In [1]:
```
import Pkg
Pkg.activate(@__DIR__)
Pkg.instantiate()
using LinearAlgebra, Plots; plotly()
import ForwardDiff as FD
using MeshCat
using Test
using Plots
```

```
  Activating environment at `~/Dropbox/My Mac (MacBook Pro (2))/Desktop/CMU/Optimal Control/HW1_S23/Project.toml`
┌ Warning: backend `PlotlyBase` is not installed.
└ @ Plots ~/.julia/packages/Plots/io9zQ/src/backends.jl:43
┌ Warning: backend `PlotlyKaleido` is not installed.
└ @ Plots ~/.julia/packages/Plots/io9zQ/src/backends.jl:43
```

Q2: Equality Constrained Optimization (20 pts)

In this problem, we are going to use Newton's method to solve some constrained optimization problems. We will start with a smaller problem where we can experiment with Full Newton vs Gauss-Newton, then we will use these methods to solve for the motor torques that make a quadruped balance on one leg.

Part A (10 pts)

Here we are going to solve some equality-constrained optimization problems with Newton's method. We are given a problem

$$\begin{aligned} \min_x \quad & f(x) && (1) \\ \text{st} \quad & c(x) = 0 && (2) \end{aligned}$$

Which has the following Lagrangian:

$$\mathcal{L}(x, \lambda) = f(x) + \lambda^T c(x),$$

and the following KKT conditions for optimality:

$$\begin{aligned} \nabla_x \mathcal{L} = \nabla_x f(x) + \left[\frac{\partial c}{\partial x}\right]^T \lambda = 0 && (3) \\ c(x) = 0 && (4) \end{aligned}$$

Which is just a root-finding problem. To solve this, we are going to solve for a $z = [x^T, \lambda]^T$ that satisfies these KKT conditions.

Newton's Method with a Linesearch

We use Newton's method to solve for when $r(z) = 0$. To do this, we specify `res_fx(z)` as $r(z)$, and `res_jac_fx(z)` as $\partial r / \partial z$. To calculate a Newton step, we do the following:

$$\Delta z = -\left[\frac{\partial r}{\partial z}\right]^{-1} r(z_k)$$

We then decide the step length with a linesearch that finds the largest $\alpha \leq 1$ such that the following is true:

$$\phi(z_k + \alpha \Delta z) < \phi(z_k)$$

Where ϕ is a "merit function", or `merit_fx(z)` in the code. In this assignment you will use a backtracking linesearch where α is initialized as $\alpha = 1.0$, and is divided by 2 until the above condition is satisfied.

NOTE: YOU DO NOT NEED TO (AND SHOULD NOT) USE A WHILE LOOP ANYWHERE IN THIS ASSIGNMENT.

In [2]:

```
function linesearch(z::Vector, Δz::Vector, merit_fx::Function;
                    max_ls_iters = 10)::Float64 # optional argument with a default

    # TODO: return maximum α≤1 such that merit_fx(z + α*Δz) < merit_fx(z)
    # with a backtracking linesearch (α = α/2 after each iteration)

    # NOTE: DO NOT USE A WHILE LOOP
    α = 1
    for i = 1:max_ls_iters
        # TODO: return α when merit_fx(z + α*Δz) < merit_fx(z)
        if merit_fx(z + α*Δz) < merit_fx(z)
            return α
        end
        α = α/2
    end
    #If linesearch fails in the max iterations, return 1
    return 1
    error("linesearch failed")
end

function newtons_method(z0::Vector, res_fx::Function, res_jac_fx::Function, merit_fx::Fu
                        tol = 1e-10, max_iters = 50, verbose = false)::Vector{Vector{Flo

    # TODO: implement Newton's method given the following inputs:
    # - z0, initial guess
    # - res_fx, residual function
    # - res_jac_fx, Jacobian of residual function wrt z
    # - merit_fx, merit function for use in linesearch

    # optional arguments
    # - tol, tolerance for convergence. Return when norm(residual)<tol
    # - max iter, max # of iterations
    # - verbose, bool telling the function to output information at each iteration

    # return a vector of vectors containing the iterates
    # the last vector in this vector of vectors should be the approx. solution

    # NOTE: DO NOT USE A WHILE LOOP ANYWHERE

    # return the history of guesses as a vector
    Z = [zeros(length(z0)) for i = 1:max_iters]
    Z[1] = z0

    for i = 1:(max_iters - 1)
```

```julia
        # NOTE: everything here is a suggestion, do whatever you want to

        # TODO: evaluate current residual
        res = res_fx(Z[i])

        norm_r = norm(res) # TODO: update this
        if verbose
            print("iter: $i    |r|: $norm_r   ")
        end

        # TODO: check convergence with norm of residual < tol
        # if converged, return Z[1:i]
        if norm_r < tol
            return Z[1:i]
        end

        # TODO: caculate Newton step (don't forget the negative sign)
        ΔZi = -res_jac_fx(Z[i])\res

        # TODO: linesearch and update z
        α = linesearch(Z[i], ΔZi, merit_fx)
        Z[i+1] = Z[i] + α*ΔZi

        if verbose
            print("α: $α \n")
        end

    end
    error("Newton's method did not converge")
end
```

Out[2]: newtons_method (generic function with 1 method)

In [3]:

```julia
@testset "check Newton" begin

    f(_x) = [sin(_x[1]), cos(_x[2])]
    df(_x) = FD.jacobian(f, _x)
    merit(_x) = norm(f(_x))

    x0 = [-1.742410372590328, 1.4020334125022704]

    X = newtons_method(x0, f, df, merit; tol = 1e-10, max_iters = 50, verbose = true)

    # check this took the correct number of iterations
    # if your linesearch isn't working, this will fail
    # you should see 1 iteration where α = 0.5
    @test length(X) == 6

    # check we actually converged
    @test norm(f(X[end])) < 1e-10

end
```

