Gaussian Process Based Visual Pursuit Control with Unknown Target Motion Learning in Three Dimensions

Marco Omainiska *, Junya Yamauchi *, Thomas Beckers **, Takeshi Hatanaka ***, Sandra Hirche ****, and Masayuki Fujita *****

Abstract: In this paper, we propose an observer-based visual pursuit control integrating 3-dimensional target motion learning by Gaussian Process Regression (GPR). We consider a situation where a visual sensor equipped rigid body pursues a target rigid body whose velocity is unknown, but dependent on the target’s pose. We estimate the pose from visual information and propose a Gaussian Process (GP) model to predict the target velocity from the pose estimate. We analyze stability of the proposed control by showing that estimation and control errors are ultimately bounded with high probability. Finally, simulations illustrate the performance of the proposed control schemes even if the visual measurement is corrupted by noise.

Key Words: vision-based estimation and control; rigid body motion; Gaussian Process; passivity

1. Introduction

Vision sensors are essential for the recognition of the external world because of their capability of obtaining rich information. The use of vision sensors in robot control has a long history [1] and their importance is increasing along with technological advances in mobile robots. Important applications for vision-equipped mobile robots include infrastructure inspections [2], bird control for farm [3] and biological studies [4]. This paper deals with the problem of estimating and tracking the motion of an object by a mobile robot equipped with a vision sensor.

Control methods that use a vision sensor to estimate the state of a robot in the environment and maintain it in a desired position have been proposed, for example in [5],[6]. The authors of [7],[8] consider tracking control of a target with simultaneous vision-based estimation of the unknown target pose in two dimensions. In contrast to [7] and [8], [9] proposes an observer-based control to pursuit a target rigid body moving in three dimensions. Furthermore, since the target motion is generally unknown, the approach in [9] extends the control law by a target body velocity generator model to achieve pursuit with zero steady-state error. However, since the information of the generator is required prior to the control system design, applicable situations are possibly limited. A promising technique to identify uncertain dynamics without the necessity of prior abundant knowledge is exploited in Machine Learning (ML).

Attention in the control community has been given to Gaussian Process (GP) models due to the strong Bayesian foundation including their advantage of estimating the uncertainty [10]. However, ML techniques typically suffer from lacking theoretical guarantees such as stability analysis, which limits the applicability to non-safety relevant systems. In [11]–[14], a GP model is utilized to learn the unknown dynamics and to analyze control performance and stability. By using the mean function of a GP model in a feed-forward manner, [13] aims to eliminate unmodeled dynamics and further provide a method to adjust the error feedback gains based on the GP variance. The author’s recent publication [15] extends the result in [9] with the technique from [13] by integrating the learned GP target motion model into the visual pursuit control scheme to guarantee stability with high probability. In [15], a GP model learns the unknown body velocity as a function of the target’s position for an observer-based control, assuming that the target is moving influenced by the environment, such as terrains and obstacles. However, since the target motion consists of both translation and rotation, the proposed visual pursuit control scheme is limited to a special class of target motions.

This paper proposes a stability-guaranteed visual pursuit control scheme based on a GP model that learns the unknown target body velocity, which is not only dependent on the position but also orientation. To begin with, we introduce rigid body motion, visual measurements and GPR. Then, the learning method by using GP models is addressed. Next, we propose a visual pursuit control law where the learned GP mean function is utilized to cancel the target body velocity, and the variance function to adjust error feedback gains. We then derive conditions on the gains to prove ultimate boundedness with high probability of the estimation and control errors. The main contributions of this paper are as follows: (i) extending the class of target body velocity to that of pose-dependent body velocity, (ii) proposing a visual pursuit control law based on the learned GP model and proving stability, (iii) showcase effect of gain adjustments by variance for noise attenuation in visual measurement.

In the following, Section 2 briefly describes the problem set-
Fig. 1: Target rigid body and camera configuration.

and Section 3 addresses a method of Visual Motion Observed-based target motion learning. Thereafter, a new visual pursuit control with GP-prediction is proposed and stability is also analyzed in Section 4. Finally, simulations illustrate the efficiency of the proposed control law in Section 5.

2. Problem Setting

This section introduces the basics of rigid body motion, visual measurement [9], and the class of the target body velocity.

2.1 Rigid Body Motion

Assume a target and visual sensor moving in 3-dimensional space (Fig. 1) with inertial coordinate frame $\Sigma_i$, and body-fixed frames $\Sigma_w, \Sigma_h$. Their orientation and position are denoted by the pose $\hat{g}_{wo}$ in $SE(3)$ with respect to $\Sigma_i$. To this end, we define the ball with radius $\pi$ centered at the origin as $\mathcal{B}_\pi(0):=\{a \in \mathbb{R}^3 | |a| \leq \pi\}$. Since the exponential map is surjective from $\mathcal{B}_\pi(0)$ to $SO(3)$ [16], all target orientation $\hat{\xi}_{th,i}$ are described by $\hat{\xi}_{th,i} \in \mathcal{B}_\pi(0)$. Thus, we introduce the vector representation of $g \in SE(3)$ as

$$\hat{g} := \begin{bmatrix} p' \xi' \end{bmatrix} \in \mathbb{R}^6 \quad (4)$$

and denote the body velocity as $V^b_{wo} : \mathbb{R}^3 \times \mathcal{B}_\pi(0) \rightarrow \mathbb{R}^6$. $\hat{g}_{wo} \mapsto V^b_{wo}(\hat{g}_{wo})$. (5)

This is a wider class of the body velocity than that assumed in [15] where the class of body velocity is assumed to be dependent just on the position $p_{wo}$, namely, $V^b_{wo} : \mathbb{R}^3 \rightarrow \mathbb{R}^6$. This paper uses a GP model to identify the unknown body velocity $V^b_{wo}$ as a function of the pose $\hat{g}_{wo}$, and use it for visual pursuit control later in Section 4. The stability of the proposed visual pursuit system is also discussed there.

