

Data-driven abstractions via adaptive refinements and a Kantorovich metric

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Abstract—We introduce an adaptive refinement procedure for smart and scalable abstraction of dynamical systems. Our technique relies on partitioning the state space depending on the observation of future outputs. However, this knowledge is dynamically constructed in an adaptive, asymmetric way. In order to learn the optimal structure, we define a Kantorovich-inspired metric between Markov chains, and we use it to guide the state partition refinement. Our technique is prone to data-driven frameworks, but not restricted to.

We also study properties of the above mentioned metric between Markov chains, which we believe could be of broader interest. We propose an algorithm to approximate it, and we show that our method yields a much better computational complexity than using classical linear programming techniques.

I. INTRODUCTION

Feedback control of dynamical systems is at the core of several techniques that have caused tremendous impact in several industries, being essential to important advancements in e.g. aerospace and robotics. Traditionally, these control techniques were model-based, relying on a complete mathematical model to perform controller design. With recent technological advancements, however, where a vast amount of data can be collected online or offline, the interest within the control community to study methods that leverage available data for feedback controller design has been reignited [1], [2], [3], [4].

In this paper, we focus on data-driven techniques for building *abstractions of dynamical systems*. We call these *data-driven abstractions*. Abstraction methods create a symbolic model [5], [6] that approximates the behavior of the original (the “concrete”) dynamics in a way that controllers designed for such a symbolic representation can be refined to a valid controller for the original dynamics [7]. Several recent research efforts started exploring the possibility of generating abstractions for dynamical systems from observations of the latter [8], [9], [10], [11], [12].

In [8], we show that memory-based Markov models can be built from trajectory data. Memory has been classically

used as a tool to mitigate non-Markovian behaviors of the original dynamics [13], [14], a feature also explored in recent papers [13], [10]. Increasing memory allows us to create more precise representations of the original dynamics using Markov decision processes (MDPs) or Markov chains. Despite promising results, [8] does not offer an adaptive mechanism to compute the generated abstraction, and thus it faces the curse of dimensionality, as the number of possible observations grows exponentially with the memory length. In this paper, we further develop the techniques in [8] by proposing an adaptive state space partitioning to mitigate the curse of dimensionality.

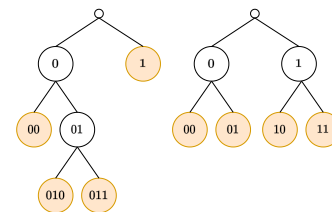


Fig. 1: Difference between an adaptive and a brute-force approach. On the left, an adaptive approach: only some of the possible observations are expanded. On the right, a brute-force approach: every observation is expanded. The two resulting abstractions have four states, but the adaptive one provides a better abstraction (see Example 1).

A key contribution in this paper is the construction of a novel metric between two Markov chains; this metric is then exploited to adaptively increase memory in certain regions of the state space, in view of taming the complexity of the generated abstraction. An illustration of the difference between these two approaches is depicted in Figure 1. As opposed to [8], where states of the chain are associated with past memory, the abstractions we construct in this paper are based on forward memory. In order to define a metric between two Markov models, we leverage the *Kantorovich* metric (also known as the Wasserstein or Earth’s mover distance) between the induced probability on words of a fixed length and let the word length go to infinity. To define the Kantorovich metric, we equip the space of words with the *Cantor distance*, which is classically used in symbolic dynamics [5], [15]. We argue by means of numerical experiments that such a Kantorovich metric is natural and meaningful for control problems. We also show that the proposed metric is a well-defined and intuitive notion of similarity between Markov chains, and propose an algorithm for its computation that has better computational complexity over a naive application of linear programming techniques.

We believe that the proposed Kantorovich metric could be

R. M. Jungers is a FNRS honorary Research Associate. This project has received funding from the European Research Council (ERC) under the European Unions Horizon 2020 research and innovation program under grant agreement No 864017 - L2C. R. M. Jungers is also supported by the Walloon Region and the Innoviris Foundation. He is currently on sabbatical leave at Oxford University, Department of Computer Science, Oxford, UK. Adrien Banse is supported by the French Community of Belgium in the framework of a FNRS/FRIA grant. Adrien Banse and Raphaël M. Jungers are with ICTEAM, UCLouvain. E-mail addresses: {adrien.banse, raphael.jungers}@uclouvain.be. Licio Romao and Alessandro Abate are with the Department of Computer Science, Oxford University. E-mail addresses: {licio.romao, alessandro.abate}@cs.ox.ac.uk.

of much broader interest. Indeed, computing metrics between Markov models has been an active research topic within the computer science community [16]. Our construction on the metric between Markov chains resembles the one presented in [17], however with another distance. In [18] computability and complexity results are shown for the total variation metric. Kantorovich metrics for Markov models have been studied in [19], [20], [21], [22], but their underlying distance is different from ours. Our choice of the Cantor distance is crucial both for computational aspects and for building smart abstractions of dynamical systems.

