

# Inverse Kinematics via Gaussian Mixture Modeling

Aykut C. Satici

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## 1 Problem Statement

We want to come up with a general procedure that solves the inverse kinematics problem for redundant manipulators. We will, in particular, work with the planar three-link articulated robot. We are only interested in the position of its end-effector. Therefore, the forward kinematics map goes from the joint angles:  $\theta = (\theta_1, \theta_2, \theta_3)$  to  $\mathbf{x} = (x, y)$ .

## 2 Theory

The solution will be to utilize a Gaussian Mixture Model (GMM) to represent the inverse kinematics map. My presentation will closely follow three sources: [Ghahramani \(1993\)](#); [McLachlan and Krishnan \(2007\)](#); [Xu, Chen, Lau, and Ren \(2017\)](#).

We assume that the data  $\Xi = \{\xi_1, \dots, \xi_N\}$  were generated independently by a mixture density:

$$P(\xi_i) = \sum_{j=1}^M \underbrace{P(\omega_j)}_{\pi_j} P(\xi_i | \omega_j; \psi_j), \quad (1)$$

where  $\{\pi_j\}_j^M$  are the mixture proportions, each component of the mixture is denoted  $\omega_j$  and parametrized by  $\psi_j$ . The mixture proportions are to be picked such that

$$\sum_{j=1}^M \pi_j = 1.$$

The full set of parameters of this model are  $\pi_j$ 's and  $\psi_j$ 's. We will write  $\Psi = (\pi_j, \psi_j)_j$ . When we restrict these probability distributions to be Gaussian, we will further have  $\psi_j = (\mu_j, \Sigma_j)$ , where  $\mu_j$  is the mean and  $\Sigma_j$  the covariance of the  $j^{\text{th}}$  Gaussian. The log of the likelihood of the parameters given the data set is

$$\ell(\Psi | \Xi) = \log \prod_{i=1}^N \sum_{j=1}^M P(\xi_i | \omega_j; \psi_j) P(\omega_j) = \sum_{i=1}^N \log \sum_{j=1}^M P(\xi_i | \omega_j; \psi_j) P(\omega_j). \quad (2)$$

We seek to find the parameter vector  $\Psi$  that maximizes  $\ell(\Psi | \Xi)$ . However, this function is not easily maximized numerically because it involves the log of a sum. Intuitively, it is not easily maximized because for each data point, there is a “credit-assignment” problem, i.e., it is not clear which component of the mixture generated the data point and thus which parameters to adjust to fit that data point.

The expectation maximization (EM) algorithm applied to mixtures is an iterative method for overcoming this credit-assignment problem. The intuition behind it is that if one had access to a “hidden” random variable  $z$  that indicated which data point was generated by which component, then the maximization problem would decouple into a set of simple maximizations. Mathematically, given  $\mathcal{Z} = \{z_1, \dots, z_N\}$  a “complete-data” log likelihood function could be written,

$$\ell_c(\Psi \mid \Xi, \mathcal{Z}) = \sum_{i=1}^N \sum_{j=1}^M z_{ij} \log P(\xi_i \mid z_i; \Psi) P(z_i; \Psi), \quad (3)$$

such that it does not involve a log of a summation.

As proven in [Dempster, Laird, and Rubin \(1977\)](#),  $\ell(\Psi \mid \Xi)$  can be maximized by iterating the following two steps,

$$\begin{aligned} \text{E-step:} \quad Q(\Psi \mid \Psi_k) &= \mathbb{E}[\ell_c(\Psi \mid \Xi, \mathcal{Z}) \mid \Xi, \Psi_k] \\ \text{M-step:} \quad \Psi_{k+1} &= \arg \max_{\Psi} Q(\Psi \mid \Psi_k). \end{aligned} \quad (4)$$

The E (Expectation) step computes the expected complete data log likelihood and the M (Maximization) step finds the parameters that maximize this likelihood.

## 2.1 Mixture of Gaussians

Let me now specialize to the case where the probability functions above are Gaussians. For this model, the E-step simplifies to computing  $h_{ij} = \mathbb{E}[z_{ij} \mid \xi_i, \psi_k]$ , the probability that Gaussian  $j$ , as defined by the mean  $\hat{\mu}_j$  and covariance matrix  $\hat{\Sigma}_j$  estimated at time step  $k$ , generated data point  $i$ :

$$h_{ij}^{(k)} = \frac{\left| \hat{\Sigma}_j^{(k)} \right|^{-\frac{1}{2}} \exp \left\{ -\frac{1}{2} \left( \xi_i - \hat{\mu}_j^{(k)} \right)^\top \left( \hat{\Sigma}_j^{(k)} \right)^{-1} \left( \xi_i - \hat{\mu}_j^{(k)} \right) \right\}}{\sum_{l=1}^M \left| \hat{\Sigma}_l^{(k)} \right|^{-\frac{1}{2}} \exp \left\{ -\frac{1}{2} \left( \xi_i - \hat{\mu}_l^{(k)} \right)^\top \left( \hat{\Sigma}_l^{(k)} \right)^{-1} \left( \xi_i - \hat{\mu}_l^{(k)} \right) \right\}}. \quad (5)$$