2.2 Visual Measurements

In line with [9,p.105] and following the author’s results, the camera model of a pinhole camera is defined. It is used to measure feature points of the moving target in a 3D-environment as shown in Fig. 1. This process of extracting feature points in vast image data is common for real-time visual control scenarios [17]. Thus, we assume that the target has $n_f$ feature points whose position vectors relative to its object frame $\Sigma_o$ are denoted by $p_{ci} \in \mathbb{R}^3, i = [1, \ldots, n_f]$, which are known a priori.

Let the position of $p_{ci}$ as viewed from $\Sigma_i$ be $p_{ci} = \begin{bmatrix} x_{ci} \ y_{ci} \ z_{ci} \end{bmatrix} \in \mathbb{R}^3$ satisfying $[p_{ci}']^T = g_{co}[p_{ci}']^T, i = [1, \ldots, n_f]$. It is then projected onto the image plane of the camera by perspective projection [1] as a feature point $f_i \in \mathbb{R}^2$:

$$f_i = \frac{\lambda}{z_{ci}} \begin{bmatrix} x_{ci} \\ y_{ci} \end{bmatrix} \in \mathbb{R}^2$$

with $\lambda > 0$ the focal length. By stacking (6) into a vector we obtain the visual measurement $f := [f'_1 \ \cdots \ f'_{n_f}] \in \mathbb{R}^{2n_f}$.

3. Observer-based Target Motion Learning

This section addresses how the target motion is learned. Consequently, the GP model for the purpose of target motion learning is defined, and in order to collect data for learning of the GP model, the Visual Motion Observer (VMO) [9] is introduced.

3.1 Gaussian Process Regression

Gaussian Process Regression (GPR) predicts unknown functions based on input output data and further provides a measure to quantify the model fidelity. Suppose one can measure data pairs of an unknown function $h : \mathbb{R}^N \rightarrow \mathbb{R}^N$ as

$$y = h(x) + \epsilon \in \mathbb{R}^N, \quad x \in \mathbb{R}^N$$

$$\epsilon \sim \mathcal{N}(0, \sigma^2 \Sigma)$$

with sub-Gaussian noise such that $|\epsilon| \leq \sigma_{n\delta}$ almost surely. The training dataset $\mathcal{D}$ consists of $M$ measurements of the input $\{x^{(m)}\}_{m=1}^M$ and output $\{y^{(m)}\}_{m=1}^M$ stacked into matrices
\[ D = \{ X, Y \}, \quad X := \left[ x^{(1)} \ldots x^{(M)} \right] \in \mathbb{R}^{N \times M}, \quad Y := \left[ y^{(1)} \ldots y^{(M)} \right] \in \mathbb{R}^{N \times N} \] (8)

Consequently, the prediction \( y^* \in \mathbb{R}^N \) at an input \( x^* \in \mathbb{R}^N \) is jointly Gaussian distributed with prior mean zero, and the mean and variance are defined as follows:

\[ \mu(y^* \mid D, \varphi, x^*) = K_p(x^*, X) \left( \mathbf{K}_p + \sigma_n^2 \mathbf{I}_M \right)^{-1} Y, \]

\[ \Sigma(y^* \mid D, \varphi, x^*) = K_p(x^*, x^*) - K_p(x^*, X) \left( \mathbf{K}_p + \sigma_n^2 \mathbf{I}_M \right)^{-1} K_p(X, x^*). \] (9)

For notational convenience, the above terms are shortened to \( \mu(x^*) \) and \( \Sigma(x^*) \) hereon. Let the correlation between two inputs \( (x, x') \) be measured by the SE-ARD kernel

\[ k_p(x, x') = \sigma^2_{j,k} \exp \left( -\frac{1}{2} \sum_{i=1}^{N} \left( x_i - x'_i \right)^2 \rho_{ij} \right). \] (10)

**Remark 1** Since the SE-ARD kernel is a universal kernel, GPR with (10) can approximate any continuous function arbitrarily close on a compact set.

The entries of the GP kernel matrix \( \mathbf{K}_p := K_p(X, X) \in \mathbb{R}^{M \times M} \) represent the covariance between two elements of the dataset \( X \)

\[ k_p(x_j, x_{j'}) := k_p(X_j, X_{j'}), \quad j, j' \in \{1, \ldots, M\} \cdot \]

\( k_p(x_j, X) \in \mathbb{R}^M \) denotes the vector-valued extended covariance function. \( Y, X \) resemble the \( i \) th, \( j \) th column of matrix \( Y, X \) and \( y^j, x^j \) is the \( i \) th, \( j \) th element of vector \( y^*, x^* \). Lastly, \( \varphi := \left[ \rho_{11}, \ldots \rho_{1b} \sigma_{1}^2 \right] \in \mathbb{R}^2 \) represents the set of hyperparameters with lengthscale \( \rho \) and signal variance \( \sigma^2 \) which are typically obtained by likelihood maximization [10].

A kernel for SE(3) is proposed in [18], and it can be expected to achieve better regression performance. However, we leave it as future work replacing (10) by the kernel proposed in [18].