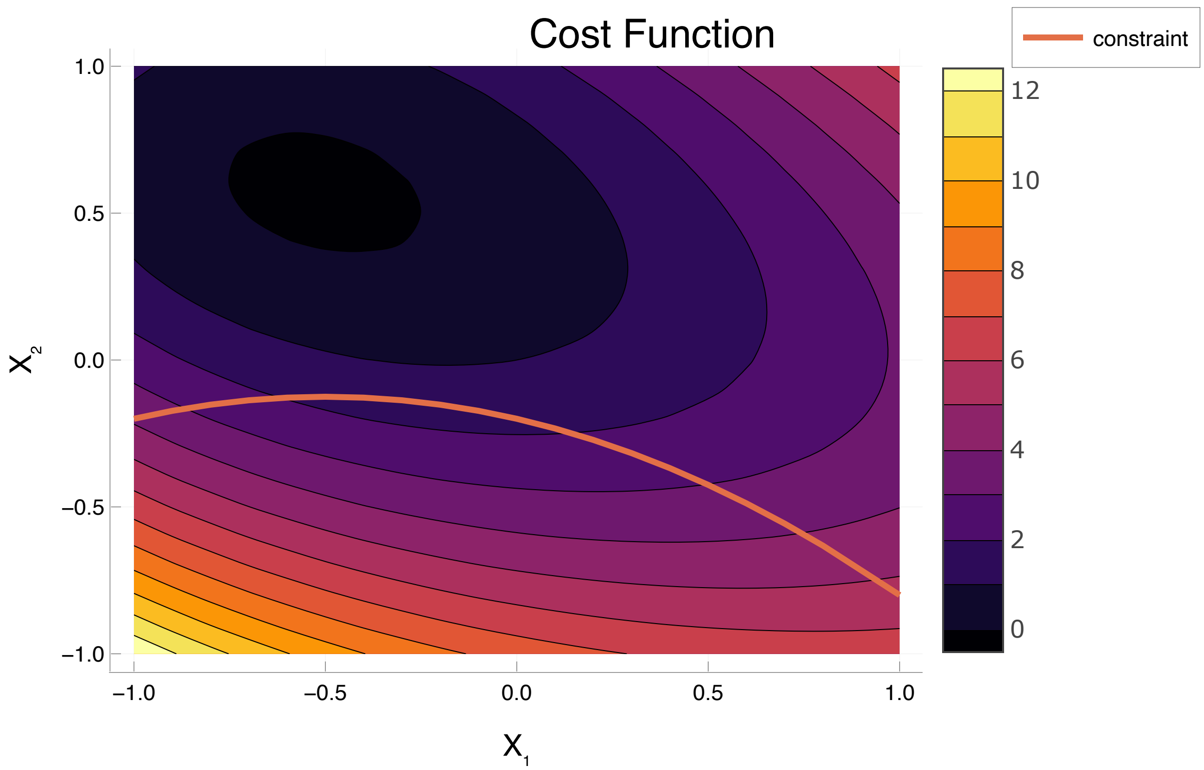
```
iter: 1    |r|: 0.9995239729818045   α: 1.0
iter: 2    |r|: 0.9421342427117169   α: 0.5
iter: 3    |r|: 0.1753172908866053   α: 1.0
iter: 4    |r|: 0.0018472215879181287   α: 1.0
iter: 5    |r|: 2.1010529101114843e-9   α: 1.0
iter: 6    |r|: 2.5246740534795566e-16   Test Summary: | Pass  Total
check Newton  |    2      2
```

Out[3]: Test.DefaultTestSet("check Newton", Any[], 2, false, false)

We will now use Newton's method to solve the following constrained optimization problem. We will write functions for the full Newton Jacobian, as well as the Gauss-Newton Jacobian.

In [4]:
```
let
    Q = [1.65539  2.89376; 2.89376  6.51521];
    q = [2;-3]
    cost(x) = 0.5*x'*Q*x + q'*x + exp(-1.3*x[1] + 0.3*x[2]^2) # cost function
    contour(-1:.1:1,-1:.1:1, (x1,x2)-> cost([x1;x2]),title = "Cost Function",
            xlabel = "X₁", ylabel = "X₂",fill = true)
        plot!(-1:.1:1, -0.3*(-1:.1:1).^2 - 0.3*(-1:.1:1) .- .2,lw = 3,label = "constrain
end
```

Out[4]:



In [5]:
```
# we will use Newton's method to solve the constrained optimization problem shown above
function cost(x::Vector)
    Q = [1.65539  2.89376; 2.89376  6.51521];
    q = [2;-3]
    return 0.5*x'*Q*x + q'*x + exp(-1.3*x[1] + 0.3*x[2]^2)
end
function constraint(x::Vector)
    norm(x) - 0.5
end
# HINT: use this if you want to, but you don't have to
function constraint_jacobian(x::Vector)::Matrix
    # since `constraint` returns a scalar value, ForwardDiff
    # will only allow us to compute a gradient of this function
    # (instead of a Jacobian). This means we have two options for
    # computing the Jacobian: Option 1 is to just reshape the gradient
    # into a row vector

    # J = reshape(FD.gradient(constraint, x), 1, 2)

    # or we can just make the output of constraint an array,
    constraint_array(_x) = [constraint(_x)]
    J = FD.jacobian(constraint_array, x)
```

```julia
    # assert the jacobian has # rows = # outputs
    # and # columns = # inputs
    @assert size(J) == (length(constraint(x)), length(x))

    return J
end
function kkt_conditions(z::Vector)::Vector
    # TODO: return the KKT conditions

    x = z[1:2]
    λ = z[3:3]

    # TODO: return the stationarity condition for the cost function
    # and the primal feasibility
    return [FD.gradient(cost, x) + transpose(constraint_jacobian(x))*λ; constraint(x)]
end

function fn_kkt_jac(z::Vector)::Matrix
    # TODO: return full Newton Jacobian of kkt conditions wrt z
    x = z[1:2]
    λ = z[3]

    #Hessian of lagrange equation
    J = constraint_jacobian(x)
    JT = transpose(J)
    L = x_ -> cost(x_) + transpose(λ)*constraint(x_)
    H = FD.hessian(cost, x) + FD.jacobian(x_ -> constraint_jacobian(x_)'*λ, x)
    #regularize H with β = 1e-3
    β = 1e-3
    fn_jac = [(H+β*I) JT; J -β*I]

    # TODO: return full Newton jacobian with a 1e-3 regularizer
    return fn_jac
end
function gn_kkt_jac(z::Vector)::Matrix
    # TODO: return Gauss-Newton Jacobian of kkt conditions wrt z
    x = z[1:2]
    λ = z[3]

    #Hessian of cost function instead of lagrange equation
    J = reshape(FD.gradient(constraint, x), 1, 2)
    H = FD.hessian(cost, x)
    #regularize H with β = 1e-3
    β = 1e-3
    gn_jac = [(H + β*I) transpose(J); J -β*I]
    return gn_jac

    # TODO: return Gauss-Newton jacobian with a 1e-3 regularizer
    error("gn_kkt_jac not implemented")
end
```

