ECE 6553: Optimal Control Notes

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Contents

Chapter 1

Parameter Optimization

1.1 What is optimal control?

Optimal   Maximize/minimize cost (subject to constraints): $\min_u g(u)$
With constraints,
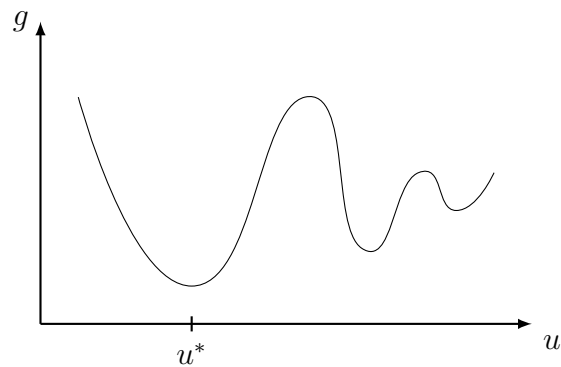
$$\min_u \ g(u)$$

$$\text{s.t.} \ \begin{cases} h_1(u) = 0 \\ h_2(u) \leq 0 \end{cases}$$

First-order necessary condition (FONC):

$$\frac{\partial g}{\partial u}(u^*) = 0$$

Optimality can be

- local vs global

- max vs min

Control control design: pick u such that specifications are satisfied:

$$\dot{x} = f(x, u), \qquad \dot{x} = Ax + Bu,$$

where $x(t) \in \mathbb{R}^n$ is the state, $u(t) \in \mathbb{R}^m$ is the control, and $f(\cdot)$ is the dynamics.
Actually, x and u are signals:

$$x : [0, T] \to \mathbb{R}^n, \qquad u : [0, T] \to \mathbb{R}^m$$

Optimal control find the "best" u!
For "best" to mean anything, we need a cost. The big/deep question is

$$\frac{\partial \text{"cost"}}{\partial u} = 0$$

Example
Suppose we have a car with position p. Its acceleration $\ddot{p}$ is controlled by the gas/brake input u ($\ddot{p} = u$). In order to express the dynamics of the system in the form $\dot{x} = f(x, u)$, we introduce state variables:

$$\begin{aligned} x_1 &= p \\ x_2 &= \dot{p} \end{aligned} \implies \begin{cases} \dot{x}_1 = x_2 \\ \dot{x}_2 = u \end{cases}$$

The task is to move the car from its initial position to a stop at a distance c away.

Minimum energy problem

$$\min_u \int_0^T u^2(t) \, \mathrm{d}t$$

$$\text{s.t.} \quad \begin{cases} \dot{x}_1 = x_2 \\ \dot{x}_2 = u \end{cases}$$

$$x_1(0) = 0, \ x_2(0) = 0$$
$$x_1(T) = c, \ x_2(T) = 0$$

Minimum time problem

$$\min_{u,T} \ T = \int_0^T \mathrm{d}t$$

$$\text{s.t.} \quad \begin{cases} \dot{x}_1 = x_2 \\ \dot{x}_2 = u \end{cases}$$

$$x_1(0) = 0, \ x_2(0) = 0$$
$$x_1(T) = c, \ x_2(T) = 0$$
$$u(t) \in [u_{\min}, u_{\max}]$$

The general optimal control problem we will solve will look like

$$\min_{u,T} \int_0^T L(x(t), u(t), t)\, \mathrm{d}t + \Psi(x(T))$$
$$\text{s.t. } \dot{x}(t) = f(x(t), u(t), t),\ t \in [0, T]$$
$$x(0) = x_0$$
$$x(T) \in S$$
$$u(t) \in \Omega,\ t \in [0, T]$$

where $\Psi(\cdot)$ is the terminal cost and S is the terminal manifold. This is a so-called **Bolza Problem**.

What tools do we need to solve this?

1. optimality conditions $\partial \text{cost}/\partial u = 0$

2. some way of representing the optimal signal $u^*(x, t)$

3. some way of actually finding/computing the optimal controllers

1.2   Unconstrained Optimization

Let the decision variable be $u = [u_1, \ldots, u_m]^{\mathrm{T}} \in \mathbb{R}^m$. The cost is $g(u) \in C^1$ (C^k means k times continuously differentiable). The problem is

$$\min_u g(u), \quad g : \mathbb{R}^m \to \mathbb{R}$$

For u^* to be a minimizer, we need

$$\frac{\partial g}{\partial u}(u^*) = 0$$

Definition. u^* is a (local) minimizer to g if $\exists \delta > 0$ s.t.

$$g(u^*) \leq g(u) \quad \forall u \in B_\delta(u^*)$$
$$B_\delta(u^*) = \{u \mid \|u - u^*\| \leq \delta\}$$

Note:

- $\frac{\partial g}{\partial u}(u^*)\delta u \in \mathbb{R}$ and δu is $m \times 1$, so $\frac{\partial g}{\partial u}$ is a $1 \times m$ row vector. For the column vector,

$$\nabla g = \frac{\partial g^{\mathrm{T}}}{\partial u} \in \mathbb{R}^m$$

- $\frac{\partial g}{\partial u}\delta u$ is an inner product

$$\langle \nabla g, \delta u \rangle = \left\langle \frac{\partial g^{\mathrm{T}}}{\partial u}, \delta u \right\rangle$$

- $o(\varepsilon)$ encodes higher-order terms

$$\lim_{\varepsilon \to 0} \frac{o(\varepsilon)}{\varepsilon} = 0 \qquad \text{``faster than linear''}$$

This is opposed to big-O notation:

$$\lim_{\varepsilon \to 0} \frac{\mathcal{O}(\varepsilon)}{\varepsilon} = c$$

- δu has direction and scale so we could write it as

$$\delta u = \varepsilon v, \quad \varepsilon \in \mathbb{R}, \ v \in \mathbb{R}^m$$

Theorem. *For u^* to be a minimizer, we need*

$$\frac{\partial g}{\partial u}(u^*) = 0$$

or, equivalently,

$$\frac{\partial g}{\partial u}(u^*)v = 0 \quad \forall v \in \mathbb{R}^m$$

Proof. Let u^* be a minimizer. Evaluating the cost $g(u)$ in the ball and using Taylor's expansion,

$$g(u^* + \delta u) = g(u^*) + \frac{\partial g}{\partial u}(u^*)\delta u + o(\|\delta u\|) = g(u^*) + \varepsilon \frac{\partial g}{\partial u}(u^*)v + o(\varepsilon)$$

Assume that $\frac{\partial g}{\partial u} \neq 0$. Then we could pick $v = -\frac{\partial g^{\mathrm{T}}}{\partial u}(u^*)$, i.e.

$$g(u^* + \varepsilon v) = g(u^*) - \varepsilon \left\| \frac{\partial g^{\mathrm{T}}}{\partial u}(u^*) \right\|^2 + o(\varepsilon)$$

Note that the second term is negative per our assumptions. So, for ε sufficiently small, we have

$$g\left(u^* - \varepsilon \frac{\partial g^{\mathrm{T}}}{\partial u}(u^*) \right) < g(u^*)$$

This contradicts u^* being a minimizer. ⚔ (crossed swords) □

Definition (Positive definite). $M = M^{\mathrm{T}} \succ 0$ if

$$z^{\mathrm{T}} M z > 0 \quad \forall z \neq 0, \ z \in \mathbb{R}^m$$
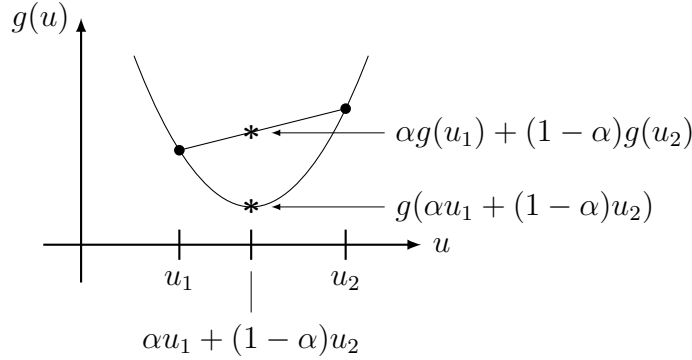$$\iff M \text{ has real and positive eigenvalues}$$

Theorem. *If $g \in C^2$, then a **sufficient** condition for u^* to be a (local) minimizer is*

1. $\dfrac{\partial g}{\partial u}(u^*) = 0$

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2. $\frac{\partial^2 g}{\partial u^2}(u^*) \succ 0$ *(the Hessian is positive definite)*

Definition. $g : \mathbb{R}^m \to \mathbb{R}$ is convex if

$$g(\alpha u_1 + (1-\alpha)u_2) \leq \alpha g(u_1) + (1-\alpha)g(u_2) \quad \forall \alpha \in [0,1], \ u_1, u_2 \in \mathbb{R}^m$$

Theorem. *If $\frac{\partial^2 g}{\partial u^2}(u) \succeq 0 \ \forall u \in \mathbb{R}^m$, then g is convex. ($\iff$ for $g \in C^2$)*

Example $\min\limits_{u} u^{\mathrm{T}}Qu - b^{\mathrm{T}}u$ where $Q = Q^{\mathrm{T}} \succ 0$ (positive definite matrix)

$$\begin{aligned}
\frac{\partial g}{\partial u} &= \frac{\partial}{\partial u}(u^{\mathrm{T}}Qu - b^{\mathrm{T}}u) \\
&= u^{\mathrm{T}}Q^{\mathrm{T}} + u^{\mathrm{T}}Q - b^{\mathrm{T}} \\
&= 2u^{\mathrm{T}}Q - b^{\mathrm{T}} \\
\frac{\partial^2 g}{\partial u^2} &= 2Q
\end{aligned}$$

$$\frac{\partial^2 g}{\partial u^2} = \begin{bmatrix} \frac{\partial^2 g}{\partial u_1^2} & \cdots & \frac{\partial^2 g}{\partial u_1 \partial u_m} \\ \vdots & \ddots & \vdots \\ \frac{\partial^2 g}{\partial u_m \partial u_1} & \cdots & \frac{\partial^2 g}{\partial u_m^2} \end{bmatrix}$$

From $\frac{\partial g}{\partial u} = 2u^{\mathrm{T}}Q - b^{\mathrm{T}} = 0$,

$$u = \frac{1}{2}Q^{-1}b$$

To see whether this is a minimizer, consider the Hessian. Since $Q \succ 0$, it follows that $\frac{\partial^2 g}{\partial u^2}(u^*) \succ 0$ and $u^* = \frac{1}{2}Q^{-1}b$ is a (local) minimizer. Additionally, since $\frac{\partial^2 g}{\partial u^2} \succ 0$, g is convex and u^* is a global minimizer. In fact, since we have strict convexity ($\succ 0$ rather than $\succeq 0$), it is the unique global minimizer.

