
pycvxset Documentation

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Abraham P. Vinod

Mitsubishi Electric Research Laboratories (MERL)

Email: vinod@merl.com, abraham.p.vinod@ieee.org

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WHAT IS PYCVXSET?

pycvxset (pronounced “Pie CVX Set”) is a Python package for manipulation and visualization of convex sets. The code is open-source (see <https://github.com/merlresearch/pycvxset>), and is maintained by Abraham P. Vinod.

Currently, pycvxset supports the following three representations:

1. **polytopes**,
2. **ellipsoids**, and
3. **constrained zonotopes** (which are equivalent to polytopes).

Some of the operations enabled by pycvxset include:

- construct sets from a variety of representations and transform between these representations,
- perform various operations on these sets including (but not limited to):
 - plot sets in 2D and 3D,
 - affine and inverse-affine transformation,
 - checking for containment,
 - intersection,
 - Minkowski sum,
 - Pontryagin difference,
 - projection,
 - slicing, and
 - support function evaluation.

See the Jupyter notebooks in `examples` folder for more details on how pycvxset can be used in set-based control and perform reachability analysis.

QUICK START

2.1 Requirements

pycvxset supports Python 3.9+ on Ubuntu, Windows, and MacOS. As described in [pyproject.toml](#), pycvxset has the following core dependencies:

1. [numpy](#)
2. [scipy](#)
3. [cvxpy](#)
4. [matplotlib](#)
5. [pycddlib](#): pycvxset requires `pycddlib>=3.0.0`. Use `pycvxset<=1.0.2` to use pycvxset with earlier versions of `pycddlib<=2.1.8.post1`.
6. [gurobipy](#): This dependency is **optional**. Almost all functionalities of pycvxset are available without [Gurobi](#). However, pycvxset uses [Gurobi](#) (through [cvxpy](#)) to perform *some* containment and equality checks involving constrained zonotopes. See [License](#) section for more details.

2.2 Installation

Refer to [.github/workflows](#) for exact steps to install pycvxset for different OSes. These steps are summarized below:

1. OS-dependent pre-installation steps:

- **Ubuntu**: Install [gmp](#).

```
$ sudo apt-get install libgmp-dev libcdd-dev python3-dev
```

See [pycddlib documentation](#) or [pycddlib/build.yml](#) for more details.

- **MacOS**: Install [gmp](#) and [cddlib](#).

```
% brew install gmp cddlib
% python3 -m pip install --upgrade pip
% env "CFLAGS=-I$(brew --prefix)/include -L$(brew --prefix)/lib" python -m
  pip install pycddlib==3.0.0
```

See [pycddlib documentation](#) or [pycddlib/build.yml](#) for more details.

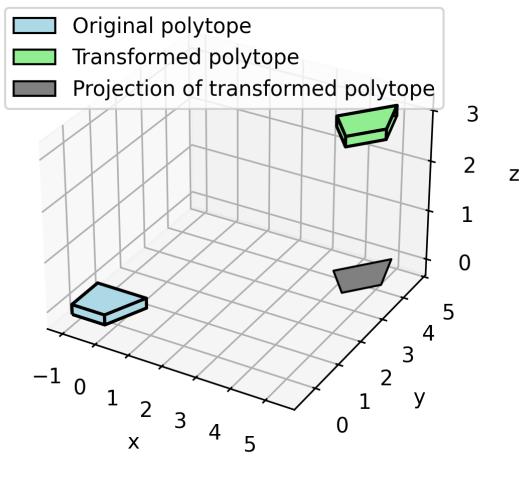
- **Windows**: No special steps required since pip takes care of it. If plotting fails, you can set `matplotlib` backend via an environment variable `set MPLBACKEND=Agg`. See <https://matplotlib.org/3.5.1/users/explain/backends.html#selecting-a-backend> for more details.

2. Clone the pycvxset repository into a desired folder `PYCVXSET_DIR`.
3. Run `pip install -e .` in the folder `PYCVXSET_DIR`.

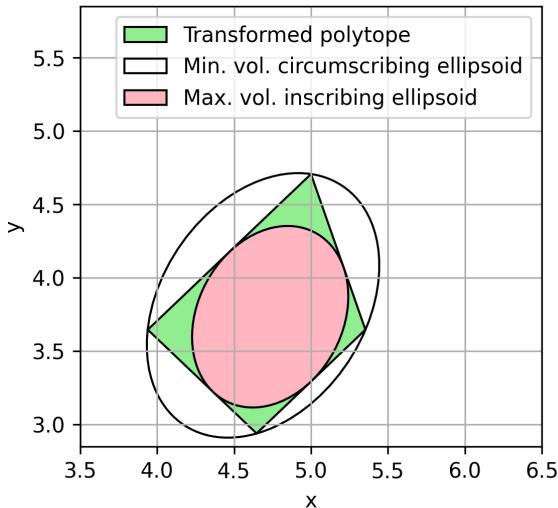
Sanity check: Check your installation by running `python3 examples/pycvxset_diag.py` in the folder `PYCVXSET_DIR`. The script should generate a figure with two subplots, each generated using pycvxset.

- *Left subplot:* A 3D plot of two polytopes (one at the origin, and the other translated and rotated). You can interact with this plot using your mouse.
- *Right subplot:* A 2D plot of the projection of the polytope, and its corresponding minimum volume circumscribing and maximum volume inscribing ellipsoids.

Rotate a polytope about z-axis by 45.0 ° and shift it by [5, 4, 3]



Projection of transformed polytope on to XY and ellipsoidal approximations



The following code block is reproduced from `run_demo` function in `examples/pycvxset_diag.py`. The code block demonstrates how one can use `pycvxset` to define sets and manipulate them:

```
# Copyright (C) 2020-2026 Mitsubishi Electric Research Laboratories (MERL)

import numpy as np
from pycvxset import Ellipsoid, Polytope
from scipy.spatial.transform import Rotation

# Define P as the intersection of a box with different sides and a halfspace
box_with_different_sides = Polytope(c=[0, 0, 0], h=[1, 0.5, 0.1])
P = box_with_different_sides.intersection_with_halfspaces([1, -0.5, 0], 0.25)
# Affine transformation (Rotate and translate P)
rotate_angle = np.pi / 4
R = Rotation.from_rotvec(rotate_angle * np.array([0, 0, 1])).as_matrix()
shift_vec = [5, 4, 3]
transformed_P = R @ P + shift_vec
# Projection (Compute its shadow on to the xy space)
project_transformed_P_to_XY = transformed_P.projection(project_away_dims=2)
# Centering ellipsoids
ellipsoid_inside_projection = Ellipsoid.deflate(project_transformed_P_to_XY)
ellipsoid_outside_projection = Ellipsoid.inflate(project_transformed_P_to_XY)
```

2.3 Optional: Testing

1. Use `pip install -e "[with_tests]"` to install the additional dependencies.
2. Run `$./scripts/run_tests_and_update_docs.sh` to view testing results on the command window.
3. View code coverage from testing at `./docs/build/_static/codecov/overall/index.html` on your browser.

2.4 Optional: Documentation

1. Use `pip install -e ".[with_docs_and_tests]"` to install the additional dependencies.
2. To produce the documentation,
 - Run `./scripts/run_all.sh`. This should take about 15 minutes. For **faster but incomplete options**,
 - To generate just the latex files for the `MANUAL.pdf`, run `./scripts/run_sphinx_pdf.sh`. This command will assume that the environment has `LaTeX` setup properly.
 - To build the API documentation without rendering the notebooks or coverage results, run `./scripts/run_sphinx_html.sh`.
3. View the documentation as,
 - PDF at `./MANUAL.pdf`
 - HTML pages (without internet) at `localhost:8000` after running `python -m http.server --directory ./docs/build/`.
 - Documentation website is available at `./docs/build/index.html`.
 - View the Jupyter notebooks at `./docs/build/tutorials/tutorials.html`.
 - View code coverage from testing at `./docs/build/_static/codecov/overall/index.html`.

**CHAPTER
THREE**

GETTING HELP

See [MANUAL.pdf](#) or <https://merlresearch.github.io/pycvxset/> for documentation of pycvxset.

Please use the [Discussion page](#) or the [Issue page](#), if you still need help.

**CHAPTER
FOUR**

CONTRIBUTING

See [CONTRIBUTING.md](#) for our policy on contributions.

**CHAPTER
FIVE**

LICENSE

pycvxset code is released under AGPL-3.0-or-later license, as found in the [LICENSE.md](#) file. The documentation for pycvxset is released under CC-BY-4.0 license, as found in the [LICENSES/CC-BY-4.0.md](#).

All files:

Copyright (c) 2020-2026 Mitsubishi Electric Research Laboratories (MERL).

SPDX-License-Identifier: AGPL-3.0-or-later

except the following files:

1. .gitignore
2. README.md
3. pycvxset/Polytope/__init__.py
4. pycvxset/Polytope/operations_binary.py
5. pycvxset/Polytope/operations_unary.py
6. pycvxset/Polytope/plotting_scripts.py
7. pycvxset/Polytope/vertex_halfspace_enumeration.py
8. pycvxset/__init__.py
9. pycvxset/common/__init__.py
10. tests/test_polytope_binary.py
11. tests/test_polytope_init.py
12. tests/test_polytope_vertex_facet_enum.py

which have the copyright

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SPDX-License-Identifier: MIT

The method `contains` in `pycvxset/ConstrainedZonotope/operations_binary.py` uses `gurobipy` (through `cvxpy`) and requires acceptance of appropriate license terms.

**CHAPTER
SIX**

ACKNOWLEDGEMENTS

The development of pcvxset started from commit [ebd85404](#) of [pytope](#).

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SPDX-License-Identifier: MIT

pcvxset extends [pytope](#) in several new directions, including:

- Plotting for 3D polytopes using [matplotlib](#),
- Interface with [cvxpy](#) for access to a wider range of solvers,
- Introduce new methods for *Polytope* class including circumscribing and inscribing ellipsoids, volume computation, and containment checks,
- Minimize the use of vertex-halfspace enumeration using convex optimization,
- Include extensive documentation and example Jupyter notebooks,
- Implement exhaustive testing with nearly 100% coverage, and
- Support for *Ellipsoid* and *ConstrainedZonotope* set representations.

**CHAPTER
SEVEN**

CITING

If you use this software in your research, please cite it using the metadata from [CITATION.cff](#) or the following bibtex entry.

```
@inproceedings{vinod2024pycvxset,  
    title={{pycvxset: A Python package for convex set manipulation}},  
    author={Vinod, Abraham P},  
    booktitle={Proceedings of American Control Conference (ACC)},  
    year={2025},  
    note = {(accepted)}  
}
```

**CHAPTER
EIGHT**

CONTACT

For questions or bugs, contact Abraham P. Vinod (Email: vinod@merl.com, abraham.p.vinod@ieee.org).

PYCVXSET.POLYTOPE

```
class pycvxset.Polytope
```

Bases: object

Polytope class.

Polytope object construction admits **one** of the following combinations (as keyword arguments):

1. (A, b) for a polytope in **halfspace representation (H-rep)** $\{x \mid Ax \leq b\}$,
2. (A, b, Ae, be) for a polytope in **halfspace representation (H-rep) with equality constraints** $\{x \mid Ax \leq b, A_e x = b_e\}$,
3. V for a polytope in **vertex representation (V-rep)** — ConvexHull(v_i) where v_i are rows of matrix V,
4. (lb, ub) for an **axis-aligned cuboid** with appropriate bounds $\{x \mid lb \leq x \leq ub\}$, and
5. (c, h) for an **axis-aligned cuboid** centered at c with specified scalar/vector half-sides h, $\{x \mid \forall i \in \{1, \dots, n\}, |x_i - c_i| \leq h_i\}$.
6. dim for an **empty Polytope** of dimension dim (no argument generates a zero-dimensional **empty Polytope**),

Parameters

- **dim (int, optional)** – Dimension of the empty polytope. If NOTHING is provided, dim=0 is assumed.
- **V (Sequence[Sequence[float]] / np.ndarray, optional)** – List of vertices of the polytope (V-Rep). The list must be 2-dimensional with vertices arranged row-wise and the polytope dimension determined by the column count.
- **A (Sequence[Sequence[float]] / np.ndarray, optional)** – Inequality coefficient vectors (H-Rep). The vectors are stacked vertically with the polytope dimension determined by the column count. When A is provided, b must also be provided.
- **b (Sequence[float] / np.ndarray, optional)** – Inequality constants (H-Rep). The constants are expected to be in a 1D numpy array. When b is provided, A must also be provided.
- **Ae (Sequence[Sequence[float]] / np.ndarray)** – Equality coefficient vectors (H-Rep). The vectors are stacked vertically with matching number of columns as A. When Ae is provided, A, b, and be must also be provided.
- **be (Sequence[float] / np.ndarray)** – Equality coefficient constants (H-Rep). The constants are expected to be in a 1D numpy array. When be is provided, A, b, and Ae must also be provided.
- **lb (Sequence[float] / np.ndarray, optional)** – Lower bounds of the axis-aligned cuboid. Must be 1D array, and the polytope dimension is determined by number of elements in lb. When lb is provided, ub must also be provided.

- **ub** (*Sequence[float] / np.ndarray, optional*) – Upper bounds of the axis-aligned cuboid. Must be 1D array of length as same as lb. When ub is provided, lb must also be provided.
- **c** (*Sequence[float] / np.ndarray, optional*) – Center of the axis-aligned cuboid. Must be 1D array, and the polytope dimension is determined by number of elements in c. When c is provided, h must also be provided.
- **h** (*float / Sequence[float] / np.ndarray, optional*) – Half-side length of the axis-aligned cuboid. Can be a scalar or a vector of length as same as c. When h is provided, c must also be provided.

Raises

- **ValueError** – When arguments provided is not one of [(A, b), (A, b, Ae, be), (lb, ub), (c, h), V, dim, NOTHING]
- **ValueError** – Errors raised by issues with (A, b) and (Ae, be) — mismatch in dimensions, not convertible to appropriately-dimensioned numpy arrays, incompatible systems (A, b) and (Ae, be) etc.
- **ValueError** – Errors raised by issues with V — not convertible to a 2-D numpy array, etc.
- **ValueError** – Errors raised by issues with lb, ub — mismatch in dimensions, not convertible to 1D numpy arrays, etc.
- **ValueError** – Errors raised by issues with c, h — mismatch in dimensions, not convertible to 1D numpy arrays, etc.
- **ValueError** – Polytope is not bounded in any direction. We use a sufficient condition for speed, and therefore the detection may not be exhaustive.
- **ValueError** – Polytope is not bounded in some directions. We use a sufficient condition for speed, and therefore the detection may not be exhaustive.
- **UserWarning** – If some rows are removed from (A, b) due to all zeros in A or np.inf in b | (Ae, be) when all zeros in Ae and be.

```
__init__() → None
__init__(*, dim: int) → None
__init__(*, V: Sequence[Sequence[float]] | ndarray) → None
__init__(*, A: Sequence[Sequence[float]] | ndarray, b: Sequence[float] | ndarray) → None
__init__(*, A: Sequence[Sequence[float]] | ndarray, b: Sequence[float] | ndarray, Ae:
         Sequence[Sequence[float]] | ndarray, be: Sequence[float] | ndarray) → None
__init__(*, lb: Sequence[float] | ndarray, ub: Sequence[float] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, h: float | Sequence[float] | ndarray) → None
```

Constructor for Polytope class.

Methods

<code>__init__()</code>	Constructor for Polytope class.
<code>affine_map(M)</code>	Compute the matrix times set.
<code>chebyshev_centering()</code>	Computes a ball with the largest radius that fits within the polytope.
<code>closest_point(points[, p])</code>	Wrapper for <code>project()</code> to compute the point in the convex set closest to the given point.
<code>containment_constraints(x[, flatten_order])</code>	Get CVXPY constraints for containment of x (a cvxpy.Variable) in a polytope.

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Table 1 – continued from previous page

<code>contains(Q)</code>	Check containment of a set Q (could be a polytope, an ellipsoid, or a constrained zonotope), or a collection of points $Q \in \mathbb{R}^{n_Q \times \mathcal{P}.dim}$ in the polytope \mathcal{P} .
<code>copy()</code>	Create a copy of the polytope
<code>decompose_as_affine_transform_of_polytop</code>	Express a polytope with equality constraints as an affine transformation of a lower-dimensional polytope without any equality constraints (hence full-dimensional).
<code>deflate_rectangle(set_to_be_centered)</code>	Compute the rectangle with the smallest volume that contains the given set.
<code>determine_H_rep([prefer_qhull_over_cdd, prune_V])</code>	Determine the halfspace representation from a given vertex representation of the polytope.
<code>determine_V_rep([prefer_qhull_over_cdd])</code>	Determine the vertex representation from a given halfspace representation of the polytope.
<code>distance(points[, p])</code>	Wrapper for <code>project()</code> to compute distance of a point to a convex set.
<code>extreme(eta)</code>	Wrapper for <code>support()</code> to compute the extreme point.
<code>interior_point([point_type])</code>	Compute a point in the interior of the polytope.
<code>intersection(Q)</code>	Intersect the polytope \mathcal{P} with another polytope Q .
<code>intersection_under_inverse_affine_map(Q, R)</code>	Compute the intersection of constrained zonotope under an inverse affine map
<code>intersection_with_affine_set(Ae, be)</code>	Intersect the polytope with an affine set.
<code>intersection_with_halfspaces(A, b)</code>	Intersect the polytope with a collection of halfspaces.
<code>inverse_affine_map_under_invertible_matrix(M)</code>	Compute the set times matrix, the inverse affine map of the set under an invertible matrix M .
<code>maximum_volume_inscribing_ellipsoid()</code>	Compute the maximum volume ellipsoid that fits within the given polytope.
<code>minimize(x, objective_to_minimize, cvxpy_args)</code>	Solve a convex program with CVXPY objective subject to containment constraints.
<code>minimize_H_rep()</code>	Remove any redundant inequalities from the halfspace representation of the polytope using cdd.
<code>minimize_V_rep([prefer_qhull_over_cdd, prune_V])</code>	Remove any redundant vertices from the vertex representation of the polytope.
<code>minimum_volume_circumscribing_ellipsoid()</code>	Compute the minimum volume ellipsoid that covers the given polytope (also known as Lowner-John Ellipsoid).
<code>minimum_volume_circumscribing_rectangle()</code>	Compute the minimum volume circumscribing rectangle for a given polytope
<code>minus(Q)</code>	Implement - operation (Pontryagin difference when Q is a polytope, translation by $-Q$ when Q is a point)
<code>normalize()</code>	Normalize a H-Rep such that each row of A has unit ℓ_2 -norm.
<code>plot([ax, patch_args, vertex_args, ...])</code>	Plot a 2D or 3D polytope.
<code>plot2d([ax, patch_args, vertex_args, ...])</code>	Plot a 2D polytope using matplotlib's <code>add_patch(Polygon())</code> .
<code>plot3d([ax, patch_args, vertex_args, ...])</code>	Plot a 3D polytope using matplotlib's <code>Line3DCollection</code> .
<code>plus(Q)</code>	Add a point or a set to the polytope
<code>project(x[, p])</code>	Project a point or a collection of points on to a set.
<code>projection(project_away_dims)</code>	Orthogonal projection of a set \mathcal{P} after removing some user-specified dimensions.
<code>slice(dims, constants)</code>	Slice a set restricting certain dimensions to constants.
<code>slice_then_projection(dims, constants)</code>	Wrapper for <code>slice()</code> and <code>projection()</code> .

continues on next page

Table 1 – continued from previous page

<code>support(eta)</code>	Evaluates the support function and support vector of a set.
<code>volume()</code>	Compute the volume of the polytope using QHull

Attributes

<code>A</code>	Inequality coefficient vectors A for the polytope $\{Ax \leq b, A_e x = b_e\}$.
<code>Ae</code>	Equality coefficient vectors Ae for the polytope $\{Ax \leq b, A_e x = b_e\}$.
<code>H</code>	Inequality constraints in halfspace representation $H=[A, b]$ for the polytope $\{Ax \leq b, A_e x = b_e\}$.
<code>He</code>	Equality constraints in halfspace representation $He=[Ae, be]$ for the polytope $\{Ax \leq b, A_e x = b_e\}$.
<code>V</code>	Vertex representation (V) where the polytope is given by ConvexHull(v_i) with v_i as the rows of $V = [v_1; v_2; \dots; v_{n_v} \text{vertices}]$.
<code>b</code>	Inequality constants b for the polytope $\{Ax \leq b, A_e x = b_e\}$.
<code>be</code>	Equality constants be for the polytope $\{Ax \leq b, A_e x = b_e\}$.
<code>cvxpy_args_lp</code>	CVXPY arguments in use when solving a linear program
<code>cvxpy_args_sdp</code>	CVXPY arguments in use when solving a semi-definite program
<code>cvxpy_args_socp</code>	CVXPY arguments in use when solving a second-order cone program
<code>dim</code>	Dimension of the polytope.
<code>in_H_rep</code>	Check if the polytope have a halfspace representation (H-Rep).
<code>in_V_rep</code>	Check if the polytope have a vertex representation (V-Rep).
<code>is_bounded</code>	Check if the polytope is bounded.
<code>is_empty</code>	Check if the polytope is empty.
<code>is_full_dimensional</code>	Check if the affine dimension of the polytope is the same as the polytope dimension
<code>is_singleton</code>	Check if the polytope is singleton.
<code>n_equalities</code>	Number of linear equality constraints used to define the polytope $\{Ax \leq b, A_e x = b_e\}$
<code>n_halfspaces</code>	Number of halfspaces used to define the polytope $\{Ax \leq b, A_e x = b_e\}$
<code>n_vertices</code>	Number of vertices
<code>type_of_set</code>	Return the type of set

`__init__()` → None
`__init__(*, dim: int)` → None
`__init__(*, V: Sequence[Sequence[float]] | ndarray)` → None
`__init__(*, A: Sequence[Sequence[float]] | ndarray, b: Sequence[float] | ndarray)` → None
`__init__(*, A: Sequence[Sequence[float]] | ndarray, b: Sequence[float] | ndarray, Ae: Sequence[Sequence[float]] | ndarray, be: Sequence[float] | ndarray)` → None
`__init__(*, lb: Sequence[float] | ndarray, ub: Sequence[float] | ndarray)` → None
`__init__(*, c: Sequence[float] | ndarray, h: float | Sequence[float] | ndarray)` → None
 Constructor for Polytope class.

`__new__(kwargs)`**

PYCVXSET.POLYTOPE (API DETAILS)

`pycvxset.Polytope`

Polytope class.

`class pycvxset.Polytope.Polytope`

Bases: `object`

Polytope class.

Polytope object construction admits **one** of the following combinations (as keyword arguments):

1. (A, b) for a polytope in **halfspace representation (H-rep)** $\{x \mid Ax \leq b\}$,
2. (A, b, Ae, be) for a polytope in **halfspace representation (H-rep) with equality constraints** $\{x \mid Ax \leq b, A_e x = b_e\}$,
3. V for a polytope in **vertex representation (V-rep)** — `ConvexHull(vi)` where v_i are rows of matrix V,
4. (lb, ub) for an **axis-aligned cuboid** with appropriate bounds $\{x \mid lb \leq x \leq ub\}$, and
5. (c, h) for an **axis-aligned cuboid** centered at c with specified scalar/vector half-sides h, $\{x \mid \forall i \in \{1, \dots, n\}, |x_i - c_i| \leq h_i\}$.
6. dim for an **empty Polytope** of dimension dim (no argument generates a zero-dimensional **empty Polytope**),

Parameters

- **dim (int, optional)** – Dimension of the empty polytope. If NOTHING is provided, dim=0 is assumed.
- **V (Sequence[Sequence[float]] / np.ndarray, optional)** – List of vertices of the polytope (V-Rep). The list must be 2-dimensional with vertices arranged row-wise and the polytope dimension determined by the column count.
- **A (Sequence[Sequence[float]] / np.ndarray, optional)** – Inequality coefficient vectors (H-Rep). The vectors are stacked vertically with the polytope dimension determined by the column count. When A is provided, b must also be provided.
- **b (Sequence[float] / np.ndarray, optional)** – Inequality constants (H-Rep). The constants are expected to be in a 1D numpy array. When b is provided, A must also be provided.
- **Ae (Sequence[Sequence[float]] / np.ndarray)** – Equality coefficient vectors (H-Rep). The vectors are stacked vertically with matching number of columns as A. When Ae is provided, A, b, and be must also be provided.
- **be (Sequence[float] / np.ndarray)** – Equality coefficient constants (H-Rep). The constants are expected to be in a 1D numpy array. When be is provided, A, b, and Ae must also be provided.

