

# Constrained optimization

Nicolas Mansard

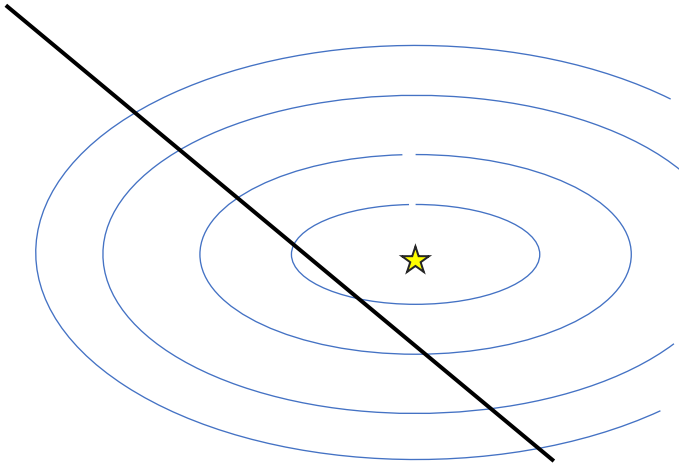
Gepetto  
LAAS-CNRS & ANITI



# Optimization with constraint

- Linearly-Constrained Quadratic Program (LCQP)

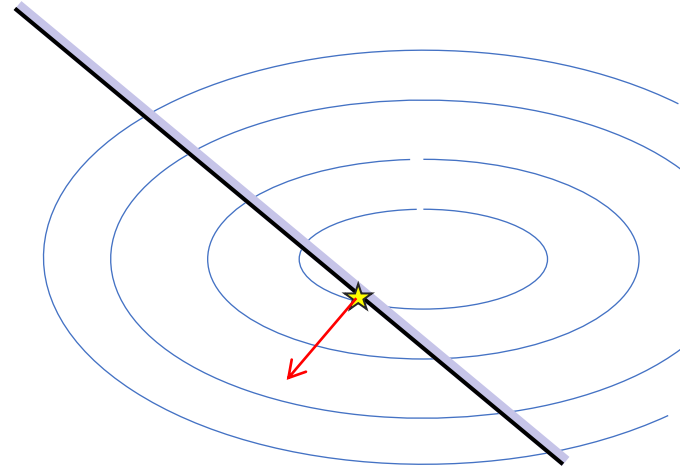
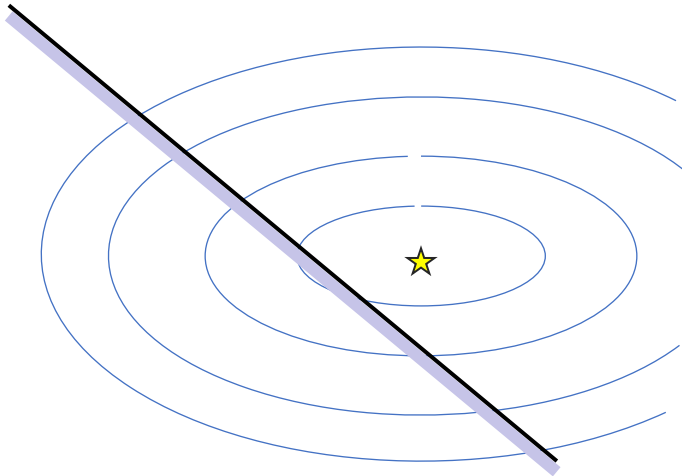
$$\begin{array}{ll} \min_x & ||Ax - b||^2 \\ \text{s.t.} & Cx = d \end{array}$$



# Optimization with constraint

- Linearly-Constrained Quadratic Program (LCQP)

$$\begin{array}{ll} \min_x & ||Ax - b||^2 \\ \text{s.t.} & Cx \leq d \end{array}$$



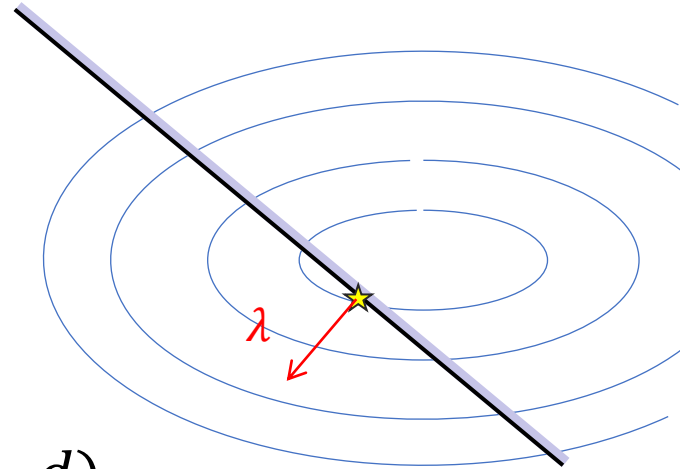
# Optimization with constraint

- Linearly-Constrained Quadratic Program (LCQP)

$$\begin{array}{ll} \min_x & ||Ax - b||^2 \\ \text{s.t.} & Cx \leq d \end{array}$$