In optimal control, *local* is typically all we can ask for. In optimization, we can do better! But wait, just because we know $\frac{\partial g}{\partial u} = 0$, it doesn't follow that we can actually find $u^*\ldots$

1.3 Numerical Methods

Idea: $u_{k+1} = u_k + \text{step}_k$. What should step_k be? For small $\text{step}_k = \gamma_k v_k$,

$$g(u_k \cdot \text{step}_k) = g(u_k) + \frac{\partial g}{\partial u}(u_k) \cdot \text{step}_k + o(\|\text{step}_k\|) = g(u_k) + \gamma_k \frac{\partial g}{\partial u}(u_k)v_k + o(\gamma_k)$$

A perfectly reasonable choice of step direction is

$$v_k = -\frac{\partial g^{\mathrm{T}}}{\partial u}(u_k),$$

known as the *steepest descend* direction. This produces

$$g\left(u_k - \gamma_k \frac{\partial g}{\partial u}(u_k)\right) = g(u_k) - \gamma_k \left\|\frac{\partial g}{\partial u}(u_k)\right\|^2 + o(\gamma_k)$$

Steepest descent

$$u_{k+1} = u_k - \gamma_k \frac{\partial g^{\mathrm{T}}}{\partial u}(u_k)$$

Note:

- What should γ_k be?

- This method "pretends" that $g(u)$ is linear. If we pretend $g(u)$ is quadratic, we get

$$u_{k+1} = u_k - \left(\frac{\partial^2 g}{\partial u^2}(u_k)\right)^{-1} \frac{\partial g^{\mathrm{T}}}{\partial u}(u_k),$$
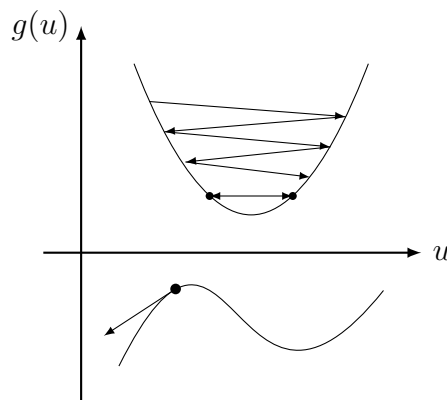
  i.e. Newton's Method

This course: steepest descent

Step-size selection?

- Choice 1: $\gamma_k = \gamma$ "small" $\forall k$; will get close to a minimizer if u_0 is close enough and γ small enough

  Problems:
  - You may not converge! (but you'll get close)
  - You may go off to infinity (diverge)

- Choice 2: Reduce γ_k as a function of k; will get close to a minimizer if u_0 is close enough

  Problem: slow

  Theorem. *If u_0 is close enough to u^* and γ_k satisfies*

  $$- \sum_{k=0}^{\infty} \gamma_k = \infty$$

  $$- \sum_{k=0}^{\infty} \gamma_k^2 < \infty$$

  e.g. $\gamma_k = c/k$, then $u_k \to u^*$ as $k \to \infty$.

- Choice 3: **Armijo step-size:** Take as big a step as possible, but no larger

  Pick $\alpha \in (0,1)$, $\beta \in (0,1)$. Let i be the smallest non-negative integer such that

  $$g\left(u_k - \beta^i \frac{\partial g^{\mathrm{T}}}{\partial u}(u_k)\right) - g(u_k) < -\alpha\beta^i \left\|\frac{\partial g}{\partial u}(u_k)\right\|^2$$

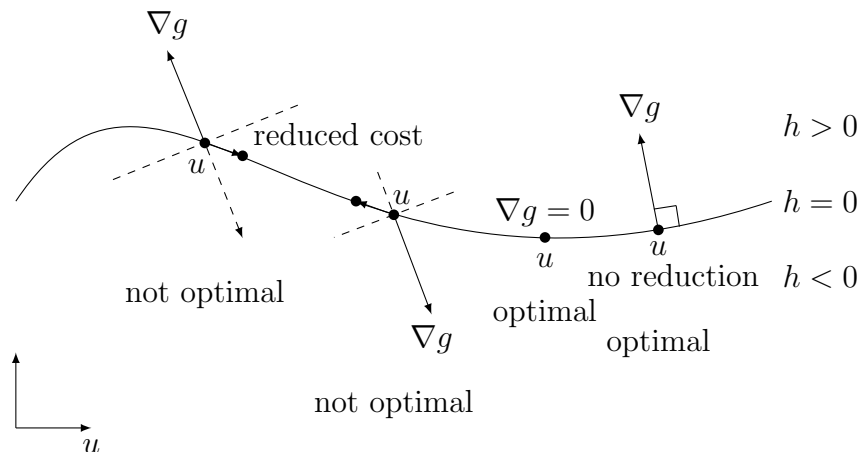 $$u_{k+1} = u_k - \beta^i \frac{\partial g^{\mathrm{T}}}{\partial u}(u_k)$$

  This will get to a minimizer blazingly fast if u_0 is close enough.

1.4 Constrained Optimization

Equality constraints:

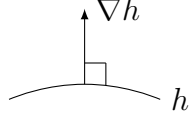$$\min_{u \in \mathcal{R}^m} \; g(u)$$

$$\text{s.t. } h(u) = \mathbf{0}$$

Consider $u \in \mathbb{R}^2$, $h : \mathbb{R}^2 \to \mathbb{R}$

So u is (locally) optimal if $\nabla g \parallel$ (is parallel to) the normal vector to tangent plane to h.

Fact: (HW# 1)
$$\nabla h \perp Th \quad \text{(tangent plane to h)}$$

We need $\nabla g \parallel \nabla h$ at u^* for optimality, i.e.
$$\frac{\partial g}{\partial u}(u^*) = \alpha \frac{\partial h}{\partial u}(u^*), \quad \text{for some } \alpha \in \mathbb{R}$$

or ($\lambda = -\alpha$),
$$\frac{\partial g}{\partial u}(u^*) + \lambda \frac{\partial h}{\partial u}(u^*) = 0$$

or
$$\frac{\partial}{\partial u}\big(g(u^*) + \lambda h(u^*)\big) = 0, \quad \text{for some } \lambda \in \mathbb{R}$$

More generally,
$$\min_{u \in \mathcal{R}^m} \; g(u)$$
$$\text{s.t. } h(u) = \mathbf{0}, \quad h : \mathbb{R}^m \to \mathbb{R}^k$$

Note that $h(u) = [h_1(u), \ldots, h_k(u)]^{\mathrm{T}}$.

We need $\frac{\partial g}{\partial u}(u^*)$ to be a linear combination of $\frac{\partial h_i}{\partial u}(u^*)$, $i = 1, \ldots, k$, for exactly the same reasons, i.e.
$$\frac{\partial g}{\partial u}(u^*) = \sum_{i=1}^{k} \alpha_i \frac{\partial h_i}{\partial u}(u^*)$$

or ($\lambda = -[\alpha_1, \ldots, \alpha_k]^{\mathrm{T}}$)
$$\frac{\partial g}{\partial u}(u^*) + \lambda^{\mathrm{T}} \frac{\partial h}{\partial u}(u^*) = 0$$

or
$$\frac{\partial}{\partial u}\big(g(u^*) + \lambda^{\mathrm{T}} h(u^*)\big) = 0, \quad \text{for some } \lambda \in \mathbb{R}^k$$

Theorem. *If u^* is a minimizer to*
$$\min_{u \in \mathcal{R}^m} \; g(u)$$
$$\text{s.t. } h(u) = \mathbf{0}, \quad h : \mathbb{R}^m \to \mathbb{R}^k$$

then $\exists \lambda \in \mathbb{R}^k$ s.t.
$$\begin{cases} \dfrac{\partial L}{\partial u}(u^*, \lambda) = 0 \\[2mm] \dfrac{\partial L}{\partial \lambda}(u^*, \lambda) = 0 \end{cases}$$

where the Lagrangian L is given by
$$L(u, \lambda) = g(u) + \lambda^T h(u)$$

Note:

- λ are the Lagrange multipliers

- $\frac{\partial L}{\partial \lambda} = 0$ is fancy speak for $h(u^*) = 0$

Example

$$\min_{u \in \mathbb{R}^m} \ \frac{1}{2}\|u\|^2$$
$$\text{s.t. } Au = b$$

where A is $k \times m$, $k \leq m$. Assume $(AA^{\mathrm{T}})^{-1}$ exists (constraints are linearly independent, none of the constraints are "duplicates", all the constraints are essential).

$$L = \frac{1}{2}u^{\mathrm{T}}u + \lambda^{\mathrm{T}}(Au - b)$$
$$\frac{\partial L}{\partial u} = u^{\mathrm{T}} + \lambda^{\mathrm{T}}A = 0$$
$$u^* = -A^{\mathrm{T}}\lambda$$

Using the equality constraint,

$$Au^* = b$$
$$-AA^{\mathrm{T}}\lambda = b$$
$$\lambda = -(AA^{\mathrm{T}})^{-1}b$$
$$u^* = A^{\mathrm{T}}(AA^{\mathrm{T}})^{-1}b$$

Example

$$\min \ u_1 u_2 + u_2 u_3 + u_1 u_3$$
$$\text{s.t. } u_1 + u_2 + u_3 = 3$$

$$L = u_1 u_2 + u_2 u_3 + u_1 u_3 + \lambda(u_1 + u_2 + u_3 - 3)$$

$$\begin{cases} \frac{\partial L}{\partial u_1} = u_2 + u_3 + \lambda = 0 \\ \frac{\partial L}{\partial u_2} = u_1 + u_3 + \lambda = 0 \\ \frac{\partial L}{\partial u_3} = u_2 + u_1 + \lambda = 0 \\ \frac{\partial L}{\partial \lambda} = u_1 + u_2 + u_3 = 3 \end{cases} \implies \begin{cases} u_1^* = 1 \\ u_2^* = 1 \\ u_3^* = 1 \\ \lambda = -2 \end{cases} \quad \text{optimal solution}$$

Note: This was actually the worst we can do—maximize! Even weirder: no local minimizer!

1.4.1 Equality Constraints

$$\min_{u \in \mathcal{R}^m} \; g(u)$$

$$\text{s.t. } h(u) = \mathbf{0}, \quad h : \mathbb{R}^m \to \mathbb{R}^k$$

Theorem. *If u^* is a minimizer/maximizer then $\exists \lambda \in \mathbb{R}^k$ s.t.*

$$\frac{\partial L}{\partial u}(u^*, \lambda) = 0$$

$$\frac{\partial L}{\partial \lambda}(u^*, \lambda) = 0 \qquad (\Longleftrightarrow h(u^*) = 0)$$

where $L(u, \lambda) = g(u) + \lambda^T h(u)$.