Summarizing, our main contribution is threefold. First, we propose a new metric to measure distance between Markov models. Second, we develop an efficient algorithm that approximates arbitrarily well the proposed metric. Third, we exploit the proposed metric to adaptively improve abstractions in specific regions of the state space.

Outline: The rest of this paper is organized as follows. In Section II, we introduce the Kantorovich metric between two Markov chains, and propose an efficient algorithm to approximate it with arbitrary precision. In Section III, we apply this metric to build abstractions of dynamical systems using a greedy strategy that leads to the refinement of the state-space partitioning. We also demonstrate the quality of our procedure on an example.

Notations: Let \mathcal{A} be a finite alphabet. We denote the set of n -long sequences of this alphabet by \mathcal{A}^n , and the set of countably infinite sequences by \mathcal{A}^* . The symbol Λ stands for the empty sequence and, for any $w_1 \in \mathcal{A}^{n_1}$, $w_2 \in \mathcal{A}^{n_2}$, the sequence $w_1 w_2 \in \mathcal{A}^{n_1+n_2}$ is the concatenation of w_1 and w_2 . Let $c(x)$ be a number of operations with respect to some attributes x . We say that an algorithm has a computational complexity $\mathcal{O}(f(x))$ if there exists $M > 0$, x_0 such that, for all $x \geq x_0$, $c(x) \leq Mf(x)$. For any bounded set $X \subset \mathbb{R}^d$, let $\sigma(X)$ be the induced σ -algebra of X , and λ be the Lebesgue measure on \mathbb{R}^d , then $\lambda_X : \sigma(X) \rightarrow [0, 1]$ is defined as $\lambda_X(A) = \lambda(A)/\lambda(X)$. Finally, for any set X and function F , the set $F(X) = \{F(x) : x \in X\}$.

II. A KANTOROVICH METRIC BETWEEN MARKOV CHAINS

In this section, a new notion of metric between Markov chains is defined. In Section III below, Markov chains will be used to represent abstractions of dynamical systems, and this distance will be used as a tool to construct adaptive abstractions. The present section, however, is concerned with Markov chains in their full generality.

A. Preliminaries

Using a similar formalism as in [8], we define a labeled Markov chain as follows.

Definition 1 (Markov chain). A *Markov chain* is a 5-tuple $\Sigma = (\mathcal{S}, \mathcal{A}, P, \mu, L)$, where \mathcal{S} is a finite set of *states*, \mathcal{A} is a finite *alphabet*, P is the *transition matrix* on $\mathcal{S} \times \mathcal{S}$, μ is the *initial measure* on \mathcal{S} , and $L : \mathcal{S} \rightarrow \mathcal{A}$ is a *labelling function*.

In Definition 1, the entry of the transition matrix $P_{s,s'}$ represents the probability $\mathbb{P}(X_{k+1} = s' | X_k = s)$. The labelling L induces a partition of the states. Consider the equivalence relation on \mathcal{S} defined as $s \sim s'$ if and only if $L(s) = L(s')$. For any $a \in \mathcal{A}$, the notion of *equivalent classes* is defined as

$$[a] = \{s \in \mathcal{S} : L(s) = a\}. \quad (1)$$

We also define the *behavior of a Markov chain* $\mathcal{B}(\Sigma) \subseteq \mathcal{A}^*$ as follows. A sequence $w^* = (a_1, a_2, \dots) \in \mathcal{B}(\Sigma_{\mathcal{W}})$ if there exists $s_1, s_2, \dots \in \mathcal{S}$ such that $\mu_{s_1} > 0$, $P_{s_i, s_{i+1}} > 0$ and $L(s_i) = a_i$.

In the present work, we focus on a notion of metric between probabilities on label sequences. Let $w = (a_1, \dots, a_n)$ be a n -long sequence of labels, and define $p^n : \mathcal{A}^n \rightarrow [0, 1]$ as

$$p^n(w) = \sum_{s_1 \in [a_1]} \mu_{s_1} \sum_{s_2 \in [a_2]} P_{s_1, s_2} \cdots \sum_{s_n \in [a_n]} P_{s_{n-1}, s_n}, \quad (2)$$

that is the probability induced by the Markov chain on n -long sequences.