$\lambda$  is called a Lagrange multiplier

$$\mathcal{L}(x, \lambda) = ||Ax - b||^2 + \lambda^T (Cx - d)$$



# Duality in optimization

- The dual variable is an auxiliary quantity
  - Needed to assert the optimality condition

$$\min_x \max_{\lambda} \mathcal{L}(x, \lambda)$$

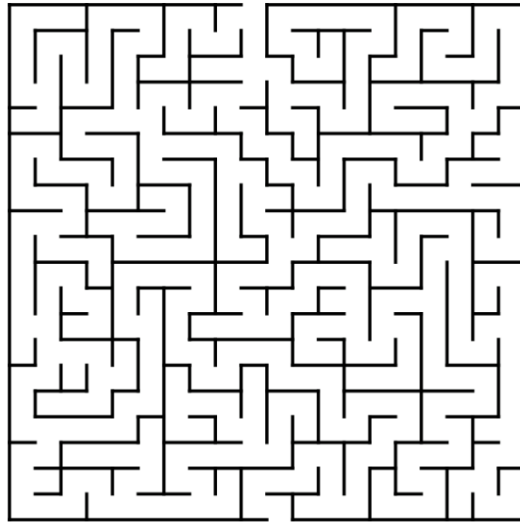
$$\begin{array}{ll} \min_x & c^T x \\ \text{s.t.} & Ax \geq b \end{array} \quad (\text{LP})$$

*Primal problem*

$$\begin{array}{ll} \max_{\lambda} & b^T \lambda \\ \text{s.t.} & A^T \lambda = c, \lambda \geq 0 \end{array} \quad (\text{LP}^*)$$

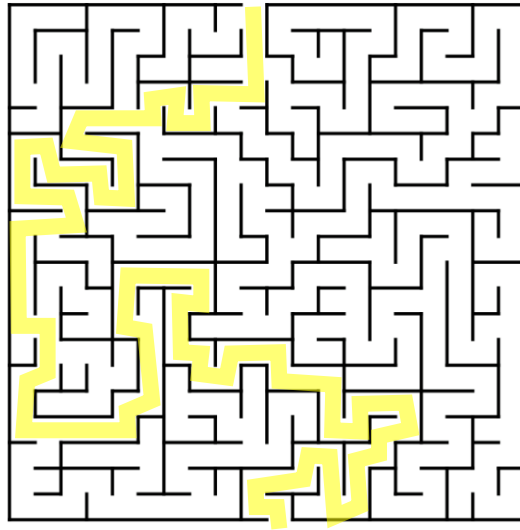
*Dual problem*

# Duality in optimization



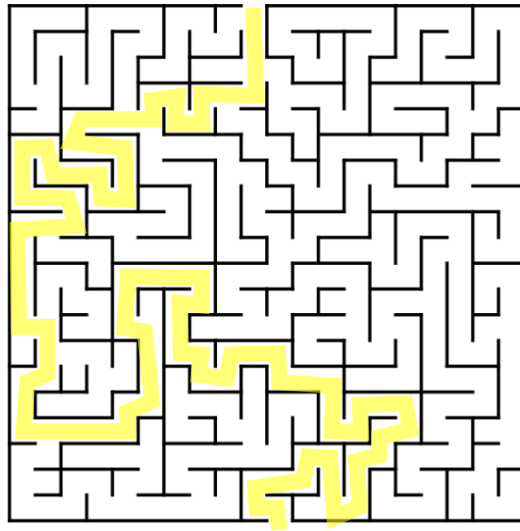
IS IT FEASIBLE ?

# Duality in optimization

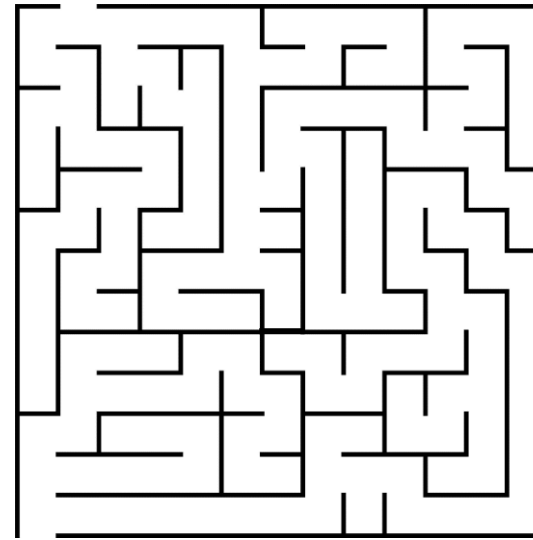


Feasible = I can demonstrate the  
existence of a path

# Duality in optimization



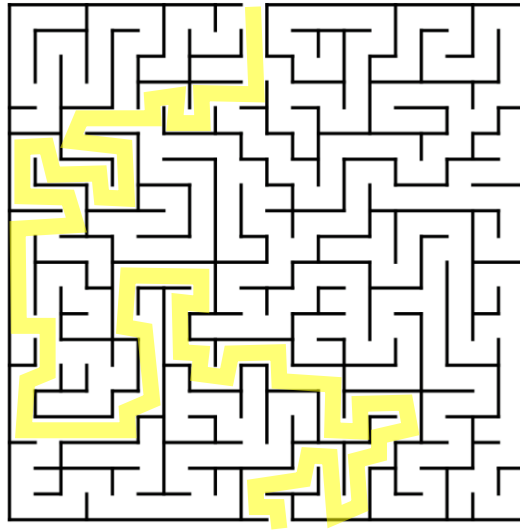
Feasible = I can demonstrate the existence of a path



IS THIS ONE FEASIBLE ?