Example [Entropy Maximization]

Given $S = \{x_1, \ldots, x_n\}$ and a distribution over S such that it takes the value x_j with probability p_j. The entropy is

$$E(p) = \sum_{j=1}^{n} (-p_j \ln p_j).$$

The mean is

$$m = \sum_{j=1}^{n} p_j x_j.$$

Problem: Given m, find p such that E is maximized.

$$\min_{p} \; -\sum_{j=1}^{n} p_j \ln p_j$$

$$\text{s.t. } \sum_{j=1}^{n} p_j x_j = m$$

$$\sum_{j=1}^{n} p_j = 1$$

$$p_j \geq 0, \; j = 1, \ldots, n \quad \text{(ignore this\ldots)}$$

$$L = -\sum p_j \ln p_j + \lambda_1 \left[\sum p_j x_j - m \right] + \lambda_2 \left[\sum p_j - 1 \right]$$

$$\frac{\partial L}{\partial p_j} = -\ln p_j - 1 + \lambda_1 x_j + \lambda_2 = 0$$

$$p_j = e^{\lambda_2 - 1 + \lambda_1 x_j}, \quad j = 1, \ldots, n \qquad (p_j \geq 0 \text{ so we're ok with ignoring that})$$

$$\sum e^{\lambda_2 - 1 + \lambda_1 x_j} x_j = m \qquad\qquad n + 2 \text{ equations and}$$

$$\sum e^{\lambda_2 - 1 + \lambda_1 x_j} = 1 \qquad\qquad n + 2 \text{ unknowns\ldots}$$

No analytical solution, but numerically "solvable"

1.4.2 Inequality Constraints

$$\min_{u \in \mathcal{R}^m} \ g(u)$$

$$\text{s.t. } h(u) \le \mathbf{0}, \quad h : \mathbb{R}^m \to \mathbb{R}^k$$
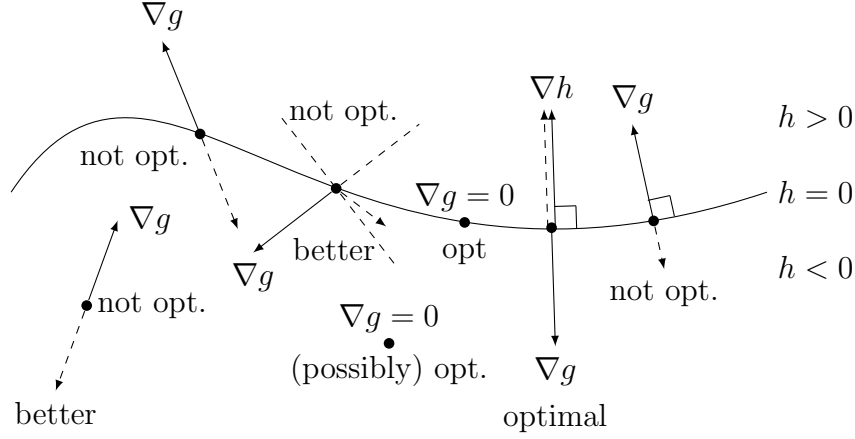
We need:

- if $h(u^*) < 0$ then $\frac{\partial g}{\partial u}(u^*) = 0$

- if $h(u^*) = 0$ then we need either

$$\frac{\partial g}{\partial u}(u^*) = 0$$

or

$$\frac{\partial g}{\partial u}(u^*) = -\lambda \frac{\partial h}{\partial u}(u^*) \quad \text{for } \lambda > 0$$

Or, even better,

$$\frac{\partial}{\partial u}\left(g(u^*) + \lambda h(u^*)\right) = 0 \quad \text{for } \lambda \ge 0,$$

where $\lambda h(u^*) = 0$. ($h < 0 \to \lambda = 0$, $h = 0 \to \lambda \ge 0$)

In general, if $u \in \mathbb{R}^m$ and $h : \mathbb{R}^m \to \mathbb{R}^k$, we have that u^*, if optimal, has to satisfy

$$\frac{\partial}{\partial u} L(u^*, \lambda) = 0$$

$$h(u^*) \le \mathbf{0}$$

$$\lambda^{\mathrm{T}} h(u^*) = 0$$

$$\lambda \ge \mathbf{0}$$

where the Lagrangian is $L(u, \lambda) = g(u) + \lambda^{\mathrm{T}} h(u)$. Note that if we're maximizing, the same holds except we need $\lambda \le 0$.

Example

$$\min \; 2u_1^2 + 2u_1u_2 + u_2^2 - 10u_1 - 10u_2$$

$$\text{s.t.} \; \begin{cases} u_1^2 + u_2^2 \leq 5 \\ 3u_1 + u_2 \leq 6 \end{cases}$$

$$L = 2u_1^2 + 2u_1u_2 + u_2^2 - 10u_1 - 10u_2 + \lambda_1(u_1^2 + u_2^2 - 5) + \lambda_2(3u_1 + u_2 - 6)$$

FONC:

   i) $\partial L/\partial u_1 = 4u_1 + 2u_2 - 10 + 2\lambda_1 u_1 + 3\lambda_2$

   ii) $\partial L/\partial u_2 = 2u_1 + 2u_2 - 10 + 2\lambda_1 u_2 + \lambda_2$

   iii) $u_1^2 + u_2^2 \leq 5$

   iv) $3u_1 + u_2 \leq 6$

   v) $\lambda_1(u_1^2 + u_2^2 - 5) = 0$

   vi) $\lambda_2(3u_1 + u_2 - 6) = 0$

   vii) $\lambda_1 \geq 0$

  viii) $\lambda_2 \geq 0$

To solve, assume different constraints are active/inactive:

1. Both constraints are inactive $(u_1^2 + u_2^2 < 5, \; 3u_1 + u_2 < 6) \implies \lambda_1 = \lambda_2 = 0$

$$\begin{cases} 4u_1 + 2u_2 - 10 = 0 \\ 2u_1 + 2u_2 - 10 = 0 \end{cases} \implies \begin{cases} u_1 = 0 \\ u_2 = 5 \end{cases}$$

   Note: iii) $0^2 + 5^2 \not\leq 5$

   Not feasible

2. Assume constraint 1 is active and constraint 2 is inactive $(u_1^2 + u_2^2 = 5, \; \lambda_2 = 0)$

$$\begin{cases} 4u_1 + 2u_2 - 10 + 2\lambda_1 u_1 = 0 \\ 2u_1 + 2u_2 - 10 + 2\lambda_1 u_2 = 0 \\ u_1^2 + u_2^2 = 5 \end{cases} \implies \begin{cases} u_1 = 1 \\ u_2 = 2 \\ \lambda_1 = 1 \end{cases}$$

   ☑ $\lambda_1 \geq 0$
   ☑ $3 \cdot 1 + 2 \leq 6$

   This is a local minimizer

3. Assume constraint 2 is active and constraint 1 is inactive

4. Assume both constraints are active

Kuhn-Tucker Conditions   (KKT conditions, Karush-Kuhn-Tucker)

Problem:

$$\min_{u \in \mathbb{R}^m} \ g(u)$$

$$\text{s.t.} \ \begin{cases} h_1(u) = 0, & h_1 : \mathbb{R}^m \to \mathbb{R}^p \\ h_2(u) \leq 0, & h_2 : \mathbb{R}^m \to \mathbb{R}^k \end{cases} \tag{1.1}$$

Theorem. *Let u^* be feasible ($h_1 = 0$, $h_2 \leq 0$). If u^* is a minimizer to (1.1) than there exists vectors $\lambda \in \mathbb{R}^p$, $\mu \in \mathbb{R}^k$ with $\mu \geq \mathbf{0}$ such that*

$$\begin{cases} \dfrac{\partial g}{\partial u}(u^*) + \lambda^T \dfrac{\partial h_1}{\partial u}(u^*) + \mu^T \dfrac{\partial h_2}{\partial u}(u^*) = 0 \\ \mu^T h_2(u^*) = 0 \end{cases}$$

Looking ahead: $\min \text{cost}(u(\cdot))$ s.t. $\dot{x} = f(x, u)$ (dynamics), where u is a function. Note the equality constraint.

Question: How do we go from $u \in \mathbb{R}^m$ to $u \in \mathcal{U}$ (function space)?

Note: Function space is a set of functions of a given kind from a set X to a set Y

1. linear function

2. square-integrable functions: $L_2[0, T] : \int_0^T \|u(t)\|^2 \, dt < \infty$

3. $C^\infty(\mathbb{R})$

What would $\partial\text{"cost"}/\partial u$ mean?

1.5   Directional Derivatives

Recall: To minimize $g(u)$, let u^* be a candidate minimizer and pitch a perturbation on u^* of εv, where ε is the scale and v is the direction. Taking Taylor's expansion at the perturbation produces
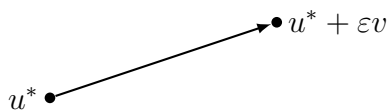
$$g(u^* + \varepsilon v) = g(u^*) + \varepsilon \frac{\partial g}{\partial u}(u^*)v + o(\varepsilon)$$

$$\text{FONC: } \frac{\partial g}{\partial u}(u^*) = 0$$

Note: $\frac{\partial g}{\partial u}(u^*)v$ tells us how much $g(u)$ increases/decreases in the direction of v.

Definition. The directional (Gateaux) derivative is given by

$$\delta g(u; v) = \lim_{\varepsilon \to 0} \frac{g(u + \varepsilon v) - g(u)}{\varepsilon}$$

Example

$$g(u) = \frac{1}{2}u_1^2 - u_1 + 2u_2, \quad g : \mathbb{R}^2 \to \mathbb{R}$$

Let's consider $e_1 = [1\ 0]^{\mathrm{T}}$, $e_2 = [0\ 1]^{\mathrm{T}}$. What is $\delta g(u; e_i)$, $i = 1, 2$?

$$\begin{aligned}
\delta g(u; v) &= \lim_{\varepsilon \to 0} \frac{g(u + \varepsilon v) - g(u)}{\varepsilon} \\
&= \lim_{\varepsilon \to 0} \frac{g(u) + \varepsilon \frac{\partial g}{\partial u}(u)v + o(\varepsilon) - g(u)}{\varepsilon} \\
&= \frac{\partial g}{\partial u}(u)v
\end{aligned}$$

$$\begin{aligned}
\frac{\partial g}{\partial u}(u) &= [u_1 - 1\ \ 2] \\
\delta g(u; e_1) &= [u_1 - 1\ \ 2]e_1 = u_1 - 1 \\
\delta g(u; e_2) &= [u_1 - 1\ \ 2]e_2 = 2
\end{aligned}$$

But the beauty of directional derivatives is that they generalize beyond vectors, $u \in \mathbb{R}^m$, to function spaces ($\mathcal{U}$) or other "objects" like matrices.