- **lb** (*Sequence[float] / np.ndarray, optional*) – Lower bounds of the axis-aligned cuboid. Must be 1D array, and the polytope dimension is determined by number of elements in lb. When lb is provided, ub must also be provided.
- **ub** (*Sequence[float] / np.ndarray, optional*) – Upper bounds of the axis-aligned cuboid. Must be 1D array of length as same as lb. When ub is provided, lb must also be provided.
- **c** (*Sequence[float] / np.ndarray, optional*) – Center of the axis-aligned cuboid. Must be 1D array, and the polytope dimension is determined by number of elements in c. When c is provided, h must also be provided.
- **h** (*float / Sequence[float] / np.ndarray, optional*) – Half-side length of the axis-aligned cuboid. Can be a scalar or a vector of length as same as c. When h is provided, c must also be provided.

Raises

- **ValueError** – When arguments provided is not one of [(A, b), (A, b, Ae, be), (lb, ub), (c, h), V, dim, NOTHING]
- **ValueError** – Errors raised by issues with (A, b) and (Ae, be) — mismatch in dimensions, not convertible to appropriately-dimensioned numpy arrays, incompatible systems (A, b) and (Ae, be) etc.
- **ValueError** – Errors raised by issues with V — not convertible to a 2-D numpy array, etc.
- **ValueError** – Errors raised by issues with lb, ub — mismatch in dimensions, not convertible to 1D numpy arrays, etc.
- **ValueError** – Errors raised by issues with c, h — mismatch in dimensions, not convertible to 1D numpy arrays, etc.
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- **ValueError** – Polytope is not bounded in some directions. We use a sufficient condition for speed, and therefore the detection may not be exhaustive.
- **UserWarning** – If some rows are removed from (A, b) due to all zeros in A or np.inf in b | (Ae, be) when all zeros in Ae and be.

```
__init__() → None
__init__(*, dim: int) → None
__init__(*, V: Sequence[Sequence[float]] | ndarray) → None
__init__(*, A: Sequence[Sequence[float]] | ndarray, b: Sequence[float] | ndarray) → None
__init__(*, A: Sequence[Sequence[float]] | ndarray, b: Sequence[float] | ndarray, Ae: Sequence[Sequence[float]] | ndarray, be: Sequence[float] | ndarray) → None
__init__(*, lb: Sequence[float] | ndarray, ub: Sequence[float] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, h: float | Sequence[float] | ndarray) → None
    Constructor for Polytope class.

affine_map(M: Sequence[float] | Sequence[Sequence[float]] | np.ndarray) → Polytope
    Compute the matrix times set.
```

Parameters

M (*Sequence[float] / Sequence[Sequence[float]] / np.ndarray*) – A vector or array (0, 1, or 2-D) with self.dim columns

Raises

- **ValueError** – When M can not be converted EXACTLY into a 2D array of float
- **ValueError** – When M does not have self.dim columns

Returns

The scaled polytope $\mathcal{R} = M\mathcal{P} = \{Mx : x \in \mathcal{P}\}$

Return type

Polytope

Notes

This function requires \mathcal{P} to be in V-Rep, and performs a vertex enumeration when \mathcal{P} is in H-Rep.

chebyshev_centering() → tuple[np.ndarray | None, float]

Computes a ball with the largest radius that fits within the polytope. The ball's center is known as the Chebyshev center, and its radius is the Chebyshev radius.

Raises

NotImplementedError – Unable to solve chebyshev centering problem using CVXPY

Returns**A tuple with two items**

1. center (numpy.ndarray): Chebyshev center of the polytope
2. radius (float): Chebyshev radius of the polytope

Return type

tuple

Notes

This function is called by the constructor for non-emptiness and boundedness check. It uses limited attributes (dim, A, b, Ae, be). This function requires H-Rep, and will perform a halfspace enumeration when a V-Rep polytope is provided.

We solve the LP (see Section 8.5.1 in [BV04]) for c (for *center*) and R (for *radius*),

$$\begin{aligned} & \text{maximize} && R \\ & \text{subject to} && Ac + R||A||_{\text{row}} \leq b, \\ & && A_e c = b_e, \\ & && R \geq 0, \end{aligned}$$

where $||A||_{\text{row}}$ is a vector of dimension *n_halfspaces* with each element as $||a_i||_2$. When (Ae, be) is non-empty, then R is forced to zero post-solve. Consequently, chebyshev_centering also serves a method to find a feasible point in the relative interior of the polytope.

We can also infer the following from the Chebyshev radius R:

1. $R = \infty$, the polytope is unbounded. Note that, this is just a sufficient condition, and an unbounded polytope can have a finite Chebyshev radius. For example, consider a 3-dimensional axis-aligned cuboid $[-1, 1] \times [-1, 1] \times \mathbb{R}$.
2. $0 < R < \infty$, the polytope is nonempty and full-dimensional.
3. $R = 0$, the polytope is nonempty and but not full-dimensional.
4. $R = -\infty$, the polytope is empty.

closest_point(points: Sequence[Sequence[float]] | np.ndarray, p: int | str = 2) → np.ndarray

Wrapper for *project()* to compute the point in the convex set closest to the given point.

Parameters

- **points** (Sequence[Sequence[float]] / np.ndarray) – Points to project. Matrix (N times self.dim), where each row is a point.
- **p (str / int)** – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2.

Returns

Projection of points to the set as a 2D numpy.ndarray. These arrays have as many rows as points.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for `project()` function.

containment_constraints(*x*: cvxpy.Variable, *flatten_order*: Literal['F', 'C'] = 'F') → tuple[list[cvxpy.Constraint], cvxpy.Variable | None]

Get CVXPY constraints for containment of *x* (a cvxpy.Variable) in a polytope.

Parameters

- **x** (cvxpy.Variable) – CVXPY variable to be optimized
- **flatten_order** (Literal["F", "C"]) – Order to use for flatten (choose between "F", "C"). Defaults to "F", which implements column-major flatten. In 2D, column-major flatten results in stacking rows horizontally to achieve a single horizontal row.

Raises

ValueError – When polytope is empty

Returns

A tuple with two items:

1. constraint_list (list): CVXPY constraints for the containment of *x* in the polytope.
2. theta (cvxpy.Variable | None): CVXPY variable representing the convex combination coefficient when polytope is in V-Rep. It is None when the polytope is in H-Rep or empty.

Return type

tuple

contains(*Q*: Sequence[float] | Sequence[Sequence[float]] | np.ndarray | ConstrainedZonotope | Ellipsoid | Polytope) → bool | np.ndarray

Check containment of a set \mathcal{Q} (could be a polytope, an ellipsoid, or a constrained zonotope), or a collection of points $Q \in \mathbb{R}^{n_Q \times \mathcal{P}.dim}$ in the polytope \mathcal{P} .

Parameters

Q (Sequence[float] / Sequence[Sequence[float]] / np.ndarray / ConstrainedZonotope / Ellipsoid / Polytope) – Set or a collection of points (each row is a point) to be tested for containment within \mathcal{P} . When providing a collection of points, *Q* is a matrix (N times self.dim) with each row is a point.

Raises

ValueError – When two polytopes | the polytope and the test point(s) are NOT of the same dimension

Returns

When *Q* is a polytope, a bool is returned which is True if and only if

$Q \subseteq P$. On the other hand, if *Q* is a sequence or numpy array (*Q* is a point or a collection of points), then a numpy.ndarray of bool is returned, with as many elements as the number of rows in *Q*.

Return type

bool | numpy.ndarray[bool]

Notes

- *Containment of polytopes*: This function accommodates the following combinations of representations for \mathcal{P} and \mathcal{Q} . It eliminates the need for enumeration by comparing support function evaluations almost always. When P is H-Rep and Q is V-Rep, then we perform a quick check for containment of vertices of Q in P . Otherwise, * Q is empty: Return True * P is empty: Return False
- *Containment of points*: This function accommodates \mathcal{P} to be in H-Rep or V-Rep. When testing if a point is in a polytope where only V-Rep is available for self, we solve a collection of second-order cone programs for each point using `project()` (check if distance between v and \mathcal{P} is nearly zero). Otherwise, we use the observation that for \mathcal{P} with (A, b, A_e, b_e) , then $v \in \mathcal{P}$ if and only if $Av \leq b$ and $A_e v = b_e$. For numerical precision considerations, we use `numpy.isclose()`.

`copy() → Polytope`

Create a copy of the polytope

`decompose_as_affine_transform_of_polytope_without_equalities() → tuple[Polytope,
np.ndarray, np.ndarray]`

Express a polytope with equality constraints as an affine transformation of a lower-dimensional polytope without any equality constraints (hence full-dimensional). The affine transformation is obtained via a QR decomposition.

If the polytope is already full-dimensional, returns a copy of itself and the identity matrix. Otherwise, finds an affine transformation that maps a lower-but-full-dimensional polytope to the original polytope.

Returns

A tuple with three items:

1. `full_dimensional_polytope (Polytope)`: A full-dimensional polytope.
2. `affine_transform_offset (numpy.ndarray)`: The affine offset (as a vector) to map the full-dimensional polytope to the original polytope.
3. `affine_transform_matrix (numpy.ndarray)`: A matrix whose columns form an orthonormal basis for the nullspace of the affine equality constraints.

Return type

`tuple`

Notes

This function requires H-Rep, and will perform a halfspace enumeration when a V-Rep polytope is provided. The decomposition is such that $self = M @ full_dim_polytope_in_relative_interior_of_self + c$. The function uses QR decomposition to find M and c . To avoid numerical issues, this function calls `pycvxset.Polytope.minimize_H_rep()`.

`classmethod deflate_rectangle(set_to_be_centered: ConstrainedZonotope | Ellipsoid | Polytope) → Polytope`

Compute the rectangle with the smallest volume that contains the given set.

Parameters

`set_to_be_centered (ConstrainedZonotope / Ellipsoid / Polytope)` – Set to compute the.

Returns

Minimum volume circumscribing rectangle

Return type

`Polytope`

Notes

This function is a wrapper for `minimum_volume_circumscribing_rectangle()` of attr:`set_to_be_centered`. Please check that function for more details including raising exceptions.

determine_H_rep(`prefer_qhull_over_cdd: bool = False, prune_V: bool = False`) → None

Determine the halfspace representation from a given vertex representation of the polytope.

Parameters

- **prefer_qhull_over_cdd**(`bool, optional`) – When True, determine_H_rep uses qhull when possible. Otherwise, we use cdd. Default is True.
- **prune_V**(`bool, optional`) – When True, prune vertices before halfspace enumeration. Defaults to False.

Raises

- **ValueError** – When H-rep computation fails OR Polytope is not bounded!

Notes

- When the set is empty, we define an empty polytope.
- Otherwise, we use cdd for the halfspace enumeration.
- The computed vertex representation need not be minimal.
- We do not check for bounded polytope since we have V-Rep.

determine_V_rep(`prefer_qhull_over_cdd: bool = False`) → None

Determine the vertex representation from a given halfspace representation of the polytope.

Parameters

- **prefer_qhull_over_cdd**(`bool, optional`) – When True, determine_V_rep uses qhull when possible. Otherwise, we use cdd. Default is True.

Raises

- **ValueError** – Vertex enumeration yielded rays! Possibly due to numerical issues or unbounded polytope!
- **ValueError** – Polytope is not bounded!

Notes

We use cdd for the vertex enumeration. cdd uses the halfspace representation $[b, -A]$ where $b - Ax \geq 0 \Leftrightarrow Ax \leq b$.

For a polyhedron described as

$$\mathcal{P} = \text{conv}(v_1, \dots, v_n) + \text{nonneg}(r_1, \dots, r_s),$$

the V-representation matrix in cdd is $[t \ V]$ where t is the column vector with n ones followed by s zeroes, and V is the stacked matrix of n vertex row vectors on top of s ray row vectors. `pycvxset` uses only bounded polyhedron, so we should never observe rays.

distance(`points: Sequence[Sequence[float]] | np.ndarray, p: int | str = 2`) → `np.ndarray`

Wrapper for `project()` to compute distance of a point to a convex set.

Parameters

- **points**(`Sequence[Sequence[float]] / np.ndarray`) – Points to project. Matrix (N times self.dim), where each row is a point.
- **p**(`int / str`) – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2.

Returns

Distance of points to the set as a 1D numpy.ndarray. These arrays have as many rows as points.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for [project\(\)](#) function.

extreme(eta: Sequence[Sequence[float]] | np.ndarray) → np.ndarray

Wrapper for [support\(\)](#) to compute the extreme point.

Parameters

eta (Sequence[Sequence[float]] / np.ndarray) – Support directions. Matrix (N times self.dim), where each row is a support direction.

Returns

Support vector evaluation(s) as a 2D numpy.ndarray. The array has as many rows as eta.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for [support\(\)](#) function.

interior_point(point_type: str | None = None) → np.ndarray

Compute a point in the interior of the polytope. When the polytope is not full-dimensional, the point may lie on the boundary.

Parameters

point_type (str, optional) – Type of interior point. Valid strings: {‘centroid’, ‘chebyshev’, ‘mvie’}. Defaults to ‘centroid’ if has V-Rep and ‘chebyshev’ if has H-Rep.

Raises

- **NotImplementedError** – When an invalid point_type is provided.
- **ValueError** – When the polytope provided is empty.
- **ValueError** – When the polytope provided is not bounded.

Returns

A feasible point in the polytope in the interior as a 1D array

Return type

numpy.ndarray

Notes

- point_type is ‘centroid’: Computes the average of the vertices. The function requires the polytope to be in V-Rep, and a vertex enumeration is performed if the polytope is in H-Rep.
- point_type is ‘chebyshev’: Computes the Chebyshev center. The function requires the polytope to be in H-Rep, and a halfspace enumeration is performed if the polytope is in V-Rep.

intersection(Q: Polytope) → Polytope

Intersect the polytope \mathcal{P} with another polytope \mathcal{Q} .

Parameters

Q (Polytope) – Polytope to be intersected with self

Raises

ValueError – Q is not a polytope | Mismatch in dimensions

Returns

The intersection of P and Q

Return type

Polytope

Notes

This function requires \mathcal{P} and Q to be of the same dimension and in H-Rep, and performs halfspace enumerations when P or Q are in V-Rep.

intersection_under_inverse_affine_map(Q : *Polytope*, R : *Sequence[Sequence[float]]* | $np.ndarray$) → *Polytope*

Compute the intersection of constrained zonotope under an inverse affine map

Parameters

- Q (*Polytope*) – Set to intersect with
- R (*Sequence[Sequence[float]]* | $np.ndarray$) – Matrix of dimension $Y.dim$ times $self.dim$

Raises

- **ValueError** – When Q is not a Polytope
- **ValueError** – When R is not of correct dimension
- **ValueError** – When $self$ is not bounded

Returns

The intersection of a polytope with another polytope under an inverse affine map. Specifically, given polytopes \mathcal{P} (self) and \mathcal{Q} , and a matrix R , we compute the set $\{x \in \mathcal{P} | Rx \in \mathcal{Q}\}$.

Return type

Polytope

Notes

This function requires both polytopes to be in H-Rep. Halfspace enumeration is performed when necessary.

Unlike `inverse_affine_map_under_invertible_matrix()`, this function does not require R to be invertible or square and also accommodates Q to be an unbounded polytope. However, $self$ must be a bounded set.

intersection_with_affine_set(A_e : *Sequence[Sequence[float]]* | $np.ndarray$, b_e : *Sequence[float]* | $np.ndarray$) → *Polytope*

Intersect the polytope with an affine set.

Parameters

- A_e (*Sequence[Sequence[float]]* | $np.ndarray$) – Equality coefficient vectors (H-Rep). The vectors are stacked vertically.
- b_e (*Sequence[float]* | $np.ndarray$) – Equality constants (H-Rep). The constants are expected to be in a 1D numpy array.

Raises

ValueError – Mismatch in dimensions | (A_e, b_e) is not a valid collection of equality constraints.

Returns

The intersection of P and $\{x : A_e x = b_e\}$

Return type

Polytope

Notes

This function requires $\mathcal{P}.\text{dim} = A.e.shape[1]$ and \mathcal{P} should be in H-Rep, and performs halfspace enumeration if \mathcal{P} in V-Rep.

intersection_with_halfspaces(*A*: Sequence[Sequence[float]] | np.ndarray, *b*: Sequence[float] | np.ndarray) → *Polytope*

Intersect the polytope with a collection of halfspaces.

Parameters

- **A** (Sequence[Sequence[float]] / np.ndarray) – Inequality coefficient vectors (H-Rep). The vectors are stacked vertically.
- **b** (Sequence[float] / np.ndarray) – Inequality constants (H-Rep). The constants are expected to be in a 1D numpy array.

Raises

ValueError – Mismatch in dimensions | (*A*, *b*) is not a valid collection of halfspaces

Returns

The intersection of P and $\{x \in \mathbb{R}^n \mid Ax \leq b\}$

Return type

Polytope

Notes

This function requires $\mathcal{P}.\text{dim} = A.e.shape[1]$ and \mathcal{P} should be in H-Rep, and performs halfspace enumeration if \mathcal{P} in V-Rep.

inverse_affine_map_under_invertible_matrix(*M*: Sequence[Sequence[float]] | np.ndarray) → *Polytope*

Compute the set times matrix, the inverse affine map of the set under an invertible matrix M .

Parameters

M (Sequence[Sequence[float]] / np.ndarray) – An invertible array of size self.dim times self.dim

Raises

- **ValueError** – When self is empty
- **TypeError** – When M is not convertible into a 2D numpy array of float
- **ValueError** – When M is not a square matrix
- **ValueError** – When M is not invertible

Returns

The inverse-scaled polytope $\mathcal{R} = \mathcal{P} \times M = \{x : Mx \in \mathcal{P}\}$

Return type

Polytope

Notes

- This function accommodates \mathcal{P} to be in H-Rep or in V-Rep. When \mathcal{P} is in H-Rep, $\mathcal{P}M = \{x | Mx \in \mathcal{P}\} = \{x | AMx \leq b, A_e Mx = b_e\}$. On the other hand, when \mathcal{P} is in V-Rep, $\mathcal{P}M = \text{ConvexHull}(M^{-1}v_i)$.
- We require M to be invertible in order to ensure that the resulting set is representable as a polytope.

maximum_volume_inscribing_ellipsoid() → tuple[np.ndarray, np.ndarray, np.ndarray]

Compute the maximum volume ellipsoid that fits within the given polytope.

Raises

- **ValueError** – When polytope is empty or has non-empty (A_e, b_e)
- **NotImplementedError** – Unable to solve convex problem using CVXPY

Returns**A tuple with three items:**

1. center (numpy.ndarray): Maximum volume inscribed ellipsoid's center
2. shape_matrix (numpy.ndarray): Maximum volume inscribed ellipsoid's shape matrix.
3. sqrt_shape_matrix (numpy.ndarray): Maximum volume inscribed ellipsoid's square root of shape matrix. Returns np.zeros((self.dim, 0)) if the polytope is a singleton.

Return type

tuple

Notes

This function requires H-Rep, and will perform a vertex enumeration when a V-Rep polytope is provided.

When the polytope is full-dimensional, we can solve a second-order cone program (SOCP). Consider the full-dimensional ellipsoid $\{Gu + c \mid \|u\|_2 \leq 1\}$, where G is a square, lower-triangular matrix with positive diagonal entries. Then, we solve the following (equivalent) optimization problem:

$$\begin{aligned} & \text{minimize} && \text{geomean}(G) \\ & \text{subject to} && \text{diag}(G) \geq 0 \\ & && \|G^T a_i\|_2 + a_i^T d \leq b_i, \end{aligned}$$

with decision variables G and c . Here, we use the observation that $\text{geomean}(G)$ is a monotone function of $\log \det(GG^T)$ (which is proportional to the volume of the ellipsoid).

When the polytope is not full-dimensional, we first compute the relative interior and then solve the SDP for a positive definite matrix $B \in \mathbb{S}_{++}^n$ and $d \in \mathbb{R}^n$,

$$\begin{aligned} & \text{maximize} && \log \det B \\ & \text{subject to} && \|Ba_i\|_2 + a_i^T d \leq b_i, \\ & && A_e d = b_e, \\ & && BA_e^\top = 0, \end{aligned}$$

where (a_i, b_i) is the set of hyperplanes characterizing \mathcal{P} , and the inscribing ellipsoid is given by $\{Bu + d \mid \|u\|_2 \leq 1\}$. The center of the ellipsoid is given by $c = d$, and the shape matrix is given by $Q = (BB)^{-1}$. See [EllipsoidalTbx-Min_verticesolEll] and Section 8.4.2 in [BV04] for more details. The last two constraints arise from requiring the inscribing ellipsoid to lie in the affine set $\{A_e x = b_e\}$.

minimize(*x: cvxpy.Variable, objective_to_minimize: cvxpy.Expression, cvxpy_args: dict[str, Any], task_str: str = ''*) → tuple[np.ndarray, float, str]

Solve a convex program with CVXPY objective subject to containment constraints.

Parameters

- **x** (*cvxpy.Variable*) – CVXPY variable to be optimized
- **objective_to_minimize** (*cvxpy.Expression*) – CVXPY expression to be minimized
- **cvxpy_args** (*dict*) – CVXPY arguments to be passed to the solver
- **task_str** (*str, optional*) – Task string to be used in error messages. Defaults to ''.

Raises**NotImplementedError** – Unable to solve problem using CVXPY

Returns**A tuple with three items:**

1. x.value (numpy.ndarray): Optimal value of x. np.nan * np.ones((self.dim,)) if the problem is not solved.
2. problem.value (float): Optimal value of the convex program. np.inf if the problem is infeasible, -np.inf if problem is unbounded, and finite otherwise.
3. problem_status (str): Status of the problem

Return type

tuple

Notes

This function uses `containment_constraints()` to obtain the list of CVXPY expressions that form the containment constraints on x.

⚠ Warning

Please pay attention to the `NotImplementedError` generated by this function. It may be possible to get CVXPY to solve the same problem by switching the solver. For example, consider the following code block.

```
from pycvxset import Polytope
P = Polytope(A=[[1, 1], [-1, -1]], b=[1, 1])
P=cvxpy_args_lp = {'solver': 'CLARABEL'}      # Default solver used in
                                                →pycvxset
try:
    print('Is polytope bounded?', P.is_bounded)
except NotImplementedError as err:
    print(str(err))
P=cvxpy_args_lp = {'solver': 'OSQP'}
print('Is polytope bounded?', P.is_bounded)
```

This code block produces the following output:

```
Unable to solve the task (support function evaluation of the set at eta =
→[-0. -1.]). CVXPY returned error:
Solver 'CLARABEL' failed. Try another solver, or solve with verbose=True
→for more information.
```

```
Is polytope bounded? False
```

minimize_H_rep() → None

Remove any redundant inequalities from the halfspace representation of the polytope using cdd.

Raises

`ValueError` – When minimal H-Rep computation fails OR polytope is not bounded!

minimize_V_rep(*prefer_ghull_over_cdd*: bool = False, *prune_V*: bool = False) → None

Remove any redundant vertices from the vertex representation of the polytope.

