

ORF522 – Linear and Nonlinear Optimization

22. Sequential Convex Programming

Final Exam

- **Date/Time:**
 - Tuesday December 20, 00:01am — Wednesday December 21, 11:59pm.
 - You can download and start whenever you prefer
 - After download, you have 24 hours to complete
 - You cannot submit after Wednesday December 21, 11:59pm.
- **Where:** take-home
- **Material allowed:** only material from the class (slides, code, books, etc.)
- **Topics:** entire course
- **Content:** mix of mathematical and coding questions (jupyter & python)

Today's lecture

[Chapter 4 and 17, NO][ee364b]


Convex algorithms to solve nonconvex optimization problems

- Sequential convex programming
- Trust region methods
- Building convex approximations
- Regularized trust region methods
- Difference of convex programming

Methods for nonconvex optimization

Convex optimization algorithms: global and typically fast

Nonconvex optimization algorithms: must give up one, global or fast

- **Local methods: fast but not global**  **heuristics**
Need not find a global (or even feasible) solution.
They cannot certify global optimality because KKT conditions are not sufficient.
- **Global methods: global but often slow**
They find a global solution and certify it.

Sequential Convex Programming

Sequential convex programming (SCP)

Local optimization method that leverages convex optimization

Subproblems are convex \longrightarrow we can solve them efficiently

It is a **heuristic**

- It **can fail** to find an optimal (or even feasible point)
- Results **depend on the starting point.**
We can run the algorithm from many initial points and take the best result.

It often works very well

it finds a feasible point with good objective value (often optimal!)

Gradient descent as SCP

Problem

$$\text{minimize } f(x)$$

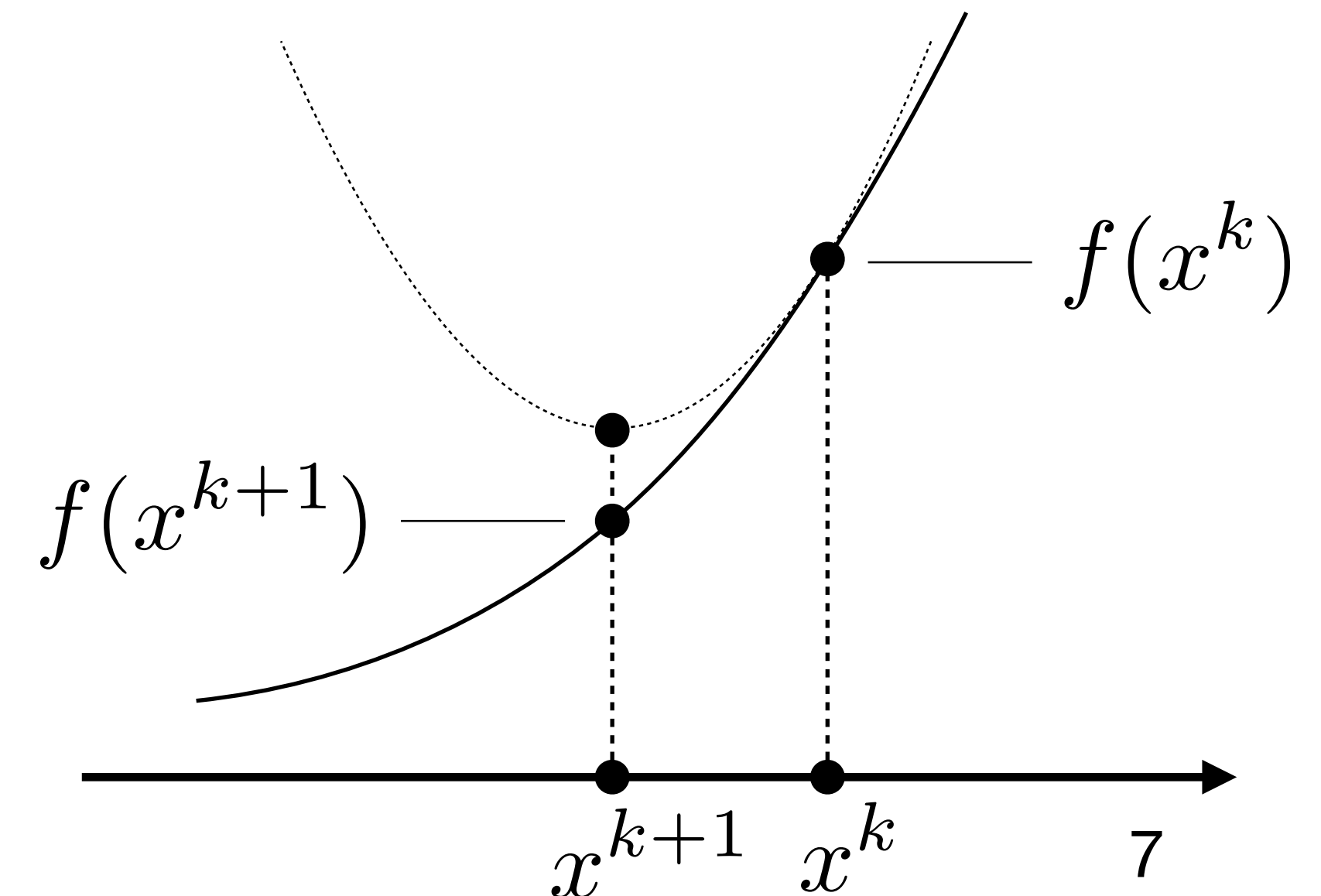
Iterates

$$x^{k+1} = x^k - t_k \nabla f(x^k)$$

Quadratic approximation, replace $\nabla^2 f(x^k)$ with $\frac{1}{t_k} I$

$$x^{k+1} = \underset{y}{\operatorname{argmin}} f(x^k) + \nabla f(x^k)^T (y - x^k) + \frac{1}{2t_k} \|y - x^k\|_2^2$$

strongly convex problem



The problem

$$\begin{array}{ll} \text{minimize} & f(x) \\ \text{subject to} & g_i(x) \leq 0, \quad i = 1, \dots, m \\ & h_i(x) = 0, \quad i = 1, \dots, p \end{array} \quad \text{with } x \in \mathbf{R}^n$$

- f and g_i can be nonconvex
- h_i can be nonaffine

Trust region methods

Main idea

$$\begin{aligned} &\text{minimize} && f(x) \\ &\text{subject to} && g_i(x) \leq 0, \quad i = 1, \dots, m \\ &&& h_i(x) = 0, \quad i = 1, \dots, p \end{aligned}$$

iterate x^k
trust region \mathcal{T}^k

**approximate
convex
problem**

$$\begin{aligned} &\text{minimize} && \hat{f}(x) \\ &\text{subject to} && \hat{g}_i(x) \leq 0, \quad i = 1, \dots, m \\ &&& \hat{h}_i(x) = 0, \quad i = 1, \dots, p \\ &&& x \in \mathcal{T}^k \end{aligned} \longrightarrow$$

