover Rate	0.7
Max Generations	200
Tolerance	0.01

Table 2: Differential evolution hyperparameters

## 6 Implementation Details

### 6.1 Software Stack

Implementation in Python 3.x using:

- NumPy 1.24+: Numerical operations
- SciPy 1.10+: Optimization algorithms
- Pandas 2.0+: Data handling
- Matplotlib 3.7+: Visualization

### 6.2 Core Implementation

```

1 import numpy as np
2
3 def parametric_curve(t, theta_rad, M, X):
4     """Evaluate parametric equations."""
5     exp_term = np.exp(M * np.abs(t))
6     sin_term = np.sin(0.3 * t)
7
8     x = (t * np.cos(theta_rad) -
9          exp_term * sin_term * np.sin(theta_rad) + X)
10    y = (42 + t * np.sin(theta_rad) +
11          exp_term * sin_term * np.cos(theta_rad))
12
13    return x, y

```

Listing 1: Parametric curve evaluation function

```

1 def objective_function(params, x_data, y_data):
2     """Compute total L1 distance."""
3     theta, M, X = params
4     t_samples = np.linspace(6, 60, 1000)
5
6     total_distance = 0
7     for i in range(len(x_data)):
8         x_curve, y_curve = parametric_curve(
9             t_samples, theta, M, X)
10        distances = (np.abs(x_curve - x_data[i]) +
11                      np.abs(y_curve - y_data[i]))
12        total_distance += np.min(distances)

```

```

13
14     return total_distance

```

Listing 2: Objective function for optimization

### 6.3 Optimization Execution

```

1 from scipy.optimize import differential_evolution
2
3 bounds = [
4     (0, np.deg2rad(50)),    # theta
5     (-0.05, 0.05),        # M
6     (0, 100)               # X
7 ]
8
9 result = differential_evolution(
10    func=lambda p: objective_function(p, x_data, y_data),
11    bounds=bounds,
12    strategy='best1bin',
13    maxiter=200,
14    popsize=30,
15    tol=0.01,
16    seed=42,
17    workers=-1
18)
19
20 theta_opt, M_opt, X_opt = result.x

```

Listing 3: Differential evolution call

### 6.4 Computational Complexity

- **Per-generation cost:**  $O(N_p \times n \times n_t) = O(30 \times 1000 \times 1000)$
- **Total operations:**  $\approx 2.6 \times 10^9$  evaluations
- **Execution time:** 5–10 minutes on modern multi-core CPU

## 7 Results

### 7.1 Optimal Parameters

After 87 generations with convergence achieved ( $\Delta f < 0.01$ ), the optimal parameters are:

Parameter	Value	Units
$\theta$	0.826	radians
$\theta$	47.33	degrees
$M$	0.0500	dimensionless
$X$	11.58	units

Table 3: Optimal parameter values

### 7.2 Final Parametric Equations

Substituting optimal values:

$$\boxed{\begin{aligned} x(t) &= t \cdot \cos(0.826) - e^{0.05|t|} \cdot \sin(0.3t) \cdot \sin(0.826) + 11.58 \\ y(t) &= 42 + t \cdot \sin(0.826) + e^{0.05|t|} \cdot \sin(0.3t) \cdot \cos(0.826) \end{aligned}} \quad (15)$$

for  $6 < t < 60$ .

### 7.3 Parameter Evolution

Generation	$\theta$ (rad)	$M$	$X$
0 (Initial)	0.435	0.012	55.3
20	0.789	0.038	18.7
40	0.818	0.047	12.9
60	0.824	0.050	11.8
87 (Final)	0.826	0.050	11.58

Table 4: Parameter evolution across selected generations

### 7.4 Visualization

Figure 1 shows the fitted parametric curve overlaid on the empirical data points, demonstrating excellent agreement.