Example $M \in \mathbb{R}^{n \times n}$, $F(M) = M^2$
  What is $\frac{\partial F}{\partial M}$? (ponder at home...)
  We can easily compute $\delta F(M; N)$!

$$\begin{aligned}
F(M + \varepsilon N) &= (M + \varepsilon N)(M + \varepsilon N) = M^2 + \varepsilon MN + \varepsilon NM + \varepsilon^2 N^2 \\
\delta F(M; N) &= \lim_{\varepsilon \to 0} \frac{F(M + \varepsilon N) - F(M)}{\varepsilon} \\
&= \lim_{\varepsilon \to 0} \frac{\varepsilon MN + \varepsilon NM + \varepsilon^2 N^2}{\varepsilon} = MN + NM
\end{aligned}$$

Infinite Dimensional Optimization Let $u \in \mathcal{U}$ (function space) and let $J(u)$ be the cost:

$$\min_{u \in \mathcal{U}} J(u)$$

Theorem. *If $u^* \in \mathcal{U}$ is a (local) minimizer then*

$$\delta J(u^*; v) = 0, \quad \forall v \in \mathcal{U}$$

Example Find minimizer u^* to

$$J(u) = \int_0^T L(u(t)) \, \mathrm{d}t$$

$$J(u + \varepsilon v) - J(u) = \int_0^T L(u(t) + \varepsilon v(t)) \, \mathrm{d}t - \int_0^T L(u(t)) \, \mathrm{d}t, \quad u, v \in \mathcal{U}$$

$$= \int_0^T \left[L(u(t)) + \varepsilon \frac{\partial L}{\partial u}(u(t)) v(t) + o(\varepsilon) - L(u(t)) \right] \mathrm{d}t$$

$$\delta J(u^*; v) = \lim_{\varepsilon \to 0} \frac{J(u + \varepsilon v) - J(u)}{\varepsilon}$$

$$= \lim_{\varepsilon \to 0} \frac{\int_0^T \varepsilon \frac{\partial L}{\partial u}(u(t)) v(t) \, \mathrm{d}t + o(\varepsilon)}{\varepsilon}$$

$$= \int_0^T \frac{\partial L}{\partial u}(u(t)) v(t) \, \mathrm{d}t$$

u^* optimizer:

$$\delta J(u^*; v) = \int_0^T \frac{\partial L}{\partial u}(u(t)) v(t) \, \mathrm{d}t = 0 \quad \forall v \in \mathcal{U}$$

$$\Updownarrow$$

$$\frac{\partial L}{\partial u}(u(t)) = 0 \quad \forall t \in [0, T]$$

But, we want *optimal control*! We want our cost to look like

$$\int_0^T L(x(t), u(t)) \, \mathrm{d}t$$

$$\dot{x} = f(x, u)$$

1.6 Calculus of Variations

What happens to $x(t)$ when $u(t)$ changes to $u(t) + \varepsilon v(t)$? Let the system be given by

$$\begin{cases} \dot{x} = f(x, u) \\ x(0) = x_0 \end{cases}$$

After perturbation of u, the new system is

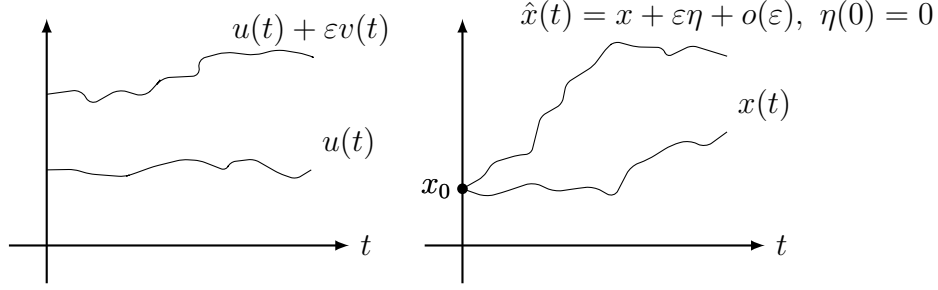$$\begin{cases} \dot{\hat{x}} = f(\hat{x}, u + \varepsilon v) \\ x(0) = x_0 \end{cases}$$

Figure 1.1: Variation in u causes a variation in x.

Consider

$$\tilde{x} = x + \varepsilon\eta,$$

where

$$\dot{x} = f(x, u), \qquad\qquad x(0) = x_0$$

$$\dot{\eta} = \frac{\partial f}{\partial x}(x, u)\eta + \frac{\partial f}{\partial u}(x, u)v, \qquad \eta(0) = 0$$

Theorem. *If f is continuously differentiable in x and u then*

$$\hat{x}(t) = \tilde{x}(t) + o(\varepsilon)$$

Proof.

i) Initial conditions:

$$\hat{x}(0) = x_0$$
$$\tilde{x}(0) = x(0) + \varepsilon\eta(0) = x_0$$

ii) Dynamics:

$$\dot{\hat{x}} = f(\hat{x}, u + \varepsilon v)$$

$$\dot{\tilde{x}} = \dot{x} + \varepsilon\dot{\eta} = f(x, u) + \varepsilon\frac{\partial f}{\partial x}(x, u)\eta + \varepsilon\frac{\partial f}{\partial u}(x, u)v$$

$$= f(x + \varepsilon\eta, u + \varepsilon v) + o(\varepsilon)$$

$$= f(\tilde{x}, u + \varepsilon v) + o(\varepsilon)$$

We can see that the dynamics of $\hat{x}(t)$ are equal to those of $\tilde{x}(t)$ plus higher order terms:

$$\dot{\tilde{x}} = f(\tilde{x}, u + \varepsilon v) + o(\varepsilon)$$
$$\dot{\hat{x}} = f(\hat{x}, u + \varepsilon v)$$

Therefore, if our perturbation is small enough, we can model $\hat{x}(t)$ as $\tilde{x}(t)$.

$\square$

Note: Taylor expansion with two elements is

$$h(w + \varepsilon v, z + \varepsilon y) = h(w, z + \varepsilon y) + \frac{\partial h}{\partial w}(w, z + \varepsilon y)\varepsilon v + o(\varepsilon)$$

$$= \left\{ h(w, z) + \frac{\partial h}{\partial z}(w, z)\varepsilon y + o(\varepsilon) \right\}$$

$$+ \left\{ \frac{\partial h}{\partial w}(w, z)\varepsilon v + \underbrace{\frac{\partial^2 h}{\partial z \partial w}\varepsilon v \odot \varepsilon y}_{o(\varepsilon)} + o(\varepsilon) \right\}$$

$$= h(w, z) + \frac{\partial h}{\partial z}\varepsilon y + \frac{\partial h}{\partial w}\varepsilon v + o(\varepsilon)$$

Last class:

1. $u \in \mathcal{U}$ (space of functions), $J : \mathcal{U} \to \mathbb{R}$ (cost).

   FONC: If u^* is optimal, then

   $$\delta J(u; \nu) = 0 \quad \forall \nu \in \mathcal{U},$$

   where the directional derivative is given by

   $$\delta J(u; \nu) = \lim_{\varepsilon \to 0} \frac{J(u + \varepsilon \nu) - J(u)}{\varepsilon}.$$

2. If

   $$\begin{cases} \dot{x} = f(x, u) \\ x(0) = x_0 \end{cases}$$

   then a variation in u:

   $$u \longmapsto u + \varepsilon \nu$$

   results in a variation in x:

   $$x \longmapsto x + \varepsilon \eta + o(\varepsilon)$$

   See Figure 1.1. Note $\eta(0) = 0$.

1.6.1   An (Almost) Optimal Control Problem

Let $\dot{x} = f(x)$, $x(0) = x_0$. Note we get to pick the initial condition!

Problem

$$\min_{x_0 \in \mathbb{R}^m} J(x_0) = \int_0^T L(x(t)) \, \mathrm{d}t$$

$$\text{s.t.} \quad \begin{cases} \dot{x}(t) = f(x(t)) & \text{the } \textit{constraint!} \text{ (equality)} \\ x(0) = x_0 \end{cases}$$

Note every constraint needs a Lagrange multiplier. We have infinitely many constraints:
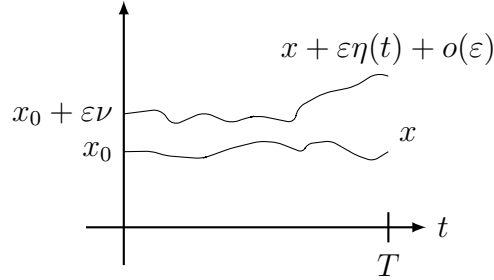
$$\dot{x}(t) = f(x(t)) \quad \forall t \in [0, T]$$

We need $\lambda(t)$ as a function of t. Also, the sum in the Lagrangian has to become an integral. The continuous-time Lagrangian thus becomes

$$\tilde{J}(x_0, \lambda) = \int_0^T \left[L(x(t)) + \lambda^{\mathrm{T}}(t)(f(x(t)) - \dot{x}(t)) \right] \mathrm{d}t$$

The task is to perturb x_0 as $x_0 \longmapsto x_0 + \varepsilon\nu$, $\nu \in \mathbb{R}^m$ and compute

$$\delta\tilde{J}(x_0; \nu) = \lim_{\varepsilon \to 0} \frac{\tilde{J}(x_0 + \varepsilon\nu) - \tilde{J}(x_0)}{\varepsilon}$$

and make this equal to 0 $\forall \nu \in \mathbb{R}^m$. The variation in x is

Note:

x_0	decision variable
ν	variation in x_0
$x(t)$	trajectory starting at x_0
$\eta(t)$	change in trajectory resulting from ν-variation in x_0
$\lambda(t)$	time-varying Lagrange multiplier

$$\tilde{J}(x_0 + \varepsilon\nu) = \int_0^T \left\{ L(x(t)) + \lambda^{\mathrm{T}}(t)[f(x(t) + \varepsilon\eta(t)) - \dot{x}(t) - \varepsilon\dot{\eta}(t)] \right\} \mathrm{d}t + o(\varepsilon)$$

$$= \int_0^T \left[L(x) + \varepsilon\frac{\partial L}{\partial x}(x)\eta + \lambda^{\mathrm{T}} \left(f(x) + \varepsilon\frac{\partial f}{\partial x}(x)\eta - \dot{x} - \varepsilon\dot{\eta} \right) \right] \mathrm{d}t + o(\varepsilon)$$

$$\tilde{J}(x_0 + \varepsilon\nu) - \tilde{J}(x_0) = \int_0^T \left[\varepsilon\frac{\partial L}{\partial x}(x)\eta + \lambda^{\mathrm{T}} \left(\varepsilon\frac{\partial f}{\partial x}\eta - \varepsilon\dot{\eta} \right) \right] \mathrm{d}t + o(\varepsilon)$$

$$\delta\tilde{J}(x_0; \nu) = \int_0^T \left[\frac{\partial L}{\partial x}(x)\eta + \lambda^{\mathrm{T}} \left(\frac{\partial f}{\partial x}\eta - \dot{\eta} \right) \right] \mathrm{d}t$$

A powerful idea: we want $\delta\tilde{J}(x_0; \nu) = 0 \; \forall \nu$. Somehow get this in the form

$$\int_0^T \Big(\text{stuff}(t)\Big)\eta(t)\,\mathrm{d}t = 0$$

We can pick $\text{stuff}(t) = 0 \; \forall t \in [0, T]$.

In $\delta\tilde{J}(x_0; \nu)$ we have $\dot{\eta}$ (problem!). We can solve this using *integration by parts*.

$$\int_0^T \lambda^{\mathrm{T}}\dot{\eta}\,\mathrm{d}t = \lambda^{\mathrm{T}}(T)\eta(T) - \lambda^{\mathrm{T}}(0)\eta(0) - \int_0^T \dot{\lambda}^{\mathrm{T}}\eta\,\mathrm{d}t$$

Hence,

$$\delta\tilde{J}(x_0; \nu) = \int_0^T \underbrace{\Big(\frac{\partial L}{\partial x} + \lambda^{\mathrm{T}}\frac{\partial f}{\partial x} + \dot{\lambda}^{\mathrm{T}}\Big)}_{\text{pick}=0}\eta\,\mathrm{d}t - \underbrace{\lambda^{\mathrm{T}}(T)}_{\text{pick}=0}\eta(T) + \lambda^{\mathrm{T}}(0)\underbrace{\eta(0)}_{\nu}$$

We are free to pick λ freely if it gives $\delta\tilde{J} = 0$.

$$\text{Pick:} \quad \begin{cases} \dot{\lambda}(t) = -\frac{\partial L^{\mathrm{T}}}{\partial x}(x(t)) - \frac{\partial f^{\mathrm{T}}}{\partial x}(x(t))\lambda(t) \\ \lambda(T) = 0 \end{cases} \qquad \text{backwards diff. eq}$$

Under this choice of λ we get

$$\delta\tilde{J}(x_0; \nu) = \lambda^{\mathrm{T}}(0)\nu$$

This is linear in ν so the FONC is $\lambda(0) = 0$.