### 3.2 Learning of Target Motion

The goal of this section is to propose a learning method for the unknown target body velocity \( V_{\text{th}}^b \) (\( \dot{g}_{\text{th}} \)) by GPR using the target pose \( \hat{g}_{\text{th}} \) as the input \( x \), and the target body velocity \( V_{\text{th}}^b \) as the output \( y \) in equation (7). In other words, the GP model in this paper predicts a function of the form

\[ y = V_{\text{th}}^b(x) + \epsilon, \quad x = \hat{g}_{\text{th}}. \] (11)

Further, the following assumption is necessary such that target motion learning is feasible:

**Assumption 1** The target moves in a bounded 3-dimensional field, namely, its position belongs to a compact set \( D \subset \mathbb{R}^3 \).

Because target movements generally happen in bounded fields and environments, Assumption 1 is non-restrictive.

Since the Cartesian product of two compact sets is again a compact set, the following set is also compact from Assumption 1 and compactness of \( B_n(0) \):

\[ X := D \times B_n(0). \] (12)

The combined multi-variable Gaussian distribution in this paper is defined as the overall GP model

\[ \mu(\hat{g}_{\text{th}}) = [\mu_1 \ldots \mu_b] \in \mathbb{R}^b, \]

\[ \Sigma(\hat{g}_{\text{th}}) = \text{diag}(\Sigma_1, \ldots, \Sigma_b) \in \mathbb{R}^{b \times b}. \] (13)

We now derive the following lemma regarding the upper bound of model fidelity from [19, Theorem 6]:

**Lemma 1** Consider the target model (2) and the trained GP model (13) with the dataset \( D \) (8). Further, define the maximum information gain after observing \( M' = M + 1 \) data pairs as

\[ \xi_i = \max_{x \in X} \log |M' + \sigma_n^2 K_p|, \quad i \in \{1, \ldots, 6\} \] (14)

with the dataset \( X' := \left[ x^{(1)} \ldots x^{(M')} \right] \in \mathbb{R}^{6 \times M'} \) and \( K_p := K_p(X', X') \in \mathbb{R}^{M' \times M'} \). Then, the model error is bounded by

\[ \mathcal{P} \left( |\hat{g}_{\text{th}} - g_{\text{th}}| < V_{\text{th}}^b \right) \leq \left\| \beta(\delta) \Sigma^{1/2}(\hat{g}_{\text{th}}) \right\| \geq \delta \] (15)

for any probability \( \delta \in (0, 1) \) and elements of \( \beta \in \mathbb{R}^6 \) satisfy

\[ \beta(\delta) = \sqrt{2} \left( |V_{\text{th}}^b| \Sigma_{k_p} + 300 \zeta \ln \left( \frac{M + 1}{1 - \sqrt{\delta}} \right) \right) \] (16)

where \( |V_{\text{th}}^b| \Sigma_{k_p} \) is the bounded reproducing kernel Hilbert space norm associated with kernel \( k_p \) of \( i \) th element of \( V_{\text{th}}^b \).

Note that one can find an upper-bound \( \hat{\delta} \) of the model error as

\[ \left\| \beta(\delta) \Sigma^{1/2}(\hat{g}_{\text{th}}) \right\| \leq \hat{\delta}(\delta) \] (17)

on \( X \) [20]. Furthermore, the parameter \( \beta_i \) increases with the amount of data, but due to a sub-linear dependency of \( \zeta \) on the number of data observed, the bound in (15) can be decreased [12]. Even though \( V_{\text{th}}^b \) is not an element of the RKHS associated with \( k_p \) (i.e., \( |V_{\text{th}}^b| \Sigma_{k_p} \) is not bounded), Remark 1 assures their boundedness for functions arbitrarily close to \( V_{\text{th}}^b \) [20].

### 3.3 Visual Motion Observer

Prior to control phase, let the VMO estimate the relative pose \( g_{\text{co}} \) of a moving target (2) in the perspective of a camera (2) in a training phase in order to collect data of the target pose \( \hat{g}_{\text{co}} := \hat{g}_{\text{co}} \). The estimated target velocity can be calculated from

\[ \hat{g}_{\text{co}} = \hat{g}_{\text{co}} + \dot{g}_{\text{co}}. \]

The estimate of \( g_{\text{co}} \) is denoted by \( \hat{g}_{\text{co}} := \hat{g}_{\text{co}} + \dot{g}_{\text{co}} \).

The model for motion estimation [9, Section 6] is given by

\[ \hat{g}_{\text{co}} = \hat{g}_{\text{co}} + \dot{g}_{\text{co}}. \] (18)

The goal of this section is to find an observer input \( u_c \) for training phase, and later in Section 4 for control phase.

The vector representation of \( g \) is given as

\[ \text{vec}(g) := \left[ P \frac{\theta}{\text{sk}(\theta^2)} \right] \in \mathbb{R}^6 \] (19)

with \( \text{sk}(A) := (1/2)(A - A^\top) \), \( A \in \mathbb{R}^{3 \times 3} \). Then, the estimation error \( e_{\text{co}} \) is given as

\( e_{\text{co}} \in \mathbb{R}^6 \) are defined as

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1 Using \( \text{vec}(g) \) is crucial to show passivity of the visual pursuit system in Lemma 2, but disadvantageous for GP learning and prediction since \( \text{sk}(\theta^2) = \xi \sin \theta = \xi \sin(\theta + \pi/2) \) for \( \theta \in [0, \pi/2] \) [9]. Hence, there might be conflicts in the rotation data.
The goal is now to combine the VMO with the GP model from Section 3.3. Similar to the estimation error (20), one defines the pose control error \( \mathbf{g}_{ce} = (\mathbf{p}_{ce}, \hat{\mathbf{e}}\hat{\mathbf{e}}) \in \mathbb{SE}(3) \) and control error \( \mathbf{e}_c \in \mathbb{R}^6 \) as
\[
\mathbf{g}_{ce} := \mathbf{g}^{-1}_d \mathbf{g}_{co}, \quad \mathbf{e}_c := \text{vec}(\mathbf{g}_{ce}). \tag{24}
\]
We assume the following for the control error:

**Assumption 3** The control error angle is bounded by \( |\theta_{ce}(t)| \leq \pi/2, \forall t \geq 0 \).

This assumption is in general satisfied due to the given scenario as the target moves slower than the robot with camera.