Remark 1. Classical procedures are well-known in the literature allowing to compute the probabilities p^n for increasing n , with a complexity proportional to $|\mathcal{S}|^2$ at every step [23].

We endow the set of n -long sequences of labels with the Cantor distance d_B .

Definition 2 (Cantor's distance, [15]). The *Cantor distance* $d_B : \mathcal{A}^n \times \mathcal{A}^n \rightarrow \mathbb{R}$ is defined as $d_B(w_1, w_2) = 2^{-l}$, where l is the length of the longest common prefix. In other words, let $w_1 = (a_1, \dots, a_n)$ and $w_2 = (b_1, \dots, b_n)$, then $d_B(w_1, w_2) = 2^{-l}$, where $l = \inf\{k : a_k \neq b_k\}$.

B. The Kantorovich metric

Consider two Markov chains $\Sigma_1 = (\mathcal{S}_1, \mathcal{A}, P_1, \mu_1, L_1)$ and $\Sigma_2 = (\mathcal{S}_2, \mathcal{A}, P_2, \mu_2, L_2)$ defined on the same alphabet \mathcal{A} . For a fixed n , they generate the distributions p_1^n and p_2^n on the metric space (\mathcal{A}^n, d_B) as described in (2).

Definition 3 (Kantorovich metric). The *Kantorovich metric* between the probability distributions p_1^n and p_2^n is given by

$$K(p_1^n, p_2^n) = \min_{\pi^n \in \Pi(p_1^n, p_2^n)} \sum_{w_1, w_2 \in \mathcal{A}^n} d_B(w_1, w_2) \pi^n(w_1, w_2), \quad (3)$$

where $\Pi(p_1^n, p_2^n)$ is the set of *couplings* of p_1^n and p_2^n , which contains the joint distributions $\pi^n : \mathcal{A}^n \times \mathcal{A}^n \rightarrow [0, 1]$ whose marginal distributions are p_1^n and p_2^n , that is,

$$\begin{aligned} \forall w_1, w_2 \in \mathcal{A}^n : \pi^n(w_1, w_2) &\geq 0, \\ \forall w_1 \in \mathcal{A}^n : \sum_{w_2 \in \mathcal{A}^n} \pi^n(w_1, w_2) &= p_1^n(w_1), \\ \forall w_2 \in \mathcal{A}^n : \sum_{w_1 \in \mathcal{A}^n} \pi^n(w_1, w_2) &= p_2^n(w_2). \end{aligned} \quad (4)$$

The Kantorovich metric is often interpreted as an optimal transport problem. Indeed one can see problem (3) as the problem of finding the optimal way to satisfy “demands” p_2^n with “supplies” p_1^n , where the cost of moving

$\pi^n(w_1, w_2)$ probability mass from w_1 to w_2 amounts to $\pi^n(w_1, w_2)d_B(w_1, w_2)$. An illustration is provided in Figure 2.

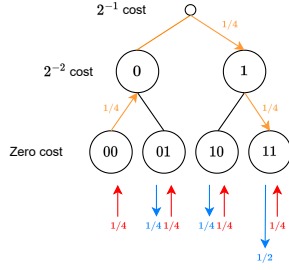


Fig. 2: Interpretation of the Kantorovich distance as an optimal transport problem. In this example, the alphabet $\mathcal{A} = \{0, 1\}$, $p_1^2(w) = 1/4$ for all $w \in \mathcal{A}^2$, and $p_2^2(00) = 0$, $p_2^2(01) = p_2^2(10) = 1/4$, and $p_2^2(11) = 1/2$. One can see that the optimal way to satisfy the demands p_2^n with the supplies p_1^n is to move $1/4$ of probability mass from 00 to 11, that is $\pi^2(00, 11) = 1/4$. Since $d_B(00, 11) = 1/2$, the Kantorovich distance is $K(p_1^2, p_2^2) = 1/8$.

A naïve computation of $K(p_1^n, p_2^n)$ in (3) entails solving a linear program. However, standard techniques, such as interior point methods and network simplex result in some cases in a complexity of $\mathcal{O}(n|\mathcal{A}|^{3n} \log(|\mathcal{A}|))$, and therefore scale very poorly with the number labels. In this section, we show that it is possible to compute $K(p_1^n, p_2^n)$ in $\mathcal{O}(|\mathcal{S}|^2|\mathcal{A}|^{n+1})$ operations.

