Distributed Model Predictive Control

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Motivation 1

- **7** agents (double integrators)
- Potential functions
- local controllers
- input constraints
- two ellipsoidal obstacles
- Same initial and final position
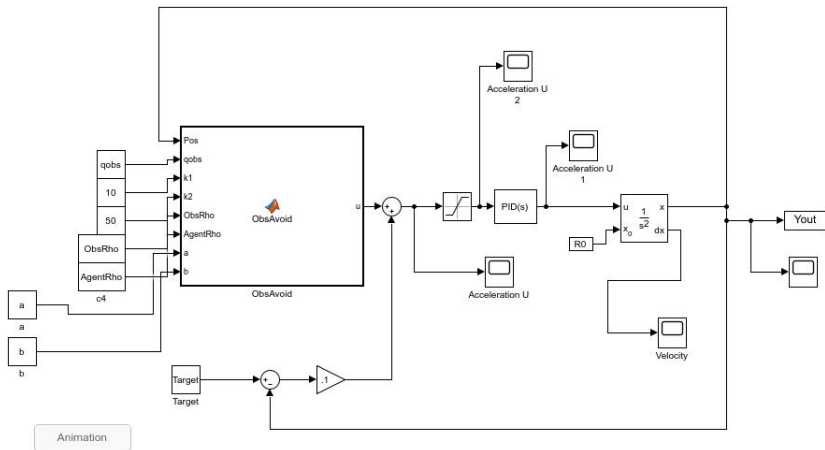- Safety distance between agents

Contents

Nonpredictive Scenario

- **7** agents (double integrators)
- Potential functions
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- Safety distance between agents

Nonpredictive Scenario (by AT) - Simulink

What I want to do

- Continue reading and filling the table
- Think about how to include consensus? (Flocking, or other ideas?!) **EiHoWe13d**, **ElAh07**
- if using a "global" costfunction, how to cope with iterations, are they avoidable to some extent?

Conclusion

- Continue reading and filling the table
- Think about how to include consensus? (Flocking, or other ideas?!)
- if using a "global" costfunction, how to cope with iterations, are they avoidable to some extent?

Outlook

- Continue reading and filling the table
- Think about how to include consensus? (Flocking, or other ideas?!)
- if using a "global" costfunction, how to cope with iterations, are they avoidable to some extent?

The End

Thank you very much for your attention!

Appendix

Here is space for further frames