Moreover, we really have a "normal" optimization problem

$$\min_{x_0 \in \mathbb{R}^m} \tilde{J}(x_0)$$

$$\delta\tilde{J}(x_0; \nu) = \frac{\partial\tilde{J}}{\partial x_0}(x_0)\nu$$

which means that

$$\frac{\partial\tilde{J}}{\partial x_0} = \lambda^{\mathrm{T}}(0)$$

If x_0^* minimizes

$$\int_0^T L(x(t))\,\mathrm{d}t$$

$$\text{s.t.} \quad \begin{cases} \dot{x}(t) = f(x(t)) \\ x(0) = x_0^* \end{cases}$$
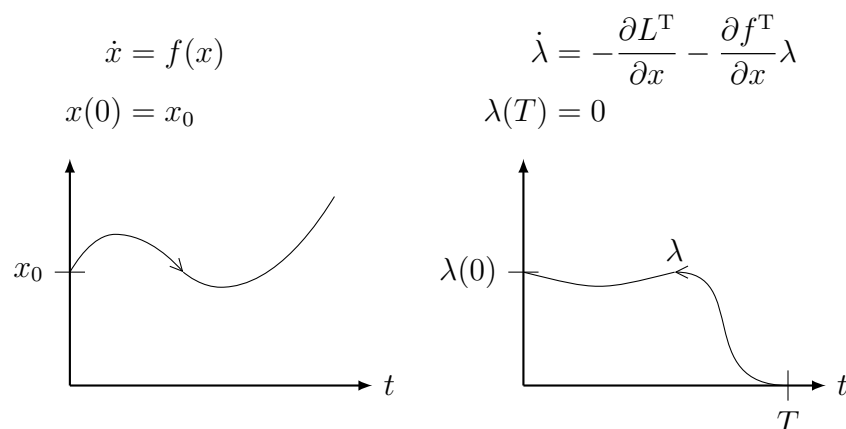
then

$$\lambda(0) = \mathbf{0}$$

where $\lambda(t)$ satisfies

$$\begin{cases} \dot{\lambda}(t) = -\frac{\partial L^{\mathrm{T}}}{\partial x}(x(t)) - \frac{\partial f^{\mathrm{T}}}{\partial x}(x(t))\lambda(t) \\ \lambda(T) = 0 \end{cases}$$

So what? We actually have a two-point boundary value problem.

$$\dot{x} = f(x) \qquad\qquad \dot{\lambda} = -\frac{\partial L^{\mathrm{T}}}{\partial x} - \frac{\partial f^{\mathrm{T}}}{\partial x}\lambda$$

$$x(0) = x_0 \qquad\qquad \lambda(T) = 0$$

We want to find x_0 that gives $f(x)$ such that after solving backwards for $\lambda(t)$, we find that

$$\lambda(0) = \frac{\partial \tilde{J}^{\mathrm{T}}}{\partial x_0} = 0.$$

This leads to the following:

An algorithm

Pick $x_{0,0}$
$k = 1$
repeat
    Simulate $x(t)$ from $x_{0,k}$ over $[0, T]$
    Simulate $\lambda(t)$ from $\lambda(T) = 0$ backwards using $x(t)$
    Update $x_{0,k}$ as $x_{0,k+1} = x_{0,k} - \gamma\lambda(0)$ $\triangleright$ $\lambda(0)$ is the gradient
    $k := k + 1$
until $\lambda(0) = 0$

Example: `optinit.m`

$$\dot{x} = Ax, \quad L = x^{\mathrm{T}}Qx - q, \quad Q = Q^{\mathrm{T}} \succ 0$$
$$\dot{\lambda} = -2Qx - A^{\mathrm{T}}\lambda$$
$$\lambda(0) = 0$$

1.6.2 Optimal Timing Control

When to switch between modes?

$$\dot{x} = \begin{cases} f_1(x) & \text{if } t \in [0, \tau) \\ f_2(x) & \text{if } t \in [\tau, T] \end{cases} \tag{1.2}$$
$$x(0) = x_0$$

K. Okkelberg
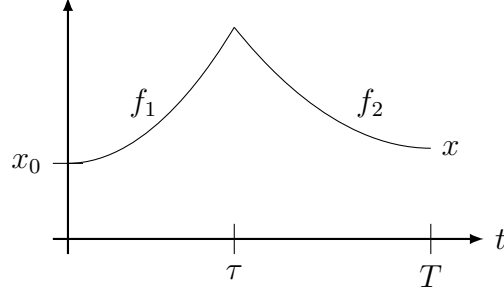
$$\min_{\tau} \int_0^T L(x(t))\,\mathrm{d}t = J(\tau)$$

s.t. (1.2) holds

Step 1: Augment cost with constraint

$$\tilde{J} = \int_0^\tau \left[L(x) + \lambda^{\mathrm{T}}(f_1(x) - \dot{x}) \right]\mathrm{d}t + \int_\tau^T \left[L(x) + \lambda^{\mathrm{T}}(f_2(x) - \dot{x}) \right]\mathrm{d}t$$

Step 2: Variation $\tau \longmapsto \tau + \varepsilon\theta$

Step 3: Compute $\delta\tilde{J}(\tau; \theta)$
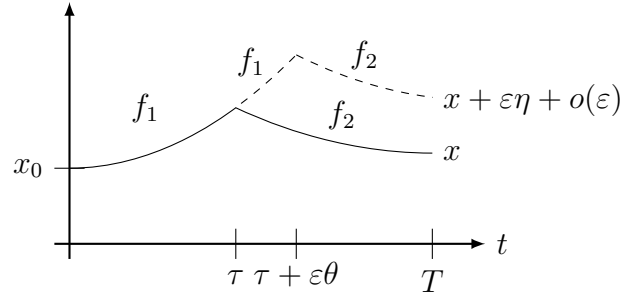
$$\tilde{J}(\tau + \varepsilon\theta) = \int_0^{\tau+\varepsilon\theta} \left\{ L(x + \varepsilon\eta) + \lambda^{\mathrm{T}}[f_1(x + \varepsilon\eta) - \dot{x} - \varepsilon\dot{\eta}] \right\}\mathrm{d}t$$

$$+ \int_{\tau+\varepsilon\theta}^T \left\{ L(x + \varepsilon\eta) + \lambda^{\mathrm{T}}[f_2(x + \varepsilon\eta) - \dot{x} - \varepsilon\dot{\eta}] \right\}\mathrm{d}t + o(\varepsilon)$$

Note that $\eta = \dot{\eta} = 0$ on $[0, \tau)$.

$$\tilde{J}(\tau + \varepsilon\theta) = \int_0^\tau \left\{ L(x) + \lambda^{\mathrm{T}}[f_1(x) - \dot{x}] \right\}\mathrm{d}t$$

$$+ \int_\tau^{\tau+\varepsilon\theta} \left\{ \underbrace{L(x + \varepsilon\eta)}_{L(x)+\varepsilon\frac{\partial L}{\partial x}\eta} + \lambda^{\mathrm{T}}[\underbrace{f_1(x + \varepsilon\eta)}_{f_1(x)+\varepsilon\frac{\partial f_1}{\partial x}\eta} - \dot{x} - \varepsilon\dot{\eta}] \right\}\mathrm{d}t$$

$$+ \int_{\tau+\varepsilon\theta}^T \left\{ \underbrace{L(x + \varepsilon\eta)}_{L(x)+\varepsilon\frac{\partial L}{\partial x}\eta} + \lambda^{\mathrm{T}}[\underbrace{f_2(x + \varepsilon\eta)}_{f_2(x)+\varepsilon\frac{\partial f_2}{\partial x}\eta} - \dot{x} - \varepsilon\dot{\eta}] \right\}\mathrm{d}t + o(\varepsilon)$$

$$\delta \tilde{J}(\tau; \theta) = \lim_{\varepsilon \to 0} \frac{\tilde{J}(\tau + \varepsilon\theta) - \tilde{J}(\tau)}{\varepsilon}$$

$$\tilde{J}(\tau + \varepsilon\theta) - \tilde{J}(\tau) = \int_0^\tau 0 \cdot \mathrm{d}t + \underbrace{\int_\tau^{\tau+\varepsilon\theta} \left[\varepsilon \frac{\partial L}{\partial x} \eta + \lambda^\mathrm{T} \left(f_1(x) + \varepsilon \frac{\partial f_1}{\partial x} \eta - f_2(x) - \varepsilon \dot{\eta} \right) \right] \mathrm{d}t}_{I_1}$$

$$+ \underbrace{\int_{\tau+\varepsilon\theta}^T \left[\varepsilon \frac{\partial L}{\partial x} \eta + \lambda^\mathrm{T} \left(\varepsilon \frac{\partial f_2}{\partial x} \eta - \varepsilon \dot{\eta} \right) \right] \mathrm{d}t}_{I_2} + o(\varepsilon)$$

Theorem (Mean-value theorem).

$$\int_{t_1}^{t_2} h(t)\, \mathrm{d}t = (t_2 - t_1) h(\xi) \quad \text{for some } \xi \in [t_1, t_2]$$

The first integral is

$$I_1 = \int_\tau^{\tau+\varepsilon\theta} \left\{ \varepsilon \frac{\partial L}{\partial x} \eta + \lambda^\mathrm{T} \left[f_1(x) + \varepsilon \frac{\partial f_1}{\partial x} \eta - \varepsilon \dot{\eta} - f_2(x) \right] \right\} \mathrm{d}t$$

$$= \varepsilon\theta \left\{ \lambda^\mathrm{T}(\xi) \left[f_1(x(\xi)) - f_2(x(\xi)) \right] \right\} + o(\varepsilon)$$

Note that as $\varepsilon \to 0$, $\xi \to \tau$. Using integration by parts, the second integral is

$$\int_\tau^T \lambda^\mathrm{T} \dot{\eta}\, \mathrm{d}t = \lambda^\mathrm{T}(T)\eta(T) - \lambda^\mathrm{T}(\tau) \underbrace{\eta(\tau)}_{=0} - \int_\tau^T \dot{\lambda}^\mathrm{T} \eta\, \mathrm{d}t$$

$$I_2 = \int_\tau^T \left[\varepsilon \frac{\partial L}{\partial x} \eta + \lambda^\mathrm{T} \left(\varepsilon \frac{\partial f_2}{\partial x} \eta - \varepsilon \dot{\eta} \right) \right] \mathrm{d}t - \underbrace{\int_\tau^{\tau+\varepsilon\theta} \left[\varepsilon \frac{\partial L}{\partial x} \eta + \lambda^\mathrm{T} \left(\varepsilon \frac{\partial f_2}{\partial x} \eta - \varepsilon \dot{\eta} \right) \right] \mathrm{d}t}_{o(\varepsilon)}$$

$$= \varepsilon \int_\tau^T \left[\frac{\partial L}{\partial x} + \lambda^\mathrm{T} \frac{\partial f_2}{\partial x} + \dot{\lambda}^\mathrm{T} \right] \eta\, \mathrm{d}t - \varepsilon \lambda^\mathrm{T}(T)\eta(T) + o(\varepsilon)$$