Again, differentiating the control error (24) we achieve
\[
\dot{\mathbf{g}}_{ce} = \mathbf{u}_c \mathbf{g}_{ce} - \mathbf{g}_c \dot{\mathbf{u}}_c, \tag{25}
\]
and thus the control error system results to
\[
\dot{\mathbf{V}}^b_{ce} := (\mathbf{g}^{-1}_d \mathbf{g}_{ce}) = -\mathbf{u}_c + \text{Ad}_{(\mathbf{g}_c)} \mathbf{u}_c \tag{26}
\]
with \( \dot{\mathbf{V}}^b_{ce} \) the control error velocity. Finally, the combination of both \( \mathbf{V}^b_{ce} \) and \( \dot{\mathbf{V}}^b_{ce} \) obtained in Section 3.3 yields the error system
\[
\begin{align*}
\dot{\mathbf{V}}^b_{ce} &= \begin{bmatrix} \text{Ad}_{(\mathbf{g}_c)} & -I_b \end{bmatrix} \mathbf{u} + \begin{bmatrix} 0 & I_b \end{bmatrix} \mathbf{V}^b_{wo}(\mathbf{g}_{wo}) \\
\mathbf{u} &:= \begin{bmatrix} \mathbf{u}_c & \mathbf{e}_c \end{bmatrix} \in \mathbb{R}^{12}.
\end{align*}
\tag{27}
\]

The goal is now to find a suitable input \( \mathbf{u} \) that adapts the GP model from Section 3.2.

To this end, we first show passivity of the error system. We define the positive definite function
\[
S := \frac{1}{2} \|\mathbf{p}_{ce} \|^2 + \phi(\mathbf{e}) \tag{28}
\]
and the total error \( \mathbf{e} = [\mathbf{e}_c^T \mathbf{e}_w^T]^T \in \mathbb{R}^6 \) and output \( \mathbf{v} \in \mathbb{R}^{12} \) as
\[
\mathbf{v} := N \mathbf{e}, \quad N := \begin{bmatrix} I_b & 0 \\
-\text{Ad}_{(\mathbf{e}^w)} & I_b \end{bmatrix}. \tag{29}
\]

Then, the following lemma is derived:

**Lemma 2 (Lemma 7.1)** [9] The time derivative of \( S \) (28) along with the error system (27) obeys
\[
\dot{S} = \mathbf{v}^T \mathbf{u} + \mathbf{e}^T \begin{bmatrix} I_b & 0 \end{bmatrix} \mathbf{V}^b_{wo}(\mathbf{g}_{wo}). \tag{30}
\]

**Proof:** Refer to [9,Equation (6.2)].

Hence, for the case of the static target (\( \mathbf{V}^b_{wo} \equiv 0 \)), the error system (27) is passive from input \( \mathbf{u} \) to output \( \mathbf{v} \) with respect to the storage function \( S \). Thus, for the given scenario of a moving target (\( \mathbf{V}^b_{wo} \neq 0 \)) under Assumption 2, we propose the following input \( \mathbf{u} \) using \( \mathbf{g}_{wo} = \mathbf{g}_{wc} \mathbf{g}_{wo} \) as
\[
\mathbf{u} = -K\{\mathbf{g}_{wo}\} \mathbf{v} - \begin{bmatrix} \text{Ad}_{(\mathbf{e}^w)} & 0 \\
0 & \text{Ad}_{(\mathbf{e}^w)} \end{bmatrix} \mu(\mathbf{g}_{wo}). \tag{31}
\]

The first term achieves asymptotic stability of the equilibrium point \( \mathbf{e} = 0 \) when \( \mathbf{V}^b_{wo} = 0 \) [9,Corollary 7.2]. In addition, the
mean $\hat{\theta}_w$ from (13) attempts to cancel the disturbance $V_w$ in feed-forward fashion. Moreover, the error feedback gain $K$ varies depending on the GP model confidence $\Sigma(\hat{\theta}_w)$, which is designed later. Hereafter, we denote $\Sigma(\hat{\theta}_w)$ as simply $\Sigma$. The rotational error $\hat{\theta}_w$ in $\text{Ad}(\hat{\theta}_w)$ can be calculated from $\text{sk}(\hat{\theta}_w)$ under Assumption 2 from [21] as follows:

$$\hat{\theta}_w = \exp \left( \frac{\sin^{-1} \left( \left\| \text{sk}(\hat{\theta}_w) \right\| \right)}{\left\| \text{sk}(\hat{\theta}_w) \right\|} \right) \text{sk}(\hat{\theta}_w).$$  