Out[5]: gn_kkt_jac (generic function with 1 method)

In [6]:
```julia
@testset "Test Jacobians" begin
    # first we check the regularizer
    z = randn(3)
    J_fn = fn_kkt_jac(z)
    J_gn = gn_kkt_jac(z)

    # check what should/shouldn't be the same between
```

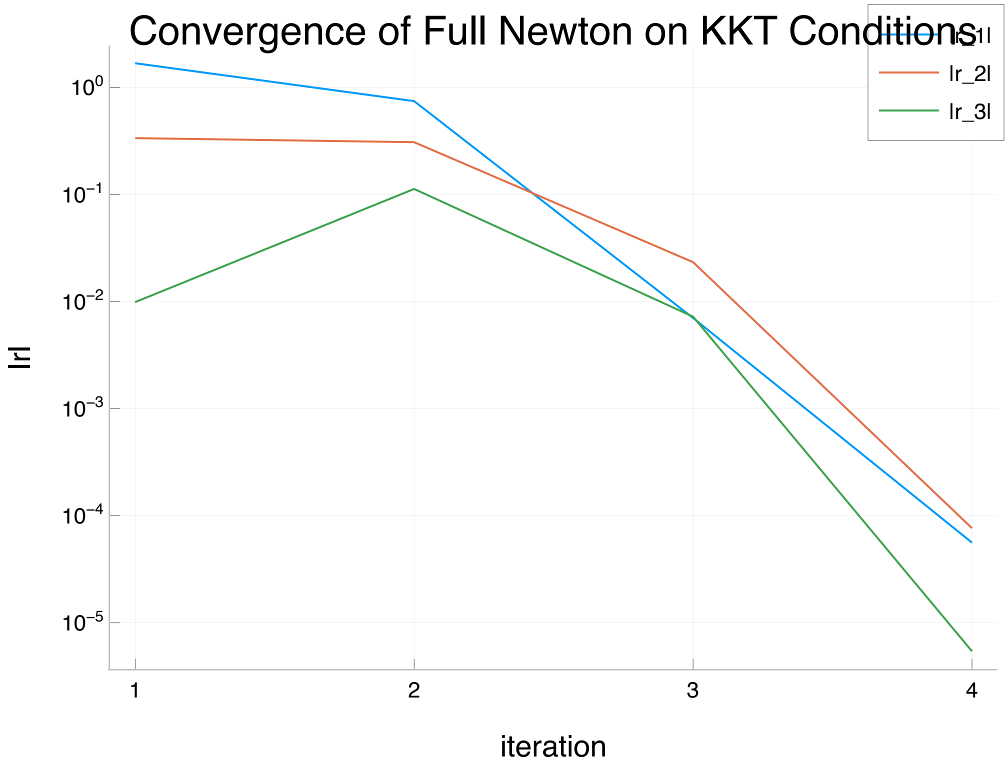
```
    @test norm(J_fn[1:2,1:2] - J_gn[1:2,1:2]) > 1e-10
    @test abs(J_fn[3,3] + 1e-3) < 1e-10
    @test abs(J_gn[3,3] + 1e-3) < 1e-10
    @test norm(J_fn[1:2,3] - J_gn[1:2,3]) < 1e-10
    @test norm(J_fn[3,1:2] - J_gn[3,1:2]) < 1e-10
end
```