We present in Theorem 1 a key result for writing an efficient algorithm. Due to space constraints, all the proofs in this paper are omitted and can be found in the extended version of this paper [24].

Theorem 1. For any $n \geq 1$, let π^n be the solution of (3). Then the following holds:

$$K(p_1^{n+1}, p_2^{n+1}) = K(p_1^n, p_2^n) + 2^{-(n+1)} \sum_{w \in \mathcal{A}^n} \left[r(w) - \sum_{a \in \mathcal{A}} r(wa) \right], \quad (5)$$

where

$$r(w) = \min\{p_1^n(w), p_2^n(w)\},$$

$$r(wa) = \min\{p_1^{n+1}(wa), p_2^{n+1}(wa)\}.$$

Theorem 1 allows to prove that Algorithm 1 efficiently computes the Kantorovich metric between p_1^n and p_2^n .

Algorithm 1 KANT(k, m, w, n)

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for  $i = 1, \dots, |\mathcal{A}|$  do
  Compute  $p_1^n(wa_i)$  and  $p_2^n(wa_i)$  (see Remark 1)
   $r_i \leftarrow \min\{p_1^n(wa_i), p_2^n(wa_i)\}$ 
RES =  $2^{-(k+1)}(m - \sum_{i=1, \dots, |\mathcal{A}|} r_i)$ 
if  $k + 1 = n$  then
  return RES
for  $i = 1, \dots, |\mathcal{A}|$  do
  if  $r_i \neq 0$  then
    RES  $\leftarrow$  RES + KANT( $k + 1, r_i, wa_i, n$ )
return RES

```

Corollary 1. Let KANT be the algorithm described in Algorithm 1, then

$$K(p_1^n, p_2^n) = \text{KANT}(0, 1, \Lambda, n). \quad (6)$$

Moreover KANT terminates in $\mathcal{O}(|\mathcal{S}|^2|\mathcal{A}|^{n+1})$ operations.

C. A metric between Markov chains

Let Σ_1 and Σ_2 be two Markov chains defined on the same alphabet \mathcal{A} . We define a metric between them as

$$d(\Sigma_1, \Sigma_2) = \lim_{n \rightarrow \infty} K(p_1^n, p_2^n),$$

where p_1^n and p_2^n are the distributions on \mathcal{A}^n induced by each Markov chain on n -long label sequences.

Remark 2. The Cantor distance 2^{-l} can be interpreted as a discount factor. Therefore, the metric $d(\Sigma_1, \Sigma_2)$, if well-defined, can be interpreted as a discounted measure of the difference between the behaviors $\mathcal{B}(\Sigma_1)$ and $\mathcal{B}(\Sigma_2)$.

We now prove that this metric is well-defined¹.

Theorem 2. The metric $d(\Sigma_1, \Sigma_2)$ is well-defined. Moreover, for any $n \geq 1$,

$$0 \leq d(\Sigma_1, \Sigma_2) - K(p_1^n, p_2^n) \leq 2^{-n}.$$

Theorem 2 provides a guarantee on the approximation of $d(\Sigma_1, \Sigma_2)$ that we will be able to compute. Indeed, for any $\varepsilon > 0$, if $n \geq \lceil \log_2(\varepsilon^{-1}) \rceil$, then $0 \leq d(\Sigma_1, \Sigma_2) - K(p_1^n, p_2^n) \leq \varepsilon$. Following Corollary 1, for a fixed number of labels and states, this implies that an ε -solution can be found in $\mathcal{O}(\varepsilon^{-1})$ computational complexity.

III. APPLICATION TO DATA-DRIVEN MODEL ABSTRACTIONS

We now show how the metric $d(\Sigma_1, \Sigma_2)$ enables an adaptive refinement procedure for dynamical systems abstraction.

A. Abstractions with adaptive refinement

In this section, we introduce a new abstraction based on adaptive refinements. Even though our approach can be generalized to stochastic systems, in this preliminary work we focus on deterministic ones, which we now define.

Definition 4 (Dynamical system). A dynamical system is the 4-tuple $S = (X, \mathcal{A}, F, H)$ that defines the relation

$$x_{k+1} = F(x_k), \quad y_k = H(x_k),$$

where $X \subseteq \mathbb{R}^d$ is the state space, \mathcal{A} is a finite alphabet called the output space, $F : X \rightarrow X$ is a transition function, and $H : X \rightarrow \mathcal{A}$ is the output function. The variables x_k and y_k are called the state and the output at time k .