Parameters

- `prefer_ghull_over_cdd` (bool, optional) – When True, `minimize_V_rep` uses ghull when possible. Otherwise, we use cdd. Default is True.
- `prune_V` (bool, optional) – When True, prune vertices before minimizing. Defaults to False.

Raises

ValueError – When minimal V-Rep computation fails!

Notes

Use cdd or qhull for the reduction of vertices.

minimum_volume_circumscribing_ellipsoid() → tuple[np.ndarray, np.ndarray, np.ndarray | None]
 Compute the minimum volume ellipsoid that covers the given polytope (also known as Lowner-John Ellipsoid).

Raises

- **ValueError** – When polytope is empty
- **NotImplementedError** – Unable to solve convex problem using CVXPY

Returns

A tuple with three items:

1. center (numpy.ndarray): Minimum volume circumscribed ellipsoid's center
2. shape_matrix (numpy.ndarray): Minimum volume circumscribed ellipsoid's shape matrix
3. sqrt_shape_matrix (numpy.ndarray): Minimum volume circumscribed ellipsoid's square root of shape matrix. Returns None if the polytope is not full-dimensional.

Return type

tuple

Notes

This function requires V-Rep, and will perform a vertex enumeration when a H-Rep polytope is provided.

We solve the SDP for a positive definite matrix $A \in \mathbb{S}_{++}^n$ and $b \in \mathbb{R}^n$,

$$\begin{aligned} & \text{maximize} && \log \det A^{-1} \\ & \text{subject to} && \|Av_i + b\|_2 \leq 1, \forall \text{ vertices } v_i \text{ of } \mathcal{P} \end{aligned}$$

where the circumscribing ellipsoid is given by $\{x \mid \|Ax + b\|_2 \leq 1\}$, and we use the observation that $\log \det A^{-1} = -\log \det A$. The center of the ellipsoid is given by $c = -A^{-1}b$, and the shape matrix is given by $Q = (A^T A)^{-1}$. See [EllipsoidalTbx-Min_verticesell] and Section 8.4.1 in [BV04] for more details.

When the polytope is full-dimensional, we can instead solve a second-order cone program (SOCP). Consider the full-dimensional ellipsoid $\{Lu + c \mid \|u\|_2 \leq 1\}$, where G is a square, lower-triangular matrix with positive diagonal entries. Then, we solve the following (equivalent) optimization problem:

$$\begin{aligned} & \text{minimize} && \text{geomean}(L) \\ & \text{subject to} && \text{diag}(L) > 0 \\ & && v_i = Lu_i + c, \forall \text{ vertices } v_i \text{ of } \mathcal{P}, \\ & && u_i \in \mathbb{R}^n, \|u_i\|_2 \leq 1, \end{aligned}$$

with decision variables G , c , and u_i , and geomean is the geometric mean of the diagonal elements of G . Here, we use the observation that $\text{geomean}(L)$ is a monotone function of $\log \det(GG^T)$ (the volume of the ellipsoid). For the sake of convexity, we solve the following equivalent optimization problem after a change of variables $L_{\text{inv}} = L^{-1}$ and $c_{L_{\text{inv}}} = L^{-1}c$, and substituting for the variables u_i :

$$\begin{aligned} & \text{maximize} && \text{geomean}(L_{\text{inv}}) \\ & \text{subject to} && \text{diag}(L_{\text{inv}}) > 0 \\ & && \|L_{\text{inv}}v_i - c_{L_{\text{inv}}}\|_2 \leq 1, \forall \text{ vertices } v_i \end{aligned}$$

The center of the ellipsoid is $c = Lc_{L_{\text{inv}}}$, and the shape matrix is $Q = GG^T$, where $L = L_{\text{inv}}^{-1}$.

minimum_volume_circumscribing_rectangle() → tuple[np.ndarray, np.ndarray]

Compute the minimum volume circumscribing rectangle for a given polytope

Raises

- **ValueError** – When polytope is empty
- **ValueError** – When polytope is unbounded

Returns**A tuple of two items**

1. lb (numpy.ndarray): Lower bound l on the polytope, $\mathcal{P} \subseteq \{l\} \oplus \mathbb{R}_{\geq 0}$.
2. ub (numpy.ndarray): Upper bound u on the polytope, $\mathcal{P} \subseteq \{u\} \oplus (-\mathbb{R}_{\geq 0})$.

Return type

tuple

Notes

This function accommodates H-Rep and V-Rep. The lower/upper bound for V-Rep is given by an element-wise minimization/maximization operation, while the lower/upper bound for H-Rep is given by an element-wise support computation ($2 * \text{self.dim}$ linear programs). For a H-Rep polytope, the function uses `support()` and is a wrapper for `pycvxset.common.minimum_volume_circumscribing_rectangle()`.

This function is called to check for boundedness of a polytope.

minus(Q: Sequence[float] | Sequence[Sequence[float]] | np.ndarray | ConstrainedZonotope | Ellipsoid | Polytope) → Polytope

Implement - operation (Pontryagin difference when Q is a polytope, translation by -Q when Q is a point)

Parameters

Q (Sequence[float] | Sequence[Sequence[float]] | np.ndarray | ConstrainedZonotope | Ellipsoid | Polytope) – Polytope to be subtracted in Pontryagin difference sense from self or a vector for negative translation of the polytope

Raises

- **TypeError** – When Q is neither a Polytope or a point
- **ValueError** – When Q is not of the same dimension as self

Returns

The polytope \mathcal{R} that is the Pontryagin difference of P and Q or a negative translation of P by Q .

Return type

Polytope

Notes

- *Subtraction with a point*: This function accommodates \mathcal{P} in H-Rep and V-Rep. See `plus()` for more details.
- *Subtraction with a polytope*: This function requires \mathcal{P} and Q to be of the same dimension and \mathcal{P} in H-Rep, and performs halfspace enumerations when \mathcal{P} is in V-Rep. The H-rep of the polytope \mathcal{R} is, $H_{\mathcal{R}} = [\mathcal{P}.A, \mathcal{P}.b - \rho_Q(\mathcal{P}.A)]$ where ρ_Q is the support function (see `support()`). [KG98]

normalize() → None

Normalize a H-Rep such that each row of A has unit ℓ_2 -norm.

Notes

This function requires P to be in H-Rep. If P is in V-Rep, a halfspace enumeration is performed.

```
plot(ax: Axes | Axes3D | None | None = None, patch_args: dict[str, Any] | None = None, vertex_args: dict[str, Any] | None = None, autoscale_enable: bool = True, decimal_precision: int = 3, enable_warning: bool = True) → tuple[Any, Any, Any]
```

Plot a 2D or 3D polytope.

Parameters

- **ax** (Axes / Axes3D / None, optional) – Axis on which the patch is to be plotted
- **patch_args** (dict, optional) – Arguments to pass for plotting faces and edges. See [\[Matplotlib-patch\]](#) for options for patch_args for 2D and [\[Matplotlib-Line3DCollection\]](#) for options for patch_args for 3D. Defaults to None, in which case we set edgecolor to black, and facecolor to skyblue.
- **vertex_args** (dict, optional) – Arguments to pass for plotting vertices. See [\[Matplotlib-scatter\]](#) for options for vertex_args for 2D and [\[Matplotlib-Axes3D.scatter\]](#) for options for vertex_args for 3D. Defaults to None, in which case we skip plotting the vertices.
- **autoscale_enable** (bool, optional) – When set to True, matplotlib adjusts axes to view full polytope. Defaults to True.
- **decimal_precision** (int, optional) – When plotting a 3D polytope that is in V-Rep and not in H-Rep, we round vertex to the specified precision to avoid numerical issues. Defaults to PLOTTING_DECIMAL_PRECISION_CDD specified in pycvxset.common.constants.
- **enable_warning** (bool, optional) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Raises

- **ValueError** – When an incorrect axes is provided.
- **NotImplementedError** – When a polytope.dim >= 4 or == 1 | autoscale_enable is set to False for 3D plotting.
- **UserWarning** – When an empty polytope or an unbounded polytope is provided.
- **UserWarning** – In 3D plotting, when all faces have less than 3 vertices

Returns

Tuple with axes containing the polygon, handle for plotting patch, handle for plotting vertices

Return type

(axes, handle, handle)

Notes

- plot is a wrapper for [plot2d\(\)](#) and [plot3d\(\)](#) functions. See their documentation for more details.
- *Vertex-halfspace enumeration for 2D polytopes:* If a 2D polytope is in H-Rep, vertex enumeration is performed to plot the polytope in 2D. No vertex enumeration is performed for a 2D polytope in V-Rep. This function calls minimize_V_rep to simplify plotting.
- *Vertex-halfspace enumeration for 3D polytopes:* The 3D polytope needs to have both V-Rep and H-Rep. Consequently, at least a halfspace/vertex enumeration is performed for a 3D polytope in single representation.
- *Rounding vertices:* This function calls [pycvxset.common.prune_and_round_vertices\(\)](#) when a 3D polytope in V-Rep is given to be plotted.

- *Handle returned for the patches:* For 2D plot, axis handle of the single patch is returned. For 3D plotting, multiple patches are present, and plot returns the first patch's axis handle. In this case, the order of patches are determined by the use of `pycddlib.copy_input_incidence` from the from the specified (A, b). Also, labeling the first patch is done using Poly3DCollection.
- *Disabling face colors:* We can plot the polytope frames without filling it by setting `patch_args['facecolor'] = None` or `patch_args['fill'] = False`. If visual comparison of 3D polytopes is desired, it may be better to plot just the polytope frames instead by setting `patch_args['facecolor'] = None`.

⚠ Warning

This function may produce erroneous-looking plots when visually comparing multiple 3D sets. For more info on matplotlib limitations, see <https://matplotlib.org/stable/api/toolkits/mplot3d/faq.html#my-3d-plot-doesn-t-look-right-at-certain-viewing-angles>. If visual comparison is desired, it may be better to plot just the polytope frame instead by setting `patch_args['facecolor'] = None`.

plot2d(*ax*: *Axes* | *Axes3D* | *None* | *None* = *None*, *patch_args*: *dict[str, Any]* | *None* = *None*, *vertex_args*: *dict[str, Any]* | *None* = *None*, *autoscale_enable*: *bool* = *True*, *enable_warning*: *bool* = *True*) → *tuple[Any, Any, Any]*

Plot a 2D polytope using matplotlib's `add_patch(Polygon())`.

Parameters

- **ax** (*Axes* / *Axes3D* / *None*, *optional*) – Axis on which the patch is to be plotted
- **patch_args** (*dict*, *optional*) – Arguments to pass for plotting faces and edges. See [Matplotlib-patch] for options for `patch_args`. Defaults to *None*, in which case we set `edgecolor` to black, and `facecolor` to skyblue.
- **vertex_args** (*dict*, *optional*) – Arguments to pass for plotting vertices. See [Matplotlib-scatter] for options for `vertex_args`. Defaults to *None*, in which case we skip plotting the vertices.
- **autoscale_enable** (*bool*, *optional*) – When set to *True* (default), matplotlib adjusts axes to view full polytope.
- **enable_warning** (*bool*, *optional*) – Enables the `UserWarning`. May be turned off if expected. Defaults to *True*.

Raises

`ValueError` – When a 2D polytope is provided

Returns

Tuple with axes containing the polygon, handle for plotting patch, handle for plotting vertices

Return type

`(axes, handle, handle)`

Notes

This function requires polytope in V-Rep, and performs a vertex enumeration if the polytope is H-Rep.

We sort the vertices in counter-clockwise direction with respect to the centroid, and then plot it using matplotlib's `Polygon`. We can plot just the polytope frames without filling it by setting `patch_args['facecolor'] = None` or `patch_args['fill'] = False`.

plot3d(*ax*: *Axes* | *Axes3D* | *None* | *None* = *None*, *patch_args*: *dict[str, Any]* | *None* = *None*, *vertex_args*: *dict[str, Any]* | *None* = *None*, *autoscale_enable*: *bool* = *True*, *decimal_precision*: *int* = 3, *enable_warning*: *bool* = *True*, *prune_V*: *bool* = *True*) → *tuple[Any, Any, Any]*

Plot a 3D polytope using matplotlib's `Line3DCollection`.

Parameters

- **ax** (*Axes / Axes3D / None, optional*) – Axes to plot. Defaults to None, in which case a new axes is created. The function assumes that the provided axes was defined with projection='3d'.
- **patch_args** (*dict, optional*) – Arguments to pass for plotting faces and edges. See [Matplotlib-Line3DCollection] for options for patch_args. Defaults to None, in which case we set edgecolor to black, and facecolor to skyblue.
- **vertex_args** (*dict, optional*) – Arguments to pass for plotting vertices. See [Matplotlib-Axes3D.scatter] for options for vertex_args. Defaults to None, in which case we skip plotting the vertices.
- **autoscale_enable** (*bool, optional*) – When set to True (default), matplotlib adjusts axes to view full polytope.
- **decimal_precision** (*int, optional*) – When plotting a 3D polytope that is in V-Rep and not in H-Rep, we round vertex to the specified precision to avoid numerical issues. Defaults to PLOTTING_DECIMAL_PRECISION_CDD specified in pycvxset.common.constants.
- **enable_warning** (*bool, optional*) – Enables the UserWarning. May be turned off if expected. Defaults to True.
- **prune_V** (*bool, optional*) – When True, prune vertices before plotting. Defaults to True.

Raises

- **ValueError** – When either a non-3D polytope is provided.
- **UserWarning** – When all faces have less than 3 vertices
- **NotImplementedError** – autoscale_enable needs to be currently enabled for 3D plotting

Returns

Tuple with axes containing the polygon, handle for plotting patch, handle for plotting vertices

Return type

(axes, handle, handle)

Notes

- This function requires polytope in H-Rep and V-Rep, and uses CDD to compute incidences, and vertices. Consequently, at least one halfspace/vertex enumeration is performed.
- Since 3D plotting involves multiple patches, the first patch's axis handle is returned. In this case, the order of patches are determined by the use of `pycddlib.copy_input_incidence` from the specified (A, b).
- This function calls `pycvxset.common.prune_and_round_vertices()` when a 3D polytope in V-Rep is given to be plotted.
- When label is passed in patch_args, the label is only applied to the first patch. Subsequent patches will not have a label. Moreover, the first patch is plotted using Poly3DCollection, while the subsequent patches are plotted using Line3DCollection in this case. Otherwise, when no label is provided, all patches are plotted using Line3DCollection.
- We iterate over each halfspace, rotate the halfspace about its centroid so that halfspace is now parallel to XY plane, and then sort the vertices based on their XY coordinates in counter-clockwise direction with respect to the centroid, and then plot it using matplotlib's Line3DCollection.

⚠ Warning

This function may produce erroneous-looking plots when visually comparing multiple 3D sets. For more info on matplotlib limitations, see <https://matplotlib.org/stable/api/toolkits/mplot3d/faq.html#my-3d-plot-doesn-t-look-right-at-certain-viewing-angles>. If visual comparison is desired, it may be better to plot just the polytope frame instead by setting `patch_args['facecolor'] = None`.

plus(*Q*: Sequence[float] | Sequence[Sequence[float]] | np.ndarray | Polytope) → Polytope

Add a point or a set to the polytope

Parameters

Q (Sequence[float] | Sequence[Sequence[float]] | np.ndarray | Polytope) – Point or set to add to the polytope.

Raises

ValueError – When the point dimension does not match the polytope dimension.

Returns

Polytope which is the sum of self and Q.

Return type

Polytope

Notes

- Given a polytope \mathcal{P} , and a set Q , this function computes the Minkowski sum of Q and the polytope, defined as $\mathcal{R} = \{x + q | x \in \mathcal{P}, q \in Q\}$. On the other hand, when Q is a point, this function computes the polytope $\mathcal{R} = \{x + Q | x \in \mathcal{P}\}$.
- Addition with a point*: This function allows for \mathcal{P} to be in V-Rep or in H-Rep. For \mathcal{P} in V-Rep, the polytope \mathcal{R} is the convex hull of the vertices of \mathcal{P} shifted by point. Given $\{v_i\}$ as the collection of vertices of \mathcal{P} , $\mathcal{R} = \text{convexHull}(v_i + \text{point})$. For \mathcal{P} in H-Rep, the polytope \mathcal{R} is defined by all points $r = \text{point} + x$ with $Ax \leq b$, $A_e x = b_e$. Thus, $\mathcal{R} = \{x : Ax \leq b + A\text{point}, A_e x = b_e + A_e\text{point}\}$.
- Addition with a polytope*: This function requires self and Q to be in V-Rep, and performs a vertex enumeration when self or Q are in H-Rep.. In vertex representation, \mathcal{R} is the convex hull of the pairwise sum of all combinations of points in \mathcal{P} and Q .

project(*x*: Sequence[float] | Sequence[Sequence[float]] | ndarray, *p*: int | str = 2) → tuple[ndarray, ndarray]

Project a point or a collection of points on to a set.

Given a set \mathcal{P} and a test point $y \in \mathbb{R}^{\mathcal{P}.\text{dim}}$, this function solves a convex program,

$$\begin{aligned} & \text{minimize} && \|x - y\|_p \\ & \text{subject to} && x \in \mathcal{P} \end{aligned}$$

Parameters

- points** (Sequence[Sequence[float]] | np.ndarray) – Points to project (N times self.dim) with each row as a point.
- p (str / int)** – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2, which is the Euclidean norm.

Raises

- ValueError** – Set is empty
- ValueError** – Dimension mismatch — no. of columns in points is different from self.dim.

- **ValueError** – Points is not convertible into a 2D array
- **NotImplementedError** – Unable to solve problem using CVXPY

Returns**A tuple with two items:**

1. projected_point (numpy.ndarray): Projection point(s) as a 2D numpy.ndarray. Matrix (N times self.dim), where each row is a projection of the point in points to the set \mathcal{P} .
2. distance (numpy.ndarray): Distance(s) as a 1D numpy.ndarray. Vector (N,), where each row is a projection of the point in points to the set \mathcal{P} .

Return type

tuple

Notes

- This function allows for \mathcal{P} to be in V-Rep or in H-Rep.
- Given a polytope \mathcal{P} in V-Rep and a test point $y \in \mathbb{R}^{\mathcal{P}.dim}$, this function solves a convex program with decision variables $x \in \mathbb{R}^{\mathcal{P}.dim}$ and $\theta \in \mathbb{R}^{\mathcal{P}.n_vertices}$,

$$\begin{aligned} & \text{minimize} && \|x - y\|_p \\ & \text{subject to} && x = \sum_i \theta_i v_i \\ & && \sum_i \theta_i = 1, \theta_i \geq 0 \end{aligned}$$

- Given a polytope \mathcal{P} in H-Rep and a test point $y \in \mathbb{R}^{\mathcal{P}.dim}$, this function solves a convex program with a decision variable $x \in \mathbb{R}^{\mathcal{P}.dim}$,

$$\begin{aligned} & \text{minimize} && \|x - y\|_p \\ & \text{subject to} && Ax \leq b \\ & && A_e x = b_e \end{aligned}$$

`projection(project_away_dims: int | Sequence[int] | ndarray) → Polytope`Orthogonal projection of a set \mathcal{P} after removing some user-specified dimensions.

$$\mathcal{R} = \{r \in \mathbb{R}^m \mid \exists v \in \mathbb{R}^{n-m}, \text{Lift}(r, v) \in \mathcal{P}\}$$

Here, $m = \mathcal{P}.dim - \text{length}(\text{project_away_dim})$, and Lift(r, v) lifts (“undo”s the projection) using the appropriate components of v . This function uses `affine_map()` to implement the projection by designing an appropriate affine map $M \in \{0, 1\}^{m \times \mathcal{P}.dim}$ with each row of M corresponding to some standard axis vector $e_i \in \mathbb{R}^m$.

Parameters

`project_away_dims` (`Sequence[int]` / `np.ndarray`) – Dimensions to projected away in integer interval [0, 1, ..., n - 1].

Raises

ValueError – When project_away_dims are not in the integer interval | All dimensions are projected away

Returns

Set obtained via projection.

Return type

object

Returns

m-dimensional set obtained via projection.

Return type

Polytope

Notes

This function requires P to be in V-Rep, and performs a vertex enumeration when P is in H-Rep.

slice(dims: int | Sequence[int] | ndarray, constants: float | Sequence[float] | ndarray) → Polytope

Slice a set restricting certain dimensions to constants.

This function uses [*intersection_with_affine_set\(\)*](#) to implement the slicing by designing an appropriate affine set from dims and constants.

Parameters

- **dims** (*Sequence[int]* / *np.ndarray*) – List of dims to restrict to a constant in the integer interval [0, 1, ..., n - 1].
- **constants** (*float* / *Sequence[float]* / *np.ndarray*) – List of constants

Raises

- **ValueError** – dims has entries beyond n
- **ValueError** – dims and constants are not 1D arrays of same size

Returns

Sliced set.

Return type

object

Returns

Polytope that has been sliced at the specified dimensions.

Return type

Polytope

Notes

This function requires \mathcal{P} to be in H-Rep, and performs a vertex halfspace when \mathcal{P} is in V-Rep.

slice_then_projection(dims: int | Sequence[int] | ndarray, constants: float | Sequence[float] | ndarray) → Polytope

Wrapper for [*slice\(\)*](#) and [*projection\(\)*](#).

The function first restricts a set at certain dimensions to constants, and then projects away those dimensions. Useful for visual inspection of higher dimensional sets.

Parameters

- **dims** (*Sequence[int]* / *np.ndarray*) – List of dims to restrict to a constant in the integer interval [0, 1, ..., dim - 1], and then project away.
- **constants** (*float* / *Sequence[float]* / *np.ndarray*) – List of constants

Raises

- **ValueError** – dims has entries beyond n
- **ValueError** – dims and constants are not 1D arrays of same size
- **ValueError** – When dims are not in the integer interval | All dimensions are projected away

Returns

Sliced then projected set.

Return type

object

Returns

m-dimensional set obtained via projection after slicing.

Return type*Polytope***Notes**

This function requires \mathcal{P} to be in H-Rep, and performs a vertex halfspace when \mathcal{P} is in V-Rep.

support(*eta*: Sequence[float] | Sequence[Sequence[float]] | ndarray) → tuple[ndarray, ndarray]

Evaluates the support function and support vector of a set.

The support function of a set \mathcal{P} is defined as $\rho_{\mathcal{P}}(\eta) = \max_{x \in \mathcal{P}} \eta^\top x$. The support vector of a set \mathcal{P} is defined as $\nu_{\mathcal{P}}(\eta) = \arg \max_{x \in \mathcal{P}} \eta^\top x$.

Parameters

eta (Sequence[float] / Sequence[Sequence[float]] / np.ndarray) – Support directions. Matrix (N times self.dim), where each row is a support direction.

Raises

- **ValueError** – Set is empty
- **ValueError** – Mismatch in eta dimension
- **ValueError** – eta is not convertible into a 2D array
- **NotImplementedError** – Unable to solve problem using CVXPY

Returns

A tuple with two items:

1. support_function_evaluations (numpy.ndarray): Support function evaluation(s) as a 2D numpy.ndarray. Vector (N,) with as many rows as eta.
2. support_vectors (numpy.ndarray): Support vectors as a 2D numpy.ndarray. Matrix N x self.dim with as many rows as eta.

