

# Asymptotic Optimality of AO-x

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Asymptotically optimal x (AO-x) [1] is a meta kinodynamic motion planner [4], which can take as input any feasible kinodynamic motion planner, and convert it into an asymptotically optimal planner. Common choices for  $x$  are the rapidly-exploring random tree (RRT) [3] planner or the expansive space-trees (EST) [2] planner. In this document, I will summarize the proof of asymptotic optimality for AO-x, which is fully detailed in [1].

Let us first declare some variables. Let  $X$  be a feasible kinodynamic motion planning algorithm. Note that  $X$  needs to be a probabilistically complete kinodynamic planner (but not necessarily asymptotically optimal).

To prove that AO-x with algorithm  $X$  is asymptotically optimal, let us first write down two assumptions:

**Assumption 1.** *Algorithm  $X$  will terminate in finite time.*

**Assumption 2.** *Algorithm  $X$  reduces cost by a non-negligible amount. This means: Let  $\bar{C}$  be the cost limit, and  $C^*$  the optimal cost. Then the expected suboptimality is shrunk toward  $C^*$  by a non-negligible amount each iteration. If  $C(\pi)$  is the current path cost, then*

$$\mathbb{E}[C(\pi) \mid \bar{C} - C^*] \leq (1 - w)(\bar{C} - C^*), \quad (1)$$

whereby  $w > 0$  is a constant positive value.

By assuming Assumption 1 and 2, we can state and prove the following theorem.

**Theorem 1.** *AO-x is asymptotically optimal.*

*Proof.* Let  $S_0, \dots, S_n$  be non-negative random variables denoting  $C(\pi_i) - C^*$ , i.e. the cost difference between the cost of the returned path in iteration  $i$  and the optimal path cost  $C^*$ .

Our goal is to prove that the sequence converges almost surely, i.e.

$$P(\lim_{n \rightarrow \infty} S_n = 0) = 1. \quad (2)$$

This means, that the sequence  $S_0, \dots, S_n$  will converge to 0 when  $n$  goes to infinity with probability 1. The proof itself consists of 4 steps.

**Step 1: Transformation to convergence in probability**

Let us first make a transformation of Eq. (2). Since  $S_n$  is always non-negative, it is sufficient to show that  $S_n$  converges in probability (see info box below) as  $S_n \rightarrow 0$ , to prove the original result which results in

$$\lim_{n \rightarrow \infty} P(S_n > \epsilon) = 0. \quad (3)$$

While this is a weaker statement (in probability) compared to Eq. (2) (almost surely), we can, however, rely on the fact that if a nonnegative sequence (like  $S_n$ ) converges to 0 in probability, then there exists a subsequence that actually converges to 0 with probability 1 [5]. From here, we are left to prove that the sequence converges in probability.

**Convergence in Probability.** Let  $X_1, X_2, \dots$  be a sequence of random variables. We say this sequence *converges in probability* to a random variable  $X$ , written as  $X_n \xrightarrow{P} X$ , if, for all  $\epsilon > 0$

$$\lim_{n \rightarrow \infty} P(|X_n - X| > \epsilon) = 0.$$

**Step 2: Applying Markov inequality**

The Markov inequality states that  $P(S_n \geq \epsilon) \leq \frac{\mathbb{E}[S_n]}{\epsilon}$ . If we could prove that

$$\lim_{n \rightarrow \infty} \frac{\mathbb{E}[S_n]}{\epsilon} = 0, \quad (4)$$

then this would imply Eq. 3. This is a valuable step, since our assumptions already provide an upper bound for the expected value.

**Step 3: Find upper bound to conditional expectancy**

By using Assumption (2), we can find an upper bound to the expected value of  $S_n$  as

$$\mathbb{E}[S_n] = \int \mathbb{E}[S_n | S_{n-1}] P(S_{n-1}) dS_{n-1} \quad (5)$$

$$\leq (1 - w) \int S_{n-1} P(S_{n-1}) dS_{n-1} \quad (6)$$

$$= (1 - w) \mathbb{E}[S_{n-1}] = (1 - w)^n \mathbb{E}[S_0] \quad (7)$$

**Step 4: Evaluate the expectancy**

Using the upper bound for the expectancy we can now evaluate

$$\lim_{n \rightarrow \infty} P(S_n > \epsilon) \leq \lim_{n \rightarrow \infty} \frac{\mathbb{E}[S_n]}{\epsilon} \quad (8)$$

$$\leq \lim_{n \rightarrow \infty} \frac{\mathbb{E}[S_0](1 - w)^n}{\epsilon} \quad (9)$$

$$\leq \frac{\mathbb{E}[S_0]}{\epsilon} \lim_{n \rightarrow \infty} (1 - w)^n = 0. \quad (10)$$

This in turn verifies Eq. 2 through Eq. 3 as desired.  $\square$

## References

- [1] Kris Hauser and Yilun Zhou. Asymptotically optimal planning by feasible kinodynamic planning in a state–cost space. *IEEE Transactions on Robotics*, 32(6):1431–1443, 2016.
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