Also, in parallel to the definition of behavior of a Markov chain, we define the behavior of a dynamical system $\mathcal{B}(S) \subseteq \mathcal{A}^*$ as follows. A sequence $w^* = (a_1, a_2, \dots) \in \mathcal{B}(S)$ if there exists $x_1, x_2, \dots \in X$ such that $x_{i+1} = F(x_i)$ and $H(x_i) = a_i$. Also, in parallel to equivalent classes (1) on Markov chains, we define equivalent classes on the

¹That is, the function satisfies positivity, symmetry and triangle inequality.

continuous state space X . A subset of states is an *equivalent class* if it satisfies the recursive relation

$$[wa]_S = \{x \in [w]_S \mid H^n(x) = a\}, \quad [\Lambda]_S = X,$$

for any $w \in \mathcal{A}^n$ and $a \in \mathcal{A}$. In other words, for a given sequence $w = (a_1, \dots, a_n)$, a state $x \in [w]_S$ if $H(x) = a_1$, $H(F(x)) = a_2$, \dots , and $H(F^{n-1}(x)) = a_n$. In this work, we impose the following assumption on dynamical systems.

Assumption 1. The dynamical system S as defined as Definition 4 is such that, for any $w \in \mathcal{A}^n$ and $a \in \mathcal{A}$, the following two conditions hold:

- If $\lambda_X([w]_S) = 0$, then $[w]_S = \emptyset$.
- If $\lambda_X([wa]_S) = \lambda_X([w]_S)$, then $[w]_S = [wa]_S$.

Informally, Assumption 1 requires that any possible trajectory has a nonzero probability to be sampled.

Definition 5 (Adaptive partitioning). Let $w_1 \in \mathcal{A}^{n_1}$, $w_2 \in \mathcal{A}^{n_2}$, \dots , $w_k \in \mathcal{A}^{n_k}$ be k sequences of labels of different lengths. The set of sequences $\mathcal{W} = \{w_i\}_{i=1,\dots,k}$ is an *adaptive partitioning* for S if

$$\bigcup_{w \in \mathcal{W}} [w]_S = X, \quad \forall i \neq j, [w_i]_S \cap [w_j]_S = \emptyset.$$

We now introduce an abstraction procedure based on an adaptive partitioning refinements.

Definition 6 (Abstraction based on adaptive refinements). Let $S = (X, \mathcal{A}, F, H)$ be a dynamical system as defined in Definition 4, and let \mathcal{W} be an adaptive partitioning for S as defined in Definition 5. Then the corresponding *abstraction based on adaptive refinements* is the Markov chain $\Sigma_{\mathcal{W}} = (\mathcal{S}, \mathcal{A}, P, \mu, L)$ defined as follows:

- The states are the partitions, that is $\mathcal{S} = \mathcal{W}$.
- μ_w is the Lebesgue measure of equivalent class $[w]_S$ on X , that is $\mu_w = \lambda_X([w]_S)$.
- For $w_1 = (a_1, \dots, a_{n_1})$, and $w_2 = (b_1, \dots, b_{n_2})$, let $k = \min\{n_1 - 1, n_2\}$, $w'_1 = (a_2, \dots, a_{k+1})$, and $w'_2 = (b_1, \dots, b_k)$. If $w'_1 \neq w'_2$ or $\lambda_X([w_1]_S) = 0$, then $P_{w_1, w_2} = 0$. Else

$$P_{w_1, w_2} = \frac{\lambda_X([a_1 w_2]_S)}{\lambda_X([w_1]_S)}.$$

- For $w = (a_1, \dots, a_n)$, $L(w) = a_1$.

Informally, for a given adaptive partitioning \mathcal{W} , the abstraction $\Sigma_{\mathcal{W}}$ can be interpreted as follows. The initial probability to be in the state w in the Markov chain is the proportion of $[w]_S$ in X , and the probability to jump from the state w_1 to the state w_2 is the proportion of $[w_1]_S$ that goes into $[w_2]_S$ given the dynamics. For any sequence $w = (a_1, \dots, a_n) \in \mathcal{A}^n$, the probability $p^n(w)$ as defined in (2) is therefore the approximation for our abstraction of the probability that the output signal starts with the sequence w .

We now provide a result that gives a sufficient condition for the abstraction to have the same behavior as the original system.

Proposition 1. Given a dynamical system S satisfying Assumption 1, consider abstraction $\Sigma_{\mathcal{W}}$ as per Definition 6. If for all $w_1, w_2 \in \mathcal{W}$, $P_{w_1, w_2} \in \{0, 1\}$, then $\mathcal{B}(\Sigma_{\mathcal{W}}) = \mathcal{B}(S)$.