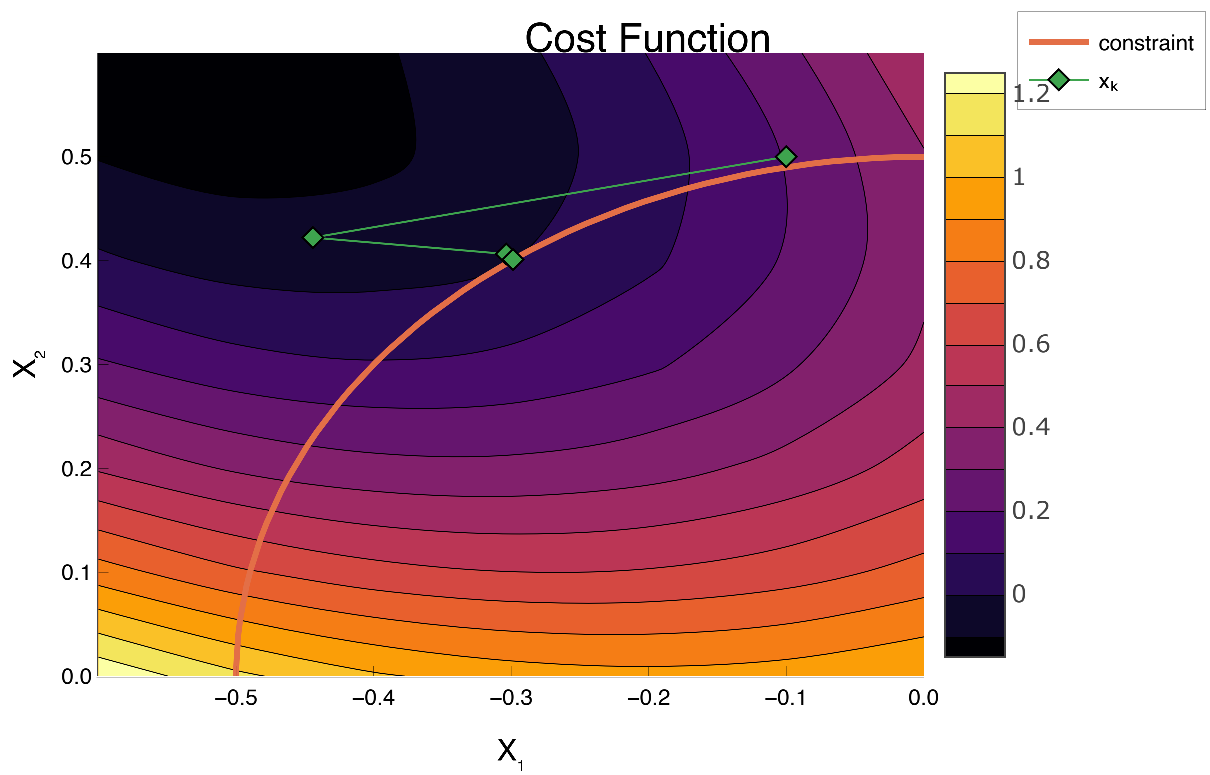
```
Test Summary:  | Pass  Total
Test Jacobians |    5      5
```

Out[6]:
```
Test.DefaultTestSet("Test Jacobians", Any[], 5, false, false)
```

In [7]:
```
@testset "Full Newton" begin

    z0 = [-.1, .5, 0] # initial guess
    merit_fx(_z) = norm(kkt_conditions(_z)) # simple merit function
    Z = newtons_method(z0, kkt_conditions, fn_kkt_jac, merit_fx; tol = 1e-4, max_iters =
    R = kkt_conditions.(Z)

    # make sure we converged on a solution to the KKT conditions
    @test norm(kkt_conditions(Z[end])) < 1e-4
    @test length(R) < 6



    # -----------------------plotting stuff------------------------
    Rp = [[abs(R[i][ii]) + 1e-15 for i = 1:length(R)] for ii = 1:length(R[1])] # this ge

    plot(Rp[1],yaxis=:log,ylabel = "|r|",xlabel = "iteration",
         yticks= [1.0*10.0^(-x) for x = float(15:-1:-2)],
         title = "Convergence of Full Newton on KKT Conditions",label = "|r_1|")
    plot!(Rp[2],label = "|r_2|")
    display(plot!(Rp[3],label = "|r_3|"))

    contour(-.6:.1:0,0:.1:.6, (x1,x2)-> cost([x1;x2]),title = "Cost Function",
            xlabel = "X₁", ylabel = "X₂",fill = true)
    xcirc = [.5*cos(θ) for θ in range(0, 2*pi, length = 200)]
    ycirc = [.5*sin(θ) for θ in range(0, 2*pi, length = 200)]
    plot!(xcirc,ycirc, lw = 3.0, xlim = (-.6, 0), ylim = (0, .6),label = "constraint")
    z1_hist = [z[1] for z in Z]
    z2_hist = [z[2] for z in Z]
    display(plot!(z1_hist, z2_hist, marker = :d, label = "xₖ"))
    # -----------------------plotting stuff------------------------
end
```

```
iter: 1    |r|: 1.7188450769812715   α: 1.0
iter: 2    |r|: 0.8150495962203247   α: 1.0
iter: 3    |r|: 0.025448943695826287   α: 1.0
iter: 4    |r|: 9.501514353500914e-5
```





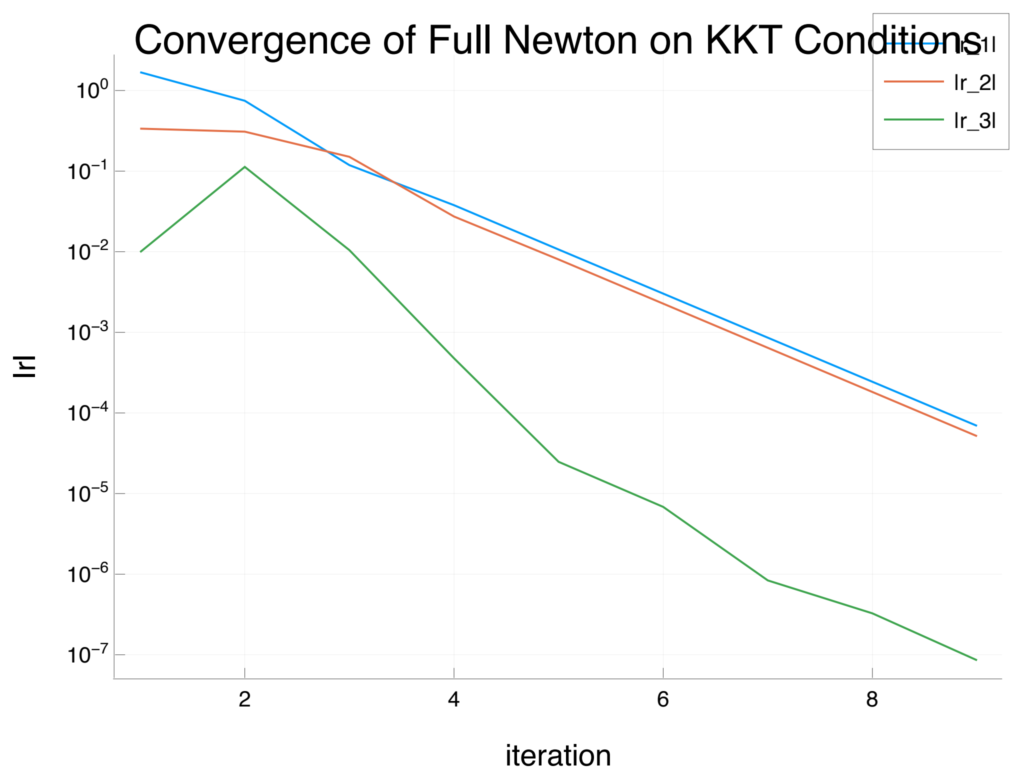

```
Test Summary: | Pass  Total
Full Newton   |    2      2
```