Hence,

$$\delta \tilde{J}(\tau; \theta) = \lim_{\varepsilon \to 0} \frac{\tilde{J}(\tau + \varepsilon\theta) - \tilde{J}(\tau)}{\varepsilon}$$

$$= \theta\lambda^\mathrm{T}(\tau) \left[f_1(x(\tau)) - f_2(x(\tau)) \right] + \int_\tau^T \left[\frac{\partial L}{\partial x} + \lambda^\mathrm{T} \frac{\partial f_2}{\partial x} + \dot{\lambda}^\mathrm{T} \right] \eta\, \mathrm{d}t - \lambda^\mathrm{T}(T)\eta(T)$$

Step 4: Select the *costate* $\lambda(t)$. The key idea is to get rid of any term that has η in it, i.e.

$$\dot{\lambda} = -\frac{\partial L^\mathrm{T}}{\partial x} - \frac{\partial f_2^\mathrm{T}}{\partial x} \lambda \quad \text{on } [\tau, T]$$

$$\lambda(T) = 0$$

Step 5: With this choice of $\lambda(t)$, we have

$$\delta\tilde{J}(\tau;\theta) = \theta\lambda^{\mathrm{T}}(\tau)\Big[f_1(x(\tau)) - f_2(x(\tau))\Big] = \frac{\partial\tilde{J}}{\partial\tau}\theta.$$

Therefore,

$$\frac{\partial\tilde{J}}{\partial\tau} = \lambda^{\mathrm{T}}(\tau)\Big[f_1(x(\tau)) - f_2(x(\tau))\Big] = 0 \quad \text{(for optimality)}$$

Algorithm

Pick τ_0
$k = 0$
repeat
    Simulate x forward in time from $x(0) = x_0$
    Simulate λ backwards from $\lambda(T) = 0$
    Update τ_k as $\tau_{k+1} = \tau_k - \gamma\lambda^{\mathrm{T}}(\tau_k)\big[f_1(x(\tau_k)) - f_2(x(\tau_k))\big]$
    $k := k + 1$
until $\|\lambda^{\mathrm{T}}(f_1 - f_2)\| < \varepsilon$

Where are we going? Come up with general principles for $\min_{u\in\mathcal{U}} J(u)$:

- Costate equations

- Optimality conditions

- Algorithms

- Applications

1.6.3 The Bolza Problem

Up until now, we have optimized with respect to finite-dimensional parameters. Today, we will minimize with respect to $u \in \mathcal{U}$.

$$\min_{u\in\mathcal{U}} J(u) = \int_0^T L(x(t), u(t), t)\,\mathrm{d}t + \underbrace{\Psi(x(T))}_{\substack{\text{terminal cost}\\\text{(parking cost)}}}$$

$$\text{s.t.}\quad \dot{x}(t) = f(x(t), u(t), t)$$
$$x(0) = x_0$$

Assume that f and L are C^1 in x, u and piecewise continuous in t. Then, a small change in u causes small changes in f and L. The variation: $u \longmapsto u + \varepsilon v$, $\varepsilon \in \mathbb{R}$, $v \in \mathcal{U}$. See Figure 1.1.

$$\tilde{J}(u) = \int_0^T \left[L(x, u, t) + \lambda^{\mathrm{T}}(f(x, u, t) - \dot{x}) \right] \mathrm{d}t + \Psi(x(T))$$

$$\tilde{J}(u + \varepsilon v) = \int_0^T \left[L(x + \varepsilon\eta, u + \varepsilon v, t) + \lambda^{\mathrm{T}}(f(x + \varepsilon\eta, u + \varepsilon v, t) - \dot{x} - \varepsilon\dot{\eta}) \right] \mathrm{d}t$$
$$+ \Psi(x(T) + \varepsilon\eta(T)) + o(\varepsilon)$$

$$\tilde{J}(u + \varepsilon v) - \tilde{J}(u) = \int_0^T \bigg[L(x + \varepsilon\eta, u + \varepsilon v, t) - L(x, u, t)$$
$$+ \lambda^{\mathrm{T}}\Big(f(x + \varepsilon\eta, u + \varepsilon v, t) - f(x, u, t) - \dot{x} - \varepsilon\dot{\eta} + \dot{x} \Big) \bigg] \mathrm{d}t$$
$$+ \Psi(x(T) + \varepsilon\eta(T)) - \Psi(x(T)) + o(\varepsilon)$$
$$= \int_0^T \left[\frac{\partial L}{\partial x}\varepsilon\eta + \frac{\partial L}{\partial u}\varepsilon v + \lambda^{\mathrm{T}}\Big(\frac{\partial f}{\partial x}\varepsilon\eta + \frac{\partial f}{\partial u}\varepsilon v - \varepsilon\dot{\eta} \Big) \right] \mathrm{d}t$$
$$+ \frac{\partial\Psi}{\partial x}(x(T))\varepsilon\eta(T) + o(\varepsilon)$$

(See Taylor expansion with respect to two variables.)

$$\delta\tilde{J}(u; v) = \int_0^T \left(\frac{\partial L}{\partial u} + \lambda^{\mathrm{T}}\frac{\partial f}{\partial u} \right) v \,\mathrm{d}t + \int_0^T \left[\left(\frac{\partial L}{\partial x} + \lambda^{\mathrm{T}}\frac{\partial f}{\partial x} \right)\eta - \lambda^{\mathrm{T}}\dot{\eta} \right] \mathrm{d}t$$
$$+ \frac{\partial\Psi}{\partial x}(x(T))\eta(T)$$

Integrating by parts,

$$\int_0^T \lambda^{\mathrm{T}}\dot{\eta} \,\mathrm{d}t = \lambda^{\mathrm{T}}(T)\eta(T) - \lambda^{\mathrm{T}}(0)\eta(0) - \int_0^T \dot{\lambda}^{\mathrm{T}}\eta \,\mathrm{d}t$$
$$= \lambda^{\mathrm{T}}(T)\eta(T) - \int_0^T \dot{\lambda}^{\mathrm{T}}\eta \,\mathrm{d}t$$

$$\delta\tilde{J}(u; v) = \int_0^T \left(\frac{\partial L}{\partial u} + \lambda^{\mathrm{T}}\frac{\partial f}{\partial u} \right) v \,\mathrm{d}t + \int_0^T \left(\frac{\partial L}{\partial x} + \lambda^{\mathrm{T}}\frac{\partial f}{\partial x} + \dot{\lambda}^{\mathrm{T}} \right)\eta \,\mathrm{d}t$$
$$+ \left(\frac{\partial\Psi}{\partial x}(x(T)) - \lambda^{\mathrm{T}}(T) \right)\eta(T)$$

For optimality, we need the directional derivative to be zero for every $v \in \mathcal{U}$, where v represents the direction of the derivative. Therefore, the term $\left(\frac{\partial L}{\partial u} + \lambda^{\mathrm{T}}\frac{\partial f}{\partial u} \right)$ in the first integral has to be identically zero. Thus, we need

$$\begin{cases} \dfrac{\partial L}{\partial u} + \lambda^{\mathrm{T}}\dfrac{\partial f}{\partial u} = 0, & \forall t \in [0, T] \\[2mm] \dfrac{\partial L}{\partial x} + \lambda^{\mathrm{T}}\dfrac{\partial f}{\partial x} + \dot{\lambda}^{\mathrm{T}} = 0, & \forall t \in [0, T] \\[2mm] \dfrac{\partial\Psi}{\partial x}(x(T)) - \lambda^{\mathrm{T}}(T) = 0 \end{cases}$$

Definition. Let the *Hamiltonian* $H(x, u, t, \lambda)$ be given by

$$H(x, u, t, \lambda) = L(x, u, t) + \lambda^{\mathrm{T}} f(x, u, t)$$

Theorem. *For u to solve the Bolza problem, it has to satisfy*

$$\frac{\partial H}{\partial u}(x, u, t, \lambda) = 0,$$

where the costate *satisfies*

$$\begin{cases} \dot{\lambda} = -\dfrac{\partial H^T}{\partial x}(x, u, t, \lambda) \\ \lambda(T) = \dfrac{\partial \Psi^T}{\partial x}(x(T)) \end{cases}$$

Example

$$\min_u \int_0^1 \frac{1}{2} u^2(t) \, \mathrm{d}t + \frac{1}{2} x^2(1)$$

$$\text{s.t.} \quad \begin{cases} \dot{x} = u, \quad x, u \in \mathbb{R} \\ x(0) = 1 \end{cases}$$

$$H = \frac{1}{2} u^2 + \lambda u$$

$$\frac{\partial H}{\partial u} = u + \lambda = 0 \implies u = -\lambda$$

$$\dot{\lambda} = -\frac{\partial H}{\partial x} = 0 \implies \lambda(t) = c$$
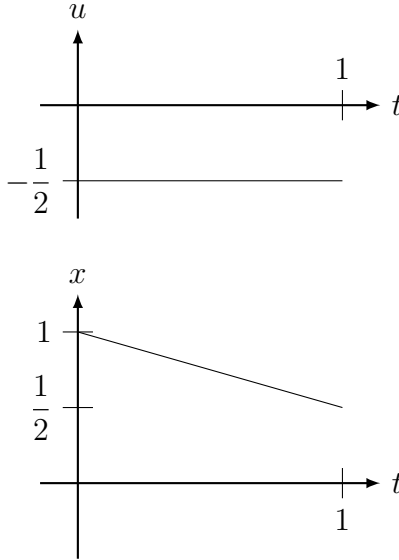
$$\lambda(T) = c = \frac{\partial \Psi}{\partial x}(x(1)) = x(1)$$

$$\dot{x} = u = -c \implies x(t) = -ct + x(0) = -ct + 1$$

$$x(1) = -c + 1$$

$$\lambda(1) = c = x(1) = -c + 1 \implies c = \frac{1}{2}$$

$$\boxed{u^* = -\frac{1}{2}}$$

We really used five different equations to solve this!