Return type

tuple

Notes

- This function allows for :math:mathcal{P} to be in V-Rep or in H-Rep.
- Given a polytope \mathcal{P} in V-Rep and a support direction $\eta \in \mathbb{R}^{\mathcal{P}.dim}$, this function solves a convex program with decision variables $x \in \mathbb{R}^{\mathcal{P}.dim}$ and $\theta \in \mathbb{R}^{\mathcal{P}.n_vertices}$,

$$\begin{aligned} & \text{maximize} && \eta^\top x \\ & \text{subject to} && x = \sum_i \theta_i v_i \\ & && \sum_i \theta_i = 1, \theta_i \geq 0 \end{aligned}$$

- Given a polytope \mathcal{P} in H-Rep and a support direction $\eta \in \mathbb{R}^{\mathcal{P}.dim}$, this function solves a convex program with a decision variable $x \in \mathbb{R}^{\mathcal{P}.dim}$,

$$\begin{aligned} & \text{maximize} && \eta^\top x \\ & \text{subject to} && Ax \leq b \\ & && A_e x = b_e \end{aligned}$$

volume() → float

Compute the volume of the polytope using QHull

Returns

Volume of the polytope

Return type

float

Notes

- Works with V-representation: Yes
- Works with H-representation: No
- Performs a vertex-halfspace enumeration when H-rep is provided
- Returns 0 when the polytope is empty
- Requires polytope to be full-dimensional

property A: ndarray

Inequality coefficient vectors A for the polytope $\{Ax \leq b, A_e x = b_e\}$.

Returns

Inequality coefficient vector (H-Rep). A is `np.empty((0, self.dim))` for empty polytope.

Return type

`numpy.ndarray`

Notes

This function requires the polytope to be in H-Rep, and performs a halfspace enumeration if required.

property Ae: ndarray

Equality coefficient vectors A_e for the polytope $\{Ax \leq b, A_e x = b_e\}$.

Returns

Equality coefficient vector (H-Rep). A_e is `np.empty((0, self.dim))` for empty or full-dimensional polytope.

Return type

`numpy.ndarray`

Notes

This function requires the polytope to be in H-Rep, and performs a halfspace enumeration if required.

property H: ndarray

Inequality constraints in halfspace representation $H=[A, b]$ for the polytope $\{Ax \leq b, A_e x = b_e\}$.

Returns

H-Rep in $[A, b]$. H is `np.empty((0, self.dim + 1))` for empty polytope.

Return type

`numpy.ndarray`

Notes

This function requires the polytope to be in H-Rep, and performs a halfspace enumeration if required.

property He: ndarray

Equality constraints in halfspace representation $He = [Ae, be]$ for the polytope $\{Ax \leq b, A_ex = b_e\}$.

Returns

H-Rep in $[Ae, be]$. He is `np.empty((0, self.dim + 1))` for empty or full-dimensional polytope.

Return type

`numpy.ndarray`

Notes

This function requires the polytope to be in H-Rep, and performs a halfspace enumeration if required.

property V: ndarray

Vertex representation (V) where the polytope is given by $\text{ConvexHull}(v_i)$ with v_i as the rows of $V = [v_1; v_2; \dots; v_{n_{vertices}}]$.

Returns

Vertices of the polytope, arranged row-wise. V is `np.empty((0, self.dim))` if polytope is empty.

Return type

`numpy.ndarray`

Notes

This function requires the polytope to be in V-Rep, and performs a vertex enumeration if required.

property b: ndarray

Inequality constants b for the polytope $\{Ax \leq b, A_ex = b_e\}$.

Returns

Inequality constants (H-Rep). b is `np.empty((0,))` for empty polytope.

Return type

`numpy.ndarray`

Notes

This function requires the polytope to be in H-Rep, and performs a halfspace enumeration if required.

property be: ndarray

Equality constants be for the polytope $\{Ax \leq b, A_ex = b_e\}$.

Returns

Equality constants (H-Rep). be is `np.empty((0,))` for empty or full-dimensional polytope.

Return type

`numpy.ndarray`

Notes

This function requires the polytope to be in H-Rep, and performs a halfspace enumeration if required.

property cvxpy_args_lp: dict[str, Any]

CVXPY arguments in use when solving a linear program

Returns

CVXPY arguments in use when solving a linear program. Defaults to dictionary in `pycvxset.common.DEFAULT_CVXPY_ARGS_LP`.

Return type

dict

property cvxpy_args_sdp: dict[str, Any]

CVXPY arguments in use when solving a semi-definite program

Returns

CVXPY arguments in use when solving a semi-definite program. Defaults to dictionary in *pycvxset.common.DEFAULT_CVXPY_ARGS_SDP*.

Return type

dict

property cvxpy_args_socp: dict[str, Any]

CVXPY arguments in use when solving a second-order cone program

Returns

CVXPY arguments in use when solving a second-order cone program. Defaults to dictionary in *pycvxset.common.DEFAULT_CVXPY_ARGS_SOCP*.

Return type

dict

property dim: int

Dimension of the polytope. In H-Rep polytope (A, b), this is the number of columns of A , while in V-Rep, this is the number of components of the vertices.

Returns

Dimension of the polytope

Return type

int

property in_H_rep: bool

Check if the polytope have a halfspace representation (H-Rep).

Returns

When True, the polytope has halfspace representation (H-Rep). Otherwise, False.

Return type

bool

property in_V_rep: bool

Check if the polytope have a vertex representation (V-Rep).

Returns

When True, the polytope has vertex representation (V-Rep). Otherwise, False.

Return type

bool

property is_bounded: bool

Check if the polytope is bounded.

Returns

True if the polytope is bounded, and False otherwise.

Return type

bool

property is_empty: bool

Check if the polytope is empty.

Returns

When True, the polytope is empty

Return type

bool

Notes

This property is well-defined ($self.n_vertices == 0$) when the polytope is in V-Rep and initialized in the constructor. For H-Rep, it solves a Chebyshev centering problem.

property is_full_dimensional: bool

Check if the affine dimension of the polytope is the same as the polytope dimension

Returns

True when the affine hull containing the polytope has the dimension $self.dim$

Return type

bool

Notes

This function can have self to be in V-Rep or H-Rep. See Sec. 2.1.3 of [BV04] for discussion on affine dimension.

An empty polytope is full dimensional if $dim=0$, otherwise it is not full-dimensional.

When the n-dimensional polytope is in V-Rep, it is full-dimensional when its affine dimension is n. Recall that, the affine dimension is the dimension of the affine hull of the polytope is the linear subspace spanned by the vectors formed by subtracting the vertices with one of the vertices. Consequently, its dimension is given by the rank of the matrix $P.V[1:] - P.V[0]$. When there are fewer than $self.dim + 1$ vertices, we know it is coplanar without checking for matrix rank (simplex needs at least $self.dim + 1$ vertices and that is the polytope with the fewest vertices). For numerical stability, we zero-out all delta vertices below PYCVXSET_ZERO.

When the n-dimensional polytope is in H-Rep, it is full-dimensional if it can fit a n-dimensional ball of appropriate center and radius inside it (Chebyshev radius).

property is_singleton: bool

Check if the polytope is singleton.

Returns

When True, the polytope is singleton.

Return type

bool

Notes

This property is well-defined ($self.n_vertices == 1$) when the polytope is in V-Rep and initialized in the constructor. For H-Rep, it solves a minimum_volume_circumscribing_rectangle problem.

property n_equalities: int

Number of linear equality constraints used to define the polytope $\{Ax \leq b, A_e x = b_e\}$

Returns

Number of linear equality constraints

Return type

int

Notes

A call to this property performs a halfspace enumeration if the polytope is in V-Rep.

property n_halfspaces: int

Number of halfspaces used to define the polytope $\{Ax \leq b, A_e x = b_e\}$

Returns

Number of halfspaces

Return type

int

Notes

A call to this property performs a halfspace enumeration if the polytope is in V-Rep.

property n_vertices: int

Number of vertices

Returns

Number of vertices

Return type

int

Notes

A call to this property performs a vertex enumeration if the polytope is in H-Rep.

property type_of_set: str

Return the type of set

Returns

Type of the set

Return type

str

PYCVXSET.ELLIPSOID

```
class pycvxset.Ellipsoid
```

Bases: object

Ellipsoid class.

We can define a bounded, non-empty ellipsoid \mathcal{P} using **one** of the following combinations:

1. (c, Q) for a full-dimensional ellipsoid in the **quadratic form** $\mathcal{P} = \{x \in \mathbb{R}^n \mid (x - c)^T Q^{-1}(x - c) \leq 1\}$ with a n-dimensional positive-definite matrix Q and a n-dimensional vector c . Here, pycvxset computes a n-dimensional lower-triangular, square matrix G that satisfies $GG^T = Q$.
2. (c, G) for a full-dimensional or a degenerate ellipsoid as an **affine transformation of a unit-ball** $\mathcal{P} = \{x \in \mathbb{R}^n \mid \exists u \in \mathbb{R}^N, x = c + Gu, \|u\|_2 \leq 1\}$ with a n x N matrix G . Here, pycvxset computes $Q = GG^T$.
3. (c, r) for a ball of radius $r \geq 0$ $\mathcal{P} = \{x \in \mathbb{R}^n \mid \|x - c\|_2 \leq r\}$.
4. (c) for a singleton ellipsoid $\mathcal{P} = \{c\}$.

Parameters

- **c** (*Sequence[float] / numpy.ndarray*) – Center of the ellipsoid c. Vector of length (self.dim,)
- **Q** (*Sequence[Sequence[float]] / numpy.ndarray, optional*) – Shape matrix of the ellipsoid Q. Q must be a positive definite matrix (self.dim times self.dim). (self.dim times self.dim).
- **G** (*Sequence[Sequence[float]] / numpy.ndarray, optional*) – Square root of the shape matrix of the ellipsoid G that satisfies $GG^T = Q$. Need not be a square matrix, but must have self.dim rows. If a singleton must be specified, G must have zero columns.
- **r** (*scalar, optional*) – Non-negative scalar that provides the radius of the self.dim-dimensional ball.

Raises

- **ValueError** – When more than one of Q, G, r was provided
- **ValueError** – When c or Q or G or r does not satisfy implicit properties

Notes

1. Empty ellipsoids are not permitted (c is a required keyword argument).
2. When provided G is such that $Q = GG^T$ is positive definite, we overwrite G with a lower-triangular, square, n-dimensional matrix for consistency. Here, G has strictly positive diagonal elements, and its determinant is the product of its diagonal elements (see volume computation).
3. We use the eigenvalues of Q to determine the radii of the maximum volume inscribing ball (Chebyshev radius R^-) and the minimum volume circumscribing ball $R^+ \geq R^-$.
 - a. The ellipsoid represents a singleton when R^+ is negligible.

b. The ellipsoid is full-dimensional when R^- is non-trivial.

```
__init__(*, c: Sequence[float] | ndarray, Q: Sequence[Sequence[float]] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, G: Sequence[Sequence[float]] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, r: float) → None
__init__(*, c: Sequence[float] | ndarray) → None
```

Constructor for Ellipsoid

Methods

<code>__init__()</code>	Constructor for Ellipsoid
<code>affine_hull()</code>	Compute the left null space of self.G to identify the affine hull.
<code>affine_map(M)</code>	Compute the affine transformation of the given ellipsoid based on a given scalar/matrix.
<code>chebyshev_centering()</code>	Compute the Chebyshev center and radius of the ellipsoid.
<code>closest_point(points[, p])</code>	Wrapper for <code>project()</code> to compute the point in the convex set closest to the given point.
<code>containment_constraints(x[, flatten_order])</code>	Get CVXPY constraints for containment of x (a cvxpy.Variable) in an ellipsoid.
<code>contains(Q)</code>	Check containment of a set or a collection of points in an ellipsoid.
<code>copy()</code>	Create a copy of the ellipsoid.
<code>deflate(cvx_set)</code>	Compute the minimum volume ellipsoid that covers the given set (also known as Lowner-John Ellipsoid).
<code>distance(points[, p])</code>	Wrapper for <code>project()</code> to compute distance of a point to a convex set.
<code>extreme(eta)</code>	Wrapper for <code>support()</code> to compute the extreme point.
<code>inflate(cvx_set)</code>	Compute the maximum volume ellipsoid that fits within the given set.
<code>inflate_ball(cvx_set)</code>	Compute the largest ball (Chebyshev ball) of a given set.
<code>interior_point()</code>	Compute an interior point to the Ellipsoid
<code>intersection_with_affine_set(Ae, be)</code>	Compute the intersection of an ellipsoid with an affine set.
<code>inverse_affine_map_under_invertible_matrix()</code>	Compute the inverse affine transformation of an ellipsoid based on a given scalar/matrix.
<code>maximum_volume_inscribing_ellipsoid()</code>	Compute the parameters of the maximum volume inscribing ellipsoid for a given ellipsoid.
<code>minimize(x, objective_to_minimize, cvxpy_args)</code>	Solve a convex program with CVXPY objective subject to containment constraints.
<code>minimum_volume_circumscribing_ball()</code>	Compute the parameters of a minimum volume circumscribing ball.
<code>minimum_volume_circumscribing_ellipsoid()</code>	Compute the parameters of the minimum volume circumscribing ellipsoid for a given ellipsoid.
<code>minimum_volume_circumscribing_rectangle()</code>	Compute the minimum volume circumscribing rectangle for a set.
<code>plot([method, ax, direction_vectors, ...])</code>	Plot a polytopic approximation of the set.
<code>plus(point)</code>	Add a point to an ellipsoid
<code>polytopic_inner_approximation([...])</code>	Compute a polytopic inner-approximation of a given set via ray shooting.
<code>polytopic_outer_approximation([...])</code>	Compute a polytopic outer-approximation of a given set via ray shooting.

continues on next page

Table 1 – continued from previous page

<code>project(x[, p])</code>	Project a point or a collection of points on to a set.
<code>projection(project_away_dims)</code>	Orthogonal projection of a set \mathcal{P} after removing some user-specified dimensions.
<code>quadratic_form_as_a_symmetric_matrix()</code>	Define a $(\text{self.dim} + 1)$ -dimensional symmetric matrix M where $\text{self} = \{x [x, 1] @ M @ [x, 1] \leq 0\}$.
<code>slice(dims, constants)</code>	Slice a set restricting certain dimensions to constants.
<code>slice_then_projection(dims, constants)</code>	Wrapper for <code>slice()</code> and <code>projection()</code> .
<code>support(eta)</code>	Evaluates the support function and support vector of a set.
<code>volume()</code>	Compute the volume of the ellipsoid.

Attributes

<code>G</code>	Affine transformation matrix G that satisfies $GG^T = Q$.
<code>Q</code>	Shape matrix of the ellipsoid Q .
<code>c</code>	Center of the ellipsoid c .
<code>cvxpy_args_lp</code>	CVXPY arguments in use when solving a linear program
<code>cvxpy_args_sdp</code>	CVXPY arguments in use when solving a semi-definite program
<code>cvxpy_args_socp</code>	CVXPY arguments in use when solving a second-order cone program
<code>dim</code>	Dimension of the ellipsoid dim .
<code>is_bounded</code>	Check if the ellipsoid is bounded.
<code>is_empty</code>	Check if the ellipsoid is empty.
<code>is_full_dimensional</code>	Check if the ellipsoid is full-dimensional.
<code>is_singleton</code>	Check if the ellipsoid is a singleton.
<code>latent_dim</code>	Latent dimension of the ellipsoid dim .
<code>type_of_set</code>	Return the type of set

```

__init__(*, c: Sequence[float] | ndarray, Q: Sequence[Sequence[float]] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, G: Sequence[Sequence[float]] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, r: float) → None
__init__(*, c: Sequence[float] | ndarray) → None
    Constructor for Ellipsoid
__new__(**kwargs)

```

PYCVXSET.ELLIPSOID (API DETAILS)

`pycvxset.Ellipsoid`

Ellipsoid class.

`class pycvxset.Ellipsoid.Ellipsoid`

Bases: `object`

Ellipsoid class.

We can define a bounded, non-empty ellipsoid \mathcal{P} using **one** of the following combinations:

1. (c, Q) for a full-dimensional ellipsoid in the **quadratic form** $\mathcal{P} = \{x \in \mathbb{R}^n \mid (x - c)^T Q^{-1}(x - c) \leq 1\}$ with a n-dimensional positive-definite matrix Q and a n-dimensional vector c . Here, pycvxset computes a n-dimensional lower-triangular, square matrix G that satisfies $GG^T = Q$.
2. (c, G) for a full-dimensional or a degenerate ellipsoid as an **affine transformation of a unit-ball** $\mathcal{P} = \{x \in \mathbb{R}^n \mid \exists u \in \mathbb{R}^N, x = c + Gu, \|u\|_2 \leq 1\}$ with a n x N matrix G . Here, pycvxset computes $Q = GG^T$.
3. (c, r) for a ball of radius $r \geq 0$ $\mathcal{P} = \{x \in \mathbb{R}^n \mid \|x - c\|_2 \leq r\}$.
4. (c) for a singleton ellipsoid $\mathcal{P} = \{c\}$.

Parameters

- **c** (`Sequence[float] / numpy.ndarray`) – Center of the ellipsoid c. Vector of length (self.dim,)
- **Q** (`Sequence[Sequence[float]] / numpy.ndarray, optional`) – Shape matrix of the ellipsoid Q. Q must be a positive definite matrix (self.dim times self.dim). (self.dim times self.dim).
- **G** (`Sequence[Sequence[float]] / numpy.ndarray, optional`) – Square root of the shape matrix of the ellipsoid G that satisfies $GG^T = Q$. Need not be a square matrix, but must have self.dim rows. If a singleton must be specified, G must have zero columns.
- **r** (`scalar, optional`) – Non-negative scalar that provides the radius of the self.dim-dimensional ball.

Raises

- **ValueError** – When more than one of Q, G, r was provided
- **ValueError** – When c or Q or G or r does not satisfy implicit properties

Notes

1. Empty ellipsoids are not permitted (c is a required keyword argument).
2. When provided G is such that $Q = GG^T$ is positive definite, we overwrite G with a lower-triangular, square, n-dimensional matrix for consistency. Here, G has strictly positive diagonal elements, and its determinant is the product of its diagonal elements (see volume computation).

3. We use the eigenvalues of Q to determine the radii of the maximum volume inscribing ball (Chebyshev radius R^-) and the minimum volume circumscribing ball $R^+ \geq R^-$.

- a. The ellipsoid represents a singleton when R^+ is negligible.
- b. The ellipsoid is full-dimensional when R^- is non-trivial.

`__init__(*, c: Sequence[float] | ndarray, Q: Sequence[Sequence[float]] | ndarray) → None`
`__init__(*, c: Sequence[float] | ndarray, G: Sequence[Sequence[float]] | ndarray) → None`
`__init__(*, c: Sequence[float] | ndarray, r: float) → None`
`__init__(*, c: Sequence[float] | ndarray) → None`

Constructor for Ellipsoid

`affine_hull() → tuple[ndarray | None, ndarray | None]`

Compute the left null space of `self.G` to identify the affine hull. Affine hull is the entire `self.dim`-dimensional space when `self` is full-dimensional.

Returns

(`Ae`, `be`) defining the affine set $\{x \mid Ae x = be\}$, or (`None`, `None`) when full-dimensional.

Return type

`tuple`

`affine_map(M: int | float | Sequence[Sequence[float]] | np.ndarray) → Ellipsoid`

Compute the affine transformation of the given ellipsoid based on a given scalar/matrix.

Parameters

`M(int | float | Sequence[Sequence[float]] | np.ndarray)` – Scalar or matrix (`m` times `self.dim`) for the affine map.

Raises

- **ValueError** – When `M` is not convertible into a 2D numpy array of float
- **ValueError** – When `M` has columns not equal to `self.dim`

Returns

Affine transformation of the given ellipsoid $\mathcal{R} = M\mathcal{P} = \{Mx \mid x \in \mathcal{P}\}$

Return type

`Ellipsoid`

`chebyshev_centering() → tuple[ndarray, float]`

Compute the Chebyshev center and radius of the ellipsoid.

Returns

(center, radius) of the maximum volume inscribed ball.

Return type

`tuple`

`closest_point(points: Sequence[Sequence[float]] | np.ndarray, p: int | str = 2) → np.ndarray`

Wrapper for `project()` to compute the point in the convex set closest to the given point.

Parameters

- **points** (`Sequence[Sequence[float]] | np.ndarray`) – Points to project. Matrix (`N` times `self.dim`), where each row is a point.
- **p (str | int)** – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2.

Returns

Projection of points to the set as a 2D numpy.ndarray. These arrays have as many rows as points.

Return type

`numpy.ndarray`

Notes

For more detailed description, see documentation for `project()` function.

containment_constraints(*x*: `cvxpy.Variable`, *flatten_order*: `Literal['F', 'C']` = 'F') → tuple[list[`cvxpy.Constraint`], `cvxpy.Variable` | `None`]

Get CVXPY constraints for containment of *x* (a `cvxpy.Variable`) in an ellipsoid.

Parameters

- **x** (`cvxpy.Variable`) – CVXPY variable to be optimized
- **flatten_order** (`Literal["F", "C"]`) – Order to use for flatten (choose between "F", "C"). Defaults to "F", which implements column-major flatten. In 2D, column-major flatten results in stacking rows horizontally to achieve a single horizontal row.

Returns

A tuple with two items:

1. `constraint_list` (list[`cvxpy.Constraint`]): CVXPY constraints for the containment of *x* in the ellipsoid.
2. `xi` (`cvxpy.Variable` | `None`): CVXPY variable representing the latent dimension variable with length `G.shape[1]`. It is `None` when the ellipsoid is a singleton.

Return type

`tuple`

contains(*Q*: `Sequence[float]` | `Sequence[Sequence[float]]` | `np.ndarray` | `Polytope` | `Ellipsoid`) → `bool` | `np.ndarray`

Check containment of a set or a collection of points in an ellipsoid.

Parameters

Q (`Sequence[float]` | `Sequence[Sequence[float]]` | `np.ndarray` | `Polytope` | `Ellipsoid`) – Polytope/Ellipsoid or a collection of points (each row is a point) to be tested for containment. When providing a collection of points, *Q* is a matrix (N times self.dim) with each row is a point.

Raises

- **ValueError** – Test point(s) are NOT of the same dimension
- **ValueError** – Test point(s) can not be converted into a 2D numpy array of floats
- **ValueError** – *Q* is a constrained zonotope
- **NotImplementedError** – Unable to perform ellipsoidal containment check using CVXPY

Returns

An element of the array is True if the point is in the ellipsoid, with as many elements as the number of rows in `test_points`.

Return type

`bool` or `numpy.ndarray[bool]`

Notes

- **Containment of a polytope**: This function requires the polytope *Q* to be in V-Rep. If *Q* is in H-Rep, a vertex enumeration is performed. This function then checks if all vertices of *Q* are in the given ellipsoid, which occurs if and only if the polytope is contained within the ellipsoid [BV04].
- **Containment of an ellipsoid**: This function solves a semi-definite program (S-procedure) [BV04].
- **Containment of points**: For each point *v*, the function checks if there is a $u \in \mathbb{R}^{P.\dim}$ such that $\|u\|_2 \leq 1$ and $Gu + c = v$ [BV04]. This can be efficiently done via `numpy.linalg.lstsq`.

copy() → *Ellipsoid*

Create a copy of the ellipsoid. Copy (c , G) to preserve degenerate ellipsoids.

classmethod deflate(*cvx_set*: Ellipsoid | Polytope) → *Ellipsoid*

Compute the minimum volume ellipsoid that covers the given set (also known as Lowner-John Ellipsoid).

Parameters

cvx_set (Ellipsoid / Polytope) – Set to be circumscribed.

Returns

Minimum volume circumscribing ellipsoid

Return type

Ellipsoid

Notes

This function is a wrapper for `minimum_volume_circumscribing_ellipsoid()` of the set `set_to_be_centered`. Please check that function for more details including raising exceptions.
[EllipsoidalTbx-Min_verticesolEll]

distance(*points*: Sequence[Sequence[float]] | np.ndarray, *p*: int | str = 2) → np.ndarray

Wrapper for `project()` to compute distance of a point to a convex set.

Parameters

- **points** (Sequence[Sequence[float]] / np.ndarray) – Points to project. Matrix (N times self.dim), where each row is a point.
- **p** (int / str) – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2.

Returns

Distance of points to the set as a 1D numpy.ndarray. These arrays have as many rows as points.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for `project()` function.

extreme(*eta*: Sequence[Sequence[float]] | np.ndarray) → np.ndarray

Wrapper for `support()` to compute the extreme point.

