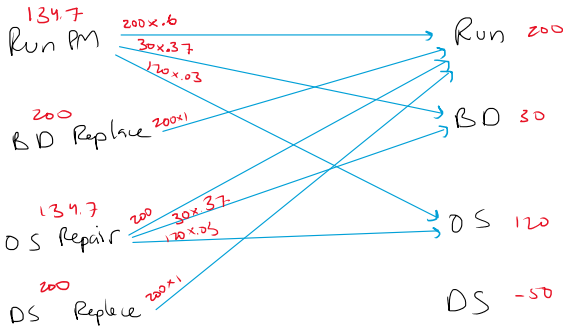
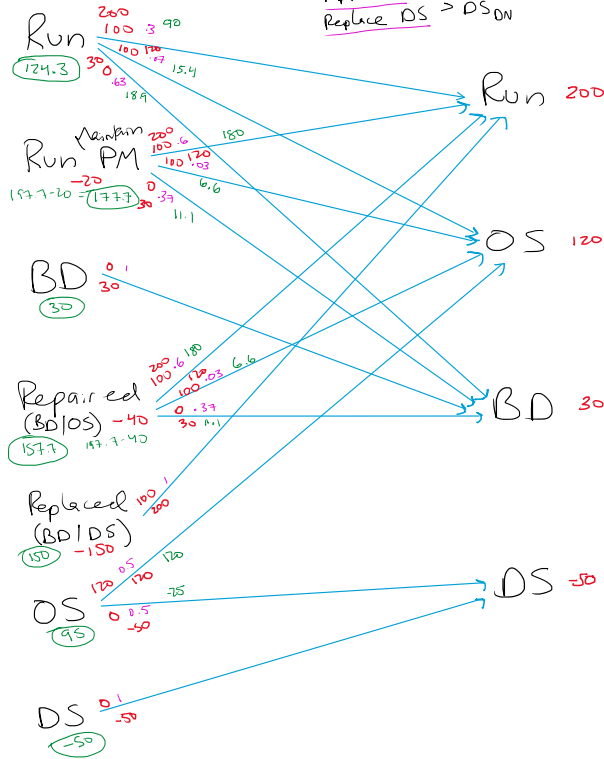


Policy: Run (Run > S Run)
 Repair BD > Replace BD > BD ON
 Repair OS > OS ON
 Replace DS > DS ON

P1 Finding Optimal Policy and W20 rewards



HW2 P3a

Optimal future cost

$$x_k^T P_k x_k = V_k(x_k) \Rightarrow V_{k+1}(x_{k+1})$$

$$V_k(x_k) = \min_{u_k} [x_k^T Q x_k + u_k^T R u_k + Z x_k^T S u_k + V_{k+1}(x_{k+1})]$$

$$V_k(x_k) = \min_{u_k} [x_k^T Q x_k + u_k^T R u_k + Z x_k^T S u_k + \underbrace{(A x_k + B u_k)^T P_{k+1} (A x_k + B u_k)}_{(A x_k + B u_k)^T P_{k+1} (A x_k + B u_k) = x_k^T A^T P_{k+1} A x_k + u_k^T B^T P_{k+1} B u_k + Z x_k^T A^T P_{k+1} B u_k}]$$

$$V_k(x_k) = \min_{u_k} [x_k^T (Q + A^T P_{k+1} A) x_k + u_k^T (R + B^T P_{k+1} B) u_k + Z x_k^T (S + A^T P_{k+1} B) u_k]$$

$$\frac{d}{du} \left[\cancel{2(R + B^T P_{k+1} B)u} + 2(S + B^T P_{k+1} A)x_k + \cancel{2(R + B^T P_{k+1} B)u} \right] = 0$$

$$(R + B^T P_{k+1} B)u = -(S + B^T P_{k+1} A)x_k$$

$$u_k^* = -\underbrace{(R + B^T P_{k+1} B)^{-1} (S + B^T P_{k+1} A)}_{\text{Optimal control gain}} x_k$$

$$\boxed{u_k^* = - \underbrace{(R + B^T P_{k+1} B)^{-1} (S + B^T P_{k+1} A)}_K x_k}$$

$$u_k^* = -K_k x_k$$

Repeated previous steps using M, H, N to help me *organize*

$$V_k(x_k) = \min_{u_k} \left[x_k^T (Q + A^T P_{k+1} A) x_k + u_k^T (R + B^T P_{k+1} B) u_k + z_k^T (S + A^T P_{k+1} B) u_k \right]$$

$$M = Q + A^T P_{k+1} A, \quad H = R + B^T P_{k+1} B, \quad N = S + A^T P_{k+1} B$$