i) $\dfrac{\partial H}{\partial u} = 0$

ii) $\dot{\lambda} = -\dfrac{\partial H^{\mathrm{T}}}{\partial x}$

iii) $\lambda(T) = \dfrac{\partial \Psi^{\mathrm{T}}}{\partial x}(x(T))$

iv) $\dot{x} = f(x, u, t)$

v) $x(0) = x_0$

There is a sixth condition that is pretty useful if L and f do not depend on t ($L(x, u)$, $f(x, u)$). This is called a *conservative system*. Then, along optimal trajectories (equations i-v are satisfied), the total time derivative of the Hamiltonian is

$$\frac{\mathrm{d}}{\mathrm{d}t} H = \underbrace{\frac{\partial H}{\partial t}}_{\substack{0 \\ H(x,u,\lambda)}} + \underbrace{\frac{\partial H}{\partial x}}_{-\dot{\lambda}^{\mathrm{T}}} \dot{x} + \underbrace{\frac{\partial H}{\partial u}}_{\substack{0 \\ u \text{ is optimal}}} \dot{u} + \underbrace{\frac{\partial H}{\partial \lambda}}_{f^{\mathrm{T}} = \dot{x}^{\mathrm{T}}} \dot{\lambda} = -\dot{\lambda}^{\mathrm{T}} \dot{x} + \dot{x}^{\mathrm{T}} \dot{\lambda} = 0$$

Therefore, for conservative systems,

vi) H is constant along optimal trajectories. (Hamilton's Principle in analytical mechanics)

Back to the example,

$$H = \frac{1}{2}u^2 + \lambda u = \frac{1}{2}c^2 - c^2 = -\frac{1}{2}c^2 = -\frac{1}{8}$$

The Hamiltonian

$$H(x, u, t, \lambda) = L(x, u, t) + \lambda^{\mathrm{T}} f(x, u, t)$$

lets us write the Lagrangian as

$$\tilde{J}(u) = \int_0^T \left[L + \lambda^{\mathrm{T}}(f - \dot{x})\right] \mathrm{d}t + \Psi = \int_0^T \left(H - \lambda^{\mathrm{T}}\dot{x}\right) \mathrm{d}t + \Psi$$

The optimality conditions are

$$\frac{\partial H}{\partial u} = 0, \tag{1.3}$$

where

$$\begin{cases} \dot{\lambda} = -\dfrac{\partial H^{\mathrm{T}}}{\partial x} \\ \lambda(T) = \dfrac{\partial \Psi}{\partial x}(x(T)) \end{cases} \tag{1.4}$$

Example   Hamilton's Principle

Let q be the generalized coordinates (positions and angles). Then, $\dot{q} = u$ are generalized velocities, which we assume we can control. Let $T(q, u) = u^{\mathrm{T}}M(q)u$, $M \succ 0$, be the kinetic energy and $V(q)$ be the potential energy.

For conservative systems, the following quantity is minimized:

$$\int_0^T \underbrace{\left[T(q, u) - V(q)\right]}_{\substack{L(q,u) = \\ \text{Lagrange's "action function"}}} \mathrm{d}t$$

The Hamiltonian is

$$H(q, u, \lambda) = L(q, u) + \lambda^{\mathrm{T}} f(q, u) = L(q, u) + \lambda^{\mathrm{T}} u$$

In mechanics, λ is called a generalized momentum, satisfying

$$\dot{\lambda} = -\frac{\partial H^{\mathrm{T}}}{\partial q} = -\frac{\partial L^{\mathrm{T}}}{\partial q} + 0$$

$$0 = \frac{\partial H}{\partial u} = \frac{\partial L}{\partial u} + \lambda^{\mathrm{T}} \implies \lambda = -\frac{\partial L^{\mathrm{T}}}{\partial u}$$

$$\dot{\lambda} = -\frac{\mathrm{d}}{\mathrm{d}t}\frac{\partial L^{\mathrm{T}}}{\partial u} = -\frac{\partial L^{\mathrm{T}}}{\partial q}$$

This produces the Euler-Lagrange Equation:

$$\frac{\mathrm{d}}{\mathrm{d}t}\frac{\partial L}{\partial \dot{q}} - \frac{\partial L}{\partial q} = 0$$

Recall, along optimal trajectories

$$\frac{\mathrm{d}H}{\mathrm{d}t} = \underbrace{\frac{\partial H}{\partial t}}_{\substack{=0 \text{ if } L \text{ and } f \text{ do not} \\ \text{depend explicitly on } t}} + \overbrace{\frac{\partial H}{\partial x}\dot{x}}^{-\dot{\lambda}^{\mathrm{T}}\dot{x}} + \underbrace{\frac{\partial H}{\partial u}}_{=0}\dot{u} \; \underbrace{\frac{\partial H}{\partial \lambda}}_{f^{\mathrm{T}}=\dot{x}^{\mathrm{T}}}\dot{\lambda} = -\dot{\lambda}^{\mathrm{T}}\dot{x} + \dot{x}^{\mathrm{T}}\dot{\lambda} = 0$$

Therefore, along optimal trajectories, the Hamiltonian is constant!
   We had

$$H = L + \lambda^{\mathrm{T}}u$$
$$\frac{\partial H}{\partial u} = \lambda^{\mathrm{T}} + \frac{\partial L}{\partial u} = 0$$

Along optimal trajectories,

$$H = L - \frac{\partial L}{\partial u}u$$

Recall, $L(q, u) = T(q, u) - V(q)$.

$$\frac{\partial L}{\partial u} = \frac{\partial T}{\partial u} - 0$$
$$T(q, u) = u^{\mathrm{T}}M(q)u$$
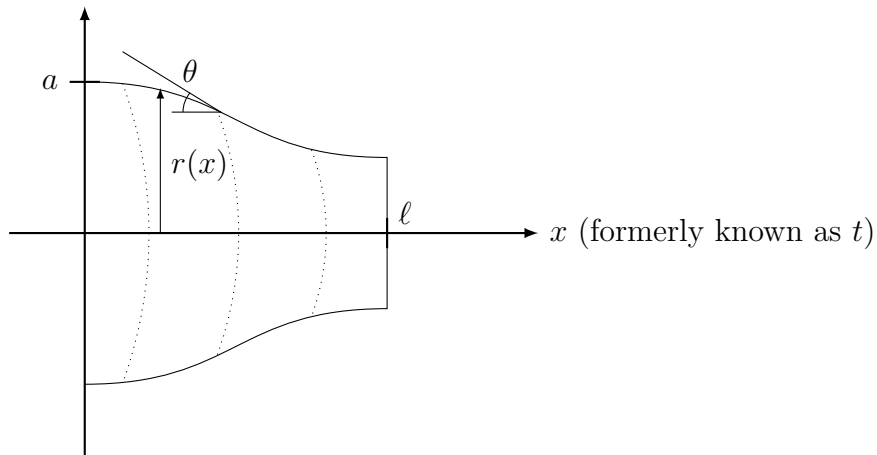$$\frac{\partial T}{\partial u} = 2u^{\mathrm{T}}M$$

So,

$$H = \underbrace{T}_{u^{\mathrm{T}}Mu} - V - 2u^{\mathrm{T}}Mu = -(V + u^{\mathrm{T}}Mu) = -(V + T)$$

Therefore, the total energy (kinetic plus potential energy) remains constant for conservative systems.

Example   minimum drag nose shape (Newton 1686)

The drag is

$$D = -2\pi q \int_{x=0}^{\ell} C_p(\theta) r \, \mathrm{d}r,$$

where q is a pressure constant and $C_p(\theta) = 2\sin^2\theta$ is Newton's pressure formula.

Geometry tells us

$$\frac{\mathrm{d}r}{\mathrm{d}x} = -\tan\theta = -u$$

Choose the control as $\tan\theta$. Manipulating the drag,

$$\frac{D}{4\pi q} = \int_0^{\ell} \frac{ru^3}{1+u^2} \, \mathrm{d}x + \frac{1}{2} r(\ell)^2$$

The optimal control problem is

$$\min_u \int_0^{\ell} \frac{ru^3}{1+u^2} \, \mathrm{d}x + \frac{1}{2} r(\ell)^2$$

$$\text{s.t. } \frac{\mathrm{d}r}{\mathrm{d}x} = -u$$

This is in the standard form with the following changes of variables:

$$\ell \longleftarrow T$$
$$x \longleftarrow t$$
$$r \longleftarrow x$$

Refer to (1.3) and (1.4) for the following steps.

$$H = \frac{ru^3}{1+u^2} - \lambda u$$
$$\frac{\partial H}{\partial u} = \frac{3ru^2(1+u^2) - ru^3 \cdot 2u}{(1+u^2)^2} - \lambda$$
$$= \frac{ru^4 + 3ru^2}{(1+u^2)^2} - \lambda = 0$$
$$\lambda = \frac{ru^2(u^2+3)}{(1+u^2)^2} \tag{1.5}$$
$$\frac{\mathrm{d}\lambda}{\mathrm{d}x} = -\frac{\partial H}{\partial r} = -\frac{u^3}{1+u^2}$$
$$\lambda(\ell) = r(\ell)$$

Right now, we know

$$\begin{cases} \dfrac{\mathrm{d}r}{\mathrm{d}x} = -u \\ r(0) = a \\ \dfrac{\mathrm{d}\lambda}{\mathrm{d}x} = -\dfrac{u^3}{1+u^2} \\ \lambda(\ell) = r(\ell) \end{cases}$$

We need to remove u and get a function of r and λ instead. However, it is difficult to solve (1.5). Maybe $H = \text{const.}$ gives us something nicer?

$$H = \frac{ru^3}{1 + u^2} - \lambda u$$
$$= \frac{ru^3}{1 + u^2} - \frac{ru^2(u^2 + 3)}{(1 + u^2)^2} u$$
$$= -\frac{2ru^3}{(1 + u^2)^2} = c$$

Assume we can find $u = G(r, c)$, either numerically or some other way. So, now we have

$$\begin{cases} \dfrac{\mathrm{d}r}{\mathrm{d}x} = -G(r, c) \\ r(0) = a \\ \dfrac{\mathrm{d}\lambda}{\mathrm{d}x} = -\dfrac{G^3(r, c)}{1 + G^2(r, c)} \\ \lambda(\ell) = r(\ell) \end{cases}$$

We do not know c, but we can guess c and simulate r forward in "time" (x) from $r(0) = a$. Then, we simulate λ backwards from $r(\ell)$.
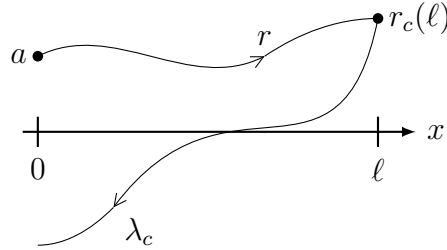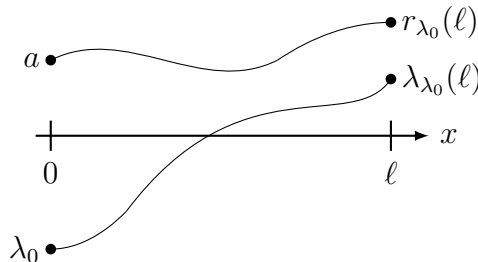

Problem: we can do this for any c. Which c is it? *Last 15 minutes was a dead end!*

Back to $u = F(r, \lambda)$. Assume we have F (numerically).

$$\frac{\mathrm{d}r}{\mathrm{d}x} = -F(r, \lambda)$$
$$r(0) = a$$
$$\frac{\mathrm{d}\lambda}{\mathrm{d}x} = -\frac{F^3(r, \lambda)}{1 + F^2(r, \lambda)}$$
$$\lambda(\ell) = r(\ell)$$

The mistake before was that the simulation forward from a depends on λ.