Parameters

eta (Sequence[Sequence[float]] / np.ndarray) – Support directions. Matrix (N times self.dim), where each row is a support direction.

Returns

Support vector evaluation(s) as a 2D numpy.ndarray. The array has as many rows as eta.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for `support()` function.

classmethod inflate(*cvx_set*: ConstrainedZonotope | Ellipsoid | Polytope) → *Ellipsoid*

Compute the maximum volume ellipsoid that fits within the given set.

Parameters

cvx_set (ConstrainedZonotope / Ellipsoid / Polytope) – Set to be inscribed.

Returns

Maximum volume inscribing ellipsoid

Return type

Ellipsoid

Notes

This function is a wrapper for `maximum_volume_inscribing_ellipsoid()` of the set `set_to_expand_within`. Please check that function for more details including raising exceptions. [[EllipsoidalTbx-MinVolEll](#)]

classmethod `inflate_ball(cvx_set: ConstrainedZonotope | Ellipsoid | Polytope) → Ellipsoid`

Compute the largest ball (Chebyshev ball) of a given set.

Parameters

`cvx_set` (`ConstrainedZonotope` / `Ellipsoid` / `Polytope`) – Set to compute Chebyshev ball for.

Returns

Maximum volume inscribing ellipsoid

Return type

Ellipsoid

Notes

This function is a wrapper for `chebyshev_center()` of attr:`set_to_be_centered`. Please check that function for more details including raising exceptions.

interior_point() → ndarray

Compute an interior point to the Ellipsoid

Returns

center of the ellipsoid, which is an interior point.

Return type

`np.ndarray`

intersection_with_affine_set(Ae: Sequence[Sequence[float]] | np.ndarray, be: Sequence[float] | np.ndarray) → Ellipsoid

Compute the intersection of an ellipsoid with an affine set.

Parameters

- `Ae` (`Sequence[Sequence[float]]` / `np.ndarray`) – Equality coefficient matrix (N times self.dim) that define the affine set $\{x | A_e x = b_e\}$.
- `be` (`Sequence[float]` / `np.ndarray`) – Equality constant vector (N,) that define the affine set $\{x | A_e x = b_e\}$.

Raises

`ValueError` – When the number of columns in Ae is different from self.dim

Returns

The intersection of an ellipsoid with the affine set.

Return type

Ellipsoid

Notes

This function implements imposes the constraints $\{A_e x = b_e\}$ as constraints in the latent dimension of the ellipsoid — $A_e(G\xi + c) = b_e$ for every feasible ξ .

inverse_affine_map_under_invertible_matrix(*M*: int | float | Sequence[Sequence[float]] | np.ndarray) → Ellipsoid

Compute the inverse affine transformation of an ellipsoid based on a given scalar/matrix.

Parameters

M (int | float | Sequence[Sequence[float]] | np.ndarray) – Scalar or invertible square matrix for the affine map

Raises

- **TypeError** – When *M* is not convertible into a 2D square numpy matrix
- **TypeError** – When *M* is not invertible

Returns

Inverse affine transformation of the given ellipsoid $\mathcal{R} = \mathcal{P}M = \{x | Mx \in \mathcal{P}\}$

Return type

Ellipsoid

Notes

1. Since *M* is invertible, \mathcal{R} is also a bounded ellipsoid.

maximum_volume_inscribing_ellipsoid() → tuple[ndarray, ndarray, ndarray]

Compute the parameters of the maximum volume inscribing ellipsoid for a given ellipsoid.

Returns

(center, Q, G) describing the ellipsoid.

Return type

tuple

minimize(*x*: cvxpy.Variable, *objective_to_minimize*: cvxpy.Expression, *cvxpy_args*: dict[str, Any], *task_str*: str = '') → tuple[np.ndarray, float, str]

Solve a convex program with CVXPY objective subject to containment constraints.

Parameters

- **x** (cvxpy.Variable) – CVXPY variable to be optimized
- **objective_to_minimize** (cvxpy.Expression) – CVXPY expression to be minimized
- **cvxpy_args** (dict) – CVXPY arguments to be passed to the solver
- **task_str** (str, optional) – Task string to be used in error messages. Defaults to ''.

Raises

NotImplementedError – Unable to solve problem using CVXPY

Returns

A tuple with three items:

1. *x.value* (numpy.ndarray): Optimal value of *x*. np.nan * np.ones((self.dim,)) if the problem is not solved.
2. *problem.value* (float): Optimal value of the convex program. np.inf if the problem is infeasible, -np.inf if problem is unbounded, and finite otherwise.
3. *problem_status* (str): Status of the problem

Return type

tuple

Notes

This function uses `containment_constraints()` to obtain the list of CVXPY expressions that form the containment constraints on x .

⚠ Warning

Please pay attention to the `NotImplementedError` generated by this function. It may be possible to get CVXPY to solve the same problem by switching the solver. For example, consider the following code block.

```
from pycvxset import Polytope
P = Polytope(A=[[1, 1], [-1, -1]], b=[1, 1])
P.cvxpyp_args_lp = {'solver': 'CLARABEL'}      # Default solver used in
                                                # pycvxset
try:
    print('Is polytope bounded?', P.is_bounded)
except NotImplementedError as err:
    print(str(err))
P.cvxpyp_args_lp = {'solver': 'OSQP'}
print('Is polytope bounded?', P.is_bounded)
```

This code block produces the following output:

```
Unable to solve the task (support function evaluation of the set at eta =
[-0. -1.]). CVXPY returned error:
Solver 'CLARABEL' failed. Try another solver, or solve with verbose=True
for more information.
```

```
Is polytope bounded? False
```

`minimum_volume_circumscribing_ball()` → tuple[ndarray, float]

Compute the parameters of a minimum volume circumscribing ball.

Returns

(center, radius) for the minimum-volume circumscribing ball.

Return type

tuple

`minimum_volume_circumscribing_ellipsoid()` → tuple[ndarray, ndarray, ndarray]

Compute the parameters of the minimum volume circumscribing ellipsoid for a given ellipsoid.

Returns

(center, Q, G) describing the ellipsoid.

Return type

tuple

`minimum_volume_circumscribing_rectangle()` → tuple[np.ndarray, np.ndarray]

Compute the minimum volume circumscribing rectangle for a set.

Raises

`ValueError` – Solver error or set is empty!

Returns

A tuple of two elements

- lb (numpy.ndarray): Lower bound l on the set, $\mathcal{P} \subseteq \{l\} \oplus \mathbb{R}_{\geq 0}$.
- ub (numpy.ndarray): Upper bound u on the set, $\mathcal{P} \subseteq \{u\} \oplus (-\mathbb{R}_{\geq 0})$.

Return type

tuple

Notes

This function computes the lower/upper bound by an element-wise support computation ($2n$ linear programs), where n is attr:`self.dim`. To reuse the `support()` function for the lower bound computation, we solve the optimization for each $i \in \{1, 2, \dots, n\}$,

$$\inf_{x \in \mathcal{P}} e_i^\top x = -\sup_{x \in \mathcal{P}} -e_i^\top x = -\rho_{\mathcal{P}}(-e_i),$$

where $e_i \in \mathbb{R}^n$ denotes the standard coordinate vector, and $\rho_{\mathcal{P}}$ is the support function of \mathcal{P} .

```
plot(method: str = 'inner', ax: Axes | Axes3D | None | None = None, direction_vectors:
      Sequence[Sequence[float]] | np.ndarray | None = None, n_vertices: int | None = None,
      n_halfspaces: int | None = None, patch_args: dict[str, Any] | None = None, vertex_args: dict[str,
      Any] | None = None, center_args: dict[str, Any] | None = None, autoscale_enable: bool = True,
      decimal_precision: int = 3, enable_warning: bool = True) → tuple[Any, ...]
```

Plot a polytopic approximation of the set.

Parameters

- **method** (str, optional) – Type of polytopic approximation to use. Can be [“inner” or “outer”]. Defaults to “inner”.
- **ax** (Axes / Axes3D / None, optional) – Axis on which the patch is to be plotted
- **direction_vectors** (Sequence[Sequence[float]] / np.ndarray, optional) – Directions to use when performing ray shooting. Matrix (N times `self.dim`) for some $N \geq 1$. Defaults to `None`, in which case we use `pycvxset.common.spread_points_on_a_unit_sphere()` to compute the direction vectors.
- **n_vertices** (int, optional) – Number of vertices to use when computing the polytopic inner-approximation. Ignored if method is “outer” or when `direction_vectors` are provided. More than `n_vertices` may be used in some cases (see notes). Defaults to `None`.
- **n_halfspaces** (int, optional) – Number of halfspaces to use when computing the polytopic outer-approximation. Ignored if method is “outer” or when `direction_vectors` are provided. More than `n_halfspaces` may be used in some cases (see notes). Defaults to `None`.
- **patch_args** (dict, optional) – Arguments to pass for plotting faces and edges. See `pycvxset.Polytope.Polytope.plot()` for more details. Defaults to `None`.
- **vertex_args** (dict, optional) – Arguments to pass for plotting vertices. See `pycvxset.Polytope.Polytope.plot()` for more details. Defaults to `None`.
- **center_args** (dict, optional) – For ellipsoidal set, arguments to pass to scatter plot for the center. If a label is desired, pass it in `center_args`.
- **autoscale_enable** (bool, optional) – When set to `True`, matplotlib adjusts axes to view full polytope. See `pycvxset.Polytope.Polytope.plot()` for more details. Defaults to `True`.
- **decimal_precision** (int, optional) – When plotting a 3D polytope that is in V-Rep and not in H-Rep, we round vertex to the specified precision to avoid numerical issues. Defaults to `PLOTTING_DECIMAL_PRECISION_CDD` specified in `pycvxset.common.constants`.
- **enable_warning** (bool, optional) – Enables the `UserWarning`. May be turned off if expected. Defaults to `True`.

Returns

See `pycvxset.Polytope.Polytope.plot()` for details.

Return type

tuple

Notes

This function is a wrapper for `polytopic_inner_approximation()` and `polytopic_outer_approximation()` for more details in polytope construction.

`plus(point: Sequence[float] | np.ndarray) → Ellipsoid`

Add a point to an ellipsoid

Parameters

`point (Sequence[float] / np.ndarray)` – Vector (self.dim,) that describes the point to be added.

Raises

- **ValueError** – point is a set (ConstrainedZonotope or Ellipsoid or Polytope)
- **TypeError** – point can not be converted into a numpy array of float
- **ValueError** – point can not be converted into a 1D numpy array of float
- **ValueError** – Mismatch in dimension

Returns

Sum of the ellipsoid and the point.

Return type

Ellipsoid

`polytopic_inner_approximation(direction_vectors: Sequence[Sequence[float]] | np.ndarray | None = None, n_vertices: int | None = None, verbose: bool = False, enable_warning: bool = True) → Polytope`

Compute a polytopic inner-approximation of a given set via ray shooting.

Parameters

- **cvx_set** (`ConstrainedZonotope / Ellipsoid / Polytope`) – Set to be approximated,
- **direction_vectors** (`Sequence[Sequence[float]] / np.ndarray, optional`) – Directions to use when performing ray shooting. Matrix (N times self.dim) for some $N \geq 1$. Defaults to None.
- **n_vertices** (`int, optional`) – Number of vertices to be used for the inner-approximation. n_vertices is overridden whenever direction_vectors are provided. Defaults to None.
- **verbose** (`bool, optional`) – If true, `pycvxset.common.spread_points_on_a_unit_sphere()` is passed with verbose. Defaults to False.
- **enable_warning** (`bool, optional`) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Returns

Polytopic inner-approximation in V-Rep of a given set with n_vertices no smaller than user-provided n_vertices.

Return type

Polytope

Notes

We compute the polytope using `extreme()` evaluated along the direction vectors computed by `pycvxset.common.spread_points_on_a_unit_sphere()`. When `direction_vectors` is `None` and `n_vertices` is `None`, we select `n_vertices = 2self.dim + 2self.dimSPOAUS_DIRECTIONS_PER_QUADRANT` (as defined in `pycvxset.common.constants()`). [BV04] The function also uses `pycvxset.common.make_aspect_ratio_equal()` to account for possibly non-symmetric sets.

```
polytopic_outer_approximation(direction_vectors: Sequence[Sequence[float]] | np.ndarray | None  
= None, n_halfspaces: int | None = None, verbose: bool = False,  
enable_warning: bool = True) → Polytope
```

Compute a polytopic outer-approximation of a given set via ray shooting.

Parameters

- **cvx_set** (ConstrainedZonotope / Ellipsoid / Polytope) – Set to be approximated,
- **direction_vectors** (Sequence[Sequence[float]] | np.ndarray, optional) – Directions to use when performing ray shooting. Matrix (N times `self.dim`) for some $N \geq 1$. Defaults to `None`.
- **n_halfspaces** (int, optional) – Number of halfspaces to be used for the inner-approximation. `n_vertices` is overridden whenever `direction_vectors` are provided. Defaults to `None`.
- **verbose** (bool, optional) – If `true`, `pycvxset.common.spread_points_on_a_unit_sphere()` is passed with `verbose`. Defaults to `False`.
- **enable_warning** (bool, optional) – Enables the `UserWarning`. May be turned off if expected. Defaults to `True`.

Returns

Polytopic outer-approximation in H-Rep of a given set with `n_halfspaces` no smaller than user-provided `n_vertices`.

Return type

`Polytope`

Notes

We compute the polytope using `support()` evaluated along the direction vectors computed by `pycvxset.common.spread_points_on_a_unit_sphere()`. When `direction_vectors` is `None` and `n_halfspaces` is `None`, we select `n_halfspaces = 2self.dim + 2self.dimSPOAUS_DIRECTIONS_PER_QUADRANT` (as defined in `pycvxset.common.constants()`). [BV04]

```
project(x: Sequence[float] | Sequence[Sequence[float]] | ndarray, p: int | str = 2) → tuple[ndarray,  
ndarray]
```

Project a point or a collection of points on to a set.

Given a set \mathcal{P} and a test point $y \in \mathbb{R}^{\mathcal{P}.dim}$, this function solves a convex program,

$$\begin{aligned} & \text{minimize} && \|x - y\|_p \\ & \text{subject to} && x \in \mathcal{P} \end{aligned}$$

Parameters

- **points** (Sequence[Sequence[float]] | np.ndarray) – Points to project (N times `self.dim`) with each row as a point.

- **p** (*str* / *int*) – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2, which is the Euclidean norm.

Raises

- **ValueError** – Set is empty
- **ValueError** – Dimension mismatch — no. of columns in points is different from self.dim.
- **ValueError** – Points is not convertible into a 2D array
- **NotImplementedError** – Unable to solve problem using CVXPY

Returns

A tuple with two items:

1. projected_point (numpy.ndarray): Projection point(s) as a 2D numpy.ndarray. Matrix (N times self.dim), where each row is a projection of the point in points to the set \mathcal{P} .
2. distance (numpy.ndarray): Distance(s) as a 1D numpy.ndarray. Vector (N,), where each row is a projection of the point in points to the set \mathcal{P} .

Return type

tuple

Notes

For a point $y \in \mathbb{R}^{\mathcal{P}.dim}$ and an ellipsoid $\mathcal{P} = \{Gu + c \mid \|u\|_2 \leq 1\}$ with $GG^T = Q$, this function solves a convex program with decision variables $x, u \in \mathbb{R}^{\mathcal{P}.dim}$,

$$\begin{aligned} & \text{minimize} && \|x - y\|_p \\ & \text{subject to} && x = Gu + c \\ & && \|u\|_2 \leq 1 \end{aligned}$$

projection(*project_away_dims*: int | Sequence[int]) → Ellipsoid

Orthogonal projection of a set \mathcal{P} after removing some user-specified dimensions.

$$\mathcal{R} = \{r \in \mathbb{R}^m \mid \exists v \in \mathbb{R}^{n-m}, \text{Lift}(r, v) \in \mathcal{P}\}$$

Here, $m = \mathcal{P}.dim - \text{length}(\text{project_away_dim})$, and Lift(r, v) lifts (“undo”s the projection) using the appropriate components of v . This function uses [affine_map\(\)](#) to implement the projection by designing an appropriate affine map $M \in \{0, 1\}^{m \times \mathcal{P}.dim}$ with each row of M corresponding to some standard axis vector $e_i \in \mathbb{R}^m$.

Parameters

project_away_dims (Sequence[int] / np.ndarray) – Dimensions to projected away in integer interval [0, 1, ..., n - 1].

Raises

ValueError – When project_away_dims are not in the integer interval | All dimensions are projected away

Returns

Set obtained via projection.

Return type

object

Returns

m-dimensional set obtained via projection.

Return type

Ellipsoid

quadratic_form_as_a_symmetric_matrix() → ndarray

Define a (self.dim + 1)-dimensional symmetric matrix M where $\text{self} = \{x | [x, 1] @ M @ [x, 1] \leq 0\}$. Here, when Q is not positive definite, we use pseudo-inverse of Q.

Returns

(self.dim + 1) x (self.dim + 1) symmetric matrix defining the quadratic form.

Return type

numpy.ndarray

slice(dims: int | Sequence[int] | ndarray, constants: float | Sequence[float] | ndarray) → *Ellipsoid*

Slice a set restricting certain dimensions to constants.

This function uses [*intersection_with_affine_set\(\)*](#) to implement the slicing by designing an appropriate affine set from dims and constants.

Parameters

- **dims** (*Sequence[int]* / *np.ndarray*) – List of dims to restrict to a constant in the integer interval $[0, 1, \dots, n - 1]$.
- **constants** (*float* / *Sequence[float]* / *np.ndarray*) – List of constants

Raises

- **ValueError** – dims has entries beyond n
- **ValueError** – dims and constants are not 1D arrays of same size

Returns

Sliced set.

Return type

object

Returns

Ellipsoid that has been sliced at the specified dimensions.

Return type

Ellipsoid

Notes

•

slice_then_projection(dims: int | Sequence[int], constants: int | Sequence[int]) → *Ellipsoid*

Wrapper for [*slice\(\)*](#) and [*projection\(\)*](#).

The function first restricts a set at certain dimensions to constants, and then projects away those dimensions. Useful for visual inspection of higher dimensional sets.

Parameters

- **dims** (*Sequence[int]* / *np.ndarray*) – List of dims to restrict to a constant in the integer interval $[0, 1, \dots, dim - 1]$, and then project away.
- **constants** (*float* / *Sequence[float]* / *np.ndarray*) – List of constants

Raises

- **ValueError** – dims has entries beyond n
- **ValueError** – dims and constants are not 1D arrays of same size
- **ValueError** – When dims are not in the integer interval | All dimensions are projected away

Returns

Sliced then projected set.

Return type

object

Returns

m-dimensional set obtained via projection after slicing.

Return type*Ellipsoid***support**(*eta*: ndarray | Sequence[float] | Sequence[Sequence[float]]) → tuple[ndarray, ndarray]

Evaluates the support function and support vector of a set.

The support function of a set \mathcal{P} is defined as $\rho_{\mathcal{P}}(\eta) = \max_{x \in \mathcal{P}} \eta^\top x$. The support vector of a set \mathcal{P} is defined as $\nu_{\mathcal{P}}(\eta) = \arg \max_{x \in \mathcal{P}} \eta^\top x$.**Parameters****eta** (Sequence[float] / Sequence[Sequence[float]] / np.ndarray) – Support directions. Matrix (N times self.dim), where each row is a support direction.**Raises**

- **ValueError** – Set is empty
- **ValueError** – Mismatch in eta dimension
- **ValueError** – eta is not convertible into a 2D array
- **NotImplementedError** – Unable to solve problem using CVXPY

Returns**A tuple with two items:**

1. support_function_evaluations (numpy.ndarray): Support function evaluation(s) as a 2D numpy.ndarray. Vector (N,) with as many rows as eta.
2. support_vectors (numpy.ndarray): Support vectors as a 2D numpy.ndarray. Matrix N x self.dim with as many rows as eta.

Notes

Using duality, the support function and vector of an ellipsoid has a closed-form expressions. For a support direction $\eta \in \mathbb{R}^{\mathcal{P}.dim}$ and an ellipsoid $\mathcal{P} = \{Gu + c \mid \|u\|_2 \leq 1\}$ with $GG^T = Q$,

$$\begin{aligned}\rho_{\mathcal{P}}(\eta) &= \eta^\top c + \sqrt{\eta^\top Q \eta} = \eta^\top c + \|G^T \eta\|_2 \\ \nu_{\mathcal{P}}(\eta) &= c + \frac{GG^\top \eta}{\|G^T \eta\|_2} = c + \frac{Q\eta}{\|G^T \eta\|_2}\end{aligned}$$

For degenerate (not full-dimensional) ellipsoids and η not in the low-dimensional affine hull containing the ellipsoid,

$$\begin{aligned}\rho_{\mathcal{P}}(\eta) &= \eta^\top c \\ \nu_{\mathcal{P}}(\eta) &= c\end{aligned}$$

Return type

tuple

volume() → float

Compute the volume of the ellipsoid.

Returns

Volume of the ellipsoid.

Return type

float

Notes

Volume of the ellipsoid is zero if it is not full-dimensional. For full-dimensional ellipsoid, we used the following observations:

1. from [BV04] , the volume of an ellipsoid is proportional to $\det(G)$.
2. Square-root of the determinant of the shape matrix coincides with the determinant of G
3. Since G is lower-triangular, its determinant is the product of its diagonal elements.

property G: ndarray

Affine transformation matrix G that satisfies $GG^T = Q$.

Returns

Generator matrix.

Return type

numpy.ndarray

property Q: ndarray

Shape matrix of the ellipsoid Q .

Returns

Shape matrix.

Return type

numpy.ndarray

property c: ndarray

Center of the ellipsoid c .

Returns

Center vector.

Return type

numpy.ndarray

property cvxpy_args_lp: dict[str, Any]

CVXPY arguments in use when solving a linear program

Returns

CVXPY arguments in use when solving a linear program. Defaults to dictionary in `pycvxset.common.DEFAULT_CVXPY_ARGS_LP`.

Return type

dict

property cvxpy_args_sdp: dict[str, Any]

CVXPY arguments in use when solving a semi-definite program

Returns

CVXPY arguments in use when solving a semi-definite program. Defaults to dictionary in `pycvxset.common.DEFAULT_CVXPY_ARGS_SDP`.

Return type

dict

property cvxpy_args_socp: dict[str, Any]

CVXPY arguments in use when solving a second-order cone program

Returns

CVXPY arguments in use when solving a second-order cone program. Defaults to dictionary in `pycvxset.common.DEFAULT_CVXPY_ARGS_SOCP`.

Return type

dict

property dim: int

Dimension of the ellipsoid *dim*.

Returns

Dimension of the ellipsoid.

Return type

int

property is_bounded: bool

Check if the ellipsoid is bounded. Always True by construction.

property is_empty: bool

Check if the ellipsoid is empty. Always False by construction.

Returns

Always False for ellipsoids since we require non-empty ellipsoids.

Return type

bool

property is_full_dimensional: bool

Check if the ellipsoid is full-dimensional.

Returns

True if full-dimensional.

Return type

bool

property is_singleton: bool

Check if the ellipsoid is a singleton.

Returns

True if the ellipsoid is a singleton.

Return type

bool

property latent_dim: int

Latent dimension of the ellipsoid *dim*.

Returns

Latent dimension of the ellipsoid.

Return type

int

property type_of_set: str

Return the type of set

Returns

Type of the set

Return type

str

CHAPTER
THIRTEEN

PYCVXSET.CONSTRAINEDZONOTOPE

```
class pycvxset.ConstrainedZonotope
```

Bases: object

Constrained zonotope class

Constrained zonotope defines a polytope in the working dimension \mathbb{R}^n as an affine transformation of a polytope defined in latent space $B_\infty(A_e, b_e) \subset \mathbb{R}^{N_C}$. Here, $B_\infty(A_e, b_e)$ is defined as the intersection of a unit ℓ_∞ -norm ball and a collection of M_C linear constraints $\{\xi \in \mathbb{R}^{N_C} | A_e \xi = b_e\}$.

