

Optimization-based Motion Planning and Optimal Control

Jun Zeng

Department of Mechanical Engineering
University of California, Berkeley

February 18th 2020

- 1 Introduction
- 2 Optimization-based path planning
 - General methods
 - Examples
- 3 Optimal control
 - Model predictive control

1 Introduction

2 Optimization-based path planning

- General methods
- Examples

3 Optimal control

- Model predictive control

Optimal Control vs Optimization-based Path Planning

- Optimal control: linear-quadratic regulator (LQR), model predictive control (MPC), sliding mode control, etc.
- Topics in optimization-based path planning:
 - Speed profile smoothing: e.g. minimum-jerk in autonomous driving.
 - Contact force: e.g. hybrid mode switch with contact force in legged robotics.
 - Energy efficiency: e.g. minimum-snap/jerk in aerial robotics.
- They are the same in mathematics: an optimization problem is formulated to generate control strategy or trajectory/robot's motions.
- They are different in the implementation: optimal control is usually holding a higher refresh rate and needs to be solved very fast, while the optimization problem in planning isn't necessarily to be solved computationally with that fast rate.

Generally, an optimal control problem or an optimization-based path planning problem could be described as follow,

$$\begin{aligned} u^*(t) &:= \arg \min_{u(\cdot)} \int_{t_0}^{t_f} c_t(x(t), u(t)) dt \\ \text{s.t. } &x(t_0) = x_0 \\ &\dot{x}(t) = f(x(t), u(t)) \quad \forall t \\ &x(t) \in \mathcal{X}_{feas} \quad \forall t \quad (\text{collision-free}) \\ &u(t) \in \mathcal{U}_{feas} \quad \forall t \quad (\text{control limits}) \end{aligned}$$

- In the view of control: generate feasible control inputs under dynamics constraints
- In the view of planning: generate dynamically-feasible waypoints (which will be tracked with appropriate control methods).

1 Introduction

2 Optimization-based path planning

- General methods
- Examples

3 Optimal control

- Model predictive control

Generally, a optimization problem will satisfy a variety of constraints, this leads us to have different methods to solve them numerically.

Some of them have explicit solutions:

- algebraic Riccati equation for the LQR problem:
 $K = R^{-1}(B^T P + N^T)$, where $A^T P + PA - PBR^{-1}B^T P + Q = 0$
- convex quadratic programming (Convex QP)

Others don't have explicit solution and don't guarantee existing solution but could be solved numerically:

- Shooting methods: we 'shoot' out trajectories in different directions until we find a trajectory that has the desired boundary value.
- Collocation methods: choose a finite-dimensional space of candidate solutions (e.g. polynomials) and a number of points in the domain (called collocation points), and to select that solution which satisfies the given equation at the collocation points.

Most likely, all problems could be formulated into a dynamic programming problem and could be solved with various numerical methods:

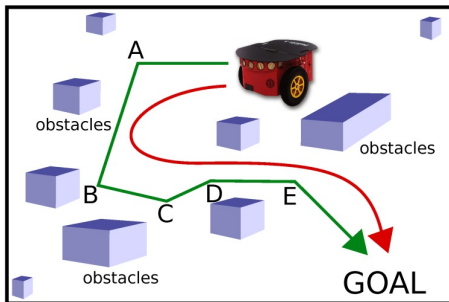
- for convex problems: Gurobi, Sedumi
 - software: CVX, OSQP
 - internal solvers: Gurobi, Sedumi, Mosek
- for non-convex problems:
 - interior point: IPOPT, SNOPT
 - active set method: SAS

We are more interested in the existence of the solution of the optimization. For a convex problem, we are likely to ensure at least one solution (might have several ones if it's nonlinear or non-convex cost function, our numerical solution will depends on the initial point where we do gradient descent).

But for general non-convex problem, we are not able to guarantee the existence of solution.

Trajectory smoothing

One of the most applicable areas about optimization-based planning is trajectory smoothing, which intends to make trajectory generated from the sample-based methods (RRT, PRM, etc) become smoother.