B. A data-driven abstraction

In this section, we propose a method to construct an abstraction based on adaptive refinements, from a data set comprising outputs sampled from the dynamical model S . Given an adaptive partitioning \mathcal{W} , we propose to construct $\Sigma_{\mathcal{W}}$ using empirical probabilities (see [8] for more details). We make the following assumption, which considers an idealised situation where one has an infinite number of samples. In practice, one typically has access to a finite number of observations, leading to approximation errors. The techniques to study these errors are investigated, for instance, in [10], and are left for further work in the context of this work.

Assumption 2. For any abstraction $\Sigma_{\mathcal{W}} = (\mathcal{W}, \mathcal{A}, P, \mu, L)$, the transition probabilities P and the initial distribution μ are known exactly.

Now we are able to use the tool investigated in Section II to find a smart adaptive partitioning. Indeed, one can construct two abstractions $\Sigma_{\mathcal{W}_1}$ and $\Sigma_{\mathcal{W}_2}$ corresponding to two different partitionings, and efficiently compute the Kantorovich metric $d(\Sigma_{\mathcal{W}_1}, \Sigma_{\mathcal{W}_2})$ up to some accuracy ε following Corollary 1. This gives a discounted measure of the difference between $\mathcal{B}(\Sigma_{\mathcal{W}_1})$ and $\mathcal{B}(\Sigma_{\mathcal{W}_2})$ (see Remark 2). This reasoning leads to the greedy procedure $\text{REFINE}(S, N, \varepsilon)$ described in Algorithm 2.

Algorithm 2 $\text{REFINE}(S, N, \varepsilon)$

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 $\mathcal{W} \leftarrow \{(a)\}_{a \in \mathcal{A}}$ 
Construct  $\Sigma_{\mathcal{W}}$  from samples of  $S$ 
while  $\exists w_1, w_2 \in \mathcal{W} : P_{w_1, w_2} \in (0, 1)$  do
  if  $N = 0$  then
    return  $\Sigma_{\mathcal{W}}$ 
  for  $i = 1, \dots, |\mathcal{W}|$  do
     $\mathcal{W}'_i \leftarrow \mathcal{W} \setminus \{w_i\}$ 
     $\mathcal{W}'_i \leftarrow \mathcal{W}'_i \cup \{w_i a\}_{a \in \mathcal{A}}$ 
    Construct  $\Sigma_{\mathcal{W}'_i}$  from samples of  $S$ 
     $d_i \leftarrow d(\Sigma_{\mathcal{W}}, \Sigma_{\mathcal{W}'_i})$  with precision  $\varepsilon$ 
   $j = \arg \max_{i=1, \dots, |\mathcal{W}|} d_i$ 
   $\mathcal{W} \leftarrow \mathcal{W}'_j$ 
   $\Sigma_{\mathcal{W}} \leftarrow \Sigma_{\mathcal{W}'_j}$ 
   $N \leftarrow N - 1$ 
return  $\Sigma_{\mathcal{W}}$ 

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An interpretation of Algorithm 2 goes as follows. Let \mathcal{W} be a coarse partitioning, and \mathcal{W}'_1 and \mathcal{W}'_2 be two more refined partitionings. If $d(\Sigma_{\mathcal{W}}, \Sigma_{\mathcal{W}'_1}) > d(\Sigma_{\mathcal{W}}, \Sigma_{\mathcal{W}'_2})$, then one could argue that it is more interesting to choose \mathcal{W}'_1 over \mathcal{W}'_2 , since the discounted measure between the behaviors corresponding to the coarse partitioning and the refined partitioning is larger. Moreover, if at some point $\Sigma_{\mathcal{W}}$ is such that $P_{w, w'} \in \{0, 1\}$ for all $w, w' \in \mathcal{A}^n$, then one has a sufficient

condition to stop the algorithm following Proposition 1, otherwise the algorithm stops after N iterations. If $N = \infty$, then the algorithm only stops in such case. An execution step of the algorithm can be found in Figure 3. A complexity analysis of Algorithm 2 can be found in Corollary 2.

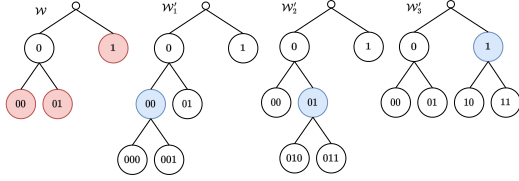