Formally, a **constrained zonotope** is defined as follows,

$$\mathcal{C} = \{G\xi + c \mid \xi \in B_\infty(A_e, b_e)\} \subset \mathbb{R}^n,$$

where

$$B_\infty(A_e, b_e) = \{\xi \mid \|\xi\|_\infty \leq 1, A_e \xi = b_e\} \subset \mathbb{R}^{N_C},$$

with $G \in \mathbb{R}^{n \times N_C}$, $c \in \mathbb{R}^n$, $A_e \in \mathbb{R}^{M_C \times N_C}$, and $b \in \mathbb{R}^{M_C}$.

A constrained zonotope provide an alternative and equivalent representation of any convex and compact polytope. Furthermore, a constrained zonotope admits closed-form expressions for several set manipulations that can often be accomplished without invoking any optimization solvers. See [SDGR16] [RK22] [VWD24] for more details.

A **zonotope** is a special class of constrained zonotopes, and are defined as

$$\mathcal{Z} = \{G\xi + c \mid \|\xi\|_\infty \leq 1\} \subset \mathbb{R}^n.$$

In other words, a zonotope is a constrained zonotope with no equality constraints in the latent dimension space. In `ConstrainedZonotope`, we model zonotopes by having (Ae,be) be empty (n_equalities is zero).

Constrained zonotope object construction admits **one** of the following combinations (as keyword arguments):

1. dim for an **empty** constrained zonotope of dimension dim,
2. (G, c, Ae, be) for a **constrained zonotope**,
3. (G, c) for a **zonotope**,
4. (lb, ub) for a **zonotope** equivalent to an **axis-aligned cuboid** with appropriate bounds $\{x \mid lb \leq x \leq ub\}$, and
5. (c, h) for a **zonotope** equivalent to an **axis-aligned cuboid** centered at c with specified scalar/vector half-sides h, $\{x \mid \forall i \in \{1, 2, \dots, n\}, |x_i - c_i| \leq h_i\}$.
6. (c=p, G=None) for a **zonotope** equivalent to a **single point** p,
7. P for a **constrained zonotope** equivalent to the `pycvxset.Polytope.Polytope` object P,

Parameters

- **dim (int, optional)** – Dimension of the empty constrained zonotope. If NOTHING is provided, dim=0 is assumed.

- **c** (*Sequence[float] | numpy.ndarray, optional*) – Affine transformation translation vector. Must be 1D array, and the constrained zonotope dimension is determined by number of elements in c. When c is provided, either (G) or (G, Ae, be) or (h) must be provided additionally. When h is provided, c is the centroid of the resulting zonotope.
- **G** (*Sequence[Sequence[float]] | numpy.ndarray*) – Affine transformation matrix. The vectors are stacked vertically with matching number of rows as c. When G is provided, (c, Ae, be) OR (c) must also be provided. To define a constrained zonotope with a single point, set c to the point AND G to None (do not set (Ae, be) or set them to (None, None)).
- **Ae** (*Sequence[Sequence[float]] | numpy.ndarray*) – Equality coefficient vectors. The vectors are stacked vertically with matching number of columns as G. When Ae is provided, (G, c, be) must also be provided.
- **be** (*Sequence[float] | numpy.ndarray*) – Equality coefficient constants. The constants are expected to be in a 1D numpy array. When be is provided, (G, c, Ae) must also be provided.
- **lb** (*Sequence[float] | numpy.ndarray, optional*) – Lower bounds of the axis-aligned cuboid. Must be 1D array, and the constrained zonotope dimension is determined by number of elements in lb. When lb is provided, ub must also be provided.
- **ub** (*Sequence[float] | numpy.ndarray, optional*) – Upper bounds of the axis-aligned cuboid. Must be 1D array of length as same as lb. When ub is provided, lb must also be provided.
- **h** (*float | Sequence[float] | numpy.ndarray, optional*) – Half-side length of the axis-aligned cuboid. Can be a scalar or a vector of length as same as c. When h is provided, c must also be provided.
- **polytope** (*Polytope, optional*) – Polytope to use to construct constrained zonotope.

Raises

- **ValueError** – (G, c) is not compatible.
- **ValueError** – (G, c, Ae, be) is not compatible.
- **ValueError** – (lb, ub) is not valid
- **ValueError** – (c, h) is not valid
- **ValueError** – Provided polytope is not bounded.
- **UserWarning** – When a row with all zeros in Ae and be.

```
__init__() → None
__init__(*, dim: int) → None
__init__(*, G: Sequence[Sequence[float]] | ndarray | None, c: Sequence[float] | ndarray) → None
__init__(*, G: Sequence[Sequence[float]] | ndarray | None, c: Sequence[float] | ndarray, Ae: Sequence[Sequence[float]] | ndarray, be: Sequence[float] | ndarray) → None
__init__(*, lb: Sequence[float] | ndarray, ub: Sequence[float] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, h: float | Sequence[float] | ndarray) → None
__init__(*, polytope: Polytope) → None
```

Constructor for ConstrainedZonotope class

Methods

<code>__init__()</code>	Constructor for ConstrainedZonotope class
<code>affine_map(M)</code>	Multiply a matrix or a scalar with a constrained zonotope
<code>approximate_pontryagin_difference(norm_ty...)</code>	Approximate Pontryagin difference between a constrained zonotope and an affine transformation of a unit-norm ball.
<code>cartesian_product(sequence_Q)</code>	Generate the Cartesian product of a set \mathcal{Q} (or a list of $\mathcal{mathcal{Q}}$) with \mathcal{P} .
<code>chebyshev_centering([enable_warning])</code>	Computes a ball with the largest radius that fits within the constrained zonotope.
<code>closest_point(points[, p])</code>	Wrapper for <code>project()</code> to compute the point in the convex set closest to the given point.
<code>containment_constraints(x[, flatten_order])</code>	Get CVXPY constraints for containment of x (a <code>cvxpy.Variable</code>) in a constrained zonotope.
<code>contains(Q[, verbose, time_limit])</code>	Check containment of a set \mathcal{Q} (could be a polytope or a constrained zonotope), or a collection of points $Q \in \mathbb{R}^{n_Q \times \mathcal{P}.dim}$ in the given constrained zonotope.
<code>copy()</code>	Get a copy of the constrained zonotope
<code>distance(points[, p])</code>	Wrapper for <code>project()</code> to compute distance of a point to a convex set.
<code>extreme(eta)</code>	Wrapper for <code>support()</code> to compute the extreme point.
<code>interior_point([point_type, enable_warning])</code>	Compute an interior point of the constrained zonotope.
<code>intersection(Q)</code>	Compute the intersection of constrained zonotope with another constrained zonotope or polytope.
<code>intersection_under_inverse_affine_map(Y, R)</code>	Compute the intersection of constrained zonotope with another constrained zonotope under an inverse affine map
<code>intersection_with_affine_set(Ae, be)</code>	Compute the intersection of a constrained zonotope with an affine set.
<code>intersection_with_halfspaces(A, b)</code>	Compute the intersection of a constrained zonotope with a collection of halfspaces (polyhedron).
<code>inverse_affine_map_under_invertible_matrix(M)</code>	Compute the inverse affine map of a constrained zonotope for a given matrix M.
<code>maximum_volume_inscribing_ellipsoid([...])</code>	Compute the maximum volume ellipsoid that fits within the given constrained zonotope.
<code>minimize(x, objective_to_minimize, cvxpy_args)</code>	Solve a convex program with CVXPY objective subject to containment constraints.
<code>minimum_volume_circumscribing_rectangle(Q)</code>	Compute the minimum volume circumscribing rectangle for a set.
<code>minus(Q[, enable_warning])</code>	Implement - operation: Pontryagin difference with a constrained zonotope minuend
<code>plot([method, ax, direction_vectors, ...])</code>	Plot a polytopic approximation of the set.
<code>plus(Q)</code>	Add a point or a set Q to a constrained zonotope (Minkowski sum).
<code>polytopic_inner_approximation([...])</code>	Compute a polytopic inner-approximation of a given set via ray shooting.
<code>polytopic_outer_approximation([...])</code>	Compute a polytopic outer-approximation of a given set via ray shooting.
<code>project(x[, p])</code>	Project a point or a collection of points on to a set.
<code>projection(project_away_dims)</code>	Orthogonal projection of a set \mathcal{P} after removing some user-specified dimensions.
<code>remove_redundancies()</code>	Remove any redundancies in CZ using pycddlib and other geometric properties.

continues on next page

Table 1 – continued from previous page

<code>slice(dims, constants)</code>	Slice a set restricting certain dimensions to constants.
<code>slice_then_projection(dims, constants)</code>	Wrapper for <code>slice()</code> and <code>projection()</code> .
<code>support(eta)</code>	Evaluates the support function and support vector of a set.

Attributes

<code>Ae</code>	Equality coefficient vectors Ae for the constrained zonotope.
<code>G</code>	Affine transformation matrix G for the constrained zonotope.
<code>He</code>	Equality constraints $He=[Ae, be]$ for the constrained zonotope.
<code>be</code>	Equality constants be for the constrained zonotope.
<code>c</code>	Affine transformation vector c for the constrained zonotope.
<code>cvxpy_args_lp</code>	CVXPY arguments in use when solving a linear program
<code>cvxpy_args_socp</code>	CVXPY arguments in use when solving a second-order cone program
<code>dim</code>	Dimension of the constrained zonotope.
<code>is_bounded</code>	Check if the constrained zonotope is bounded (which is always True)
<code>is_empty</code>	Check if the constrained zonotope is empty
<code>is_full_dimensional</code>	Check if the affine dimension of the constrained zonotope is the same as the constrained zonotope dimension
<code>is_singleton</code>	Check if the constrained zonotope is a singleton
<code>is_zonotope</code>	Check if the constrained zonotope is a zonotope
<code>latent_dim</code>	Latent dimension of the constrained zonotope.
<code>n_equalities</code>	Number of equality constraints used when defining the constrained zonotope.
<code>type_of_set</code>	Return the type of set

`__init__()` → None
`__init__(*, dim: int)` → None
`__init__(*, G: Sequence[Sequence[float]] | ndarray | None, c: Sequence[float] | ndarray)` → None
`__init__(*, G: Sequence[Sequence[float]] | ndarray | None, c: Sequence[float] | ndarray, Ae: Sequence[Sequence[float]] | ndarray, be: Sequence[float] | ndarray)` → None
`__init__(*, lb: Sequence[float] | ndarray, ub: Sequence[float] | ndarray)` → None
`__init__(*, c: Sequence[float] | ndarray, h: float | Sequence[float] | ndarray)` → None
`__init__(*, polytope: Polytope)` → None
 Constructor for ConstrainedZonotope class
`__new__(**kwargs)`

CHAPTER
FOURTEEN

PYCVXSET.CONSTRAINEDZONOTOPE (API DETAILS)

<code>pycvxset.ConstrainedZonotope</code>	Constrained zonotope class
---	----------------------------

`class pycvxset.ConstrainedZonotope.ConstrainedZonotope`

Bases: `object`

Constrained zonotope class

Constrained zonotope defines a polytope in the working dimension \mathbb{R}^n as an affine transformation of a polytope defined in latent space $B_\infty(A_e, b_e) \subset \mathbb{R}^{N_C}$. Here, $B_\infty(A_e, b_e)$ is defined as the intersection of a unit ℓ_∞ -norm ball and a collection of M_C linear constraints $\{\xi \in \mathbb{R}^{N_C} | A_e\xi = b_e\}$.

Formally, a **constrained zonotope** is defined as follows,

$$\mathcal{C} = \{G\xi + c \mid \xi \in B_\infty(A_e, b_e)\} \subset \mathbb{R}^n,$$

where

$$B_\infty(A_e, b_e) = \{\xi \mid \|\xi\|_\infty \leq 1, A_e\xi = b_e\} \subset \mathbb{R}^{N_C},$$

with $G \in \mathbb{R}^{n \times N_C}$, $c \in \mathbb{R}^n$, $A_e \in \mathbb{R}^{M_C \times N_C}$, and $b \in \mathbb{R}^{M_C}$.

A constrained zonotope provide an alternative and equivalent representation of any convex and compact polytope. Furthermore, a constrained zonotope admits closed-form expressions for several set manipulations that can often be accomplished without invoking any optimization solvers. See [SDGR16] [RK22] [VWD24] for more details.

A **zonotope** is a special class of constrained zonotopes, and are defined as

$$\mathcal{Z} = \{G\xi + c \mid \|\xi\|_\infty \leq 1\} \subset \mathbb{R}^n.$$

In other words, a zonotope is a constrained zonotope with no equality constraints in the latent dimension space. In `ConstrainedZonotope`, we model zonotopes by having `(Ae,be)` be empty (`n_equalities` is zero).

Constrained zonotope object construction admits **one** of the following combinations (as keyword arguments):

1. `dim` for an **empty** constrained zonotope of dimension `dim`,
2. `(G, c, Ae, be)` for a **constrained zonotope**,
3. `(G, c)` for a **zonotope**,
4. `(lb, ub)` for a **zonotope** equivalent to an **axis-aligned cuboid** with appropriate bounds $\{x \mid lb \leq x \leq ub\}$, and
5. `(c, h)` for a **zonotope** equivalent to an **axis-aligned cuboid** centered at `c` with specified scalar/vector half-sides `h`, $\{x \mid \forall i \in \{1, 2, \dots, n\}, |x_i - c_i| \leq h_i\}$.
6. `(c=p, G=None)` for a **zonotope** equivalent to a **single point** `p`,
7. `P` for a **constrained zonotope** equivalent to the `pycvxset.Polytope.Polytope` object `P`,

Parameters

- **dim** (*int, optional*) – Dimension of the empty constrained zonotope. If NOTHING is provided, dim=0 is assumed.
- **c** (*Sequence[float] / numpy.ndarray, optional*) – Affine transformation translation vector. Must be 1D array, and the constrained zonotope dimension is determined by number of elements in c. When c is provided, either (G) or (G, Ae, be) or (h) must be provided additionally. When h is provided, c is the centroid of the resulting zonotope.
- **G** (*Sequence[Sequence[float]] / numpy.ndarray*) – Affine transformation matrix. The vectors are stacked vertically with matching number of rows as c. When G is provided, (c, Ae, be) OR (c) must also be provided. To define a constrained zonotope with a single point, set c to the point AND G to None (do not set (Ae, be) or set them to (None, None)).
- **Ae** (*Sequence[Sequence[float]] / numpy.ndarray*) – Equality coefficient vectors. The vectors are stacked vertically with matching number of columns as G. When Ae is provided, (G, c, be) must also be provided.
- **be** (*Sequence[float] / numpy.ndarray*) – Equality coefficient constants. The constants are expected to be in a 1D numpy array. When be is provided, (G, c, Ae) must also be provided.
- **lb** (*Sequence[float] / numpy.ndarray, optional*) – Lower bounds of the axis-aligned cuboid. Must be 1D array, and the constrained zonotope dimension is determined by number of elements in lb. When lb is provided, ub must also be provided.
- **ub** (*Sequence[float] / numpy.ndarray, optional*) – Upper bounds of the axis-aligned cuboid. Must be 1D array of length as same as lb. When ub is provided, lb must also be provided.
- **h** (*float / Sequence[float] / numpy.ndarray, optional*) – Half-side length of the axis-aligned cuboid. Can be a scalar or a vector of length as same as c. When h is provided, c must also be provided.
- **polytope** (*Polytope, optional*) – Polytope to use to construct constrained zonotope.

Raises

- **ValueError** – (G, c) is not compatible.
- **ValueError** – (G, c, Ae, be) is not compatible.
- **ValueError** – (lb, ub) is not valid
- **ValueError** – (c, h) is not valid
- **ValueError** – Provided polytope is not bounded.
- **UserWarning** – When a row with all zeros in Ae and be.

```
__init__() → None
__init__(*, dim: int) → None
__init__(*, G: Sequence[Sequence[float]] | ndarray | None, c: Sequence[float] | ndarray) → None
__init__(*, G: Sequence[Sequence[float]] | ndarray | None, c: Sequence[float] | ndarray, Ae: Sequence[Sequence[float]] | ndarray, be: Sequence[float] | ndarray) → None
__init__(*, lb: Sequence[float] | ndarray, ub: Sequence[float] | ndarray) → None
__init__(*, c: Sequence[float] | ndarray, h: float | Sequence[float] | ndarray) → None
__init__(*, polytope: Polytope) → None
```

Constructor for ConstrainedZonotope class

affine_map(*M*: int | float | Sequence[float] | Sequence[Sequence[float]] | np.ndarray) →
ConstrainedZonotope

Multiply a matrix or a scalar with a constrained zonotope

Parameters

M (int | float | Sequence[float] | Sequence[Sequence[float]] | np.ndarray) – Matrix (N times self.dim) or a scalar to be multiplied with a constrained zonotope

Returns

Constrained zonotope which is the product of M and self. Specifically, given a constrained zonotope \mathcal{P} , and a matrix $M \in \mathbb{R}^{m \times P.\text{dim}}$ or scalar M , then this function returns a constrained zonotope $\mathcal{R} = \{Mx|x \in \mathcal{P}\}$.

Return type

ConstrainedZonotope

Notes

This function implements (11) of [SDGR16].

approximate_pontryagin_difference(*norm_type*: int | str, *G_S*: Sequence[Sequence[float]] | np.ndarray, *c_S*: Sequence[float] | np.ndarray, *method*: str = 'inner-least-squares', *enable_warning*: bool = True) →
ConstrainedZonotope

Approximate Pontryagin difference between a constrained zonotope and an affine transformation of a unit-norm ball.

Specifically, we approximate the Pontryagin difference $\mathcal{P} \ominus \mathcal{S} = \{x \in \mathbb{R}^n | x + \mathcal{S} \subseteq \mathcal{P}\}$ between a constrained zonotope \mathcal{P} and a subtrahend \mathcal{S} . The subtrahend must be specifically of the form $\mathcal{S} = \{G_S\xi + c_S | \|\xi\|_p \leq 1\}$ for norm_type $p \in \{1, 2, \infty\}$.

- For p=1, the subtrahend is a convex hull of intervals specified by the columns of G_S with each interval is symmetric about c_S .
- For p=2, the subtrahend is an ellipsoid is characterized by affine transformation G_S of a unit Euclidean norm ball which is then shifted to c_S . Here, G_S is given by [pycvxset.Ellipsoid.Ellipsoid.G](#). See [pycvxset.Ellipsoid.Ellipsoid\(\)](#) to obtain G_S and c_S for broader classes of ellipsoids.
- For p='inf, the subtrahend is a zonotope characterized by (G_S, c_S) .

Parameters

- **norm_type** (int | str) – Norm type.
- **G_S** (Sequence[Sequence[float]] | numpy.ndarray) – Affine transformation matrix (self.dim times N) for scaling the ball
- **c_S** (Sequence[float] | numpy.ndarray) – Affine transformation vector (self.dim,) for translating the ball
- **method** (str, optional) – Approximation method to use. Can be one of ['inner-least-squares']. Defaults to 'inner-least-squares'.
- **enable_warning** (bool, optional) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Raises

- **ValueError** – Norm type is not in [1, 2, 'inf']
- **ValueError** – Mismatch in dimension (no. of columns of G_S, length of c_S, and self.dim should match)

Returns

Approximated Pontryagin difference between self and the affine transformation of the unit-norm ball.

Return type

ConstrainedZonotope

Notes

For method ‘inner-least-squares’, this function implements Table 1 of [VWD24].

cartesian_product(*sequence_Q*: Polytope | ConstrainedZonotope | Sequence[Polytope | ConstrainedZonotope]) → *ConstrainedZonotope*

Generate the Cartesian product of a set \mathcal{Q} (or a list of $\mathcal{mathcal{Q}}$) with \mathcal{P} .

Parameters

sequence_Q (Polytope / ConstrainedZonotope / Sequence[Polytope / ConstrainedZonotope]) – List of sets to take Cartesian product with

Returns

Cartesian product of self and all sets in sequence_Q

Return type

ConstrainedZonotope

chebyshev_centering(*enable_warning*: bool = True) → tuple[np.ndarray, float]

Computes a ball with the largest radius that fits within the constrained zonotope. The ball’s center is known as the Chebyshev center, and its radius is the Chebyshev radius.

Parameters

enable_warning (bool, optional) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Raises

- **ValueError** – When the constrained zonotope is not full-dimensional
- **ValueError** – When the constrained zonotope is empty
- **NotImplementedError** – Unable to solve the linear program using CVXPY

Returns**A tuple with two items**

1. center (numpy.ndarray): Approximate Chebyshev radius of the constrained zonotope
2. radius (float): Approximate Chebyshev radius of the constrained zonotope

Return type

tuple

Notes

Unlike `pycvxset.Polytope.Polytope.chebyshev_centering()`, this function computes an approximate Chebyshev center and radius. Specifically, it guarantees that a ball of the computed radius, centered at the computed center is contained in the constrained zonotope. However, it does not guarantee that the computed radius is the radius of the largest possible ball contained in the given constrained zonotope. For more details, see [VWS24].

closest_point(*points*: Sequence[Sequence[float]] | np.ndarray, *p*: int | str = 2) → np.ndarray

Wrapper for `project()` to compute the point in the convex set closest to the given point.

Parameters

- **points** (Sequence[Sequence[float]] / np.ndarray) – Points to project. Matrix (N times self.dim), where each row is a point.

- **p** (*str* / *int*) – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2.

Returns

Projection of points to the set as a 2D numpy.ndarray. These arrays have as many rows as points.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for [project\(\)](#) function.

containment_constraints(*x*: cvxpy.Variable, *flatten_order*: Literal['F', 'C'] = 'F') → tuple[list[cvxpy.Constraint], cvxpy.Variable | None]

Get CVXPY constraints for containment of *x* (a cvxpy.Variable) in a constrained zonotope.

Parameters

- **x** (cvxpy.Variable) – CVXPY variable to be optimized.
- **flatten_order** (Literal["F", "C"]) – Order to use for flatten (choose between “F”, “C”). Defaults to “F”, which implements column-major flatten. In 2D, column-major flatten results in stacking rows horizontally to achieve a single horizontal row.

Raises

ValueError – When constrained zonotope is empty

Returns

A tuple with two items:

1. constraint_list (list): CVXPY constraints for the containment of *x* in the constrained zonotope.
2. xi (cvxpy.Variable | None): CVXPY variable representing the latent dimension variable. It is None, when the constrained zonotope is a single point.

Return type

tuple

Notes

This function imports CVXPY locally to avoid overhead.

contains(*Q*: Sequence[float] | Sequence[Sequence[float]] | np.ndarray | Polytope | ConstrainedZonotope, *verbose*: bool = False, *time_limit*: float = 60) → bool | np.ndarray

Check containment of a set *Q* (could be a polytope or a constrained zonotope), or a collection of points $Q \in \mathbb{R}^{n_Q \times P.dim}$ in the given constrained zonotope.

Parameters

- **Q** (Sequence[float] / Sequence[Sequence[float]] / np.ndarray / Polytope / ConstrainedZonotope) – Polytope object, ConstrainedZonotope object, or a collection of points to be tested for containment within the constrained zonotope. When providing a collection of points, *Q* is a matrix (N times self.dim) with each row is a point.
- **verbose** (bool, optional) – Verbosity flag to provide cvxpy when solving the MIQP related to checking containment of a constrained zonotope within another constrained zonotope. Defaults to False.
- **time_limit** (float, optional) – Time limit in seconds for GUROBI solver when solving the MIQP related to checking containment of a constrained zonotope within another constrained zonotope. Set time_limit to np.inf if no limit is desired. Defaults to 60s (see constants.py).