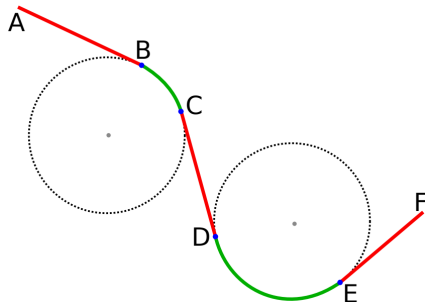
There are some traditional geometric methods for trajectory smoothing:

- Polynomial interpolation
- Bezier Curve
- Cubic Splines
- B-Splined

Geometric methods

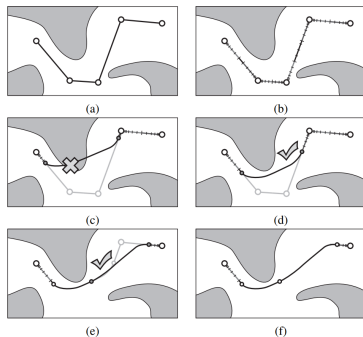
In industry, they prefer some special curves which are easy to be implemented:

- Dubin's Curve (e.g. lane change in autonomous driving)



Optimization-based methods

The optimization-based methods could also deal with trajectory smoothing problem. For example, minimum-time for obstacle avoidance¹.



Here, only bounded acceleration is considered, dynamics is still excluded.

¹Hauser and Ng-Thow-Hing, "Fast smoothing of manipulator trajectories using optimal bounded-acceleration shortcuts".

- "Time Elastic Band" planner (TEB Planner) with ROS integration is introduced²³, where non-holonomic kinematics is considered, but roughly.
- Some receding horizon methods are also introduced⁴.
- For autonomous driving, some special techniques are also proposed⁵⁶⁷.

²Rösmann et al., "Trajectory modification considering dynamic constraints of autonomous robots".

³Rösmann et al., "Efficient trajectory optimization using a sparse model".

⁴Kogan and Murray, "Optimization-based navigation for the DARPA Grand Challenge".

⁵Dolgov et al., "Path planning for autonomous vehicles in unknown semi-structured environments".

⁶Ziegler et al., "Trajectory planning for Bertha—A local, continuous method".

⁷Gu and Dolan, "On-road motion planning for autonomous vehicles".

There are many work about this area, the pipeline of path planning is mainly considered as trajectory generation + trajectory smooth, and the problem is formulated to consider mobile robots not holding too complex dynamics (autonomous cars, robot arm, etc).

How about generating a dynamically-feasible trajectory directly from an optimization-based problem? There are several tricky points to take into account.

- Obstacle avoidance
- Hybrid mode switch (contact force)
- Energy efficiency and smoothness (e.g. which kind of cost function we shall choose)

Obstacle avoidance

There are several ways to consider obstacle avoidance as constraints in an optimization-based problem:

- simple geometric constraints: e.g. $(x - x_{obs})^2 + (y - y_{obs})^2 \geq r^2$
 - very rough consideration: point-mass and round obstacle
 - nonlinear and non-convex constraints
 - it could be solved with modern solvers (IPOPT, etc) but doesn't guarantee a solution.

Obstacle avoidance

To make the problem become convex, an mixed-integer formulation could be introduced⁸⁹¹⁰.

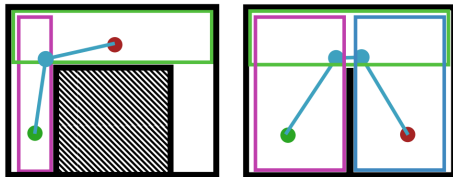



Figure: A trajectory in which each linear segment is required to remain entirely within one of the convex obstacle-free regions indicated by the colored boxes. This requirement ensures that the entire trajectory is collision-free.

A list of integer variables is used to represent the areas where the mobile robot is optimized to pass through.

⁸Richards and How, "Aircraft trajectory planning with collision avoidance using mixed integer linear programming".

⁹Deits and Tedrake, "Footstep planning on uneven terrain with mixed-integer convex optimization".

¹⁰Deits and Tedrake, "Efficient mixed-integer planning for UAVs in cluttered environments" 

Obstacle avoidance

Sometime we need to describe our robot and obstacles as rigid bodies, this leads us to define the distance between rigid body and obstacle avoidance constraint between them.

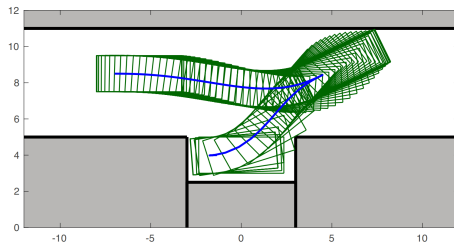


Figure: Dual variables are used to represent the collision-free constraints, see more details in¹¹.

¹¹Zhang, Liniger, and Borrelli, "Optimization-based collision avoidance".

Contact force

The intuition is simple: contact force is zero or distance between contact points should be zero. This formulates a complementarity constraint.