As a remark, the controller is similar to [15], but rather than using only the estimate target position as an input for the GP model, both estimates of position and orientation are used in this approach, since a wider class of the target velocity is considered as given by (5). Furthermore, let the controller $K(\Sigma(\hat{\theta}_w))$ be of the form

$$K(\Sigma) := \text{diag}(K_1(\Sigma), K_2(\Sigma)) \in \mathbb{R}^{12 \times 12}$$

$$K_i(\Sigma) := \text{diag}(k_{i_1}(\Sigma), \ldots, k_{i_{12}}(\Sigma)) \in \mathbb{R}^{6 \times 6}$$

$$0 < k_{i_{c_i}}(\Sigma) \leq k_i, \quad 0 < k_{i_{c_i}}(\Sigma) \leq \hat{k}_i, \quad 0 < k_{i_{c_i}}(\Sigma) \leq k_{i_{c_i}}(\Sigma) \leq \hat{k}_{i_{c_i}}.$$  

where $k_i, k_{i_{c_i}}, k_{i_{c_i}}$ are designed to be continuous in $\Sigma$. Furthermore, remember that $\mu$ is dependent on the estimate $\hat{\theta}_w$ rather than on the real $\theta_w$, which is unavailable. However, the difference between $\mu(\hat{\theta}_w)$ and $\mu(\theta_w)$ can be bounded based on Lipschitz continuity of the GP mean function and its kernel $k_\theta$. [10]:

**Lemma 3** The error between the prediction of $V_w(\hat{\theta}_w)$ by the real $\hat{\theta}_w$ and the estimate $\hat{\theta}_w$ on $X$ is bounded as follow:

$$\left\| \mu(\hat{\theta}_w) - \mu(\hat{\theta}_w) \right\| \leq L_p \| p \| + 2\pi L_o,$$

where $L_p, L_o$ denote Lipschitz constants.

**Proof:** Refer to Appendix A.

Lemma 3 is necessary for stability analysis of the error system shown in Fig. 3.

4.2 Stability Analysis

This section addresses the main theorem on stability of the system in Fig. 3 based on the notion of ultimate boundedness. Now we show the main result.

**Theorem 1** Consider the error system (27) with input (31) and a trained GP model (13) with dataset $D$ (8). Further, suppose that Assumptions 1 to 3 hold and the gain $K(\Sigma(\hat{\theta}_w))$ in (33) satisfies the following for all $\hat{\theta}_w$:

$$Q(\Sigma) := \begin{bmatrix} K_1(\Sigma) + K_2(\Sigma) & -K_1(\Sigma) \\ -K_1(\Sigma) & K_2(\Sigma) - \Gamma \end{bmatrix} > 0$$

where the matrix $\Gamma$ is defined as

$$\Gamma := \frac{1}{2} \begin{bmatrix} L_p + L_o \gamma_1 & \frac{L_p + L_o \gamma_1}{2} \\ \frac{L_p + L_o \gamma_1}{2} & L_o \gamma_1 \end{bmatrix} I_3.$$  

with positive constants $\gamma_1, \gamma_2, \gamma_3 > 0$ and $L_p$, $L_o$ obtained in Lemma 3. Then, there exist a $\rho(\delta) > 0$ and a $T(\delta) \geq 0$ with any probability $\delta \in (0, 1)$ such that

$$P\{|e(t)| \leq b, \forall t \geq T(\delta) \} \geq \delta$$

for any $e(0)$ satisfying $\| e(0) \| \leq \rho(\delta)$ where the minimum eigenvalue of $Q(\Sigma)$ is represented by $\lambda_{\min}(Q(\Sigma))$, and $\lambda_{\min}(Q(\Sigma)) := \min \lambda_{\min}(Q(\Sigma))$.

**Proof:** Refer to Appendix B.

Inferring from the gain condition (35), large Lipschitz constants $L_p$ and $L_o$ imply large control and observer gains. This may indicate that the unknown function $V_w$ may change sensitively with small variations in $\hat{\theta}_w$.

Note that [15,Theorem 1] only assures a probabilistic bounded error for the GP-enhanced VPC for a class of target body velocities $V_w(p_{ib})$, and thus $\Gamma$ and the ball (37) lack terms specific to the orientation. Furthermore, due to the matrix $Q$ being a function of the variance $\Sigma(\hat{\theta}_w)$, the condition (35) has to be confirmed for all $\hat{\theta}_w$, which makes the design difficult. Hence, we derive the following corollary for a simpler gain condition with the simplified control gain

$$K_i(\Sigma) := \text{diag}(k_{i_1}(\Sigma) I_3, k_{i_2}(\Sigma) I_3) \in \mathbb{R}^{6 \times 6}$$

$$0 < k_i \leq k_i(\Sigma) \leq \bar{k}_i, \quad 0 < \bar{k}_i \leq k_i(\Sigma) \leq \bar{k}_i.$$  

**Corollary 1** Consider the error system (27) with input (31) and a trained GP model (13) with dataset $D$ (8). Further, suppose that Assumptions 1 to 3 hold and $\bar{k}_i, \bar{k}_i$ satisfy

$$\frac{2k_i}{k_i + \bar{k}_i} > \frac{1}{\gamma_1^2} + \frac{1}{\gamma_2^2} + \frac{\alpha \gamma_3}{2} L_p + L_o, \quad i \in \{ p, R \}$$

with $\gamma_1, \gamma_2, \gamma_3 > 0$ and $\alpha = 1, \alpha = 0$. Then, there exist a $\rho(\delta) > 0$ and a $T(\delta) \geq 0$ with any probability $\delta \in (0, 1)$ such that (37) with (38) holds for any $e(0)$ satisfying $\| e(0) \| \leq \rho(\delta)$.