Raises

- **ValueError** – Dimension mismatch between Q and the constrained zonotope
- **ValueError** – Q is Ellipsoid
- **ValueError** – Unable to perform containment check between two constrained zonotopes (including time_limit issues)
- **NotImplementedError** – GUROBI is not installed when checking containment of two constrained zonotopes
- **NotImplementedError** – Failed to check containment between two constrained zonotopes, due to an unhandled status

Returns

Boolean corresponding to $\mathcal{Q} \subseteq \mathcal{P}$ or $\mathcal{Q} \in \mathcal{P}$.

Return type

bool | numpy.ndarray([bool])

Notes

- We use \mathcal{P} to denote the constrained zonotope characterized by self.
- When Q is a constrained zonotope, a bool is returned which is True if and only if $\mathcal{Q} \subseteq \mathcal{P}$. This function uses the non-convex programming capabilities of GUROBI (via CVXPY) to check containment between two constrained zonotopes.
- When Q is a polytope, a bool is returned which is True if and only if $\mathcal{Q} \subseteq \mathcal{P}$.
 - When Q is in V-Rep, the containment problem simplifies to checking if all vertices of Q are contained \mathcal{P} .
 - When Q is in H-Rep, this function converts Q into a constrained zonotope, and then checks for containment.
- When Q is a single n-dimensional point, a bool is returned which is True if and only if $Q \in \mathcal{P}$. This function uses `distance()` to check containment of a point in a constrained zonotope.
- When Q is a collection of n-dimensional points (Q is a matrix with each row describing a point), an array of is returned where each element is True if and only if $Q_i \in \mathcal{P}$. This function uses `distance()` to check containment of a point in a constrained zonotope.

 **Warning**

This function requires gurobipy when checking if the `ConstrainedZonotope` object represented by `self` contains a `ConstrainedZonotope` object `Q` or `pycvxset.Polytope.Polytope` object `Q` in H-Rep.

`copy() → ConstrainedZonotope`

Get a copy of the constrained zonotope

`distance(points: Sequence[Sequence[float]] | np.ndarray, p: int | str = 2) → np.ndarray`

Wrapper for `project()` to compute distance of a point to a convex set.

Parameters

- **points** (`Sequence[Sequence[float]] / np.ndarray`) – Points to project. Matrix (N times self.dim), where each row is a point.
- **p (int / str)** – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2.

Returns

Distance of points to the set as a 1D numpy.ndarray. These arrays have as many rows as points.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for `project()` function.

extreme(*eta*: Sequence[Sequence[float]] | np.ndarray) → np.ndarray

Wrapper for `support()` to compute the extreme point.

Parameters

eta (Sequence[Sequence[float]] / np.ndarray) – Support directions. Matrix (N times self.dim), where each row is a support direction.

Returns

Support vector evaluation(s) as a 2D numpy.ndarray. The array has as many rows as eta.

Return type

numpy.ndarray

Notes

For more detailed description, see documentation for `support()` function.

interior_point(*point_type*: str = 'mvie', *enable_warning*: bool = True) → np.ndarray

Compute an interior point of the constrained zonotope.

Parameters

- **point_type** (str, optional) – Type of interior point. Valid strings: {'mvie', 'chebyshev'}. Defaults to 'mvie'.
- **enable_warning** (bool, optional) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Returns

A point that lies in the (relative) interior of the constrained zonotope.

Return type

numpy.ndarray

Notes

This function is a wrapper for existing centering methods in ConstrainedZonotope class — maximum_volume_inscribing_ellipsoid, chebyshev_centering. For the case where self is a zonotope, it returns c.

intersection(*Q*: ConstrainedZonotope | Polytope) → ConstrainedZonotope

Compute the intersection of constrained zonotope with another constrained zonotope or polytope.

Parameters

Q (ConstrainedZonotope / Polytope) – Set to intersect with

Raises

TypeError – When Q is neither a ConstrainedZonotope object or a Polytope object

Returns

Intersection of self with Q

Return type

ConstrainedZonotope

Notes

- When Q is a constrained zonotope, this function uses `intersection_under_inverse_affine_map()` with R set to identity matrix.
- When Q is a polytope in H-Rep, this function uses `intersection_with_halfspaces()` and `intersection_with_affine_set()`.
- When Q is a polytope in V-Rep, this function converts Q into a constrained zonotope to avoid a halfspace enumeration.

`intersection_under_inverse_affine_map(Y: ConstrainedZonotope, R: Sequence[Sequence[float]] | np.ndarray) → ConstrainedZonotope`

Compute the intersection of constrained zonotope with another constrained zonotope under an inverse affine map

Parameters

- Y (`ConstrainedZonotope`) – Set to intersect with
- R (`Sequence[Sequence[float]]` / `numpy.ndarray`) – Matrix ($Y.dim$ times $self.dim$) for the inverse-affine map.

Raises

- `ValueError` – When Y is not a `ConstrainedZonotope`
- `ValueError` – When R is not of correct dimension

Returns

Intersection of self with Y under an inverse affine map R . Specifically, given constrained zonotopes \mathcal{P} (self) and \mathcal{Y} , and a matrix R , we compute the set $\mathcal{P} \cap_R \mathcal{Y} = \{x \in \mathcal{P} | Rx \in \mathcal{Y}\}$. When R is invertible, $\mathcal{P} \cap_R \mathcal{Y} = (R^{-1}\mathcal{P}) \cap \mathcal{Y}$.

Return type

`ConstrainedZonotope`

Notes

This function implements (13) of [SDGR16]. This function does not require R to be invertible.

`intersection_with_affine_set(Ae: Sequence[Sequence[float]] | np.ndarray, be: Sequence[float] | np.ndarray) → ConstrainedZonotope`

Compute the intersection of a constrained zonotope with an affine set.

Parameters

- A_e (`Sequence[Sequence[float]]` / `numpy.ndarray`) – Equality coefficient matrix (N times $self.dim$) that define the affine set $\{x | A_e x = b_e\}$.
- b_e (`Sequence[float]` / `numpy.ndarray`) – Equality constant vector (N) that define the affine set $\{x | j A_e x = b_e\}$.

Raises

- `ValueError` – When the number of columns in A_e is different from $self.dim$

Returns

The intersection of a constrained zonotope with the affine set.

Return type

`ConstrainedZonotope`

Notes

This function implements imposes the constraints $\{A_e x = b_e\}$ as constraints in the latent dimension of the constrained zonotope — $A_e(G\xi + c) = b_e$ for every feasible ξ .

intersection_with_halfspaces(*A*: Sequence[Sequence[float]] | np.ndarray, *b*: Sequence[float] | np.ndarray) → *ConstrainedZonotope*

Compute the intersection of a constrained zonotope with a collection of halfspaces (polyhedron).

Parameters

- **A** (Sequence[Sequence[float]] | numpy.ndarray) – Inequality coefficient matrix (N times self.dim) that define the polyhedron $\{x|Ax \leq b\}$.
- **b** (Sequence[float] | numpy.ndarray) – Inequality constant vector (N,) that define the polyhedron $\{x|Ax \leq b\}$.

Returns

The intersection of a constrained zonotope with a collection of halfspaces.

Return type

ConstrainedZonotope

Notes

This function implements (10) of [RK22] for each halfspace. We skip redundant inequalities when encountered and we return empty set when intersection yields an empty set.

inverse_affine_map_under_invertible_matrix(*M*: Sequence[Sequence[float]] | np.ndarray) → *ConstrainedZonotope*

Compute the inverse affine map of a constrained zonotope for a given matrix M.

Parameters

M (Sequence[Sequence[float]] | numpy.ndarray) – Square invertible matrix of dimension self.dim

Raises

- **ValueError** – M is not convertible into a 2D float array
- **ValueError** – M is not square
- **ValueError** – M is not invertible

Returns

Inverse affine map of self under M. Specifically, Given a constrained zonotope \mathcal{P} and an invertible self.dim-dimensional matrix $M \in \mathbb{R}^{\mathcal{P}.dim \times \mathcal{P}.dim}$, this function computes the constrained zonotope $\mathcal{R} = M^{-1}\mathcal{P}$.

Return type

ConstrainedZonotope

Notes

This function is a wrapper for `affine_map()`. We require M to be invertible in order to ensure that the resulting set is representable as a constrained zonotope.

maximum_volume_inscribing_ellipsoid(*enable_warning*: bool = True) → tuple[np.ndarray, np.ndarray, np.ndarray]

Compute the maximum volume ellipsoid that fits within the given constrained zonotope.

Parameters

enable_warning (bool, optional) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Raises

- **ValueError** – When the constrained zonotope is not full-dimensional
- **ValueError** – When the constrained zonotope is empty
- **NotImplementedError** – Unable to solve the convex program using CVXPY

Returns**A tuple with three items:**

1. center (numpy.ndarray): Approximate maximum volume inscribed ellipsoid's center
2. shape_matrix (numpy.ndarray): Approximate maximum volume inscribed ellipsoid's shape matrix
3. sqrt_shape_matrix (numpy.ndarray): Approximate maximum volume inscribed ellipsoid's square root of shape matrix.

Return type

tuple

Notes

Unlike `pycvxset.Polytope.Polytope.maximum_volume_inscribing_ellipsoid()`, this function computes an approximate maximum volume inscribed ellipsoid. Specifically, it guarantees that the computed ellipsoid is contained in the constrained zonotope. However, it does not guarantee that the computed ellipsoid is the largest possible ellipsoid (in terms of volume) contained in the given constrained zonotope. For more details, see [VWS24].

```
minimize(x: cvxpy.Variable, objective_to_minimize: cvxpy.Expression, cvxpy_args: dict[str, Any], task_str: str = "") → tuple[np.ndarray, float, str]
```

Solve a convex program with CVXPY objective subject to containment constraints.

Parameters

- **x** (cvxpy.Variable) – CVXPY variable to be optimized
- **objective_to_minimize** (cvxpy.Expression) – CVXPY expression to be minimized
- **cvxpy_args** (dict) – CVXPY arguments to be passed to the solver
- **task_str** (str, optional) – Task string to be used in error messages. Defaults to “”.

Raises

NotImplementedError – Unable to solve problem using CVXPY

Returns**A tuple with three items:**

1. x.value (numpy.ndarray): Optimal value of x. np.nan * np.ones((self.dim,)) if the problem is not solved.
2. problem.value (float): Optimal value of the convex program. np.inf if the problem is infeasible, -np.inf if problem is unbounded, and finite otherwise.
3. problem_status (str): Status of the problem

Return type

tuple

Notes

This function uses `containment_constraints()` to obtain the list of CVXPY expressions that form the containment constraints on x .

⚠ Warning

Please pay attention to the `NotImplementedError` generated by this function. It may be possible to get CVXPY to solve the same problem by switching the solver. For example, consider the following code block.

```
from pycvxset import Polytope
P = Polytope(A=[[1, 1], [-1, -1]], b=[1, 1])
P.cvxpyp_args_lp = {'solver': 'CLARABEL'}      # Default solver used in
                                                →pycvxset
try:
    print('Is polytope bounded?', P.is_bounded)
except NotImplementedError as err:
    print(str(err))
P.cvxpyp_args_lp = {'solver': 'OSQP'}
print('Is polytope bounded?', P.is_bounded)
```

This code block produces the following output:

```
Unable to solve the task (support function evaluation of the set at eta =
→ [-0. -1.]). CVXPY returned error:
Solver 'CLARABEL' failed. Try another solver, or solve with verbose=True
→ for more information.
```

```
Is polytope bounded? False
```

`minimum_volume_circumscribing_rectangle()` → tuple[np.ndarray, np.ndarray]

Compute the minimum volume circumscribing rectangle for a set.

Raises

`ValueError` – Solver error or set is empty!

Returns

A tuple of two elements

- `lb` (numpy.ndarray): Lower bound l on the set, $\mathcal{P} \subseteq \{l\} \oplus \mathbb{R}_{\geq 0}$.
- `ub` (numpy.ndarray): Upper bound u on the set, $\mathcal{P} \subseteq \{u\} \oplus (-\mathbb{R}_{\geq 0})$.

Return type

tuple

Notes

This function computes the lower/upper bound by an element-wise support computation ($2n$ linear programs), where n is attr:`self.dim`. To reuse the `support()` function for the lower bound computation, we solve the optimization for each $i \in \{1, 2, \dots, n\}$,

$$\inf_{x \in \mathcal{P}} e_i^\top x = -\sup_{x \in \mathcal{P}} -e_i^\top x = -\rho_{\mathcal{P}}(-e_i),$$

where $e_i \in \mathbb{R}^n$ denotes the standard coordinate vector, and $\rho_{\mathcal{P}}$ is the support function of \mathcal{P} .

`minus(Q: Sequence[float] | np.ndarray | Ellipsoid | ConstrainedZonotope, enable_warning: bool = True)` → `ConstrainedZonotope`

Implement - operation: Pontryagin difference with a constrained zonotope minuend

When Q is an ellipsoid or a zonotope, minus returns an inner-approximation of the set corresponding to the Pontryagin difference of a constrained zonotope and Q. When Q is a point or a singleton set, an exact set corresponding to the translation by -Q or -Q.c is returned.

Parameters

- **Q** (`Sequence[float] / numpy.ndarray / Ellipsoid / ConstrainedZonotope`) – Point/set to use as subtrahend in the Pontryagin difference.
- **enable_warning** (`bool, optional`) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Raises

- **TypeError** – When Q is not one of the following — convertible into a 1D numpy array, or an ellipsoid, or a zonotope.
- **ValueError** – When Q has a dimension mismatch with self.
- **UserWarning** – When using with Q that is a set, warn that an inner-approximation is returned.

Returns

Pontryagin difference of self and Q

Return type

`ConstrainedZonotope`

Notes

This function uses `approximate_pontryagin_difference()` when Q is a set and uses `plus()` when Q is a point.

```
plot(method: str = 'inner', ax: Axes | Axes3D | None | None = None, direction_vectors: Sequence[Sequence[float]] | np.ndarray | None = None, n_vertices: int | None = None, n_halfspaces: int | None = None, patch_args: dict[str, Any] | None = None, vertex_args: dict[str, Any] | None = None, center_args: dict[str, Any] | None = None, autoscale_enable: bool = True, decimal_precision: int = 3, enable_warning: bool = True) → tuple[Any, ...]
```

Plot a polytopic approximation of the set.

Parameters

- **method** (`str, optional`) – Type of polytopic approximation to use. Can be [“inner” or “outer”]. Defaults to “inner”.
- **ax** (`Axes / Axes3D / None, optional`) – Axis on which the patch is to be plotted
- **direction_vectors** (`Sequence[Sequence[float]] / np.ndarray, optional`) – Directions to use when performing ray shooting. Matrix (N times self.dim) for some N >= 1. Defaults to None, in which case we use `pycvxset.common.spread_points_on_a_unit_sphere()` to compute the direction vectors.
- **n_vertices** (`int, optional`) – Number of vertices to use when computing the polytopic inner-approximation. Ignored if method is “outer” or when direction_vectors are provided. More than n_vertices may be used in some cases (see notes). Defaults to None.
- **n_halfspaces** (`int, optional`) – Number of halfspaces to use when computing the polytopic outer-approximation. Ignored if method is “outer” or when direction_vectors are provided. More than n_halfspaces may be used in some cases (see notes). Defaults to None.
- **patch_args** (`dict, optional`) – Arguments to pass for plotting faces and edges. See `pycvxset.Polytope.Polytope.plot()` for more details. Defaults to None.

- **vertex_args** (*dict, optional*) – Arguments to pass for plotting vertices. See [pycvxset.Polytope.Polytope.plot\(\)](#) for more details. Defaults to None.
- **center_args** (*dict, optional*) – For ellipsoidal set, arguments to pass to scatter plot for the center. If a label is desired, pass it in center_args.
- **autoscale_enable** (*bool, optional*) – When set to True, matplotlib adjusts axes to view full polytope. See [pycvxset.Polytope.Polytope.plot\(\)](#) for more details. Defaults to True.
- **decimal_precision** (*int, optional*) – When plotting a 3D polytope that is in V-Rep and not in H-Rep, we round vertex to the specified precision to avoid numerical issues. Defaults to PLOTTING_DECIMAL_PRECISION_CDD specified in pycvxset.common.constants.
- **enable_warning** (*bool, optional*) – Enables the UserWarning. May be turned off if expected. Defaults to True.

Returns

See [pycvxset.Polytope.Polytope.plot\(\)](#) for details.

Return type

tuple

Notes

This function is a wrapper for [polytopic_inner_approximation\(\)](#) and [polytopic_outer_approximation\(\)](#) for more details in polytope construction.

plus(*Q: Sequence[float] | np.ndarray | Polytope | ConstrainedZonotope*) → *ConstrainedZonotope*

Add a point or a set Q to a constrained zonotope (Minkowski sum).

Parameters

Q (Sequence[float] | np.ndarray | Polytope | ConstrainedZonotope) – The point or set to add

Raises

- **TypeError** – When Q is not one of the following — convertible into a 1D numpy array or a constrained zonotope.
- **ValueError** – When Q has a dimension mismatch with self.
- **UserWarning** – When using with Q that is a set, warn that an inner-approximation is returned.

Returns

Minkowski sum of self and Q.

Return type

ConstrainedZonotope

Notes

Given a constrained zonotope \mathcal{P} and a set Q , this function computes the Minkowski sum of Q and the constrained zonotope, defined as $\mathcal{R} = \{x + q | x \in \mathcal{P}, q \in Q\}$. On the other hand, when Q is a point, this function computes the constrained zonotope $\mathcal{R} = \{x + Q | x \in \mathcal{P}\}$.

This function implements (12) of [SDGR16] when Q is a constrained zonotope. When Q is a Polytope, this function converts it into a constrained zonotope, and then uses (12) of [SDGR16].

polytopic_inner_approximation(*direction_vectors: Sequence[Sequence[float]] | np.ndarray | None = None, n_vertices: int | None = None, verbose: bool = False, enable_warning: bool = True*) → *Polytope*

Compute a polytopic inner-approximation of a given set via ray shooting.

Parameters

- **cvx_set** (`ConstrainedZonotope / Ellipsoid / Polytope`) – Set to be approximated,
- **direction_vectors** (`Sequence[Sequence[float]] / np.ndarray, optional`) – Directions to use when performing ray shooting. Matrix (N times `self.dim`) for some $N \geq 1$. Defaults to None.
- **n_vertices** (`int, optional`) – Number of vertices to be used for the inner-approximation. `n_vertices` is overridden whenever `direction_vectors` are provided. Defaults to None.
- **verbose** (`bool, optional`) – If true, `pycvxset.common.spread_points_on_a_unit_sphere()` is passed with `verbose`. Defaults to False.
- **enable_warning** (`bool, optional`) – Enables the `UserWarning`. May be turned off if expected. Defaults to True.

Returns

Polytopic inner-approximation in V-Rep of a given set with `n_vertices` no smaller than user-provided `n_vertices`.

Return type

`Polytope`

Notes

We compute the polytope using `extreme()` evaluated along the direction vectors computed by `pycvxset.common.spread_points_on_a_unit_sphere()`. When `direction_vectors` is None and `n_vertices` is None, we select `n_vertices = 2self.dim + 2self.dimSPOAUS_DIRECTIONS_PER_QUADRANT` (as defined in `pycvxset.common.constants()`). [BV04] The function also uses `pycvxset.common.make_aspect_ratio_equal()` to account for possibly non-symmetric sets.

polytopic_outer_approximation(`direction_vectors: Sequence[Sequence[float]] | np.ndarray | None = None, n_halfspaces: int | None = None, verbose: bool = False, enable_warning: bool = True`) → `Polytope`

Compute a polytopic outer-approximation of a given set via ray shooting.

Parameters

- **cvx_set** (`ConstrainedZonotope / Ellipsoid / Polytope`) – Set to be approximated,
- **direction_vectors** (`Sequence[Sequence[float]] / np.ndarray, optional`) – Directions to use when performing ray shooting. Matrix (N times `self.dim`) for some $N \geq 1$. Defaults to None.
- **n_halfspaces** (`int, optional`) – Number of halfspaces to be used for the inner-approximation. `n_vertices` is overridden whenever `direction_vectors` are provided. Defaults to None.
- **verbose** (`bool, optional`) – If true, `pycvxset.common.spread_points_on_a_unit_sphere()` is passed with `verbose`. Defaults to False.
- **enable_warning** (`bool, optional`) – Enables the `UserWarning`. May be turned off if expected. Defaults to True.

Returns

Polytopic outer-approximation in H-Rep of a given set with `n_halfspaces` no smaller than user-provided `n_vertices`.

Return type

`Polytope`

Notes

We compute the polytope using `support()` evaluated along the direction vectors computed by `pycvxset.common.spread_points_on_a_unit_sphere()`. When `direction_vectors` is `None` and `n_halfspaces` is `None`, we select `n_halfspaces = 2self.dim + 2self.dimSPOAUS_DIRECTIONS_PER_QUADRANT` (as defined in `pycvxset.common.constants`). [BV04]

project(*x*: Sequence[float] | Sequence[Sequence[float]] | ndarray, *p*: int | str = 2) → tuple[ndarray, ndarray]

Project a point or a collection of points on to a set.

Given a set \mathcal{P} and a test point $y \in \mathbb{R}^{\mathcal{P}.\text{dim}}$, this function solves a convex program,

$$\begin{aligned} & \text{minimize} && \|x - y\|_p \\ & \text{subject to} && x \in \mathcal{P} \end{aligned}$$

Parameters

- **points** (Sequence[Sequence[float]] / np.ndarray) – Points to project (N times self.dim) with each row as a point.
- **p (str / int)** – Norm-type. It can be 1, 2, or ‘inf’. Defaults to 2, which is the Euclidean norm.

Raises

- **ValueError** – Set is empty
- **ValueError** – Dimension mismatch — no. of columns in points is different from self.dim.
- **ValueError** – Points is not convertible into a 2D array
- **NotImplementedError** – Unable to solve problem using CVXPY

Returns

A tuple with two items:

1. projected_point (numpy.ndarray): Projection point(s) as a 2D numpy.ndarray. Matrix (N times self.dim), where each row is a projection of the point in points to the set \mathcal{P} .
2. distance (numpy.ndarray): Distance(s) as a 1D numpy.ndarray. Vector (N,), where each row is a projection of the point in points to the set \mathcal{P} .

Return type

tuple

Notes

Given a constrained zonotope \mathcal{P} and a test point $y \in \mathbb{R}^{\mathcal{P}.\text{dim}}$, this function solves a convex program with decision variables $x \in \mathbb{R}^{\mathcal{P}.\text{dim}}$ and $\xi \in \mathbb{R}^{\mathcal{P}.\text{latent_dim}}$,

$$\begin{aligned} & \text{minimize} && \|x - y\|_p \\ & \text{subject to} && x = G_P \xi + c_P \\ & && A_P \xi = b_P \\ & && \|\xi\|_\infty \leq 1 \end{aligned}$$

projection(*project_away_dims*: int | Sequence[int] | ndarray) → ConstrainedZonotope

Orthogonal projection of a set \mathcal{P} after removing some user-specified dimensions.

$$\mathcal{R} = \{r \in \mathbb{R}^m \mid \exists v \in \mathbb{R}^{n-m}, \text{Lift}(r, v) \in \mathcal{P}\}$$

Here, $m = \mathcal{P}.\text{dim} - \text{length}(\text{project_away_dim})$, and $\text{Lift}(r, v)$ lifts (“undo”s the projection) using the appropriate components of v . This function uses [affine_map\(\)](#) to implement the projection by designing an appropriate affine map $M \in \{0, 1\}^{m \times \mathcal{P}.\text{dim}}$ with each row of M corresponding to some standard axis vector $e_i \in \mathbb{R}^m$.

Parameters

project_away_dims (Sequence[int] / np.ndarray) – Dimensions to projected away in integer interval [0, 1, ..., n - 1].