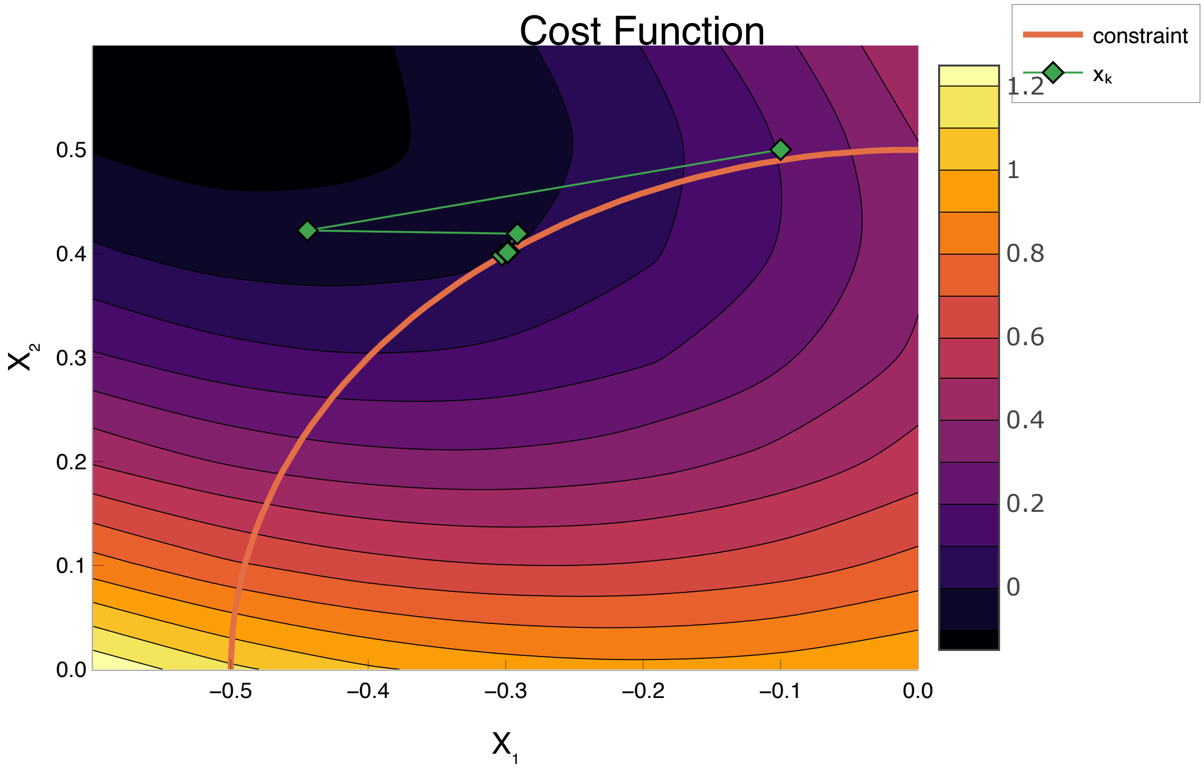
Out[7]: `Test.DefaultTestSet("Full Newton", Any[], 2, false, false)`

In [8]:
```
@testset "Gauss-Newton" begin


    z0 = [-.1, .5, 0] # initial guess
    merit_fx(_z) = norm(kkt_conditions(_z)) # simple merit function

    # the only difference in this block vs the previous is `gn_kkt_jac` instead of `fn_k
    Z = newtons_method(z0, kkt_conditions, gn_kkt_jac, merit_fx; tol = 1e-4, max_iters =
    R = kkt_conditions.(Z)
```

```
    # make sure we converged on a solution to the KKT conditions
    @test norm(kkt_conditions(Z[end])) < 1e-4
    @test length(R) < 10


    # ------------------------plotting stuff------------------------
    Rp = [[abs(R[i][ii]) + 1e-15 for i = 1:length(R)] for ii = 1:length(R[1])] # this ge

    plot(Rp[1],yaxis=:log,ylabel = "|r|",xlabel = "iteration",
         yticks= [1.0*10.0^(-x) for x = float(15:-1:-2)],
         title = "Convergence of Full Newton on KKT Conditions",label = "|r_1|")
    plot!(Rp[2],label = "|r_2|")
    display(plot!(Rp[3],label = "|r_3|"))

    contour(-.6:.1:0,0:.1:.6, (x1,x2)-> cost([x1;x2]),title = "Cost Function",
            xlabel = "X₁", ylabel = "X₂",fill = true)
    xcirc = [.5*cos(θ) for θ in range(0, 2*pi, length = 200)]
    ycirc = [.5*sin(θ) for θ in range(0, 2*pi, length = 200)]
    plot!(xcirc,ycirc, lw = 3.0, xlim = (-.6, 0), ylim = (0, .6),label = "constraint")
    z1_hist = [z[1] for z in Z]
    z2_hist = [z[2] for z in Z]
    display(plot!(z1_hist, z2_hist, marker = :d, label = "xₖ"))
    # ------------------------plotting stuff------------------------
end
```

```
iter: 1    |r|: 1.7188450769812715   α: 1.0
iter: 2    |r|: 0.8150495962203247   α: 1.0
iter: 3    |r|: 0.19186516708148574   α: 1.0
iter: 4    |r|: 0.04663490553083029   α: 1.0
iter: 5    |r|: 0.01332977842954523   α: 1.0
iter: 6    |r|: 0.0037714013578573355   α: 1.0
iter: 7    |r|: 0.001071165054782875   α: 1.0
iter: 8    |r|: 0.00030392210707413806   α: 1.0
iter: 9    |r|: 8.625764141582568e-5
```






```
Test Summary: | Pass  Total
Gauss-Newton  |    2      2
```