Generally, the methods is called *Optimization through contact*¹² and the problem is formulated as,

$$\begin{aligned} & \text{find } \ddot{q}, \lambda \\ & \text{subject to } H(q)\ddot{q} + C(q, \dot{q}) + G(q) = B(q)u + J(q)^T \lambda \\ & \quad \phi(q) \geq 0 \\ & \quad \lambda \geq 0 \\ & \quad \phi(q)^T \lambda = 0 \end{aligned}$$

¹²Posa, Cantu, and Tedrake, "A direct method for trajectory optimization of rigid bodies through contact".

Contact force

For example, the tension $T(t)$ in a massless cable could be considered as a contact force, assume the length of cable is l_0 and the distance between two ends of the cable is $l(t)$, then we have $\phi(q) = l_0 - l(t) \geq 0$ with its complementarity constraint,

$$T(t)(l_0 - l(t)) = 0$$

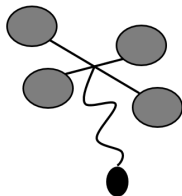



Figure: Aerial manipulation: quadrotor with a suspended point-mass payload

Energy efficiency and smoothness

- A cost function to minimize jerk (third-order derivative of vehicle's position)¹³.
- A cost function to minimize snap (fourth-order derivative of vehicle's position)¹⁴.

Actually, people find that minimum jerk or snap usually performed better than those of other orders in robots for smoothness.

¹³Pattacini et al., "An experimental evaluation of a novel minimum-jerk cartesian controller for humanoid robots".

¹⁴Mellinger and Kumar, "Minimum snap trajectory generation and control for quadrotors" 

1 Introduction

2 Optimization-based path planning

- General methods
- Examples

3 Optimal control

- Model predictive control

Linear-quadratic regulator (LQR)

The LQR algorithm reduces the amount of work done by the control systems engineer to optimize the controller.

$$J^* = \min_{u_i} \sum_{k=0}^N x_{k+1}^T Q x_{k+1} + u_k^T R u_k$$
$$\text{s.t. } x_{k+1} = A x_k + B u_k$$

There is no *prediction* here, feedback control gain is constant here.

Receding horizon control

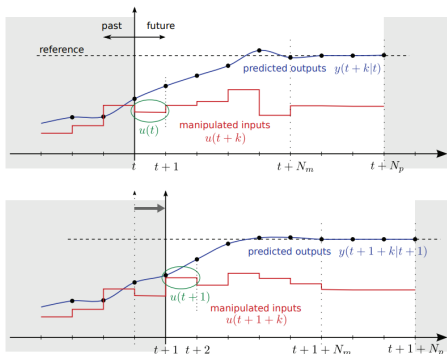
Let's present model prediction control as follow,

$$\begin{aligned} J_t^*(x(t)) &= p(x_{t+N}) + \sum_{k=0}^{N-1} q(x_{t+k}, u_{t+k}) \\ \text{s.t. } & x_{t+k+1} = Ax_{t+k} + Bu_{t+k}, k = 0, \dots, N-1 \\ & x_{t+k} \in \mathcal{X}, u_{t+k} \in \mathcal{U}, k = 0, \dots, N-1 \\ & x_{t+N} \in \mathcal{X}_f \\ & x_t = x(t) \end{aligned}$$

Truncate after a finite horizon:

- N : horizon
- $p(x_{t+N})$: terminal cost which approximate the 'tail' of the cost.
- $q(x_{t+k}, u_{t+k})$: staged cost
- \mathcal{X}_f : Approximates the 'tail' of the constraints.

Model Predictive Control



Where are the *Predictions*?

- At each sampling time, solve a constrained optimal control problem.
- Apply the optimal input only during $[t, t + 1]$.
- At $t + 1$, solve a CFTOC over a shifted horizon based on new state measurements.

Open-loop vs Closed-loop

Some definitions among researchers working on MPC:

- Open-loop trajectory: at each time step, we have a constrained optimal control problem, which solves a feasible trajectory with predictions.
- Closed-loop trajectory: since we solve optimal control problem at each time step, the robot will moves along a closed-loop trajectory with this control policy.

- Terminal cost ensures the Lyapunov convergence, but it's not necessary.
- Larger horizon brings a bigger controllable set, but needs more time to calculate the optimization.
- The dynamics constraints could be nonlinear, which will make the problem as a dynamic programming problem.
- There are many variants of MPC: Robust MPC, Adaptive MPC, MPC with obstacle avoidance, etc.