Raises

ValueError – When project_away_dims are not in the integer interval | All dimensions are projected away

Returns

Set obtained via projection.

Return type

object

Returns

m-dimensional set obtained via projection.

Return type

ConstrainedZonotope

remove_redundancies() → None

Remove any redundancies in CZ using pycddlib and other geometric properties.

Updates full-dimensional flag when empty

Updates empty flag when empty OR non-empty zonotope OR when latent set is non-empty

slice(*dims*: int | Sequence[int] | ndarray, *constants*: float | Sequence[float] | ndarray) → ConstrainedZonotope

Slice a set restricting certain dimensions to constants.

This function uses [intersection_with_affine_set\(\)](#) to implement the slicing by designing an appropriate affine set from dims and constants.

Parameters

- **dims** (Sequence[int] / np.ndarray) – List of dims to restrict to a constant in the integer interval [0, 1, ..., n - 1].
- **constants** (float / Sequence[float] / np.ndarray) – List of constants

Raises

- **ValueError** – dims has entries beyond n
- **ValueError** – dims and constants are not 1D arrays of same size

Returns

Sliced set.

Return type

object

Returns

Constrained zonotope that has been sliced at the specified dimensions.

Return type

ConstrainedZonotope

slice_then_projection(*dims*: int | Sequence[int] | ndarray, *constants*: float | Sequence[float] | ndarray) → ConstrainedZonotope

Wrapper for *slice()* and *projection()*.

The function first restricts a set at certain dimensions to constants, and then projects away those dimensions. Useful for visual inspection of higher dimensional sets.

Parameters

- **dims** (Sequence[int] / np.ndarray) – List of dims to restrict to a constant in the integer interval [0, 1, ..., dim - 1], and then project away.
- **constants** (float / Sequence[float] / np.ndarray) – List of constants

Raises

- **ValueError** – dims has entries beyond n
- **ValueError** – dims and constants are not 1D arrays of same size
- **ValueError** – When dims are not in the integer interval | All dimensions are projected away

Returns

Sliced then projected set.

Return type

object

Returns

m-dimensional set obtained via projection after slicing.

Return type

ConstrainedZonotope

support(*eta*: Sequence[float] | Sequence[Sequence[float]] | ndarray) → tuple[ndarray, ndarray]

Evaluates the support function and support vector of a set.

The support function of a set \mathcal{P} is defined as $\rho_{\mathcal{P}}(\eta) = \max_{x \in \mathcal{P}} \eta^\top x$. The support vector of a set \mathcal{P} is defined as $\nu_{\mathcal{P}}(\eta) = \arg \max_{x \in \mathcal{P}} \eta^\top x$.

Parameters

- **eta** (Sequence[float] / Sequence[Sequence[float]] / np.ndarray) – Support directions. Matrix (N times self.dim), where each row is a support direction.

Raises

- **ValueError** – Set is empty
- **ValueError** – Mismatch in eta dimension
- **ValueError** – eta is not convertible into a 2D array
- **NotImplementedError** – Unable to solve problem using CVXPY

Returns

A tuple with two items:

1. support_function_evaluations (numpy.ndarray): Support function evaluation(s) as a 2D numpy.ndarray. Vector (N,) with as many rows as eta.
2. support_vectors (numpy.ndarray): Support vectors as a 2D numpy.ndarray. Matrix N x self.dim with as many rows as eta.

Return type

tuple

Notes

Given a constrained zonotope \mathcal{P} and a support direction $\eta \in \mathbb{R}^{\mathcal{P}.\text{dim}}$, this function solves a convex program with decision variables $x \in \mathbb{R}^{\mathcal{P}.\text{dim}}$ and $\xi \in \mathbb{R}^{\mathcal{P}.\text{latent_dim}}$,

$$\begin{aligned} & \text{maximize} && \eta^\top x \\ & \text{subject to} && x = G_P \xi + c_P \\ & && A_P \xi = b_P \\ & && \|\xi\|_\infty \leq 1 \end{aligned}$$

property Ae: ndarray

Equality coefficient vectors Ae for the constrained zonotope.

Returns

Equality coefficient vectors Ae for the constrained zonotope. Ae is np.empty((0, self.latent_dim)) for a zonotope.

Return type

numpy.ndarray

property G: ndarray

Affine transformation matrix G for the constrained zonotope.

Returns

Affine transformation matrix G.

Return type

numpy.ndarray

property He: ndarray

Equality constraints $He=[Ae, be]$ for the constrained zonotope.

Returns

H-Rep in [Ae, be]. He is np.empty((0, self.latent_dim + 1)) for a zonotope.

Return type

numpy.ndarray

property be: ndarray

Equality constants be for the constrained zonotope.

Returns

Equality constants be for the constrained zonotope. be is np.empty((0,)) for a zonotope.

Return type

numpy.ndarray

property c: ndarray | None

Affine transformation vector c for the constrained zonotope.

Returns

Affine transformation vector c.

Return type

numpy.ndarray

property cvxpy_args_lp: dict[str, Any]

CVXPY arguments in use when solving a linear program

Returns

CVXPY arguments in use when solving a linear program. Defaults to dictionary in `pycvxset.common.DEFAULT_CVXPY_ARGS_LP`.

Return type

dict

property cvxpy_args_socp: dict[str, Any]

CVXPY arguments in use when solving a second-order cone program

Returns

CVXPY arguments in use when solving a second-order cone program. Defaults to dictionary in *pycvxset.common.DEFAULT_CVXPY_ARGS_SOCP*.

Return type

dict

property dim: int

Dimension of the constrained zonotope.

Returns

Dimension of the constrained zonotope.

Return type

int

Notes

We determine dimension from G, since c is set to None in case of empty (constrained) zonotope.

property is_bounded: bool

Check if the constrained zonotope is bounded (which is always True)

property is_empty: bool

Check if the constrained zonotope is empty

Raises

NotImplementedError – Unable to solve the feasibility problem using CVXPY

Returns

When True, the polytope is empty

Return type

bool

Notes

This function may trigger a cvxpy feasibility problem if emptiness is not already known.

property is_full_dimensional: bool

Check if the affine dimension of the constrained zonotope is the same as the constrained zonotope dimension

Returns

True when the affine hull containing the constrained zonotope has the dimension *self.dim*

Return type

bool

Notes

An empty polytope is full dimensional if dim=0, otherwise it is not full-dimensional. See Sec. 2.1.3 of [BV04] for discussion on affine dimension. A non-empty zonotope is full-dimensional if and only if G has full row rank. A non-empty constrained zonotope is full-dimensional if and only if [G; A] has full row rank.

This function may trigger a cvxpy feasibility problem if emptiness is not already known.

property is_singleton: bool

Check if the constrained zonotope is a singleton

This function does not invoke any optimization solver, and relies on rank computations.

A non-empty constrained zonotope is a singleton if and only if latent set is empty or a singleton.

property is_zonotope: bool

Check if the constrained zonotope is a zonotope

property latent_dim: int

Latent dimension of the constrained zonotope.

Returns

Latent dimension of the constrained zonotope.

Return type

int

property n_equalities: int

Number of equality constraints used when defining the constrained zonotope.

Returns

Number of equality constraints used when defining the constrained zonotope

Return type

int

property type_of_set: str

Return the type of set

Returns

Type of the set

Return type

str

PYCVXSET.COMMON

The following functions are few additional methods provided with pycvxset that may be useful to the user.

<code>pycvxset.common.approximate_volume_from_grid</code>	Estimate area of a two-dimensional set using a grid of given step size
<code>pycvxset.common.is_constrained_zonotope(Q)</code>	Check if the set is a constrained zonotope
<code>pycvxset.common.is_ellipsoid(Q)</code>	Check if the set is an ellipsoid
<code>pycvxset.common.is_polytope(Q)</code>	Check if the set is a polytope
<code>pycvxset.common.prune_and_round_vertices(V)</code>	Filter through the vertices to skip any point that has another point (down in the list) that is close to it in the list.
<code>pycvxset.common.spread_points_on_a_unit_sp</code>	Spread points on a unit sphere in n-dimensional space.

15.1 pycvxset.common.approximate_volume_from_grid

`pycvxset.common.approximate_volume_from_grid(cvx_set: ConstrainedZonotope | Ellipsoid | Polytope, area_grid_step_size: int | float) → float`

Estimate area of a two-dimensional set using a grid of given step size

Parameters

- `cvx_set` (`ConstrainedZonotope` / `Ellipsoid` / `Polytope`) – Set for which area is to be computed
- `area_grid_step_size` (`int` / `float`) – Scalar step size that is constant in both dimensions

Raises

`ValueError` – When set is not 2-dimensional

Returns

Approximate area of the set

Return type

`float`

Notes

This function creates a 2D grid of points with a given step size, and computes the fraction of points that lie in the set. Consequently, the computed area is an approximation of the actual area of the set. The area of the bounding box is computed using the `minimum_volume_circumscribing_rectangle()` method associated with the set.

15.2 pycvxset.common.is_constrained_zonotope

`pycvxset.common.is_constrained_zonotope(Q: Any) → bool`

Check if the set is a constrained zonotope

Parameters

`Q (object)` – Set to check

Returns

Returns True if the set is a constrained zonotope, False otherwise

Return type

`bool`

15.3 pycvxset.common.is_ellipsoid

`pycvxset.common.is_ellipsoid(Q: Any) → bool`

Check if the set is an ellipsoid

Parameters

`Q (object)` – Set to check

Returns

Returns True if the set is an ellipsoid, False otherwise

Return type

`bool`

15.4 pycvxset.common.is_polytope

`pycvxset.common.is_polytope(Q: Any) → bool`

Check if the set is a polytope

Parameters

`Q (object)` – Set to check

Returns

Returns True if the set is a polytope, False otherwise

Return type

`bool`

15.5 pycvxset.common.prune_and_round_vertices

`pycvxset.common.prune_and_round_vertices(V: Sequence[Sequence[float]] | ndarray, decimal_precision: int = 3) → ndarray`

Filter through the vertices to skip any point that has another point (down in the list) that is close to it in the list.

Parameters

- `V (Sequence[Sequence[float]] / np.ndarray)` – Matrix of vertices (N times self.dim)
- `decimal_precision (int, optional)` – The decimal precision for rounding the vertices. Defaults to PLOTTING_DECIMAL_PRECISION_CDD from pycvxset.common.constants.

Returns

The pruned and rounded array of vertices.

Return type
numpy.ndarray

15.6 pycvxset.common.spread_points_on_a_unit_sphere

```
pycvxset.common.spread_points_on_a_unit_sphere(dim: int, n_points: int | None = None,
                                                cvxpy_socp_args: dict[str, Any] | None = None,
                                                verbose: bool = False, enable_warning: bool =
                                                True, save_points_on_a_unit_sphere: bool = True)
                                                → tuple[ndarray, float, ndarray]
```

Spread points on a unit sphere in n-dimensional space.

Parameters

- **dim** (*int*) – The dimension of the sphere.
- **n_points** (*int*) – The number of points to be spread on the unit sphere. Defaults to None, in which case, we choose $= (n_points)$
- **cvxpy_socp_args** (*dict*) – Additional arguments to be passed to the CVXPY solver. Defaults to None, in which case the function uses DEFAULT_CVXPY_ARGS_SOCP from pycvxset.common.constants.
- **verbose** (*bool, optional*) – Whether to print verbose output. Defaults to False.
- **enable_warning** (*bool, optional*) – Enables the UserWarning. May be turned off if expected. Defaults to True.
- **save_points_on_a_unit_sphere** (*bool, optional*) – Whether to save the computed points and minimum separation to a file. Defaults to SPOAUS_SAVE_POINTS_ON_A_UNIT_SPHERE.

Returns

A tuple containing three items:

```
# opt_locations (ndarray): The spread points on the unit sphere. # minimum_separation
# (float): The minimum separation between the points. # opt_locations_first_quad (ndar-
ray): The spread points in the first quadrant.
```

Return type

tuple

Raises

- **ValueError** – If n_points is less than $2 * \text{dim}$.
- **UserWarning** – If $\text{n_points} - 2 * \text{dim}$ is not a multiple of 2^{dim} .
- **NotImplementedError** – Unable to solve the convexified problem using CVXPY
- **NotImplementedError** – Convex-concave procedure did not converge!

Notes

This function uses the CVXPY library to solve a convex optimization problem to spread the points on the unit sphere. The spread points are returned as opt_locations, the separation between the points is returned as separation, and the spread points in the first quadrant are returned as opt_locations_first_quad.

For dim in [1, 2], the points are available in closed-form. For dim ≥ 3 , we solve the following non-convex

optimization problem using convex-concave procedure:

$$\begin{aligned}
 & \text{maximize} && R \\
 & \text{subject to} && R \geq 0 \\
 & && x \geq R/2 \\
 & && \|x_i - x_j\| \geq R, \quad 1 \leq i < j \leq n_{\text{points}} \\
 & && \|x_i - e_j\| \geq R, \quad 1 \leq i \leq n_{\text{points}}, 1 \leq j \leq n_{\text{dim}} \\
 & && \|x_i\| \leq 1, \quad 1 \leq i \leq n_{\text{points}} \\
 & && \|x_i\| \geq 0.8, \quad 1 \leq i \leq n_{\text{points}}
 \end{aligned}$$

The optimization problem seeks to spread points (apart from the standard axes) in the first quadrant so that their pairwise separation is maximized, while they have a norm close to 1. The second constraint is motivated to ensure that the reflections of the points about the quadrant plane is also separated by R.

When `save_points_on_a_unit_sphere` is True, the function saves the computed points (all), the computed points in the first quadrant, and the minimum separation to a file named `tmp/spoaus_dim_{dim}_n_points_{n_points_int}.npz`. If the file already exists, the function loads the points and minimum separation from the file instead of recomputing them. This can save time when calling `spread_points_on_a_unit_sphere` with default values.

`pycvxset.common.approximate_volume_from_grid(cvx_set: ConstrainedZonotope | Ellipsoid | Polytope, area_grid_step_size: int | float) → float`

Estimate area of a two-dimensional set using a grid of given step size

Parameters

- `cvx_set` (`ConstrainedZonotope` / `Ellipsoid` / `Polytope`) – Set for which area is to be computed
- `area_grid_step_size` (`int` / `float`) – Scalar step size that is constant in both dimensions

Raises

`ValueError` – When set is not 2-dimensional

Returns

Approximate area of the set

Return type

`float`

Notes

This function creates a 2D grid of points with a given step size, and computes the fraction of points that lie in the set. Consequently, the computed area is an approximation of the actual area of the set. The area of the bounding box is computed using the `minimum_volume_circumscribing_rectangle()` method associated with the set.

`pycvxset.common.is_constrained_zonotope(Q: Any) → bool`

Check if the set is a constrained zonotope

Parameters

`Q (object)` – Set to check

Returns

Returns True if the set is a constrained zonotope, False otherwise

Return type

`bool`

`pycvxset.common.is_ellipsoid(Q: Any) → bool`

Check if the set is an ellipsoid

Parameters

`Q (object)` – Set to check

Returns

Returns True if the set is an ellipsoid, False otherwise

Return type

bool

`pycvxset.common.is_polytope(Q: Any) → bool`

Check if the set is a polytope

Parameters

`Q (object)` – Set to check

Returns

Returns True if the set is a polytope, False otherwise

Return type

bool

`pycvxset.common.prune_and_round_vertices(V: Sequence[Sequence[float]] | ndarray, decimal_precision: int = 3) → ndarray`

Filter through the vertices to skip any point that has another point (down in the list) that is close to it in the list.

Parameters

- `V (Sequence[Sequence[float]] / np.ndarray)` – Matrix of vertices (N times self.dim)
- `decimal_precision (int, optional)` – The decimal precision for rounding the vertices. Defaults to PLOTTING_DECIMAL_PRECISION_CDD from pycvxset.common.constants.

Returns

The pruned and rounded array of vertices.

Return type

numpy.ndarray

`pycvxset.common.spread_points_on_a_unit_sphere(dim: int, n_points: int | None = None, cvxpy_socp_args: dict[str, Any] | None = None, verbose: bool = False, enable_warning: bool = True, save_points_on_a_unit_sphere: bool = True) → tuple[ndarray, float, ndarray]`

Spread points on a unit sphere in n-dimensional space.

Parameters

- `dim (int)` – The dimension of the sphere.
- `n_points (int)` – The number of points to be spread on the unit sphere. Defaults to None, in which case, we choose `= (n_points)`
- `cvxpy_socp_args (dict)` – Additional arguments to be passed to the CVXPY solver. Defaults to None, in which case the function uses DEFAULT_CVXPY_ARGS_SOCP from pycvxset.common.constants.
- `verbose (bool, optional)` – Whether to print verbose output. Defaults to False.
- `enable_warning (bool, optional)` – Enables the UserWarning. May be turned off if expected. Defaults to True.
- `save_points_on_a_unit_sphere (bool, optional)` – Whether to save the computed points and minimum separation to a file. Defaults to SPOAUS_SAVE_POINTS_ON_A_UNIT_SPHERE.

Returns

A tuple containing three items:

opt_locations (ndarray): The spread points on the unit sphere.
minimum_separation (float): The minimum separation between the points.
opt_locations_first_quad (ndarray): The spread points in the first quadrant.

Return type

tuple

Raises

- **ValueError** – If n_points is less than 2 * dim.
- **UserWarning** – If n_points - 2 * dim is not a multiple of 2^dim.
- **NotImplementedError** – Unable to solve the convexified problem using CVXPY
- **NotImplementedError** – Convex-concave procedure did not converge!

Notes

This function uses the CVXPY library to solve a convex optimization problem to spread the points on the unit sphere. The spread points are returned as opt_locations, the separation between the points is returned as separation, and the spread points in the first quadrant are returned as opt_locations_first_quad.

For dim in [1, 2], the points are available in closed-form. For dim >= 3, we solve the following non-convex optimization problem using convex-concave procedure:

$$\begin{aligned} \text{maximize} \quad & R \\ \text{subject to} \quad & R \geq 0 \\ & x \geq R/2 \\ & \|x_i - x_j\| \geq R, \quad 1 \leq i < j \leq n_{\text{points}} \\ & \|x_i - e_j\| \geq R, \quad 1 \leq i \leq n_{\text{points}}, 1 \leq j \leq n_{\text{dim}} \\ & \|x_i\| \leq 1, \quad 1 \leq i \leq n_{\text{points}} \\ & \|x_i\| \geq 0.8, \quad 1 \leq i \leq n_{\text{points}} \end{aligned}$$

The optimization problem seeks to spread points (apart from the standard axes) in the first quadrant so that their pairwise separation is maximized, while they have a norm close to 1. The second constraint is motivated to ensure that the reflections of the points about the quadrant plane is also separated by R.

When `save_points_on_a_unit_sphere` is True, the function saves the computed points (all), the computed points in the first quadrant, and the minimum separation to a file named `tmp/spoaus_dim_{dim}_n_points_{n_points_int}.npz`. If the file already exists, the function loads the points and minimum separation from the file instead of recomputing them. This can save time when calling `spread_points_on_a_unit_sphere` with default values.

PYCVXSET.COMMON.CONSTANTS

The following provides the default constants used in pycvxset.

```
1 # Copyright (C) 2020-2026 Mitsubishi Electric Research Laboratories (MERL)
2 #
3 # SPDX-License-Identifier: AGPL-3.0-or-later
4
5 # Code purpose: Specify the constants to be used with cvxpy when optimization_
6 # problems as well as testing workflows
7
8 PYCVXSET_ZERO = 1e-6 # Zero threshold for numerical stability
9 PYCVXSET_ZERO_GUROBI = 1e-5 # Zero threshold for numerical stability when using_
10 # GUROBI
11 # Zero threshold for vertex clustering when computing polytopic inner-approximation_
12 # of constrained zonotopes
13 PYCVXSET_ZERO_CDD = 1e-5
14 PLOTTING_DECIMAL_PRECISION_CDD = 3
15
16 # Solvers used by default
17 DEFAULT_LP_SOLVER_STR = "CLARABEL" # CLARABEL, MOSEK, CVXOPT, SCS, ECOS, GUROBI, OSQP
18 DEFAULT_SOCP_SOLVER_STR = "CLARABEL" # CLARABEL, MOSEK, CVXOPT, SCS, ECOS, GUROBI
19 DEFAULT_SDPA_SOLVER_STR = "SCS" # CLARABEL, MOSEK, CVXOPT, SCS
20
21 # CVXPY args used by default (use "reoptimize": True when using GUROBI)
22 DEFAULT_CVXPY_ARGS_LP = {"solver": DEFAULT_LP_SOLVER_STR}
23 DEFAULT_CVXPY_ARGS_SOCP = {"solver": DEFAULT_SOCP_SOLVER_STR}
24 DEFAULT_CVXPY_ARGS_SDP = {"solver": DEFAULT_SDPA_SOLVER_STR}
25
26 # Constants for spread_points_on_a_unit_sphere (SPOAUS)
27 SPOAUS_SLACK_TOLERANCE = 1e-8
28 SPOAUS_COST_TOLERANCE = 1e-5
29 SPOAUS_INITIAL_TAU = 1.0
30 SPOAUS_SCALING_TAU = 1.1
31 SPOAUS_TAU_MAX = 1e4
32 SPOAUS_ITERATIONS_AT_TAU_MAX = 20
33 SPOAUS_MINIMUM_NORM_VALUE_SQR = 0.8**2
34 # For SPOAUS_DIRECTIONS_PER_QUADRANT=20, we have 2D = 84, 3D = 166, 4D = 328, 5D = 650
35 SPOAUS_DIRECTIONS_PER_QUADRANT = 20
36 SPOAUS_SAVE_POINTS_ON_A_UNIT_SPHERE = True
37
38 # Time limit
39 TIME_LIMIT_FOR_CONSTRAINED_ZONOTYPE_CONTAINMENT_GUROBI_IN_S = 60
40
41 # Testing workflow constants | You could also do "GUROBI" in cvxpy.installed_solvers()
42 # "no", "minimal", "full" ("minimal", "full" need GUROBI license set up / connection_
43 # to a gurobi license server)
```

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```
40 # "full" also tests spread_points_on_a_unit_sphere with SPOAUS_DIRECTIONS_PER_
41 →QUADRANT for 3D
42 TESTING_STATEMENTS_INCLUDING_GUROBI = "minimal" # (Default: minimal)
43 TESTING_SHOW_PLOTS = False
44
45 # Plotting constants for polytopes
46 DEFAULT_PATCH_ARGS_2D = {"edgecolor": "k", "facecolor": "skyblue"}
47 DEFAULT_PATCH_ARGS_3D = {"edgecolor": "k", "facecolor": None}
48 DEFAULT_VERTEX_ARGS = {"visible": False, "s": 30, "marker": "o", "color": "k"}
49
50 # Default constants for qhull options
51 # Be resilient to slight degeneracies by default
52 DEFAULT_QHULL_OPTIONS = ""
53 # Prefer QHULL over CDD for vertex-facet enumerations (plot still uses CDD)
54 PREFER_QHULL_OVER_CDD = False
```

CHAPTER
SEVENTEEN

TUTORIALS

We provide several tutorials to help you get started with *pycvxset*. The tutorials are designed to be run in a Jupyter notebook, which allows you to interact with the code and experiment with the library. The tutorials are available in the *docs/examples/* directory of *pycvxset*.

For your convenience, we provide a link to the tutorials below:

1. Polytope
2. ConstrainedZonotope
3. Application: Reachability using Polytope/ConstrainedZonotope classes
4. Code snippets used in ACC 2025 tool paper

In the above tutorials, we demonstrate how to use *pycvxset* to perform various operations on polytopes, ellipsoids, and constrained zonotopes. We also provide an application example that demonstrates the use of *pycvxset* in reachability analysis. The tutorials are designed to be self-contained, and we encourage you to run them in a Jupyter notebook to understand the code and experiment with the library.

**CHAPTER
EIGHTEEN**

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