Out[8]:
```
Test.DefaultTestSet("Gauss-Newton", Any[], 2, false, false)
```

Part B (10 pts): Balance a quadruped

Now we are going to solve for the control input $u \in \mathbb{R}^{12}$, and state $x \in \mathbb{R}^{30}$, such that the quadruped is balancing up on one leg. First, let's load in a model and display the rough "guess" configuration that we are going for:

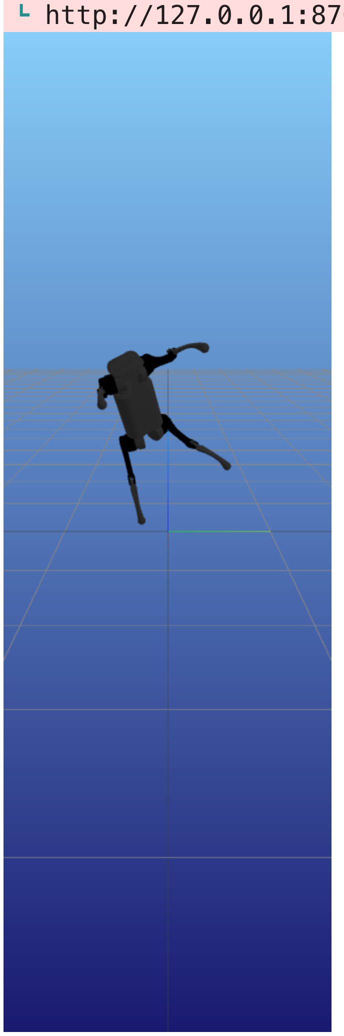
In [9]:
```
include(joinpath(@__DIR__, "quadruped.jl"))

# --------these three are global variables------------
model = UnitreeA1()
mvis = initialize_visualizer(model)
const x_guess = initial_state(model)
# ---------------------------------------------------

set_configuration!(mvis, x_guess[1:state_dim(model)÷2])
render(mvis)
```

The WebIO Jupyter extension was not detected. See the [WebIO Jupyter integration documentation]() for more information.

```
┌ Warning: Error requiring `WebSockets` from `WebIO`
│   exception =
│    LoadError: Unable to find WebIO JavaScript bundle for generic HTTP provider; try re
building WebIO (via `Pkg.build("WebIO")`).
│    Stacktrace:
│      [1] error(s::String)
│        @ Base ./error.jl:33
│      [2] top-level scope
│        @ ~/.julia/packages/WebIO/rv35l/src/providers/generic_http.jl:16
│      [3] eval
│        @ ./boot.jl:360 [inlined]
│      [4] include_string(mapexpr::typeof(identity), mod::Module, code::String, filenam
e::String)
│        @ Base ./loading.jl:1116
│      [5] include_string(m::Module, txt::String, fname::String)
│        @ Base ./loading.jl:1126
│      [6] top-level scope
│        @ ~/.julia/packages/WebIO/rv35l/src/WebIO.jl:123
│      [7] eval
│        @ ./boot.jl:360 [inlined]
│      [8] eval
│        @ ~/.julia/packages/WebIO/rv35l/src/WebIO.jl:1 [inlined]
│      [9] (::WebIO.var"#78#90")()
│        @ WebIO ~/.julia/packages/Requires/Z8rfN/src/require.jl:101
│     [10] macro expansion
│        @ timing.jl:287 [inlined]
│     [11] err(f::Any, listener::Module, modname::String, file::String, line::Any)
│        @ Requires ~/.julia/packages/Requires/Z8rfN/src/require.jl:47
│     [12] (::WebIO.var"#77#89")()
│        @ WebIO ~/.julia/packages/Requires/Z8rfN/src/require.jl:100
│     [13] withpath(f::Any, path::String)
│        @ Requires ~/.julia/packages/Requires/Z8rfN/src/require.jl:37
│     [14] (::WebIO.var"#76#88")()
│        @ WebIO ~/.julia/packages/Requires/Z8rfN/src/require.jl:99
│     [15] listenpkg(f::Any, pkg::Base.PkgId)
│        @ Requires ~/.julia/packages/Requires/Z8rfN/src/require.jl:20
│     [16] macro expansion
│        @ ~/.julia/packages/Requires/Z8rfN/src/require.jl:98 [inlined]
│     [17] __init__()
│        @ WebIO ~/.julia/packages/WebIO/rv35l/src/WebIO.jl:122
│     [18] _include_from_serialized(path::String, depmods::Vector{Any})
│        @ Base ./loading.jl:696
│     [19] _require_search_from_serialized(pkg::Base.PkgId, sourcepath::String)
│        @ Base ./loading.jl:782
│     [20] _tryrequire_from_serialized(modkey::Base.PkgId, build_id::UInt64, modpath::St
ring)
│        @ Base ./loading.jl:711
│     [21] _require_search_from_serialized(pkg::Base.PkgId, sourcepath::String)
│        @ Base ./loading.jl:771
│     [22] _tryrequire_from_serialized(modkey::Base.PkgId, build_id::UInt64, modpath::St
ring)
│        @ Base ./loading.jl:711
│     [23] _require_search_from_serialized(pkg::Base.PkgId, sourcepath::String)
│        @ Base ./loading.jl:771
│     [24] _tryrequire_from_serialized(modkey::Base.PkgId, build_id::UInt64, modpath::St
ring)
│        @ Base ./loading.jl:711
│     [25] _require_search_from_serialized(pkg::Base.PkgId, sourcepath::String)
│        @ Base ./loading.jl:771
│     [26] _require(pkg::Base.PkgId)
│        @ Base ./loading.jl:1020
```

```
│      [27] require(uuidkey::Base.PkgId)
│         @ Base ./loading.jl:936
│      [28] require(into::Module, mod::Symbol)
│         @ Base ./loading.jl:923
│      [29] include(fname::String)
│         @ Base.MainInclude ./client.jl:444
│      [30] top-level scope
│         @ In[9]:1
│      [31] eval
│         @ ./boot.jl:360 [inlined]
│      [32] include_string(mapexpr::typeof(REPL.softscope), mod::Module, code::String, fi
lename::String)
│         @ Base ./loading.jl:1116
│      [33] softscope_include_string(m::Module, code::String, filename::String)
│         @ SoftGlobalScope ~/.julia/packages/SoftGlobalScope/u4UzH/src/SoftGlobalScope.j
l:65
│      [34] execute_request(socket::ZMQ.Socket, msg::IJulia.Msg)
│         @ IJulia ~/.julia/packages/IJulia/6TIq1/src/execute_request.jl:67
│      [35] #invokelatest#2
│         @ ./essentials.jl:708 [inlined]
│      [36] invokelatest
│         @ ./essentials.jl:706 [inlined]
│      [37] eventloop(socket::ZMQ.Socket)
│         @ IJulia ~/.julia/packages/IJulia/6TIq1/src/eventloop.jl:8
│      [38] (::IJulia.var"#15#18")()
│         @ IJulia ./task.jl:417
│     in expression starting at /Users/judsonvankyle/.julia/packages/WebIO/rv35l/src/prov
iders/generic_http.jl:15
└ @ Requires ~/.julia/packages/Requires/Z8rfN/src/require.jl:51
┌ Info: MeshCat server started. You can open the visualizer by visiting the following UR
L in your browser:
└ http://127.0.0.1:8700
```