Fig. 3: Illustration of the execution of Algorithm 2. Consider a current partitioning $\mathcal{W} = \{00, 01, 1\}$, with the corresponding abstraction $\Sigma_{\mathcal{W}}$. Then the algorithm will explore the partitionings $\mathcal{W}'_1 = \{000, 001, 01, 1\}$, $\mathcal{W}'_2 = \{00, 010, 011, 1\}$ and $\mathcal{W}'_3 = \{00, 01, 10, 11\}$. For each one, it will compute $\Sigma_{\mathcal{W}'_i}$, and $d(\Sigma_{\mathcal{W}}, \Sigma_{\mathcal{W}'_i})$, and choose the one for which the distance to $\Sigma_{\mathcal{W}}$ is the largest.

Corollary 2. *The algorithm $\text{REFINE}(S, N, \varepsilon)$ terminates in $\mathcal{O}(|\mathcal{A}|^{n+4} N^4)$ operations, with $n = \lceil \log_2(\varepsilon^{-1}) \rceil$. Moreover, for S satisfying Assumption 1, if $\Sigma_{\mathcal{W}} = \text{REFINE}(S, \infty, \varepsilon)$ terminates, then $\mathcal{B}(\Sigma_{\mathcal{W}}) = \mathcal{B}(S)$.*

C. Numerical examples

In this section, we demonstrate on an example that our greedy algorithm converges to a smart partitioning², and we show how to use the proposed framework for controller design.

Example 1. Consider $S = (X, \mathcal{A}, F, H)$ with $X = [0, 2] \times [0, 1]$, $\mathcal{A} = \{0, 1\}$. Let F be defined as

$$F(x) = \begin{cases} x & \text{if } x \in P_1 \cup P_4, \\ (x_1/2 + 1/2, x_2 + 1/2) & \text{if } x \in P_2, \\ (x_1 - 1/2, x_2) & \text{if } x \in P_3, \\ (2x_1 + 1, 4x_2 - 3/4) & \text{else,} \end{cases}$$

where P_i are depicted in Figure 4, and $H(x) = 0$ if $x \in P_1$, else $H(x) = 1$. An illustration and interpretation of S is given in Figure 4.

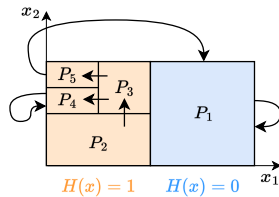


Fig. 4: Illustration and description of the transition function F of Example 1. F has to be understood in the following way: P_1 is mapped to itself, P_2 is mapped to P_3 , the lower half of P_3 is mapped to P_4 , the upper half of P_3 is mapped to P_5 , P_5 is mapped to P_1 , and P_4 to itself.

The result of the algorithm applied to Example 1 at all iterations k is depicted in Table I, and the final partitioning is illustrated in Figure 5. Observe that the generated partitioning

²All the code corresponding to this section can be found at <https://github.com/adrienbanse/KantorovichAbstraction.jl>.

aligns well with the dynamics, and that our algorithm generates an emerging structure which is not trivial. The algorithm stops at the third iteration since the obtained abstraction is such that $P_{w,w'} \in \{0, 1\}$, which is a stopping criterion following Proposition 1, and has much less states than the brute force approach of [8].

	\mathcal{W}	$d(\Sigma_{\mathcal{W}}, \Sigma_{\mathcal{W}'_j})$	$P_{w,w'} \in \{0, 1\}$
$k = 0$	$\{0, \mathbf{1}\}$	0.0015	No
$k = 1$	$\{0, 10, \mathbf{11}\}$	0.0059	No
$k = 2$	$\{0, 10, 110, \mathbf{111}\}$	0.0039	No
$k = 3$	$\{0, 10, 110, 1110, 1111\}$	-	Yes

TABLE I: Results of Algorithm 2 for Example 1. For each iteration k , the current model is the abstraction corresponding to $\Sigma_{\mathcal{W}}$, and the chosen model is $\Sigma_{\mathcal{W}'_j}$, with the largest distance $d(\Sigma_{\mathcal{W}}, \Sigma_{\mathcal{W}'_j})$. With P the transition matrix of the current model, if for all $w, w' \in \mathcal{A}^n$, $P_{w,w'} \in \{0, 1\}$, the algorithm stops.

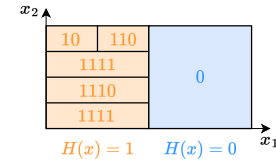


Fig. 5: Illustration of the last partitioning \mathcal{W} given by Algorithm 2 for Example 1.

We further demonstrate the quality of the obtained abstractions by designing a controller for a similar dynamical system.

