# Engineering Tripos Part IIB, 4F3: An Optimisation Based Approach to Control, 2019-20

#### **Module Leader and lecturer**

Dr G Vinnicombe [1]

#### Lecturer

Dr G Vinnicombe, Dr F.F. Forni [2]

#### **Timing and Structure**

Lent term. 14 lectures + 2 examples classes, Assessment: 100% exam

#### **Prerequisites**

3F1 and 3F2 useful

#### **Aims**

The aims of the course are to:

- introduce methods for feedback system design based on the optimization of an objective, including reinforcement learning and predictive control.
- demonstrate how such control laws can be computed and implemented in practice.

### **Objectives**

As specific objectives, by the end of the course students should be able to:

- understand the derivation and application of optimal control methods.
- · appreciate the main ideas, applications and techniques of predictive control and reinforcement learning.

#### Content

#### Optimal Control (7L + 1 examples class, Dr F Forni)

- Formulation of convex optimisation problems
- · Status of theoretical results and algorithms
- Formulation of optimal control problems. Typical applications
- Optimal control with full information (dynamic programming)
- Control of Linear Systems with a quadratic objective function
- Output feedback: 'LQG' control
- Control design with an "H-infinity" criterion

## Predictive Control and an Introduction to Reinforcement Learning (7L + 1 examples class, Dr G Vinnicombe)

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Published on CUED undergraduate teaching site (https://teaching23-24.eng.cam.ac.uk)

- What is predictive control? Importance of constraints. Flexibility of specifications. Typical applications
- Basic formulation of predictive control problem without constraints and the receding horizon concept.
  Comparison with unconstrained Linear Quadratic Regulator
- Including constraints in the problem formulation. Constrained convex optimization
- · Terminal conditions for stability
- Emerging applications: advantages and challenges
- · Policy and generalized policy iteration; rollout algorithms and predictive control
- Approximate dynamic programming
- Deep neural nets as universal approximators for value and policy.
- Simulation based vs state space models Q learning.

#### **Booklists**

Please see the **Booklist for Group F Courses** [3] for references for this module.

#### **Examination Guidelines**

Please refer to Form & conduct of the examinations [4].

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#### Links

- [1] mailto:gv103@cam.ac.uk
- [2] mailto:gv103@cam.ac.uk, ff286@cam.ac.uk
- [3] https://www.vle.cam.ac.uk/mod/book/view.php?id=364101&chapterid=55891
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