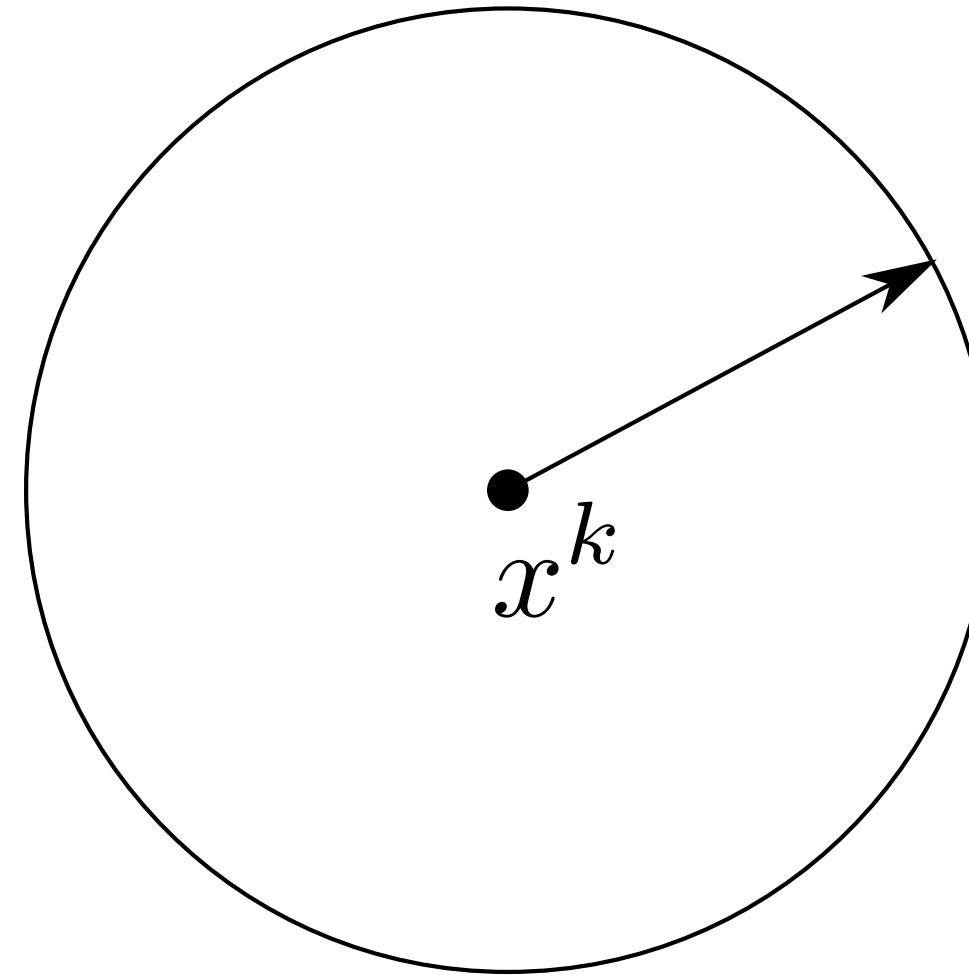
solve to get
 x^{k+1}

- \hat{f} (\hat{g}_i) is a convex approximation of f (g_i) over \mathcal{T}^k
- \hat{h} is an affine approximation of h over \mathcal{T}^k

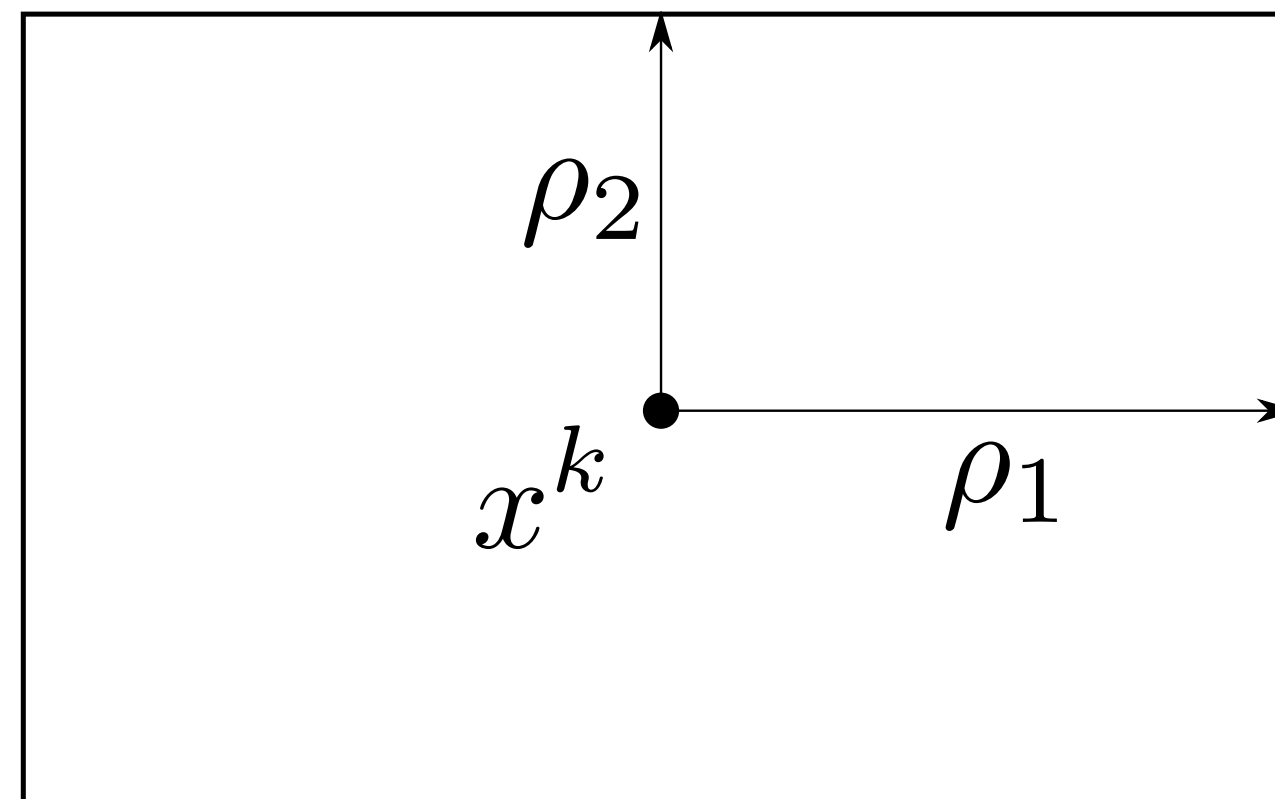
The trust region

$$\mathcal{T}^k = \{x \mid \|x - x^k\| \leq \rho\}$$

Ball $\mathcal{T}^k = \{x \mid \|x - x^k\|_2 \leq \rho\}$



Box $\mathcal{T}^k = \{x \mid |x_i - x_i^k| \leq \rho_i\}$



Note: if f, g_i, h_i are convex or affine in x_i , then we can take $\rho_i = \infty$

Proximal operator interpretation

proximal problem

$$\text{minimize } f(x) + \frac{1}{2\lambda} \|x - x^k\|_2^2$$

optimality conditions

$$0 \in \partial f(x^{\text{pr}}) + \frac{1}{\lambda} (x^{\text{pr}} - x^k)$$

$$\longleftrightarrow \lambda = \rho/\mu$$

trust region problem

$$\begin{aligned} &\text{minimize } f(x) \\ &\text{subject to } \|x - x^k\|_2 \leq \rho \end{aligned}$$

optimality conditions

$$\begin{aligned} 0 \in \partial f(x^{\text{tr}}) + \mu \frac{x^{\text{tr}} - x^k}{\|x^{\text{tr}} - x^k\|_2}, \\ \|x^{\text{tr}} - x^k\|_2 = \rho \end{aligned}$$

Note

- Minimum outside tr: $\|x^{\text{tr}} - x^k\| = \rho$
- $\partial \|z\|_2 = \nabla (z^T z)^{1/2} = z/\|z\|$ (if $z \neq 0$)

Building convex approximations

Convex Taylor expansions

Given nonconvex function f

First order $\hat{f}(x) = f(x^k) + \nabla f(x^k)^T (x - x^k)$

Second order $\hat{f}(x) = f(x^k) + \nabla f(x^k)^T (x - x^k) + (1/2)(x - x^k)^T P_+(x - x^k)$

where $P_+ = \Pi_{\mathbf{S}_+}(\nabla^2 f(x)) = U(\mathbf{diag}(\lambda))_+ U^T$ **positive semidefinite cone projection**

