Optimal Control and Optimization in Robotics

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Introduction

My internship is co-supervised by Justin Carpentier (Willow, Inria Paris) and Nicolas Mansard (Gepetto, LAAS/CNRS) in the Willow research group at INRIA Paris in France.

Figure 1: Justin Carpentier

Figure 2: Nicolas Mansard

Hosting institution

L'**Institut national de recherche en informatique et en automatique (Inria)** est un établissement public à caractère scientifique et technologique français spécialisé en mathématiques et informatique, placé sous la double tutelle du ministère de l'Enseignement supérieur, de la Recherche et de l'Innovation et du ministère de l'Économie et des Finances créé le 3 janvier 1967 dans le cadre du « plan calcul ».

WILLOW
Computer vision and machine learning research laboratory

ENS

INVENTEURS DU MONDE NUMÉRIQUE

WILLOW is based in the Laboratoire d'Informatique de l'École Normale Superiéure (CNRS/ENS/INRIA UMR 8548) and is a joint research team between INRIA Rocquencourt, École Normale Supérieure de Paris and Centre National de la Recherche Scientifique.

Their research is concerned with representational issues in visual object recognition and scene understanding.

Motivations and Problems in a general context

I want my robot to move one thing somewhere and pass some point at some moment with a lowest cost.

Optimization: lowest cost

Control: from some point to another point

and *Constraints*

Outline

Optimal Control Problem

Optimal Control Problem

Goal 1: Controllability

$$\begin{aligned} &\text{find} && u \\ &\text{subject to} && x(0) = x_0,\ x(T) = p, \\ & && \dot{x}(t) = f(x(t), u(t)). \end{aligned} \tag{1}$$

Goal 2: Optimal Control

$$\begin{aligned} &\underset{u}{\text{minimize}} && \int_0^T l(x(t), u(t))dt \\ &\text{subject to} && x(0) = x_0,\ x(T) = p, \\ & && \dot{x}(t) = f(x(t), u(t)). \end{aligned} \tag{2}$$

Transformation of the problem

Adding penalty to the terminal lost:

$$
\begin{aligned}
\underset{u}{\text{minimize}} \quad & \int_{[0,T[} l(x(t), u(t))dt + l_T(x(T)) \\
\text{subject to} \quad & x(0) = x_0, \\
& \dot{x}(t) = f(x(t), u(t)).
\end{aligned} \tag{3}
$$

Discretization of functions and variables:

$$
\begin{aligned}
\underset{x \in \ell^\infty_{N+1}, u \in \ell^\infty_N}{\text{minimize}} \quad & J(x, u) = \sum_{i=0}^{N-1} L(x_i, u_i) + L_T(x_N) \\
\text{subject to} \quad & x(0) = x_0, \\
& x_{i+1} = F(x_i, u_i) \ \forall i \in [0..N-1]
\end{aligned} \tag{4}
$$

Differential Dynamic Programming

Dynamic Programming

Optimize one by one:

$$\min_U J(U) = \min_{u_0} \min_{u_1} \ldots \min_{u_{N-1}} J(U) \tag{5}$$

Definitions of Value Function and Q-functions:

$$\begin{aligned} V_i(x_i) &= \min_{u_i} L(x_i, u_i) + V_{i+1}(x_{i+1}) \\ V_N(x_N) &= L_T(x_N) \end{aligned} \tag{6}$$

$$\begin{aligned} Q_i(x_i, u_i) &= L(x_i, u_i) + V_{i+1}(x_{i+1}) \\ &= L(x_i, u_i) + V_{i+1}(f(x_i, u_i)) \\ &= L(x_i, u_i) + \min_{u_{i+1}} Q_{i+1}(f(x_i, u_i), u_{i+1}), \;\; i \leq N-2 \end{aligned} \tag{7}$$

$$V_i(x_i) = \min_{u_i} Q_i(x_i, u_i) \tag{8}$$

Linear Quadratic Regulator (LQR)

The LQR is an algorithm that solves the problem 4 *in one iteration* in case L, L_T are **quadratic** and F is **linear**.

Two phases in the algorithm:

- **Backward and Forward pass**:
  Compute V_x, V_{xx} and Q_u, Q_{uu}, Q_{ux} alternately
- **Roll-out**:
  Compute δ_u^* by V_x, V_{xx} and Q_u, Q_{uu}, Q_{ux}

Backward and Forward pass

Backward pass: from the partial derivatives of V_{i+1} back to the partial derivatives of Q_i

$$
\begin{aligned}
Q_u &= L_u + \underline{V_x'}\ F_u \quad {}^{1} \\
Q_{uu} &= L_{uu} + \underline{V_x'} \cdot F_{uu} + F_u^T \underline{V_{xx}'} F_u \\
Q_{ux} &= L_{ux} + \underline{V_x'} \cdot F_{ux} + F_u^T \underline{V_{xx}'} F_x
\end{aligned}
\tag{9}
$$

Forward pass: from the partial derivatives of Q_i back to the partial derivatives of V_i

$$
\begin{aligned}
V_x &= Q_x - Q_u Q_{uu}^{-1} Q_{ux} &&= Q_x + Q_u K \\
V_{xx} &= Q_{xx} - Q_{xu} Q_{uu}^{-1} Q_{ux} &&= Q_{xx} + Q_{xu} K
\end{aligned}
\tag{10}
$$

[1] "Q, V'" mean "Q_i, V_{i+1}".

Roll-out

Roll-**out**: determine the new trajectory x, u by computing the best control change δ_u.

$$
\begin{aligned}
\delta_u^*(i) &:= \arg\min_{\delta_u(i)} Q_i(x_i + \delta_x(i), u_i + \delta_u(i)) \\
\delta_u^* &= -Q_{uu}^{-1}(Q_u + Q_{ux}\delta_x) \quad \forall i \in [0..N-1]
\end{aligned}
\tag{11}
$$

$$
\begin{aligned}
u^* &:= u + \delta_u^*, \\
x_0^* &= x_0, \\
x_{i+1}^* &= F(x_i^*, u_i^*) \quad \forall i \in [0..N-1]
\end{aligned}
\tag{12}
$$