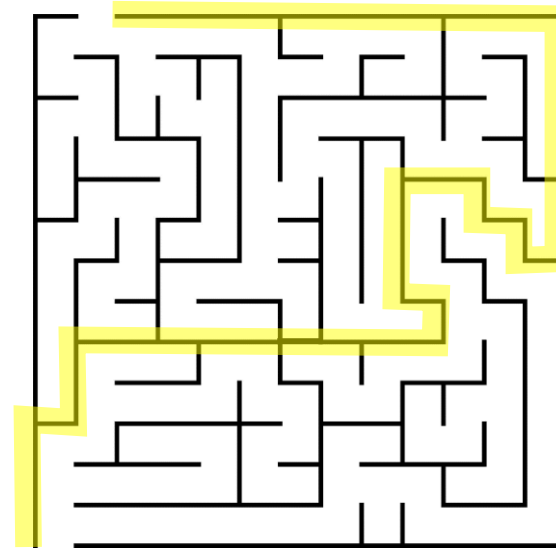


# Duality in optimization



Feasible = I can demonstrate the existence of a path

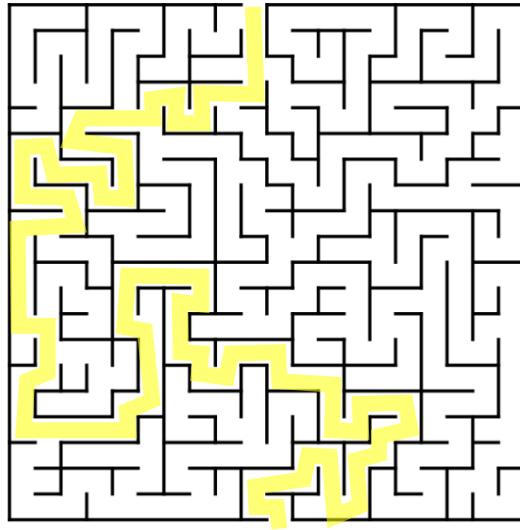
white



Unfeasible = I can demonstrate the  
existence of a wall

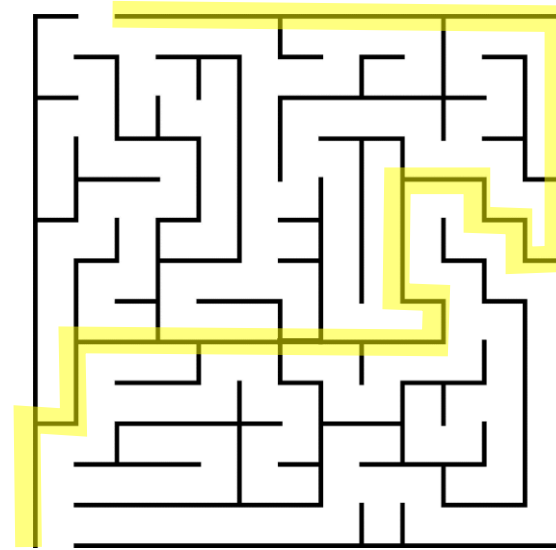
black path

# Duality in optimization



Feasible = I can demonstrate the existence of a path

### Primal problem



Unfeasible = I can demonstrate the existence of a wall

### Dual problem

# KKT conditions

$$\begin{array}{ll} \min_x & c(x) \\ \text{s. t.} & g(x) \geq 0 \end{array}$$

- $x, \lambda$  are solutions if they respects:

$$\mathcal{L}(x, \lambda) = c(x) - \lambda^T g(x) \quad \text{Lagrangian}$$

$$\nabla_x \mathcal{L} = \nabla c - \lambda^T \nabla g = 0 \quad \text{Gradient normal to constraints}$$

$$\nabla_\lambda \mathcal{L} = g(x) \geq 0 \quad \text{Constraint satisfied}$$

$$\lambda^T g(x) = 0 \quad \text{Complementarity}$$

# Dynamics for simulation

- Complementarity problem

$$\ddot{q} = M^{-1}(\tau - b + J^T f)$$

$$J\ddot{q} + \dot{J}\dot{q} \geq 0 \quad \perp \quad f \geq 0$$

*no penetration*

*no pulling*

*one or the other*

- Equivalent to a principled QP

$$\min_{\ddot{q}} \|\ddot{q} - \ddot{q}_{free}\|_M \quad \text{s.t.} \quad J\ddot{q} + \dot{J}\dot{q} \geq 0$$