Out[9]:



Open Controls

Now, we are going to solve for the state and control that get us a statically stable stance on just one leg. We are going to do this by solving the following optimization problem:

$$\min_{x,u} \quad \frac{1}{2}(x - x_{guess})^T(x - x_{guess}) + \frac{1}{2}10^{-3}u^T u \tag{5}$$

$$\text{st} \quad f(x, u) = 0 \tag{6}$$

Where our primal variables are $x \in \mathbb{R}^{30}$ and $u \in \mathbb{R}^{12}$, that we can stack up in a new variable $y = [x^T, u^T]^T \in \mathbb{R}^{42}$. We have a constraint $f(x, u) = \dot{x} = 0$, which will ensure the resulting configuration is stable. This constraint is enforced with a dual variable $\lambda \in \mathbb{R}^{30}$. We are now ready to use Newton's method to solve this equality constrained optimization problem, where we will solve for a variable $z = [y^T, \lambda^T]^T \in \mathbb{R}^{72}$.

In this next section, you should fill out `quadruped_kkt(z)` with the KKT conditions for this optimization problem, given the constraint is that `dynamics(model, x, u) = zeros(30)`. When forming the Jacobian of the KKT conditions, use the Gauss-Newton approximation for the hessian of the Lagrangian (see example above if you're having trouble with this).

In [10]:
```julia
# initial guess
const x_guess = initial_state(model)

# indexing stuff
const idx_x = 1:30
const idx_u = 31:42
const idx_c = 43:72

# I like stacking up all the primal variables in y, where y = [x;u]
# Newton's method will solve for z = [x;u;λ], or z = [y;λ]

function quadruped_cost(y::Vector)
    # cost function
    @assert length(y) == 42
    x = y[idx_x]
    u = y[idx_u]

    # TODO: return cost
    return (1/2)*(x - x_guess)'*(x - x_guess) + (1/2)*1e-3*u'*u
end
function quadruped_constraint(y::Vector)::Vector
    # constraint function
    @assert length(y) == 42
    x = y[idx_x]
    u = y[idx_u]

    # TODO: return constraint
    return dynamics(model, x, u)
end
function quadruped_kkt(z::Vector)::Vector
    @assert length(z) == 72
    x = z[idx_x]
    u = z[idx_u]
    λ = z[idx_c]

    y = [x;u]

    gradF = FD.gradient(quadruped_cost, y)
    J = FD.jacobian(quadruped_constraint, y)
```

```julia
    # TODO: return the KKT conditions
    return [gradF + J'*λ; quadruped_constraint(y)]
end

function quadruped_kkt_jac(z::Vector)::Matrix
    @assert length(z) == 72
    x = z[idx_x]
    u = z[idx_u]
    λ = z[idx_c]

    y = [x;u]

    #Hessian of cost function instead of lagrange equation
    J = FD.jacobian(quadruped_constraint, y)
    JT = J'
    H = FD.hessian(quadruped_cost, y)

    #regularize H with β = 1e-4
    β = 1e-4
    gn_jac = [(H + β*I) JT; J -β*I]

    # TODO: return Gauss-Newton Jacobian with 1e-4 regularizer
    return gn_jac
end
```