$$\rightarrow V_k(x_k) = x_k^T M x_k + u_k^T H u_k + z_k^T N u_k$$

$$\frac{\partial V_k}{\partial u_k} = 0 + z_k^T H u_k + z_k^T N x_k = 0$$

$$H u_k = -N^T x_k$$

$$u_k = -N^T x_k H^{-1}$$

$$\boxed{u_k^* = - (S + A^T P_{k+1} B) (R + B^T P_{k+1} B)^{-1} x_k}$$

$$V_k(x_k) = \cancel{x_k^T P_k x_k} = \cancel{x_k^T} M \cancel{x_k} + u_k^T H u_k + z_k^T N u_k$$

$$= \quad \quad \quad + (-N^T x_k H^{-1})^T H (-N^T x_k H^{-1}) + z_k^T N (-N^T x_k H^{-1})$$

$$= H^T x_k^T N \cancel{H^{-1} N^T x_k H^{-1}} - z_k^T N N^T x_k H^{-1}$$

$$= \cancel{x_k^T N H^{-1} N^T x_k}$$

$$P_k = M - N H^{-1} N^T$$

$$\boxed{P_k = Q + A^T P_{k+1} A - (S + A^T P_{k+1} B) (R + B^T P_{k+1} B)^{-1} (S + B^T P_{k+1} A)}$$

HW2 P3b

$$x_{k+1} = A_k x_k + B_k u_k$$

Terminal cost: $V_N(x_N) = x_N^T Q_N x_N$, $P_N = Q_N$

as
 $V_k(x_k) = x_k^T P_k x_k$

$$V_k(x_k) = \min_{u_k} \left[x_k^T Q_k x_k + u_k^T R_k u_k + x_{k+1}^T Q_{k+1} x_{k+1} \right]$$

\downarrow
 $x_{k+1}^T P_{k+1} x_{k+1}$
 \downarrow
 $(A_k x_k + B_k u_k)^T P_{k+1} (A_k x_k + B_k u_k)$
 \downarrow
 x_k^T

$$\min_{u_k} \left[x_k^T Q_k x_k + u_k^T R_k u_k + x_k^T A_k^T P_{k+1} A_k x_k + u_k^T B_k^T P_{k+1} B_k u_k + 2 x_k^T A_k^T P_{k+1} B_k u_k \right]$$

$$\left(x_k^T \left(Q_k + A_k^T P_{k+1} A_k \right) x_k + u_k^T \left(R_k + B_k^T P_{k+1} B_k \right) u_k + 2 x_k^T \underbrace{A_k^T P_{k+1} B_k}_{G} u_k \right)$$

Derivative wrt u_k

$$\frac{\partial}{\partial u_k} \left(u_k^T H u_k + 2 x_k^T G u_k \right) = 0$$

$$2 H u_k + 2 G^T x_k = 0$$

$$u_k^* = -G^T H^{-1} x_k$$

$$u_k^* = -A_k^T P_{k+1} B_k \left(R_k + B_k^T P_{k+1} B_k \right)^{-1} x_k$$

$$K_k = A_k^T P_{k+1} B_k \left(R_k + B_k^T P_{k+1} B_k \right)^{-1}$$

$$K_k = G^T H^{-1}$$

$$V_k(x_k) = x_k^T P_k x_k$$

$$\cancel{x_k^T P_k x_k} = \cancel{x_k^T} \left(Q_k + A_k^T P_{k+1} A_k \right) \cancel{x_k} + u_k^T \left(R_k + B_k^T P_{k+1} B_k \right) u_k + 2 \cancel{x_k^T} \underbrace{A_k^T P_{k+1} B_k}_{G} u_k$$

$$\left(-K_k x_k \right)^T H \left(-K_k x_k \right) + 2 \cancel{x_k^T} G \left(-K_k x_k \right)$$

$$\cancel{x_k^T} K_k^T H K_k \cancel{x_k} - 2 \cancel{x_k^T} G K_k \cancel{x_k}$$

$$P_k = (Q_k + A_k^T P_{k+1} A_k) + K_k^T H_k K_k - Z G K_k$$

$$\downarrow (G_k^T H_k^{-1})^T H_k (G_k^T H_k^{-1}) - Z G (G_k^T H_k^{-1})$$

$$(G_k^T H_k^{-1}) \left[(G_k^T H_k^{-1})^T H_k - Z G \right]$$

$$\downarrow H_k G_k^T H_k^{-1} - Z G = -G$$

$$-G_k^T H_k^{-1} G$$

$$P_k = Q_k + A_k^T P_{k+1} A_k - (B_k^T P_{k+1} A_k) (R_k + B_k^T P_{k+1} B_k)^{-1} (A_k^T P_{k+1} B_k)$$