**Proof:** From the Schur complement, the condition (35) is simplified to $K_i(\Sigma) \Gamma - K_i(\Sigma)(K_i(\Sigma) + K_o(\Sigma))^\dagger K_o(\Sigma) > 0$. Due to a difference in $\Gamma$, it follows two conditions on the gains for the position part and orientation part that are summarized in only one condition by defining parameter $\alpha_i$. By employing the structure of controller (33), the condition is further shortened to

$$2k_i(k_i + \bar{k}_i) > \frac{1}{\gamma_1^2} + \frac{1}{\gamma_2^2} + \frac{\alpha \gamma_3}{2} L_p + L_o, \quad i \in \{ p, R \}$$

for $i = \{ p, R \}$. Since the left term is minimal for $\bar{k}_i, \bar{k}_i$, the condition is simplified to (40).
As long as the minimum controller gains $k_v(\Sigma)$, $k_p(\Sigma)$ of (33) meet the gain condition (40), stability is assured. The purpose of having uncertainty-adjustable controller gains is to achieve better noise attenuation. Hence, small gains are desired if it does not alter the control performance.

In the next section we will show how to obtain the Lipschitz constants $L_p$, $L_d$ that are used in Theorem 1 and Corollary 1.

4.3 Calculation of Lipschitz Constant

This section aims to show a method to calculate the Lipschitz constants of the GP mean function $\mu(\hat{g}_\text{wo})$ that are necessary for designing the controller gains (33). By discretizing $X$ properly one can estimate

$$L_i = \sup_{x \in X} \left\| \frac{\partial \mu(x)}{\partial x} \right\|, \quad i \in \{1, \ldots, 6\}. \quad (42)$$

Here, we use the notation $x = [x_1^2, x_2^2]$, $x_1, x_2 \in \mathbb{R}^3$. Then, the Lipschitz constants $L_p$, $L_d$ are calculated from $\|\frac{\partial \mu}{\partial x}\| \leq \sqrt{L_1^2 + L_2^2 + L_3^2} = L_p$. For notational simplicity, restate (9) with $k_{\omega_p}(x) = k_{\omega_p}(x, X)$ and $\tau_{\omega} := \left[ k_{\omega_p}(x) + \sigma^2 \right]^{-1} \Sigma_x$, as $\mu(x) = \sum_{m=1}^{M} k_{\omega_p}(x) \tau_{\omega_m}$. Then, computing the derivative of the SE-ARD kernel (10) as

$$\frac{\partial k_{\omega_p}(x)}{\partial x_j} = k_{\omega_p}(x) \frac{x_j}{l_i} - \frac{x_j}{l_i^2}, \quad j \in \{1, \ldots, 6\}, \quad (43)$$

then the norm in (42) obeys

$$\left\| \frac{\partial \mu(x)}{\partial x} \right\| = \sqrt{\sum_{j=1}^{6} \sum_{m=1}^{M} \tau_{\omega_m} k_{\omega_p}(x) \frac{x_j^m}{l_i^m} ^2}. \quad (44)$$

By finding the maximum value in (44) on the discretized $X$, the Lipschitz constants $L_p$, $L_d$ are obtained.

5. Simulation Experiment

This section aims to show the effectiveness of the proposed control scheme (33) in two simulations. The first simulation showcases the effectiveness of using pose information $\hat{g}_\text{wo}$ rather than only the position $p_\text{wo}$, from the author’s previous work [15]. In the second simulation we show the advantage of using variance-dependent varying gains when the visual measurements (6) are corrupted by noise. Feature extractions from visual measurements always cause noise. We consider the combination of two kinds of noise: a stochastic signal and an impulsive signal.

As long as the minimum controller gains $k_v(\Sigma)$, $k_p(\Sigma)$ of (33) meet the gain condition (40), stability is assured. The purpose of having uncertainty-adjustable controller gains is to achieve better noise attenuation. Hence, small gains are desired if it does not alter the control performance.

In the next section we will show how to obtain the Lipschitz constants $L_p$, $L_d$ that are used in Theorem 1 and Corollary 1.

4.3 Calculation of Lipschitz Constant

This section aims to show a method to calculate the Lipschitz constants of the GP mean function $\mu(\hat{g}_\text{wo})$ that are necessary for designing the controller gains (33). By discretizing $X$ properly one can estimate

$$L_i = \sup_{x \in X} \left\| \frac{\partial \mu(x)}{\partial x} \right\|, \quad i \in \{1, \ldots, 6\}. \quad (42)$$

Here, we use the notation $x = [x_1^2, x_2^2]$, $x_1, x_2 \in \mathbb{R}^3$. Then, the Lipschitz constants $L_p$, $L_d$ are calculated from $\|\frac{\partial \mu}{\partial x}\| \leq \sqrt{L_1^2 + L_2^2 + L_3^2} = L_p$. For notational simplicity, restate (9) with $k_{\omega_p}(x) = k_{\omega_p}(x, X)$ and $\tau_{\omega} := \left[ k_{\omega_p}(x) + \sigma^2 \right]^{-1} \Sigma_x$, as $\mu(x) = \sum_{m=1}^{M} k_{\omega_p}(x) \tau_{\omega_m}$. Then, computing the derivative of the SE-ARD kernel (10) as

$$\frac{\partial k_{\omega_p}(x)}{\partial x_j} = k_{\omega_p}(x) \frac{x_j}{l_i} - \frac{x_j}{l_i^2}, \quad j \in \{1, \ldots, 6\}, \quad (43)$$

then the norm in (42) obeys

$$\left\| \frac{\partial \mu(x)}{\partial x} \right\| = \sqrt{\sum_{j=1}^{6} \sum_{m=1}^{M} \tau_{\omega_m} k_{\omega_p}(x) \frac{x_j^m}{l_i^m} ^2}. \quad (44)$$

By finding the maximum value in (44) on the discretized $X$, the Lipschitz constants $L_p$, $L_d$ are obtained.

5. Simulation Experiment

This section aims to show the effectiveness of the proposed control scheme (33) in two simulations. The first simulation showcases the effectiveness of using pose information $\hat{g}_\text{wo}$ rather than only the position $p_\text{wo}$, from the author’s previous work [15]. In the second simulation we show the advantage of using variance-dependent varying gains when the visual measurements (6) are corrupted by noise. Feature extractions from visual measurements always cause noise. We consider the combination of two kinds of noise: a stochastic signal and an impulsive signal.
is smaller than that of the upper gain case. The results of the varying gain and upper gain cases are shown in Fig. 6b, where it can be observed that $\hat{e}_i$ and $e_i$ are similar after the initial responses converge at around 2s. Furthermore, $\hat{e}_i$ shows the effect of impulsive noise clearly. The lower gain case shows the best noise attenuation at 5s but the varying gain case has similar performance at 10s since the variance and gains are also small. On the other hand, the upper gain amplifies the impulsive noise at 10s much larger than the other cases. In summary, the varying gain can achieve similar performance as the upper bound static gain but with better noise attenuation.

6. Conclusion

This paper proposed a visual pursuit control scheme based on a GP model that learns the unknown but pose dependent target body velocity. First, the learning method by using GP models was addressed. Second, we proposed a visual pursuit control law in which the learned GP mean function is used to cancel the target body velocity, and the variance function to adjust gains. We then derived conditions on the gains to make the estimation and control errors ultimate bounded with high probability. Finally, we demonstrated the effectiveness of the proposed control law in the situation where the visual measurements are corrupted by noise.

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Note that di…

Since Proposition 5.3 in [9], \( \| \mathbf{s}(e^{\hat{\theta}}) \| ^2 \leq \phi(e^{\hat{\theta}}) \leq 2\| \mathbf{s}(e^{\hat{\theta}}) \| ^2 \) holds when Assumption 2 and 3 are satisfied. Then, (1) \( (| e \| ) \geq (| e \| ) \) holds from (28).

Next, we consider the time derivative of \( S \) (28). Applying the proposed input \( u \) in (31) to (30) yields

\[
S = -v^T \mathbf{K}(\Sigma)v + e^T \left[ \begin{array}{c} 0 \\ \mathbf{A}(\hat{\mathbf{e}}(\theta)) \end{array} \right] \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right). \tag{49}
\]

This is further bounded by Cauchy-Schwarz-inequality as

\[
S \leq -v^T \mathbf{K}(\Sigma)v + | e \| \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right), \tag{50}
\]

where \( \mathbf{A}(\hat{\mathbf{e}}(\theta)) \| e \| \) holds in (50) since a rotation matrix does not change the norm of a vector. From triangle inequality, the second term in (50) is bounded as

\[
| e \| \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right) \leq \| e \| \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right) + | e \| \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right). \tag{51}
\]

From Peter-Paul inequality and Lemma 3, we have

\[
| e \| \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right) \leq \frac{1}{2\gamma_1} | e \| ^2 + \frac{\gamma_2}{2} \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right) \tag{52}
\]

\[
| e \| \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right) \leq \frac{1}{2\gamma_2} | e \| ^2 + \frac{\gamma_2}{2} \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right) \tag{53}
\]

\[
| e \| \cdot 2\pi \leq \frac{1}{2\gamma_3} | e \| ^2 + 2\pi \gamma_3 \tag{54}
\]

with positive constants \( \gamma_1, \gamma_2, \gamma_3 \). Then, from Lemma 3 and inserting (51) to (54) into (50) yields

\[
S \leq -v^T \mathbf{K}(\Sigma)v + \frac{1}{2} | e \| ^2 \left( \frac{1}{\gamma_1} + \frac{\gamma_2}{\gamma_2} + \frac{\gamma_2}{\gamma_3} \right) + \frac{\gamma_2}{2} \left( \mathbf{V}^\theta_{\mathbf{w}(\dot{\theta}(\mathbf{w}))} - \mathbf{\mu}(\hat{\mathbf{w}}(\dot{\mathbf{w}})) \right) \tag{55}
\]
and by refactoring the terms with \( \Gamma \) from (36), we obtain

\[
S \leq -e^T \hat{Q}(\Sigma) e + \frac{\gamma_1^2}{2} ||\Sigma_{wo}(\hat{\epsilon}_{wo})||^2 + 2\gamma_2 r^2 L_0 \\
\hat{Q}(\Sigma) := \begin{bmatrix}
K_1(\Sigma) + K_2(\Sigma) - K_1(\Sigma)\Lambda_{d(\psi)} \\
-\Lambda_{d(\psi)}K_1(\Sigma) \\
K_1(\Sigma) - \Gamma
\end{bmatrix}.
\]

From Lemma 4, \( \hat{Q}(\Sigma) \) is positive definite when \( Q(\Sigma) \) is positive definite. Therefore, \( \min_{\beta, \zeta, \lambda} \hat{Q}(\Sigma) = Q \) also holds. From (15) in Lemma 1 and (17), the following holds with probability \( \delta \in (0, 1) \):

\[
S \leq -\lambda_0 ||\epsilon||^2 + \frac{\gamma_1^2}{2} \Delta^2 + 2\gamma_2 r^2 L_0. \tag{56}
\]

Thus, using a positive constant \( \eta \in (0, 1) \) yields

\[
S \leq -\lambda_0(1 - \eta)||\epsilon||^2 - \lambda_0\eta||\epsilon||^2 + \frac{\gamma_1^2}{2} \Delta^2 + 2\gamma_2 r^2 L_0. \tag{57}
\]

Define

\[
\zeta(\epsilon) := \sqrt{\frac{\gamma_1^2 \Delta^2(\epsilon) + 4\gamma_2 r^2 L_0}{2\eta \lambda_0}}, \tag{58}
\]

\[
D_\epsilon := \{ e \in \mathbb{R}^2 | ||e|| \leq \pi/2, ||\theta|| \leq \pi/2, ||\epsilon|| \geq \zeta \}. \tag{59}
\]

then the following holds with probability \( \delta \):

\[
P\left( S < 0, \forall \epsilon \in D_\epsilon \right) \geq \delta \tag{60}
\]

Thus, from [22] it follows that the error \( \epsilon \) is ultimately bounded with probability, and the ultimate bound is derived as

\[
\alpha^{-1}(\alpha_2(\zeta(\epsilon))) = \sqrt{\zeta(\epsilon)} = \sqrt{\frac{\gamma_1^2 \Delta^2(\epsilon) + 4\gamma_2 r^2 L_0}{\eta \lambda_0}}. \tag{61}
\]

This completes the proof.

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**Marco Omainka**

received the B.Sc. and M.Sc. degree in cybernetics from the University of Stuttgart, Germany, in 2016 and 2019, respectively. He is currently working towards his Ph.D. degree at the Information Physics and Computation Department at The University of Tokyo. His research interests include vision-based estimation and control with machine learning, and cooperative control of human-robotic networks.

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**Junya Yamachii (Member)**

received the Ph.D. degree from Tokyo Institute of Technology in 2018. He was an assistant professor at Tokyo Institute of Technology from 2018 to 2020, and he is currently an assistant professor at The University of Tokyo from 2020. His research interests include vision-based estimation and control, and cooperative control of human–robotic networks.

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**Thomas Beckers**

is a postdoctoral researcher at the Department of Electrical and Systems Engineering, University of Pennsylvania. In 2020, he successfully defended his Ph.D. thesis at the Technical University of Munich (TUM), Germany. He received the B.Sc. and M.Sc. degree in electrical engineering in 2010 and 2013, respectively, from the Technical University of Braunschweig, Germany. In 2018, he was a visiting researcher at the University of California, Berkeley. His research interests include data-driven based identification and control, non-parametric systems, and formal methods for safe learning.

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**Takeshi Hatamura (Member)**

received the Ph.D. degree in applied mathematics and physics from Kyoto University in 2007. He then held faculty positions at Tokyo Institute of Technology and Osaka University. Since April 2020, he is an associate professor at Tokyo Institute of Technology. He is the coauthor of “Passivity-Based Control and Estimation in Networked Robotics” (Springer, 2015), coauthor of “Control of Multi-agent Systems” (Corona Publishing Co., 2015) and the editor of “Economically-enabled Energy Management: Interplay between Control Engineering and Economics” (Springer Nature, 2020). His research interests include cyber-physical & human systems and networked robotics. He received the Kimura Award (2017), Pioneer Award (2014), Outstanding Book Award (2016), Control Division Conference Award (2018), Takeda Prize (2020), and Outstanding Paper Awards (2009, 2015, 2020) all from The Society of Instrumental and Control Engineers (SICE). He also received 3rd IFAC CPS Best Research Paper Award (2020) and 10th Asian Control Conference Best Paper Prize Award (2015). He is serving/served as an AE for IEEE TSC and SICE JCMSI, and is a member of the Conference Editorial Board of IEEE CSS. He is a senior member of IEEE.

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**Sandra Hirche**

received the Diplom-Ingenieur degree in aeronautical engineering from Technical University Berlin, Germany, in 2002 and the Doktor-Ingenieur degree in electrical engineering from Technical University Munich, Germany, in 2005. From 2005 to 2007 she was awarded a Postdoc scholarship from the Japanese Society for the Promotion of Science at the Fujita Laboratory, Tokyo Institute of Technology, Tokyo, Japan. From 2008 to 2012 she has been an associate professor at Technical University Munich. Since 2013 she is TUM Liesel Beckmann Distinguished Professor and has the Chair of Information-oriented Control in the Department of Electrical and Computer Engineering at Technical University Munich. Her main research interests include cooperative and distributed networked control as well as learning control with applications in human–robot interaction, multi-robot systems, and general robotics. She has published more than 150 papers in international journals, books, and refereed conferences.

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**Masayuki Fujita (Member, Fellow)**

is a Professor and the Course Chair at The University of Tokyo, a Professor Emeritus and a Visiting Professor at Tokyo Institute of Technology. He is also the 2021 president of SICE. He was the Research Supervisor for the Japan Science and Technology Agency Core Research for Evolutional Science and Technology from 2012 to 2020. He received the Eng.D. degree in electrical engineering from Waseda University, Tokyo, in 1987. Prior to his appointment at The University of Tokyo, he held professor/faculty appointments at Tokyo Institute of Technology, Kanazawa University, and the Japan Advanced Institute of Science and Technology. His research interests include passivity-based control in robotics and robust control. He is the coauthor of the book Passivity-Based Control and Estimation in Networked Robotics (Springer, 2015). He was the IEEE Control Systems Society (CSS) Vice President of Conference Activities and a member of the CSS Board of Governors. He served as the General Chair of the 2010 IEEE Multi-Conference on Systems and Control. He was a recipient of the 2008 IEEE Transactions on Control Systems Technology Outstanding Paper Award, a Plenary Lecturer at the 54th IEEE Conference on Decision and Control in 2015, and CSS Distinguished Lecturer from 2017 to 2019. He is a Fellow of the IEEE and SICE.