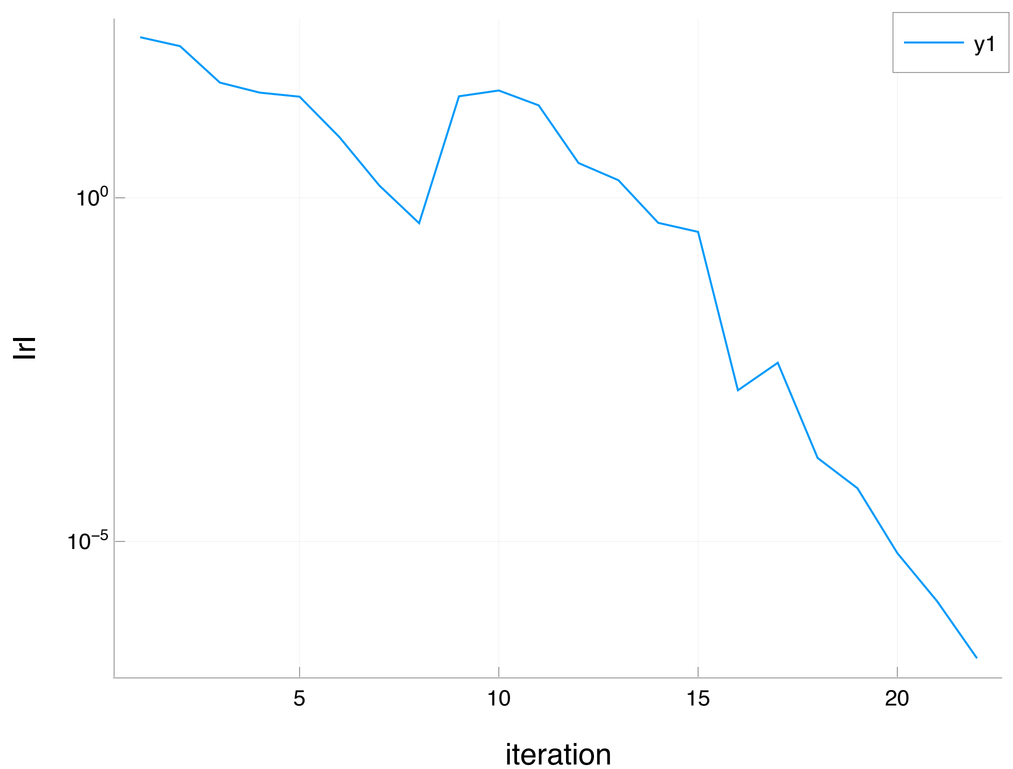
```
WARNING: redefinition of constant x_guess. This may fail, cause incorrect answers, or pr
oduce other errors.
```

Out[10]: quadruped_kkt_jac (generic function with 1 method)

In [11]:

```julia
function quadruped_merit(z)
    # merit function for the quadruped problem
    @assert length(z) == 72
    r = quadruped_kkt(z)
    return norm(r[1:42]) + 1e4*norm(r[43:end])
end

@testset "quadruped standing" begin

    z0 = [x_guess; zeros(12); zeros(30)]
    Z = newtons_method(z0, quadruped_kkt, quadruped_kkt_jac, quadruped_merit; tol = 1e-6
    set_configuration!(mvis, Z[end][1:state_dim(model)÷2])
    R = norm.(quadruped_kkt.(Z))

    display(plot(1:length(R), R, yaxis=:log,xlabel = "iteration", ylabel = "|r|"))

    @test R[end] < 1e-6
    @test length(Z) < 25

    x,u = Z[end][idx_x], Z[end][idx_u]

    @test norm(dynamics(model, x, u)) < 1e-6

end
```

```
iter: 1    |r|: 217.37236872332227   α: 1.0
iter: 2    |r|: 161.16396674083236   α: 1.0
iter: 3    |r|: 47.50490953610319   α: 0.25
iter: 4    |r|: 33.959450828517575   α: 1.0
iter: 5    |r|: 29.65001615544073   α: 1.0
iter: 6    |r|: 7.641266769674606   α: 1.0
iter: 7    |r|: 1.5134162776059055   α: 1.0
iter: 8    |r|: 0.4276867566425382   α: 1.0
iter: 9    |r|: 30.04834893815269   α: 0.5
iter: 10    |r|: 36.45243134502717   α: 1.0
iter: 11    |r|: 22.15521342129516   α: 1.0
iter: 12    |r|: 3.211248060822504   α: 1.0
iter: 13    |r|: 1.8070762872478208   α: 1.0
iter: 14    |r|: 0.4327699213327245   α: 1.0
iter: 15    |r|: 0.31983314827300036   α: 1.0
iter: 16    |r|: 0.0015851398411056423   α: 1.0
iter: 17    |r|: 0.00398333053123828   α: 1.0
iter: 18    |r|: 0.00016413130238524995   α: 1.0
iter: 19    |r|: 5.946768875457325e-5   α: 1.0
iter: 20    |r|: 6.778109747377083e-6   α: 1.0
iter: 21    |r|: 1.3459643412719268e-6   α: 1.0
iter: 22    |r|: 1.9970501927199098e-7
```




```
Test Summary:       | Pass  Total
quadruped standing |    3      3
```

Out[11]: Test.DefaultTestSet("quadruped standing", Any[], 3, false, false)

In [12]:
```
let

    # let's visualize the balancing position we found

    z0 = [x_guess; zeros(12); zeros(30)]
    Z = newtons_method(z0, quadruped_kkt, quadruped_kkt_jac, quadruped_merit; tol = 1e-6
    # visualizer
    mvis = initialize_visualizer(model)
    set_configuration!(mvis, Z[end][1:state_dim(model)÷2])
    render(mvis)
```

```julia
end
```

```
┌ Info: MeshCat server started. You can open the visualizer by visiting the following URL in your browser:
└ http://127.0.0.1:8703
```

Out[12]:

Open Controls

In [ ]: