

Optimal Control of Nonlinear Systems Using the Homotopy Perturbation Method

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Abstract—This paper presents a new method for solving a class of nonlinear optimal control problems with a quadratic performance index. In this method, first the original optimal control problem is transformed into a nonlinear two-point boundary value problem (TPBVP) via the Pontryagin's maximum principle. Then, using the Homotopy Perturbation Method (HPM) and introducing a convex homotopy in topologic space, the nonlinear TPBVP is transformed into a sequence of linear time-invariant TPBVP's. By solving the presented linear TPBVP sequence in a recursive manner, the optimal control law and the optimal trajectory are determined in the form of infinite series. Finally, in order to obtain an accurate enough suboptimal control law, an iterative algorithm with low computational complexity is introduced. An illustrative example demonstrates the simplicity and efficiency of proposed method.

Index Terms—nonlinear optimal control problem, Pontryagin's maximum principle, two-point boundary value problem, Homotopy Perturbation Method

I. INTRODUCTION

Theory and application of optimal control has been widely used in different fields such as biomedicine [1], aircraft systems [2], robotic [3], etc. However, optimal control of nonlinear systems is a challenging task which has been studied extensively for decades.

Methods of solving nonlinear optimal control problems (NOCVP's) can be divided into two categories. The first category, which contains direct methods, converts the problem into a nonlinear programming by using the discretization or parameterization techniques [4-5]. The second category contains indirect methods and leads to the Hamilton-Jacobi-Bellman (HJB) equation, based on dynamic programming [6], or nonlinear two-point boundary value problem (TPBVP), based on the Pontryagin's maximum principle [7]. In general, the HJB equation is a nonlinear partial differential equation that is hard to solve in most cases. An excellent literature review on the methods for approximating the solution of HJB

equation is provided in [8]. Besides, nonlinear TPBVP has no analytical solution except for a few simple cases. Thus, many researches have been devoted to find an approximate solution for the nonlinear TPBVP's. Recently, successive approximation approach (SAA) and sensitivity approach have been introduced in [9] and [10], respectively. In those, a sequence of nonhomogeneous linear time-varying TPBVP's is solved instead of directly solving the nonlinear TPBVP derived from the Pontryagin's maximum principle. However, solving time-varying equations is much more difficult than solving time-invariant ones.

The Homotopy Perturbation Method (HPM) was initially proposed by the Chinese mathematician J. H. He [11-12]. This method has been widely used to solve nonlinear problems in different fields [13-15]. In contrast to the perturbation method [16], the HPM is independent upon small/large physical parameters in system model. However, like the other traditional non-perturbation methods such as the Lyapunov's artificial small parameter method [17] and Adomian's decomposition method [18], uniform convergence of the solution series obtained via the HPM can not be ensured.

In this paper, based on the HPM, a new method is proposed to solve a class of nonlinear OCP's. In this method, first the original nonlinear OCP is transformed into a nonlinear TPBVP by using the maximum principle. Applying the HPM transforms the nonlinear TPBVP into a sequence of linear time-invariant TPBVP's. Solving the proposed linear TPBVP sequence in a recursive manner leads to the optimal control law and the optimal trajectory in the form of infinite series. The proposed method avoids the trouble of directly solving the nonlinear TPBVP or the HJB equation. In addition, it avoids solving a sequence of linear time-varying TPBVP's. It only requires solving a sequence of linear time-invariant TPBVP's. Hence, it reduces the computational complexity, effectively. The rest of paper is organized as follows. In section 2 the statement of problem is discussed. Section 3 elaborates the

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Deep Reinforcement Learning with Guaranteed Performance Yinyan Zhang, Shuai Li, Xuefeng Zhou, 2019-11-09 This book discusses methods and algorithms for the near optimal adaptive control of nonlinear systems including the corresponding theoretical analysis and simulative examples and presents two innovative methods for the redundancy resolution of redundant manipulators with consideration of parameter uncertainty and periodic disturbances It also reports on a series of systematic investigations on a near optimal adaptive control method based on the Taylor expansion neural networks estimator design approaches and the idea of sliding mode control focusing on the tracking control problem of nonlinear systems under different scenarios The book culminates with a presentation of two new redundancy resolution methods one addresses adaptive kinematic control of redundant manipulators and the other centers on the effect of periodic input disturbance on redundancy resolution Each self contained chapter is clearly written making the book accessible to graduate students as well as academic and industrial researchers in the fields of adaptive and optimal control robotics and dynamic neural networks

Computational Optimal Control Dr Subchan Subchan, Dr Rafal Zbikowski, 2009-08-19 Computational Optimal Control Tools and Practice provides a detailed guide to informed use of computational optimal control in advanced engineering practice addressing the need for a better understanding of the practical application of optimal control using computational techniques Throughout the text the authors employ an advanced aeronautical case study to provide a practical real life setting for optimal control theory This case study focuses on an advanced real world problem known as the terminal bunt manoeuvre or special trajectory shaping of a cruise missile Representing the many problems involved in flight dynamics practical control and flight path constraints this case study offers an excellent illustration of advanced engineering practice using optimal solutions The book describes in practical detail the real and tested optimal control software examining the advantages and limitations of the technology Featuring tutorial insights into computational optimal formulations and an advanced case study approach to the topic Computational Optimal Control Tools and Practice provides an essential handbook for practising engineers and academics interested in practical optimal solutions in engineering Focuses on an advanced real world aeronautical case study examining optimisation of the bunt manoeuvre Covers DIRCOL NUDOCCS PROMIS and SOCS under the GESOP environment and BNDSCO Explains how to configure and optimize software to solve complex real world computational optimal control problems Presents a tutorial three stage hybrid approach to solving optimal control problem formulations

Analysis and Control of Nonlinear Systems Christopher I. Byrnes, Clyde Martin, Richard Saeks, 1988

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Role of Nutrients in Neurological Disorders Senthilkumar Rajagopal, Saravanan Ramachandran, Geethalakshmi Sundararaman, Swarnalatha Gadde Venkata, 2022-03-12 This book provides the latest research on the role of nutrients in the

prevention and treatment of neurological disorders It discusses dietary supplements and dietary restrictions for combating neurological disorders including Alzheimer s disease Parkinson s disease stroke and epilepsy The book also explains the impact of different nutrients such as herbal products algae micronutrients in stimulating the brain and central nervous system during abnormal functions It covers the effect of the nutrients on the function of neurotransmitters their stimulatory effect in autism dementia Alzheimer s and other neuropathological states The book also defines the mechanistic effects of neuroprotective and psycho protective effects of natural food in repairing brain damage This book is essential reading for neuroscientists and neurologists and healthcare professionals International Aerospace Abstracts ,1999 *Nonlinear and Optimal Control Systems* Thomas L. Vincent,Walter J. Grantham,1997-06-23 Designed for one semester introductory senior or graduate level course the authors provide the student with an introduction of analysis techniques used in the design of nonlinear and optimal feedback control systems There is special emphasis on the fundamental topics of stability controllability and optimality and on the corresponding geometry associated with these topics Each chapter contains several examples and a variety of exercises **Nonlinear Controllability and Optimal Control** H.J. Sussmann,2017-11-22 This outstanding reference presents current state of the art research on important problems of finite dimensional nonlinear optimal control and controllability theory It presents an overview of a broad variety of new techniques useful in solving classical control theory problems Written and edited by renowned mathematicians at the forefront of research in this evolving field *Nonlinear Controllability and Optimal Control* provides detailed coverage of the construction of solutions of differential inclusions by means of directionally continuous sections Lie algebraic conditions for local controllability the use of the Campbell Hausdorff series to derive properties of optimal trajectories the Fuller phenomenon the theory of orbits and more Containing more than 1 300 display equations this exemplary instructive reference is an invaluable source for mathematical researchers and applied mathematicians electrical and electronics aerospace mechanical control systems and computer engineers and graduate students in these disciplines **Proceedings, 1995 International Symposium on Nonlinear Theory and Its Applications** ,1995 **On the Necessary Condition for Optimal Control of Nonlinear Systems** H. Halkin,1963 *Mathematical Reviews* ,2007 **Dissertation Abstracts International** ,2006 **Technology for Large Space Systems: A Bibliography with Indexes (supplement 22)** ,1990 *Journal of Guidance, Control, and Dynamics* ,2008 **Applied Science & Technology Index** ,1997 **Documentation Abstracts** ,1996 **SIAM Journal on Control and Optimization** Society for Industrial and Applied Mathematics,1999 Contains research articles on the mathematics and applications of control theory and on those parts of optimization theory concerned with the dynamics of deterministic or stochastic systems in continuous or discrete time or otherwise dealing with differential equations dynamics infinite dimensional spaces or fundamental issues in variational analysis and geometry

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web nov 30 2017 here s a basic explanation of the recap hours recaps are the hours you get back after the 8th day basically you have 70 hours to last 8 days after the 8th day you get back the hours you worked on the first

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web fmcsa s educational tool for hours of service ethos helps motor carriers and drivers better understand the hos regulations going into effect on september 29 2020 when drivers and carriers enter their duty statuses into the web based log below ethos will identify where potential violations of the following rules may have occurred

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web to two hours so property carriers have a 16 hour driving window within which to complete up to 13 hours of driving and passenger carriers have a 17 hour duty period within which to complete up to 12 hours of driving the revised definition of adverse driving conditions clarifies the role of the driver in determining when such

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web jun 1 2020 any 10 consecutive hour or more break or under the sleeper berth exception a sleeper berth period of at least 7 hours paired with a separate rest period of at least 2 hours in the sleeper berth or off duty these two period must total at least 10 hours the 30 minute break is not a qualifying rest break or sleeper berth period

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web this form is designed for use in maintaining a running record of a driver s on duty time regardless of the time your company designates as the start of its 24 hour period it can also be used to accurately compute the drivers time used and hours available by making the entries in the appropriate chart for either

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web jul 19 2023 in trucking recap hours refer to the practice of running on recaps or recycling available work hours after completing an 8 day cycle without a 34 hour reset in other words recap hours are those regained by a trucker after their clock resets at midnight on the 8th day

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web hours of service hos hours of service refers to the maximum amount of time drivers are permitted to be on duty including driving time and specifies number and length of rest periods to help ensure that drivers stay awake and alert

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web nov 11 2020 logbook form which tracks the hours of service statuses of a driver for 24 hours motor carrier company or person supplying transportation of property or passengers via cmvs off duty status leisure time or rest time for a driver

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web sep 26 2022 the hours that truck drivers spend on duty are the hours used for calculations like the 70 hour 8 day rule and the 14 hour limit see below for detailed information time behind the wheel is calculated separately and is used to measure when 30 minute breaks should be taken and how many hours a driver may spend behind the

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web example 1 8 days 70 hours instructions in the sample log recap form shown below the on duty information is shown for the last 7 days of march and the first day of april fill out the log recap form for the period april 2 april 7 using the information which follows

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web dec 12 2019 a beginner s guide to understanding dot hours of service rules the federal motor carrier safety administration fmcsa regulates the number of hours commercial drivers may drive and work per day and week these hos rules also encompass other restrictions such as taking mandatory rest breaks

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web instructions when using a driver for the first time or intermittently a signed statement must be obtained giving the total time on duty driving and on duty during the immediate preceding seven days and the time at which the driver was last relieved from duty prior to beginning work