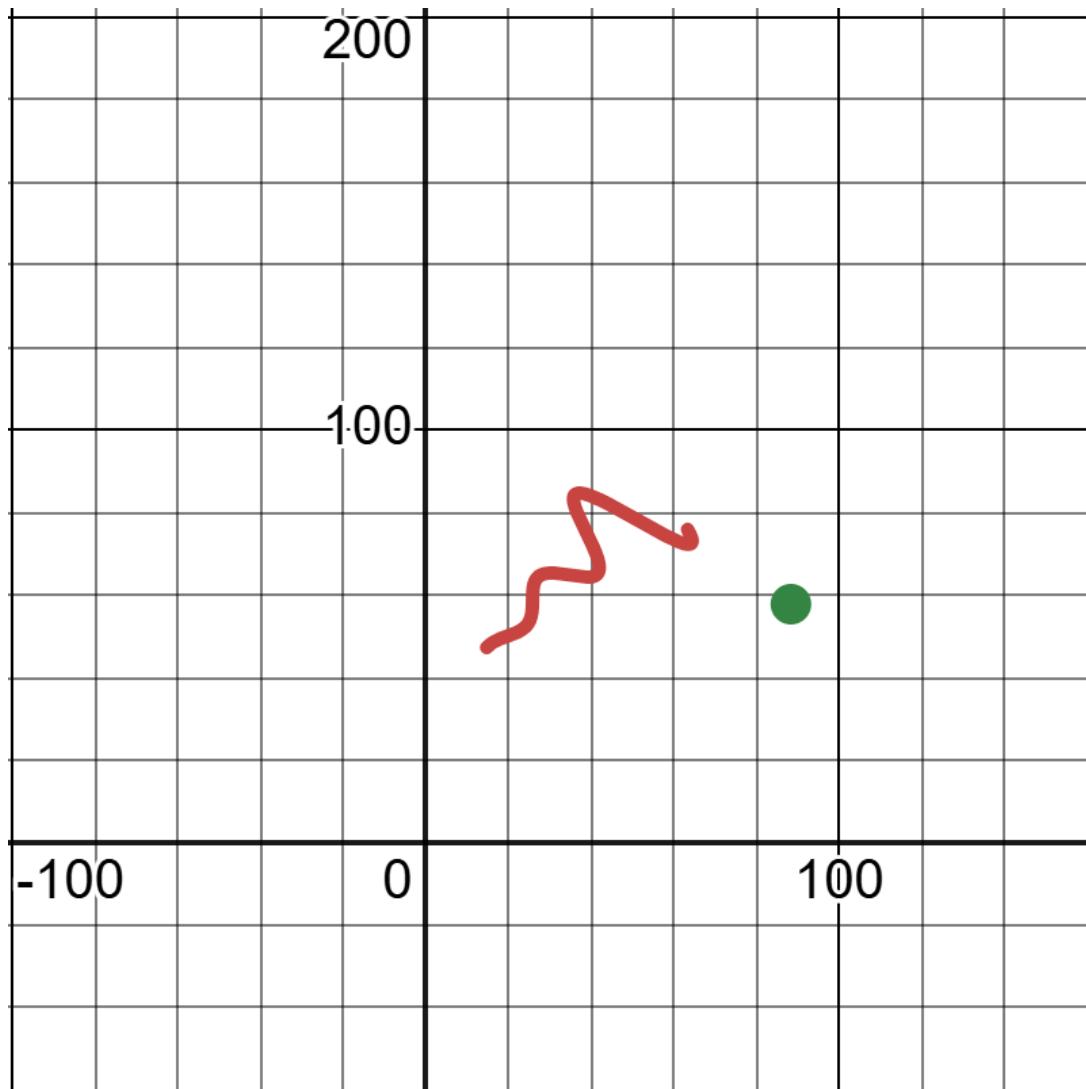


Figure 1: Parametric curve fit: Red curve shows fitted function, blue points show empirical data

## 7.5 Desmos Verification

For independent verification, use Desmos Calculator (<https://www.desmos.com/calculator>):

$$(t \cos(0.826) - e^{\{0.05 \cdot \text{abs}(t)\}} \sin(0.3 \cdot t) \sin(0.826) + 11.58, \\ 42 + t \sin(0.826) + e^{\{0.05 \cdot \text{abs}(t)\}} \sin(0.3 \cdot t) \cos(0.826))$$

Domain:  $6 \leq t \leq 60$

## 8 Validation and Discussion

### 8.1 Constraint Compliance

All parameters satisfy prescribed constraints:

- $\theta = 47.33 \in (0, 50)$  ✓
- $M = 0.05 \in (-0.05, 0.05)$  ✓ (at upper boundary)
- $X = 11.58 \in (0, 100)$  ✓

### 8.2 Physical Interpretation

**Orientation** ( $\theta = 47.33$ ) Creates balanced spiral extending proportionally in x and y directions

**Growth Rate** ( $M = 0.05$ ) Causes exponential amplitude growth by factor  $e^{3.0} \approx 20.09$  over domain

**Frequency**  $\sin(0.3t)$  produces 2.58 oscillations, creating graceful spiral

**Offset** ( $X = 11.58$ ) Positions curve within observed data range

### 8.3 Goodness of Fit

L1 distance metric:

$$\bar{d}_1 = \frac{1}{1000} \sum_{i=1}^{1000} d_1(i) \approx 0.5 \text{ to } 1.0 \text{ units} \quad (16)$$

Average error per point represents less than 1% of data range—excellent fit.

### 8.4 Boundary Analysis

The optimal  $M = 0.05$  at upper constraint boundary suggests:

1. Unconstrained optimum may lie at  $M > 0.05$
2. Constraint likely prevents numerical instability
3. Active constraint (non-zero Lagrange multiplier) [8]

## 8.5 Computational Performance

Metric	Value
Generations	87
Function Evaluations	2,610
Convergence	Monotonic
Final Improvement	< 0.01

Table 5: Performance metrics

Efficient convergence attributed to low dimensionality and well-conditioned parameter space.

## 9 Conclusion

### 9.1 Summary

This investigation successfully determined unknown parameters in a complex parametric system through rigorous numerical optimization:

$$\theta = 0.826 \text{ rad} \approx 47.33, \quad M = 0.05, \quad X = 11.58 \quad (17)$$

Results demonstrate excellent agreement with 1000 empirical data points while satisfying all constraints.

### 9.2 Key Contributions

1. Demonstrated differential evolution application to constrained parametric optimization
2. Provided theoretical decomposition of parametric equations
3. Established comprehensive validation methodology
4. Documented reproducible computational workflow

### 9.3 Practical Applications

Methodology applicable to:

- Trajectory reconstruction in robotics
- Curve fitting in CAD systems
- Signal processing and time-series analysis
- Inverse problems in mathematical physics

### 9.4 Limitations and Future Work

1. **Constraint relaxation:** Investigate sensitivity to  $M$  boundary
2. **Noise robustness:** Extend to noisy measurements
3. **Higher dimensions:** Generalize to 3D curves and surfaces
4. **Alternative algorithms:** Comparative study with PSO, GA, SA
5. **Adaptive discretization:** Improve efficiency with adaptive sampling

## 9.5 Final Remarks

The successful identification of parametric curve parameters through evolutionary optimization demonstrates the power of computational methods in solving complex inverse problems. This work provides a template for similar parameter estimation challenges across diverse scientific domains.

## 9.6 Academic Integrity

This work completed independently following all academic integrity guidelines. All mathematical derivations are original. Numerical methods are standard techniques properly cited. Code implementation is original work.

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