The M-step then involves re-estimating the means and covariances of the Gaussians along with the mixing proportions using the data set weighted by the  $h_{ij}$ :

$$\begin{aligned} \hat{\mu}_j^{(k+1)} &= \frac{\sum_{i=1}^N h_{ij}^{(k)} \xi_i}{\sum_{i=1}^N h_{ij}^{(k)}}, \\ \hat{\Sigma}_j^{(k+1)} &= \frac{\sum_{i=1}^N h_{ij}^{(k)} \left( \xi_i - \hat{\mu}_j^{(k+1)} \right) \left( \xi_i - \hat{\mu}_j^{(k+1)} \right)^\top}{\sum_{i=1}^N h_{ij}^{(k)}}, \\ \pi_j^{(k+1)} &= \frac{1}{N} \sum_{i=1}^N h_{ij}^{(k)}. \end{aligned} \quad (6)$$

## 2.2 Supervised Learning

When viewed as supervised learning, each vector  $\xi_i$  in the training set is composed of an “input” subvector  $\mathbf{x}_i$  and a “target” or output subvector  $\theta_i$ . Applying the learning algorithm, we obtain

an estimate of the density of the data in this input/output space. This estimate can be used to approximate a function in the following way:

Given the input vector  $\mathbf{x}_i$ , we extract all the relevant information from the joint probability density function (pdf)  $P(\mathbf{x}, \theta)$  by conditionalizing to  $P(\theta | \mathbf{x})$ . For a single Gaussian this conditional density is normal, and by linearity, since  $P(\mathbf{x}, \theta)$  is a mixture of Gaussians, so is  $P(\theta | \mathbf{x})$ . Let me elaborate on how to compute this posterior (conditional) density for Gaussian mixture models. First, we partition the mean vector  $\hat{\mu}_j$  and the covariance matrix  $\hat{\Sigma}_j$ .

$$\hat{\mu}_j = \begin{bmatrix} \hat{\mu}_{\mathbf{x},j} & \hat{\mu}_{\theta,j} \end{bmatrix}, \quad \hat{\Sigma}_j = \begin{bmatrix} \Sigma_{\mathbf{x}\mathbf{x},j} & \Sigma_{\mathbf{x}\theta,j} \\ \Sigma_{\theta\mathbf{x},j} & \Sigma_{\theta\theta,j} \end{bmatrix}. \quad (7)$$

Given each component  $\omega_j$  and output  $x$ , the conditional probability distributioin of  $\theta$  can be obtained as:

$$\begin{aligned} P(\theta | \mathbf{x}; \omega_j) &= \mathcal{N}(\theta | \tilde{\mu}_{\theta,j}, \tilde{\Sigma}_{\theta\theta,j}), \\ \tilde{\mu}_{\theta,j} &= \mu_{\theta,j} + \Sigma_{\theta\mathbf{x},j} \Sigma_{\mathbf{x}\mathbf{x},j}^{-1} (\mathbf{x} - \mu_{\mathbf{x},j}), \\ \tilde{\Sigma}_{\theta\theta,j} &= \Sigma_{\theta\theta,j} - \Sigma_{\theta\mathbf{x},j} \Sigma_{\mathbf{x}\mathbf{x},j}^{-1} \Sigma_{\mathbf{x}\theta,j}. \end{aligned} \quad (8)$$

Finally, we marginalize out the component  $\omega_j$  to find the conditional probability of  $\theta$  given  $\mathbf{x}$ :

$$\begin{aligned} P(\theta | \mathbf{x}) &= \sum_{j=1}^M \beta_j \mathcal{N}(\theta | \tilde{\mu}_{\theta,j}, \tilde{\Sigma}_{\theta\theta,j}), \\ \beta_j &= \frac{\pi_j P(\mathbf{x}_j)}{\sum_{j=1}^M \pi_j P(\mathbf{x}_j)} = \frac{\pi_j \mathcal{N}(\mathbf{x} | \mu_{\mathbf{x},j}, \Sigma_{\mathbf{x}\mathbf{x},j})}{\sum_{j=1}^M \pi_j \mathcal{N}(\mathbf{x} | \mu_{\mathbf{x},j}, \Sigma_{\mathbf{x}\mathbf{x},j})}. \end{aligned} \quad (9)$$

Here, notice that, to compute  $\beta_j$ , we compute the probability of observing the data point  $\mathbf{x}$  under the Gaussian distribution whose mean is  $\mu_{\mathbf{x},j}$  and whose covariance is  $\Sigma_{\mathbf{x}\mathbf{x},j}$ , for each  $j$ .

