## trainHelicopterModel.m

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**Summary:** Script to learn the dynamics model. If SNR is too high, white noise is added to the GP targets and model is trained again.

## **High-level-steps**

- 1. Set up GP structure
- 2. Train one GP for each variable separately and merge results into the complete GP
- 3. Check length-scales

## Code

```
% 1. Set up GP inputs and targets
Du = length(policy.maxU); Da = length(plant.angi); % no. of ctrl and angles
xaug = [x(:,dyno) \ x(:,end-Du-2*Da+1:end-Du)]; % x augmented with angles
dynmodel.inputs = [xaug(:,dyni) x(:,end-Du+1:end)];
                                                        % use dyni and ctrl
dynmodel.targets = y(:,dyno);
dynmodel.targets(:,difi) = dynmodel.targets(:,difi) - x(:,dyno(difi));
dynmodel.hyp = zeros([nVar+nU+2, nVar]);
% 2. For each variable, train a separate GP until SNR falls below the limit
for k=1:nVar
    disp(['Training GP for variable ' num2str(k)]);
    auxDynmodel.fcn = dynmodel.fcn;
    auxDynmodel.train = dynmodel.train;
    auxDynmodel.induce = dynmodel.induce;
    auxDynmodel.inputs = dynmodel.inputs;
    auxDynmodel.targets = dynmodel.targets(:,observationIdx(k));
    auxDynmodel.hyp = dynmodel.hyp(:,k);
    auxDynmodel = auxDynmodel.train(auxDynmodel, plant, trainOpt);
    Xh = auxDynmodel.hyp;
    SNR = exp(Xh(end-1)-Xh(end));
    disp(['SNR = ' num2str(SNR)]);
    while SNR>500
        disp('SNR too high. Add noise and re-train.');
        std_target = std(auxDynmodel.targets);
        auxDynmodel.targets = auxDynmodel.targets + 0.01*std_target*randn(size(aux
        auxDynmodel = auxDynmodel.train(auxDynmodel, plant, trainOpt);
        Xh = auxDynmodel.hyp;
```

```
SNR = exp(Xh(end-1)-Xh(end));
        disp(['Now SNR is ' num2str(SNR)]);
    end
    2.1. Merge the trained hyper-parameters with the complete GP
    dynmodel.hyp(:,k) = auxDynmodel.hyp;
end
% 3. Show the result of various tests based on the model's length-scales
Xh = dynmodel.hyp;
\log_{signal_std} = (Xh(end-1,:) < \log(0.1)) + (Xh(end-1,:) > \log(10));
if any(log signal std)
    fprintf('Helicopter model log-signal-std hyperparameter is out of range for va
end
input_std = std(dynmodel.inputs);
if any(Xh(1:16,:) > 100*repmat(input_std',[1, nVar]))
    fprintf('Length-scales are much bigger than input std\n');
end
if any(Xh(1:16,:) < 0.01*repmat(input_std',[1, nVar]))</pre>
    fprintf('Length-scales are much smaller than input std\n');
end
```

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