Therefore, we should guess λ_0 and simulate both r and λ to get $r_{\lambda_0}(\ell)$ and $\lambda_{\lambda_0}(\ell)$. We need

$$r_{\lambda_0}(\ell) = \lambda_{\lambda_0}$$

for optimality. To do this, we need numerics.

Terminal Constraints

Let $x = [x_1, \ldots, x_n]^{\mathrm{T}} \in \mathbb{R}^n$ and solve

$$\min_{u \in \mathcal{U}} \int_0^T L(x, u, t)\, \mathrm{d}t + \Psi(x(T))$$

$$\text{s.t.} \quad \dot{x} = f(x, u, t)$$

$$x(0) = x_0$$

$$x_i(T) = x_{iT} \quad \text{given for } i \in \mathcal{T} \subset \{1, \ldots, n\}$$

First, we augment the cost:

$$\tilde{J}(u) = \int_0^T \left[L + \lambda^{\mathrm{T}}(f - \dot{x}) \right] \mathrm{d}t + \Psi$$

$$= \int_0^T (H - \lambda^{\mathrm{T}}\dot{x})\, \mathrm{d}t + \Psi$$

$$\tilde{J}(u + \varepsilon v) - \tilde{J}(u) = \int_0^T \left(\varepsilon \frac{\partial H}{\partial u} v + \varepsilon \frac{\partial H}{\partial x} \eta - \varepsilon \lambda^{\mathrm{T}} \dot{\eta} \right) \mathrm{d}t + \varepsilon \frac{\partial \Psi}{\partial x}(x(T))\eta(T) + o(\varepsilon)$$

$$\delta \tilde{J}(u; v) = \int_0^T \left(\frac{\partial H}{\partial x} + \dot{\lambda}^{\mathrm{T}} \right) \eta\, \mathrm{d}t + \int_0^T \frac{\partial H}{\partial u} v\, \mathrm{d}t$$

$$+ \lambda^{\mathrm{T}}(0)\eta(0) - \lambda^{\mathrm{T}}(T)\eta(T) + \frac{\partial \Psi}{\partial x}(x(T))\eta(T)$$

As always,

$$\dot{\lambda} = -\frac{\partial H^{\mathrm{T}}}{\partial x}$$

$$\frac{\partial H}{\partial u} = 0 \quad \text{(FONC)}$$

Additionally,

$$\eta(0) = 0$$

$$\eta_i(T) = 0 \quad \text{for } i \in \mathcal{T}$$

Note that if $x(T) = x_T$ is given, then $x(T) = x(T) + \varepsilon \eta(T) + o(\varepsilon)$, so $\eta(T) = 0$. Here, we have $x_i(T) = x_{iT}$ fixed for $i \in \mathcal{T}$ so $\eta_i(T) = 0$ for $i \in \mathcal{T}$.

For optimality, we want

$$\left[-\lambda^{\mathrm{T}}(T) + \frac{\partial \Psi}{\partial x}(x(T)) \right] \eta(T) = 0 \quad \text{for all } \textit{admissible} \text{ variations}$$

$$\left[\frac{\partial \Psi}{\partial x_1} - \lambda_1, \quad \cdots, \quad \frac{\partial \Psi}{\partial x_n} - \lambda_n \right] \begin{bmatrix} \eta_1(T) \\ \vdots \\ \eta_n(T) \end{bmatrix} = 0$$

Hence, we need

$$\lambda_j(T) = \frac{\partial \Psi}{\partial x_j}(x(T)) \quad \text{if } j \notin \mathcal{T}$$

$$\lambda_i(T) = \text{free} \qquad\qquad \text{if } i \in \mathcal{T}$$

So we have

$$\begin{cases} \dot{x} = f \\ \dot{\lambda} = -\dfrac{\partial H^{\mathrm{T}}}{\partial x}, \end{cases}$$

an ODE with $2n$ variables. We need $2n$ boundary conditions for this ODE to be well-posed.

At $t = 0$		At $t = T$	
$x(0) = x_0$	$[n]$	$x_i(T) = x_{iT},\ i \in \mathcal{T}$	$[q]$
		$\lvert \mathcal{T} \rvert = q$	
		$x_j(T)$ free, $j \notin \mathcal{T}$	$[0]$
$\lambda(0)$ free	$[0]$	$\lambda_i(T)$ free, $i \in \mathcal{T}$	$[0]$
		$\lambda_j(T) = \dfrac{\partial \Psi}{\partial x_j}(x(T)),\ j \notin \mathcal{T}$	$[n-q]$

So we have $n + q + (n - q) = 2n$ boundary conditions.

We could even fix some but not all of $x(0)$, i.e.

$$x_i(0) = x_{i0} \quad \text{if } i \in \mathcal{I}$$

$$x_j(0) = \text{free} \quad \text{if } j \notin \mathcal{I}$$

Recall,

$$\delta \tilde{J}(u; v) = \int_0^T \left(\frac{\partial H}{\partial x} + \dot{\lambda}^{\mathrm{T}} \right) \eta \, \mathrm{d}t + \int_0^T \frac{\partial H}{\partial u} v \, \mathrm{d}t + \lambda^{\mathrm{T}}(0)\eta(0) + \left[\lambda^{\mathrm{T}}(T) - \frac{\partial \Psi}{\partial x}(x(T)) \right] \eta(T)$$

For $x_i(0) = x_{i0}$ fixed, we have $\eta_i(0) = 0$ and $\lambda_i(0)$ free. For $x_j(0)$ free, we have $\eta_j(0)$ free and $\lambda_j(0) = 0$.

To ponder, what if $J = \int L \, \mathrm{d}t + \Psi(x(T)) + \Theta(x(0))$?

To summarize, the minimizer to

$$\min_{u \in \mathcal{U}} \int_0^T L(x, u, t) \, \mathrm{d}t + \Psi(x(T))$$

$$\text{s.t.} \qquad \dot{x} = f(x, u, t)$$

$$x_i(0) = x_{i0}, \quad i \in \mathcal{I}$$

$$x_j(T) = x_{jT} \quad j \in \mathcal{T}$$

has to satisfy

$$\frac{\partial H}{\partial u} = 0$$

$$\dot{\lambda} = -\frac{\partial H^{\mathrm{T}}}{\partial x}$$

$$\lambda_i(0) = 0, \quad i \notin \mathcal{I}$$

$$\lambda_j(T) = \frac{\partial \Psi}{\partial x_j}(x(T)), \quad j \notin \mathcal{T}$$

Example

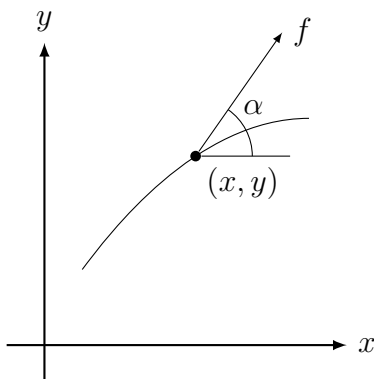$$\frac{\mathrm{d}}{\mathrm{d}t} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \\ x_4 \end{bmatrix} = f(x_1, x_2, x_3, x_4)$$

$$x_1(0) = 1,\ x_3(0) = 7,\ x_4(0) = 0,\ x_1(1) = 2$$

$$\mathcal{I} = \{1, 3, 4\},\ \mathcal{T} = \{1\}$$

$$\min \int_0^1 L(x, u)\, \mathrm{d}t + \left(x_2^2(1) - x_3^2(1) + 7x_1(1) + 14 \right)$$

Note there are 4 boundary conditions on x so there must be 4 boundary conditions on λ:

$\lambda_1(0)$ free/unspecified	$\lambda_1(1)$ free
$\lambda_2(0) = 0$	$\lambda_2(1) = 2x_2(1)$
$\lambda_3(0)$ free	$\lambda_3(1) = -2x_3(1)$
$\lambda_4(0)$ free	$\lambda_4(1) = 0$

Example
A force f acts on a particle at position (x, y) (mass = 1).

$$\dot{x} = v_x$$
$$\dot{y} = v_y$$
$$\dot{v}_x = |f| \cos \alpha$$
$$\dot{v}_y = |f| \sin \alpha$$
$$\alpha = \text{control variable}$$

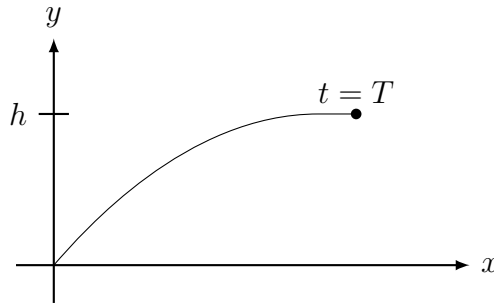Assume we only care about where the particle ends up (to be specified later), i.e. $L = 0$.

$$H = \begin{bmatrix} \lambda_x & \lambda_y & \lambda_{v_x} & \lambda_{v_y} \end{bmatrix} \begin{bmatrix} v_x \\ v_y \\ |f| \cos \alpha \\ |f| \sin \alpha \end{bmatrix}$$

$$\dot{\lambda}_x = -\frac{\partial H}{\partial x} = 0 \qquad \implies \qquad \lambda_x(t) = c_1$$

$$\dot{\lambda}_y = -\frac{\partial H}{\partial y} = 0 \qquad \implies \qquad \lambda_y(t) = c_2$$

$$\dot{\lambda}_{v_x} = -\frac{\partial H}{\partial v_x} = -\lambda_x \qquad \implies \qquad \lambda_{v_x}(t) = -c_1 t + c_3$$

$$\dot{\lambda}_{v_y} = -\frac{\partial H}{\partial v_y} = -\lambda_y \qquad \implies \qquad \lambda_{v_y}(t) = -c_2 t + c_4$$

Moreover,

$$\frac{\partial H}{\partial \alpha} = -\lambda_{v_x}|f|\sin\alpha + \lambda_{v_y}|f|\cos\alpha = 0$$

$$\tan \alpha = \frac{\lambda_{v_y}}{\lambda_{v_x}} = \frac{-c_2 t + c_4}{-c_1 t + c_3}$$

We want to drive the particle from $[0,0,0,0]^\mathrm{T}$ to a path parallel to the x-axis with $y(T) = h$.

Choose $\Psi = -v_x$,

$$
\begin{aligned}
&y(T) = h &&v_y(T) = 0 \\
&x(T) \text{ free} &&v_x(T) \text{ free, but costs} \\
&\lambda_i(0) \text{ free} \\
&\lambda_y(T) \text{ free} &&\lambda_{v_y}(T) \text{ free} \\
&\lambda_x(T) = 0 &&\lambda_{v_x}(T) = -1
\end{aligned}
$$

$$c_1 = \lambda_x(t) = 0$$
$$\implies \lambda_{v_x} = -c_1 t + c_3 = c_3 = -1$$
$$\implies \tan \alpha = -\frac{-c_2 t + c_4}{-1} = c_2 t + c_4$$

How do we find c_2 and c_4? Plug into $\dot{x}$ and $\dot{\lambda}$ and try to satisfy the remaining boundary conditions. (This is hard=numerics.)