In principle, this conditional density is the final output of the density estimator. That is, given a particular input, the network returns the complete conditional density of the output. However, for the purposes of comparison to function approximation methods and since many applications require a single estimate of the output, I will outline two possible ways to obtain such an estimate  $\hat{\theta}_i$  of  $\theta_i = f(x_i)$ .

1. Stochastic Sampling (STOCH) samples according to the distribution  $\hat{\theta}(\mathbf{x}_i) \sim P(\theta | \mathbf{x}_i)$ :

$$\begin{aligned} \hat{\theta} &= \sum_{j=1}^M \beta_j \tilde{\mu}_{\theta,j}, \\ \hat{\Sigma}_{\theta\theta} &= \sum_{j=1}^M \beta_j^2 \tilde{\Sigma}_{\theta\theta,j}. \end{aligned}$$

2. Single component least-squares estimation (SLSE) takes  $\hat{\theta}(\mathbf{x}_i) = \mathbb{E}(\theta | \mathbf{x}_i, \omega_j)$ , where  $j = \arg \max_k \mathcal{N}(\mathbf{x} | \mu_{\mathbf{x},k}, \Sigma_{\mathbf{x}\mathbf{x},k})$ . That is, for a given input, SLSE picks the Gaussian with the highest posterior, and for that Gaussian approximates the output with the least-squares estimator given by that Gaussian alone.

## 2.3 Initialization of EM

The EM algorithm is iterative, which means, in particular, that we need to start it off with an initial guess for the parameters. Clearly, the better the initial guess, the faster/easier the convergence will be. The initial guesses I used were as follows:

1. For  $\pi_j$ , I used a uniform distribution:  $\pi_j^{(0)} = \frac{1}{M}$  for all  $j = 1, \dots, M$ .
2. For each  $j$ , I started the covariance matrix as a multiple of the identity matrix:  $\Sigma_j^{(0)} = \alpha_j I$ .
3. I used the  $k$ -means clustering method to generate initial values for  $\mu_j^{(0)}$ . This method aims to partition the  $N$  observations into  $M \leq N$  sets so as to minimize the within-cluster sum-of-squares cost [Wikipedia \(2021\)](#).

## 2.4 Summary of the Algorithm

Let me provide a brief explanation of the method.

1. Randomly select the data points  $\{\theta_1, \dots, \theta_N\}$  and generate the corresponding  $\{x_1, \dots, x_N\}$ .
2. Collect the full data in one vector:  $\xi_i = [x_i, \theta_i]$  and  $\xi = \{\xi_i\}_{i=1}^N$ .
3. Model the data to be generated independently by a Gaussian mixture density (1) and initialize the parameters of the model following Section 2.3.
4. Employ EM to find  $P(\xi) = P(x, \theta)$  using equations (5) and (6).
5. Marginalize the sum of the Gaussians to find  $P(\theta | x)$  using equation (7)–(9).
6. Given an end-effector position  $x$ , estimate the joint angles using STOCH or SLSE.

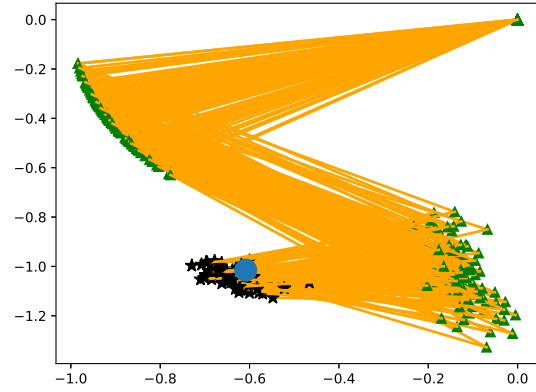


Figure 1: A visualization of the algorithm. The desired end-effector position,  $x$  is depicted by the big blue circle. The learned posterior distribution  $P(\theta | x)$  is used to sample 100 solutions, which yields the robot configurations shown in orange. The actual location of the end-effector these orange configurations yield are depicted by the black stars in the plot.

## 3 Numerical Example

A Julia implementation of this algorithm may be found in [Satici \(2021\)](#). The implementation allows the user to specify how many data points to randomly generate and how many components to use in the Gaussian mixture model. Once these are specified, the model can be trained by executing the `execute_em!` function.

The trained model may be tested by running the `test_training` function, which generates 200 extra points and returns the average error incurred by the output of the algorithm. A visualization of the performance of the algorithm is depicted in Figure 1.

## References

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