Example 2. Consider the dynamical system S as described in Example 1, except that the dynamics is controlled as follows:

$$\tilde{x}_k = x_k + \begin{pmatrix} 0 \\ 1 \end{pmatrix} u_k, \quad x_{k+1} = F(\tilde{x}_k)$$

where $u_k = K(x_k) \in \{0, 1/4, 1/2\}$ is an input to the system. Consider the reward $r(x) = 1$ if $H(x) = 0$, else $r(x) = 0$, and a discounted expected reward maximization objective, that is

$$\max_K \mathbb{E}_{x_1 \sim \mu(X)} \sum_k \gamma^k r(x_k), \quad (7)$$

where $\mu(X)$ is the uniform distribution on X , and $\gamma = 0.95$ is a discount factor.

To solve this optimal control problem, we will use the abstractions constructed by Algorithm 2. For each partitioning \mathcal{W} in Table I, we will construct the abstraction $\Sigma_{\mathcal{W}}^u$ corresponding to the actions given in Example 2, that is $u = 0$, $u = 1/4$ and $u = 1/2$. We will then solve a Markov Decision Process (or MDP for short, see [25] for an introduction) maximizing the expected reward of the MDP. For this, we used the implementation of the value iteration algorithm implemented in the `POMDPs.jl` Julia package [26]. Now, let $P(s)$ be the optimal policy for the state s , we design the controller for the system 2 as follows: for $x_k \in [w]_S$, then

$$u_k = K(x_k) = P(w). \quad (8)$$

For the different abstractions found by Algorithm 2, the corresponding expected rewards (7) for the original system controlled by (8) are given in Table II. One can see that the expected reward increases as our algorithm refines the state-space.

Iteration	Controller (8)	Expected reward (7)
$k = 0$	$K(x) = \begin{cases} 0 & \text{if } x \in [0]_S \\ 0 & \text{if } x \in [1]_S \end{cases}$	14.4784
$k = 1$	$K(x) = \begin{cases} 0 & \text{if } x \in [0]_S \\ 0 & \text{if } x \in [10]_S \\ 1/4 & \text{if } x \in [11]_S \end{cases}$	18.8726
$k = 2$	$K(x) = \begin{cases} 0 & \text{if } x \in [0]_S \\ 0 & \text{if } x \in [10]_S \\ 0 & \text{if } x \in [110]_S \\ 1/4 & \text{if } x \in [111]_S \end{cases}$	19.0311
$k = 3$	$K(x) = \begin{cases} 0 & \text{if } x \in [0]_S \\ 0 & \text{if } x \in [10]_S \\ 0 & \text{if } x \in [110]_S \\ 1/2 & \text{if } x \in [1110]_S \\ 1/4 & \text{if } x \in [1111]_S \end{cases}$	19.1022

TABLE II: Expected rewards (7) for the Example 2 controlled by (8). The iterations k correspond to the iterations of Algorithm 2 represented in Table I. The optimal policy is found by solving MDPs corresponding to the three possible actions $u_k \in \{0, 1/4, 1/2\}$, and the expected reward (7) is approximated by sampling 5000 trajectories of length 1000. One can observe that the expected reward increases.

IV. CONCLUSION AND FURTHER RESEARCH

Inspired by a recent interest in developing data-driven abstractions of dynamical systems, we proposed a state refinement procedure that relies on a Kantorovich metric between Markov chains. We leverage the Cantor distance in the space of behaviours of the generated abstraction and use it to define the proposed Kantorovich metric. A key feature of our approach is a greedy strategy to perform state refinement that leads to an adaptive and smart partition of the state space. We show promising results in some control problems.

As further research, we plan to design a smart stopping criterion for our refinement procedure. We would also like to investigate convergence properties of our method, in the same fashion as in [8, Theorem 8].

ACKNOWLEDGMENT

We thank Prof. Franck van Breugel and Prof. Prakash Panangaden for their insightful comments and the interesting conversations about this work.

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