Local approximation

it does not depend on trust-region radius ρ

Quasi-linearization

Very easy and cheap method for affine approximation

$$\text{write } h \text{ as } h(x) = A(x)x + b(x)$$



$$\text{use } \hat{h}(x) = A(x^k)x + b(x^k)$$

Example $f(x) = (1/2)x^T P x + q^T x + r = ((1/2)P x + q)^T x + r$

Quasi-linear: $\hat{h}(x) = ((1/2)P x^k + q)^T x + r$

Taylor: $\hat{h}(x) = h(x^k) + (P x^k + q)^T (x - x^k)$

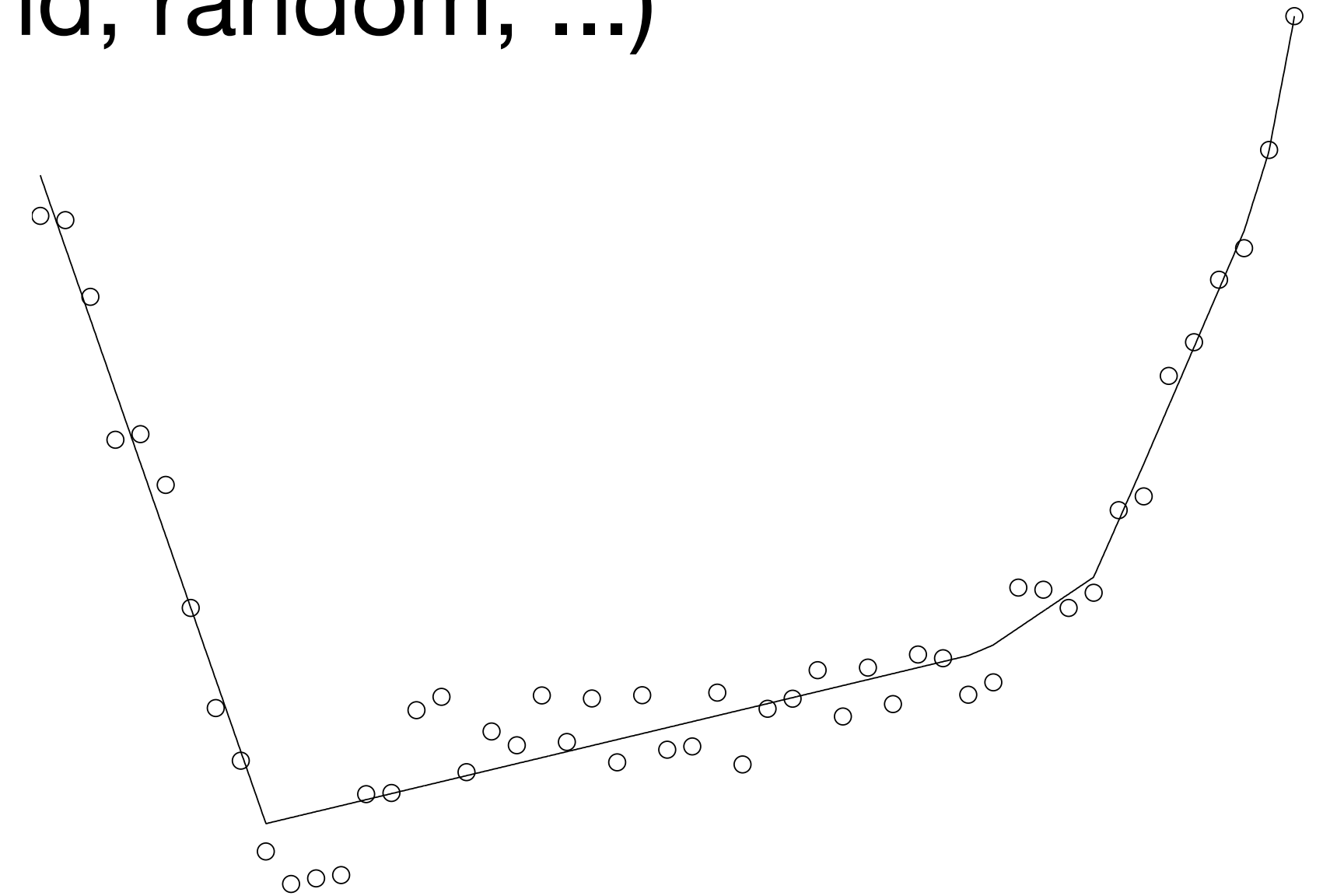
Local approximation

it does not depend on trust-region radius ρ

Particle methods

Idea

- Choose points $z_1, \dots, z_K \in \mathcal{T}^k$ (e.g., vertices, grid, random, ...)
- Evaluate function $y_i = f(z_i)$
- Fit data (z_i, y_i) with convex functions (convex optimization)



Advantages

- Nondifferentiable functions
- **regional models:** they depend on current x^k and radii ρ_i

Particle methods

Fit piecewise linear functions to data

$$\hat{f}(x) = \max_i \{ \hat{y}_i + g_i^T (x - z_i) \}$$

\hat{y}_i act as function values $\hat{f}(z_i)$

g_i act as subgradients $\partial \hat{f}(z_i)$

Fitting problem

minimize $\sum_{i=1}^K (\hat{y}_i - y_i)^2$

subject to $\hat{y}_j \geq \hat{y}_i + g_i^T (z_j - z_i), \quad i, j = 1, \dots, K$

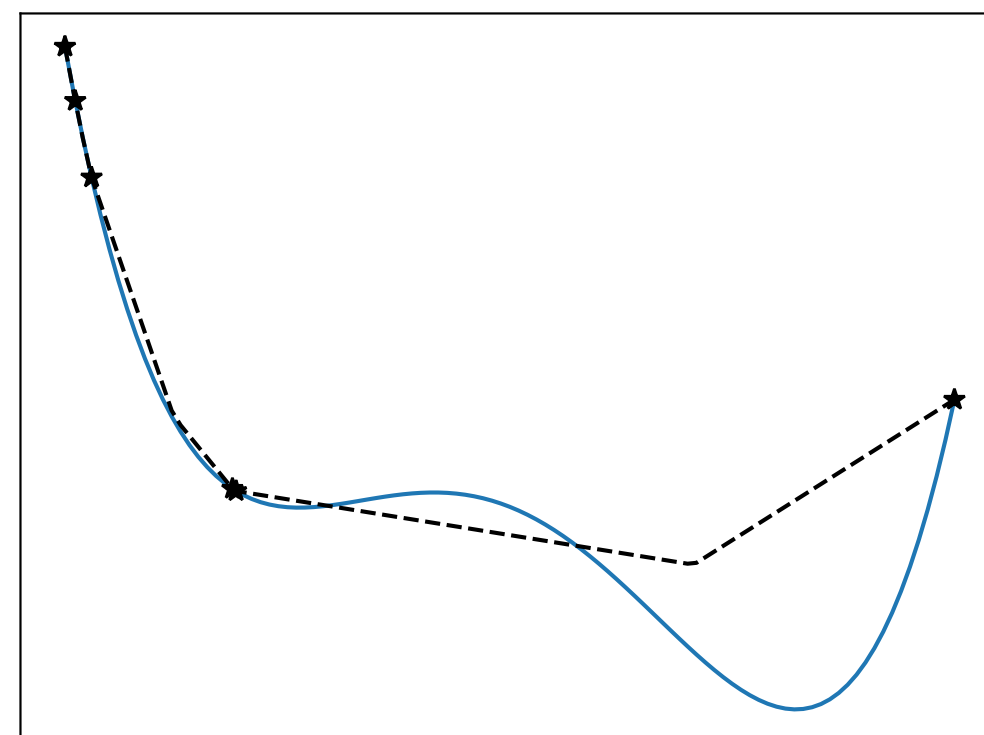
$\hat{y}_i \leq y_i, \quad i = 1, \dots, K$

convexity

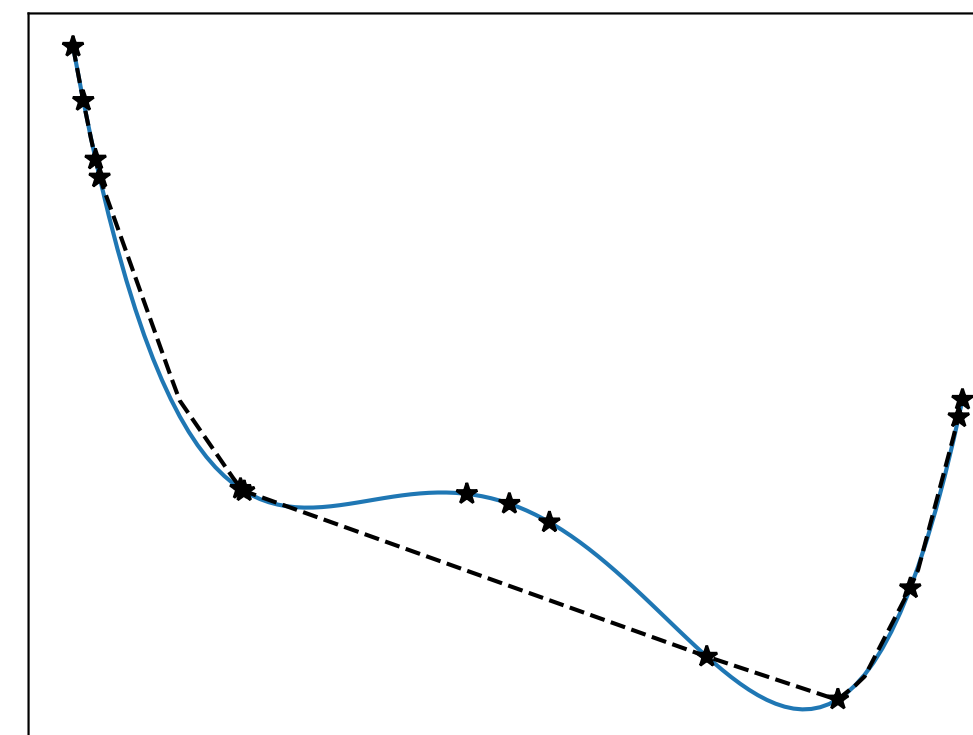
lower bound

$$f(x) = x^4 - 2x^3 + 0.3x$$

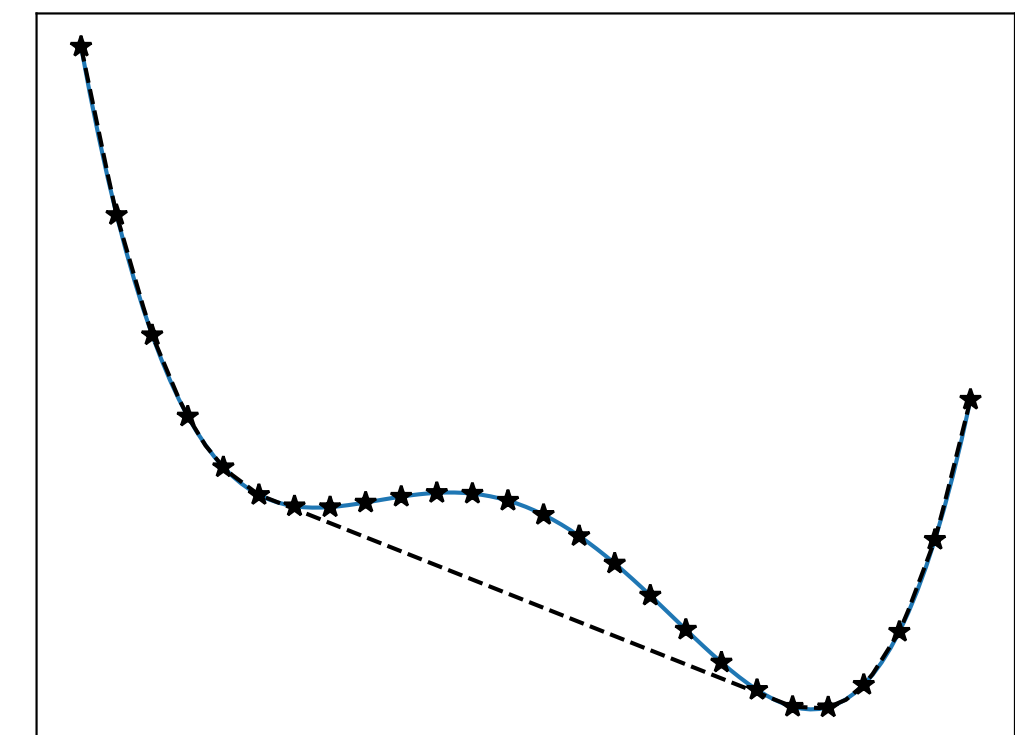
5 random



12 random



uniform grid



Particle methods

Fit quadratic functions to data

$$\hat{f}(x) = (1/2)(x - x^k)^T P(x - x^k) + q^T(x - x^k) + r$$

Fitting problem

$$\begin{aligned} \text{minimize} \quad & \sum_{i=1}^K ((1/2)(z_i - x^k)^T P(z_i - x^k) + q^T(z_i - z^k) + r - y_i)^2 \\ \text{subject to} \quad & P \succeq 0 \end{aligned}$$

Remarks

- No necessarily upper/lower bound
- We can add other objectives, convex constraints and norm penalties
- Can be more sample efficient than piecewise linear
- Need to solve a **convex problem for every function at every SCP iteration** ₁₈

Trust region example

Example: nonconvex quadratic program

$$\begin{aligned} &\text{minimize} && f(x) = (1/2)x^T P x + q^T x \\ &\text{subject to} && \|x\|_\infty \leq 1 \end{aligned}$$

P is symmetric but not positive semidefinite

Taylor approximation

$$\hat{f}(x) = f(x^k) + (P x^k + q)^T (x - x^k) + (1/2)(x - x^k)^T P_+ (x - x^k)$$

Example: nonconvex quadratic program

Lower bound via convex duality

$$\begin{aligned} &\text{minimize} && f(x) = (1/2)x^T P x + q^T x \\ &\text{subject to} && \|x\|_\infty \leq 1 \end{aligned}$$

Lagrangian

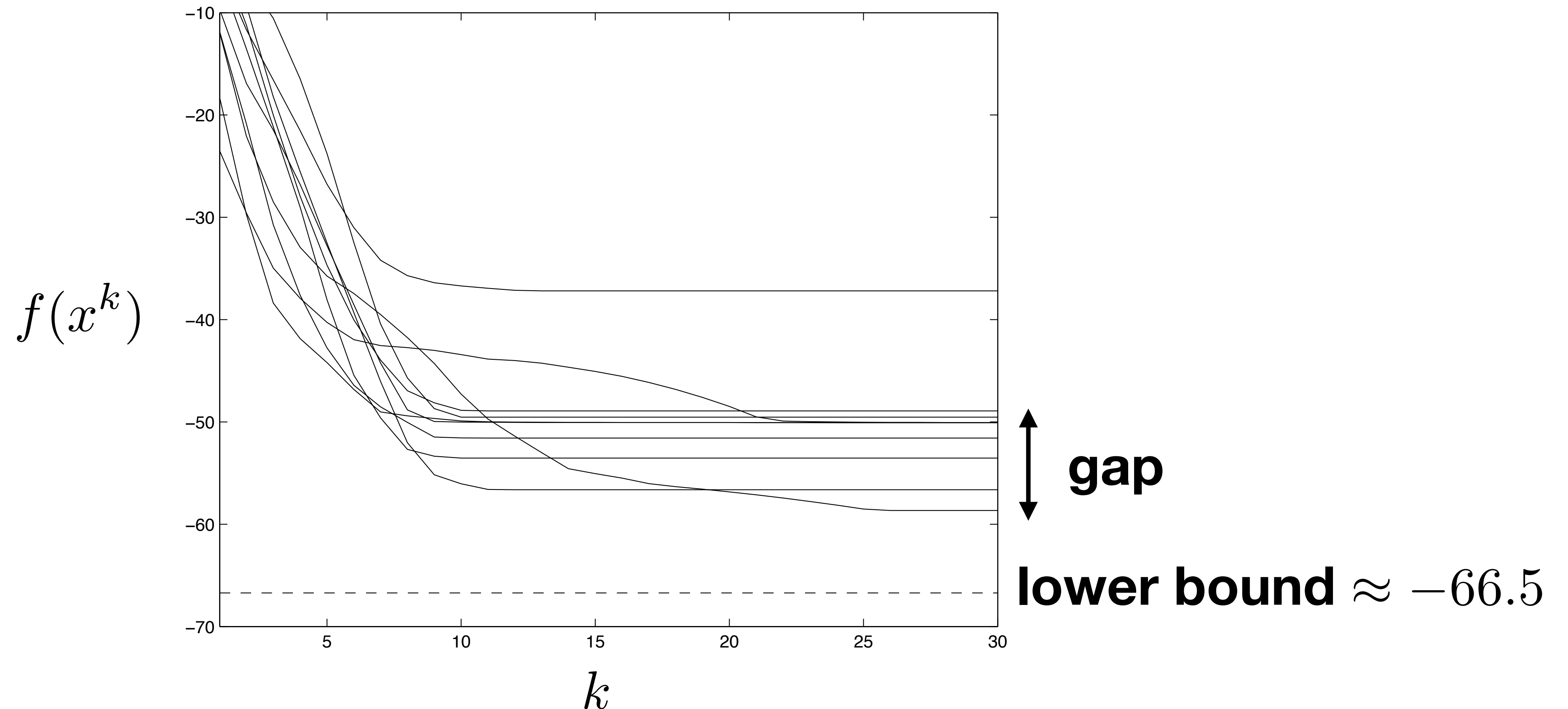
$$\begin{aligned} L(x, \lambda) &= (1/2)x^T P x + q^T x + \sum_{i=1}^n \lambda_i (x_i^2 - 1) \\ &= (1/2)x^T (P + 2\text{diag}(\lambda))x + q^T x - \mathbf{1}^T \lambda \end{aligned}$$

Dual problem (always convex)

$$\begin{aligned} &\text{maximize} && -(1/2)q^T (P + 2\text{diag}(\lambda))^{-1} q - \mathbf{1}^T \lambda && g(\lambda) \\ &&& \lambda \geq 0 \end{aligned}$$

Example: nonconvex quadratic program

SCP with $\rho = 0.2$ with 10 different random $x_0 \in \mathbb{R}^n$



Regularized trust region methods

Issues with vanilla sequential convex programming

$$\begin{array}{ll} \text{minimize} & f(x) \\ \text{subject to} & g_i(x) \leq 0, \quad i = 1, \dots, m \\ & h_i(x) = 0, \quad i = 1, \dots, p \end{array} \longrightarrow \begin{array}{ll} \text{minimize} & \hat{f}(x) \\ \text{subject to} & \hat{g}_i(x) \leq 0, \quad i = 1, \dots, m \\ & \hat{h}_i(x) = 0, \quad i = 1, \dots, p \\ & x \in \mathcal{T}^k \end{array}$$

Infeasibility

Approximate problem can be infeasible (e.g. too small ρ)

Evaluate progress

when x^k infeasible

- Objective: $f(x^k)$
- Inequality violations: $g_i(x^k)_+$
- Equality violations: $|h_i(x^k)|$

Controlling trust region size

- ρ **too large**
poor approximations \rightarrow bad x^{k+1}
- ρ **too small**
good approximations \rightarrow slow progress

Exact penalty formulation

Solve unconstrained problem instead of the original problem

$$\text{minimize } \phi(x) = f(x) + \lambda \left(\sum_{i=1}^m (g_i(x))_+ + \sum_{i=1}^p |h_i(x)| \right), \quad \lambda > 0$$

For λ large enough $\longrightarrow x^* = \operatorname{argmin} \phi(x)$ solves the original problem
($\lambda > \|y^*\|_\infty$ where y^* is the dual variable satisfying the KKT conditions)

SCP solves the convex approximation (always feasible)

$$\hat{\phi}(x) = \hat{f}(x) + \lambda \left(\sum_{i=1}^m (\hat{g}_i(x))_+ + \sum_{i=1}^p |\hat{h}_i(x)| \right)$$

If λ not large enough, we have **sparse violations**

Trust region update

Idea judge progress in ϕ using $\hat{x} = \operatorname{argmin} \hat{\phi}(x)$

Exact decrease

$$\delta = \phi(x^k) - \phi(\hat{x})$$

Approximate decrease

$$\hat{\delta} = \phi(x^k) - \hat{\phi}(\hat{x})$$

Updates

- $\delta \geq \alpha \hat{\delta} \longrightarrow$
- accept: $x^{k+1} = \hat{x}$
 - increase region $\rho = \beta^{\text{acc}} \rho$
- $\delta < \alpha \hat{\delta} \longrightarrow$
- reject: $x^{k+1} = x^k$
 - decrease region $\rho = \beta^{\text{rej}} \rho$

Parameters

tolerance α (e.g., = 0.1)

accept multiplier $\beta^{\text{acc}} \geq 1$ (e.g., = 1.1)

reject multiplier $\beta^{\text{rej}} \in (0, 1)$ (e.g., 0.5)

Interpretation

If actual decrease δ is more than α fraction of predicted decrease $\hat{\delta}$ then increase trust region size (longer steps). Otherwise decrease it.

Regularized trust region example

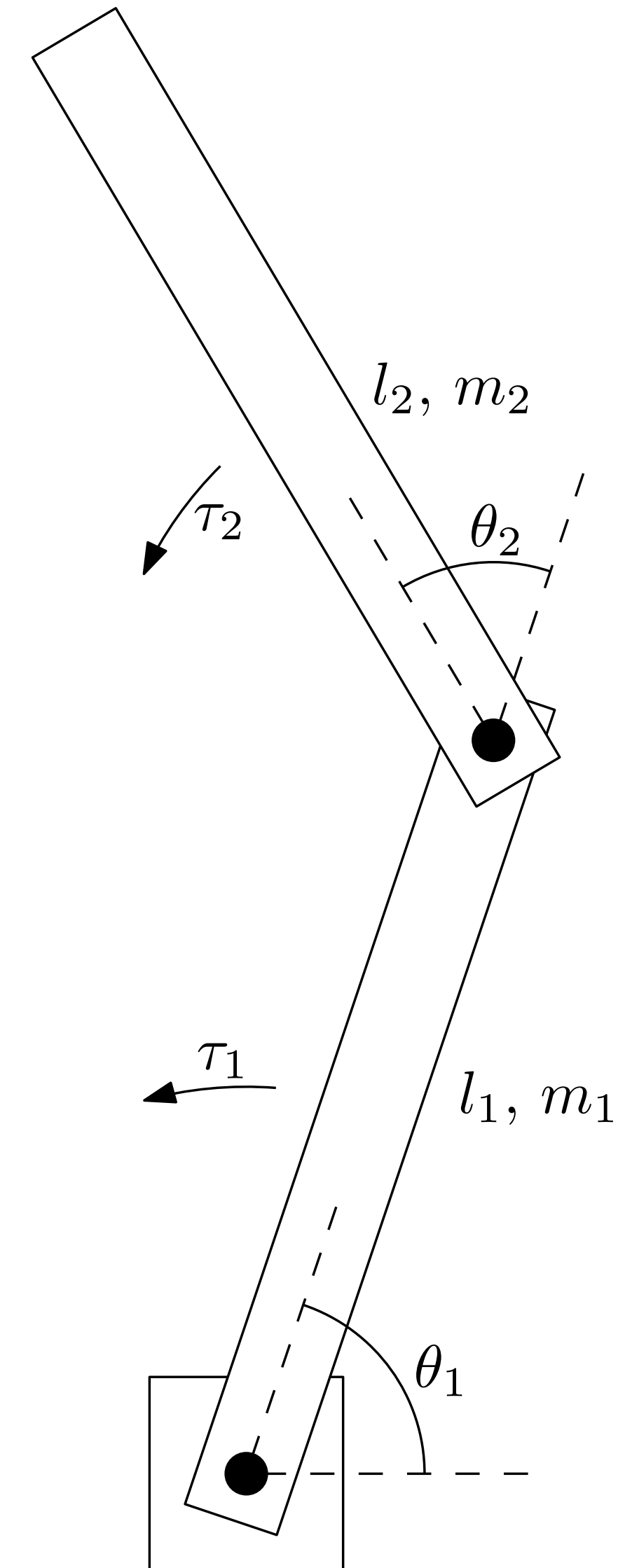
Nonlinear optimal control

Robotic arm

2-dimensional system

no gravity (horizontal)

controlled torques τ_1, τ_2



Nonlinear optimal control

The problem

minimize

$$J = \int_0^T \|\tau(t)\|_2^2 dt$$

subject to

$$\theta(0) = \theta_{\text{init}}, \quad \theta(T) = \theta_{\text{final}}$$

$$\dot{\theta}(0) = 0, \quad \dot{\theta}(T) = 0$$

$$\|\tau(t)\|_\infty \leq \tau_{\text{max}}, \quad 0 \leq t \leq T$$

**minimum
torque**

position

velocity

Dynamics

$$M(\theta)\ddot{\theta} + W(\theta, \dot{\theta})\dot{\theta} = \tau$$



Not convex!

(Hard to optimize)

Note: cheap to simulate

$$M(\theta) = \begin{bmatrix} (m_1 + m_2)l_1^2 & m_2l_1l_2(s_1s_2 + c_1c_2) \\ m_2l_1l_2(s_1s_2 + c_1c_2) & m_2l_2^2 \end{bmatrix}$$

$$W(\theta, \dot{\theta}) = \begin{bmatrix} 0 & m_2l_1l_2(s_1c_2 - c_1s_2)\dot{\theta}_2 \\ m_2l_1l_2(s_1c_2 - c_1s_2)\dot{\theta}_1 & 0 \end{bmatrix}$$

where $s_i = \sin(\theta_i)$ and $c_i = \cos(\theta_i)$

Nonlinear optimal control

Discretization

Discretize with **time intervals** $h = T/N$

Objective $J = \int_0^T \|\tau(t)\|_2^2 dt \approx h \sum_{i=1}^N \|\tau_i\|_2^2, \quad \text{with } \tau_i = \tau(ih)$

Dynamics: approximate derivatives

$$M(\theta)\ddot{\theta} + W(\theta, \dot{\theta})\dot{\theta} = \tau$$

$$\dot{\theta}(ih) \approx \frac{\theta_{i+1} - \theta_{i-1}}{2h} \quad \downarrow \quad \ddot{\theta}(ih) \approx \frac{\theta_{i+1} - 2\theta_i + \theta_{i-1}}{h^2}$$

zero initial velocities

$$\theta_0 = \theta_1 = \theta_{\text{init}}$$

$$\theta_N = \theta_{N+1} = \theta_{\text{final}}$$

nonlinear equality constraints

$$M(\theta_i) \frac{\theta_{i+1} - 2\theta_i + \theta_{i-1}}{h^2} + W\left(\theta_i, \frac{\theta_{i+1} - \theta_{i-1}}{2h}\right) \frac{\theta_{i+1} - \theta_{i-1}}{2h} = \tau_i$$

Nonlinear optimal control

Convexification

$$\begin{aligned} \text{minimize} \quad & h \sum_{i=1}^N \|\tau_i\|_2^2 \\ \text{subject to} \quad & \theta_0 = \theta_1 = \theta_{\text{init}}, \quad \theta_N = \theta_{N+1} = \theta_{\text{final}} \\ & \|\tau_i\|_\infty \leq \tau_{\text{max}} \\ & M(\theta_i) \frac{\theta_{i+1} - 2\theta_i + \theta_{i-1}}{h^2} + W \left(\theta_i, \frac{\theta_{i+1} - \theta_{i-1}}{2h} \right) \frac{\theta_{i+1} - \theta_{i-1}}{2h} = \tau_i \end{aligned}$$

Quasi-linearization of the dynamics around previous x^k

$$M(\theta_i^k) \frac{\theta_{i+1} - 2\theta_i + \theta_{i-1}}{h^2} + W \left(\theta_i^k, \frac{\theta_{i+1}^k - \theta_{i-1}^k}{2h} \right) \frac{\theta_{i+1} - \theta_{i-1}}{2h} = \tau_i$$

Remarks

- trust region only on θ_i (cost and constraints convex in τ_i)
- initialize with straight line: $\theta_i = \frac{i-1}{N-1} (\theta_{\text{final}} - \theta_{\text{init}}), \quad i = 1, \dots, N$

Nonlinear optimal control

Example

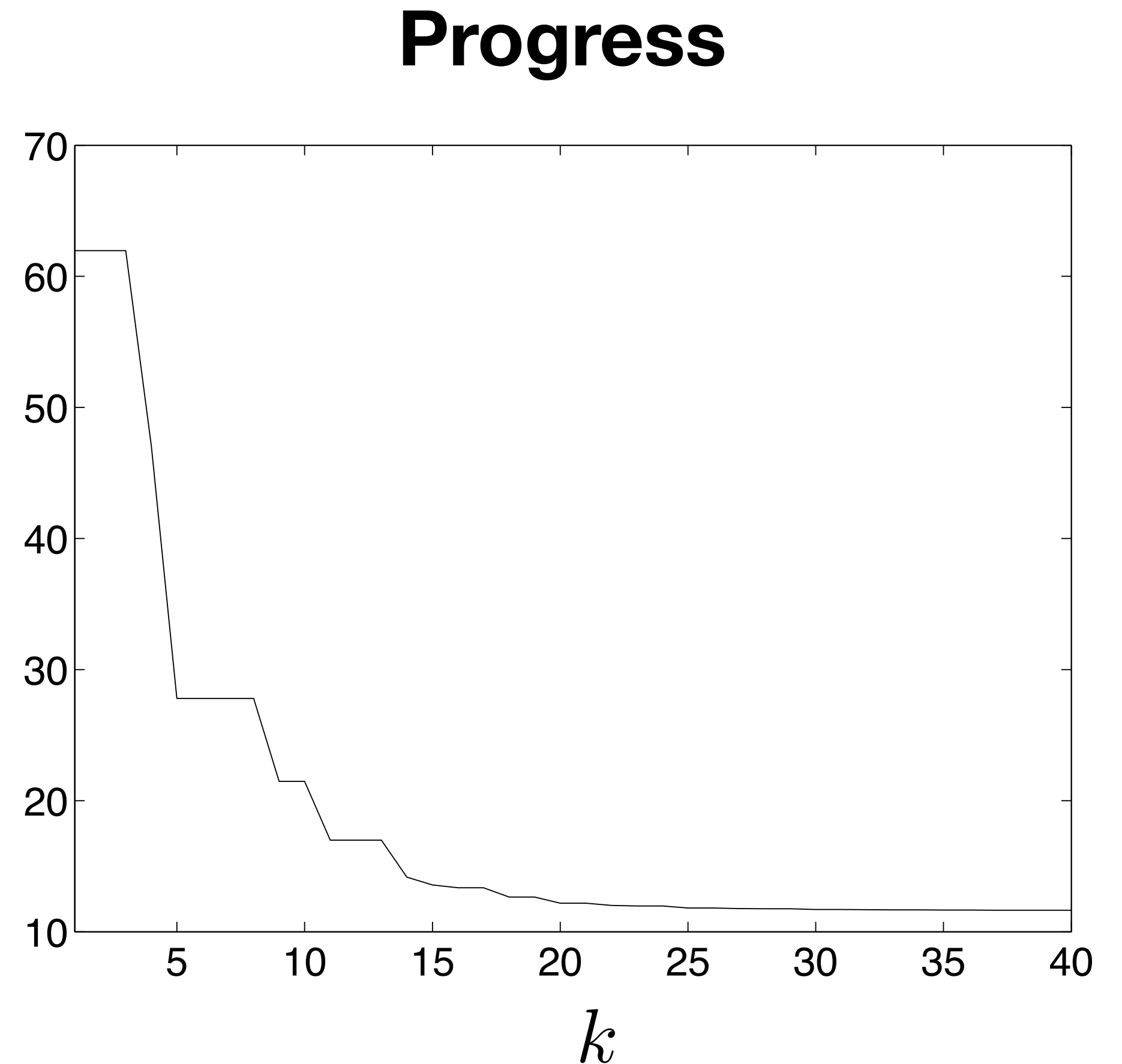
System

- $m_1 = 1, m_2 = 5, l_1 = l_2 = 1$
- $N = 40, T = 10$
- $\theta_{\text{init}} = (0, -2.9), \theta_{\text{final}} = (3, 2.9)$
- $\tau_{\text{max}} = 1.1$

Algorithm

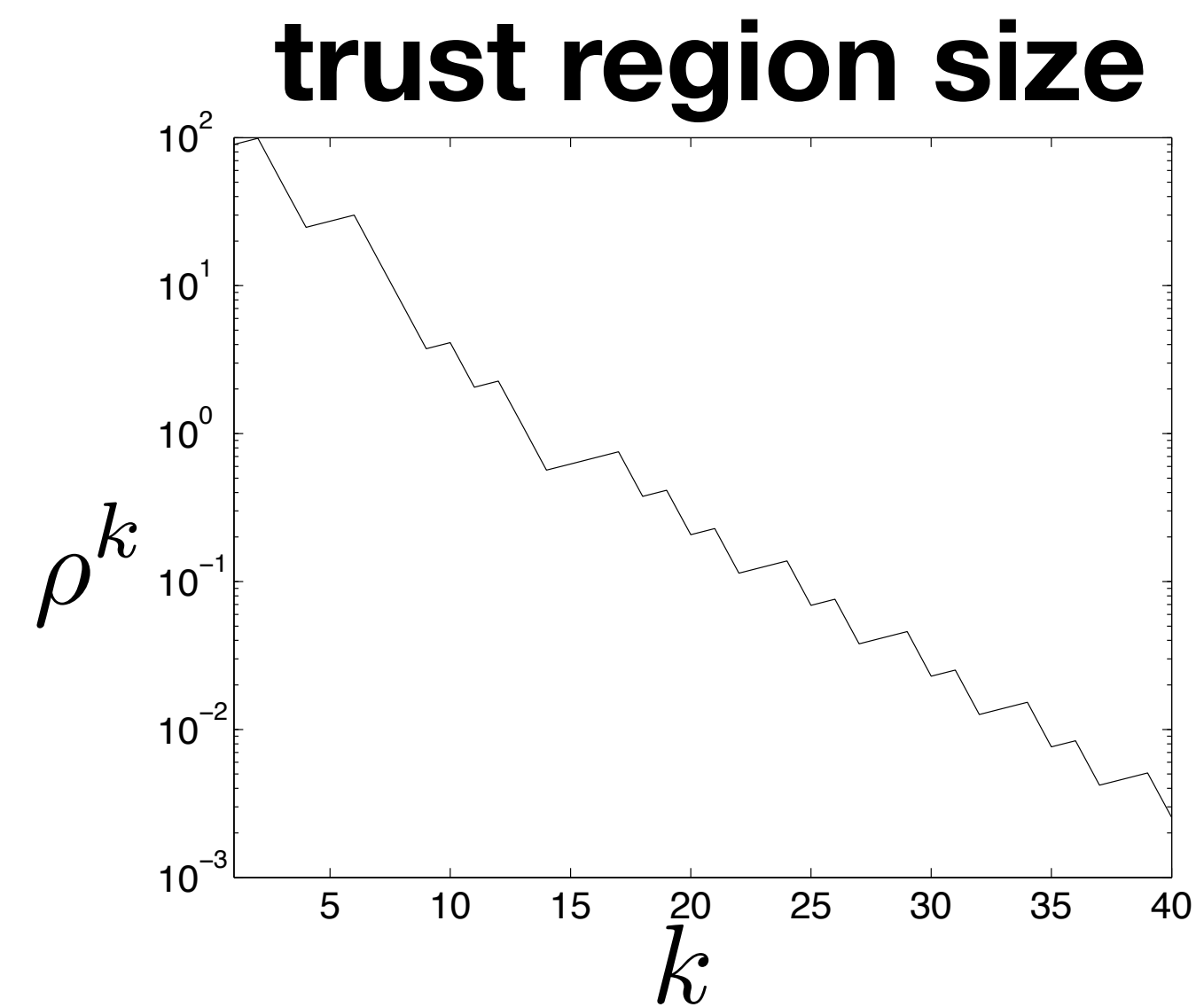
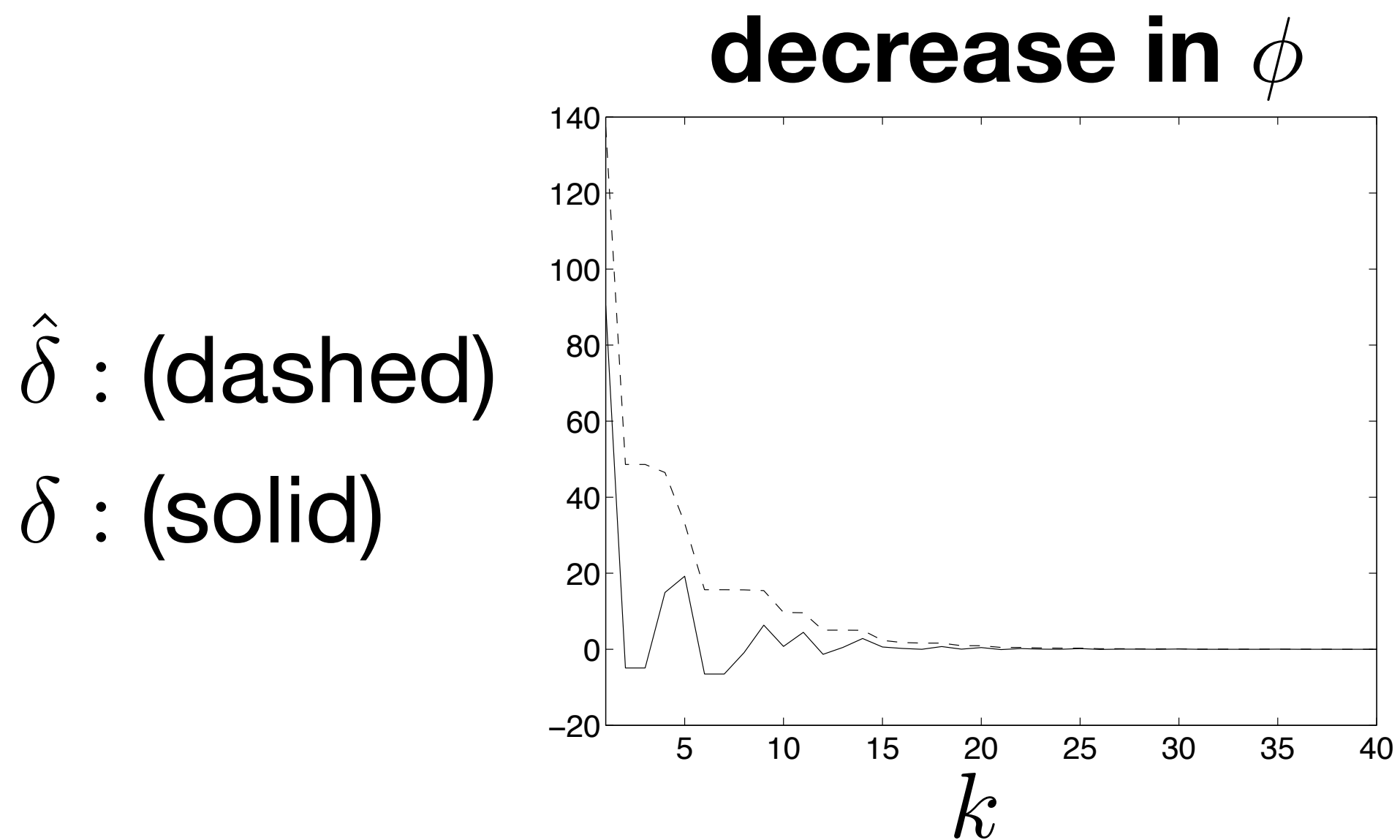
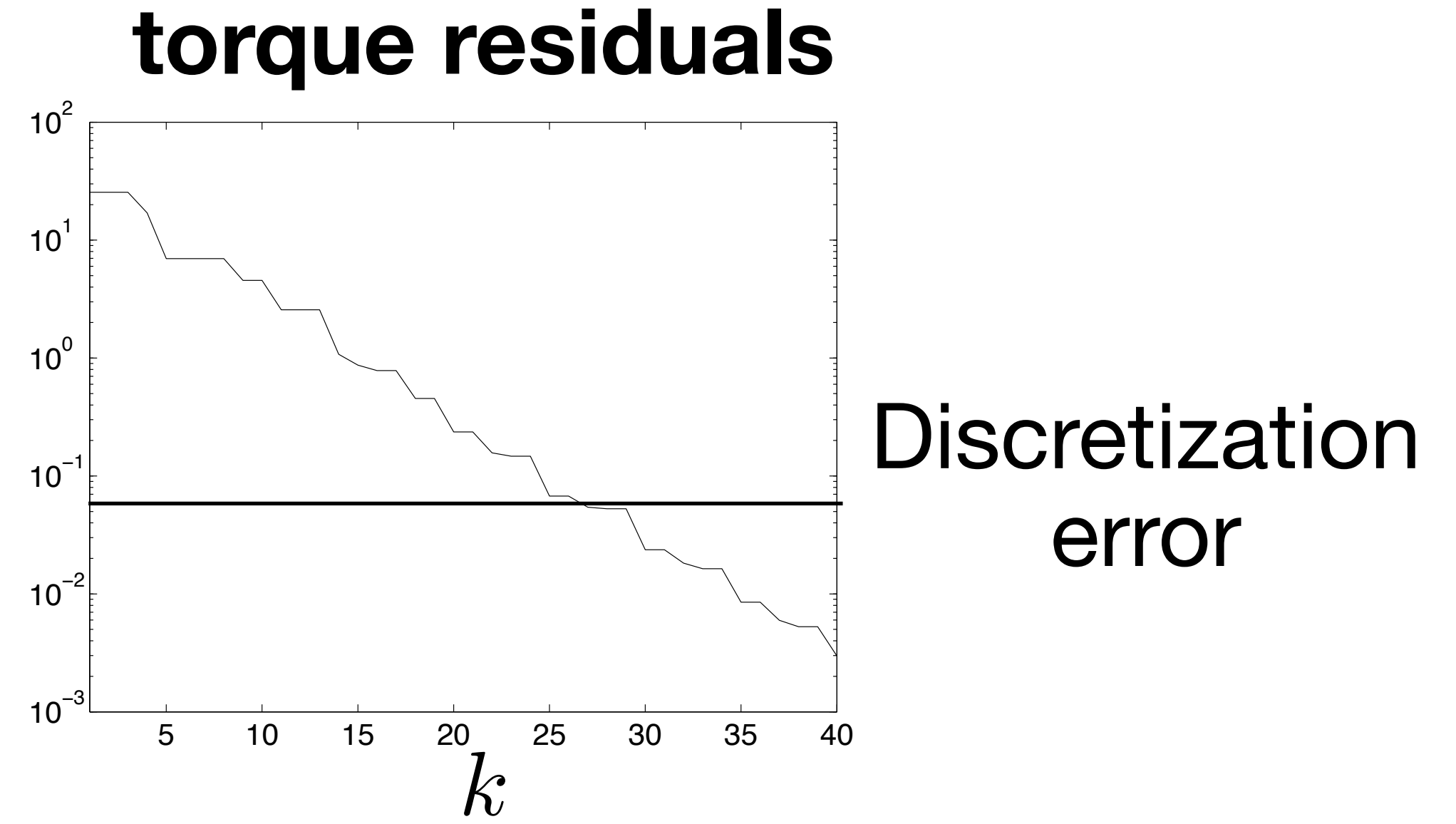
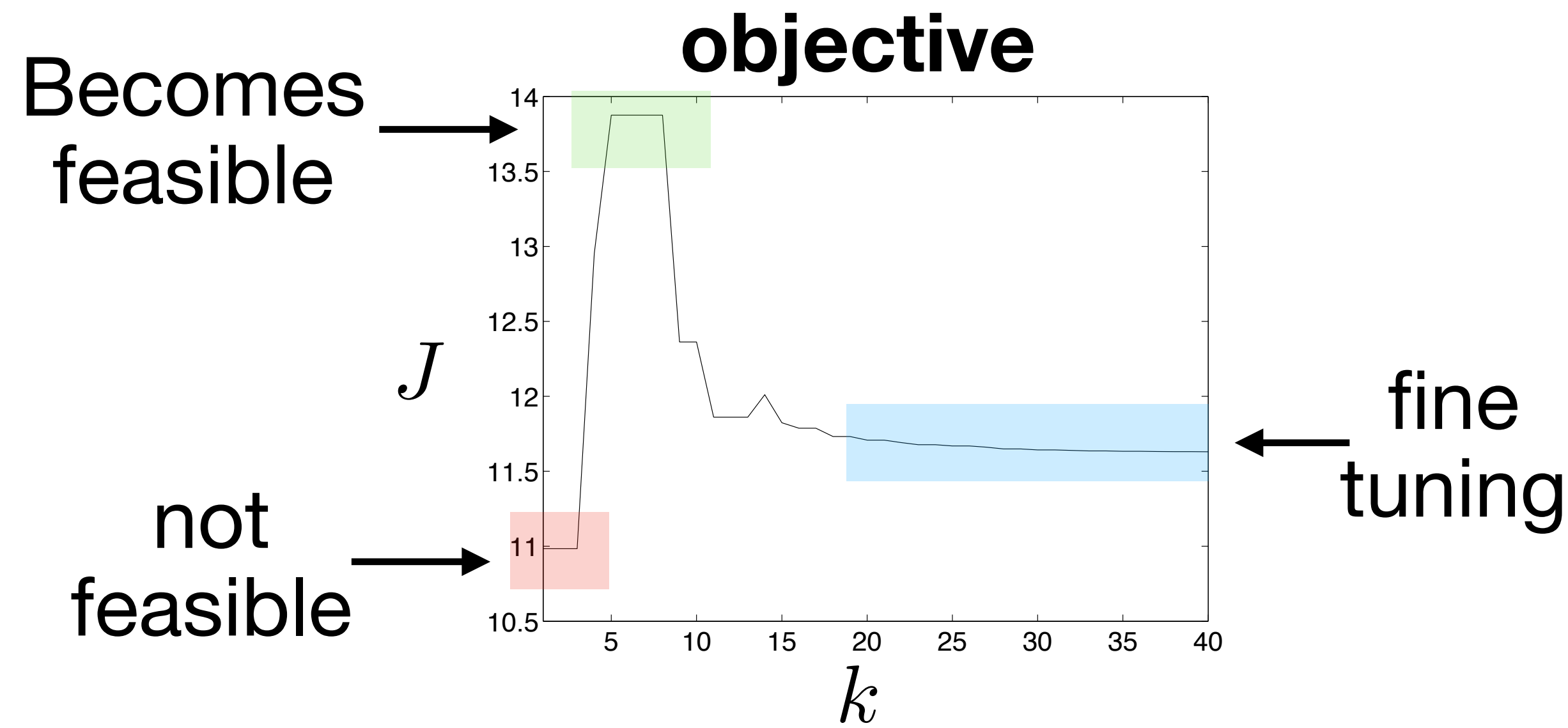
- $\lambda = 2$
- $\alpha = 0.1, \beta^{\text{acc}} = 1.1, \beta^{\text{rej}} = 0.5$
- $\rho_1 = 90^\circ$ (very large)

$\phi(x^k)$



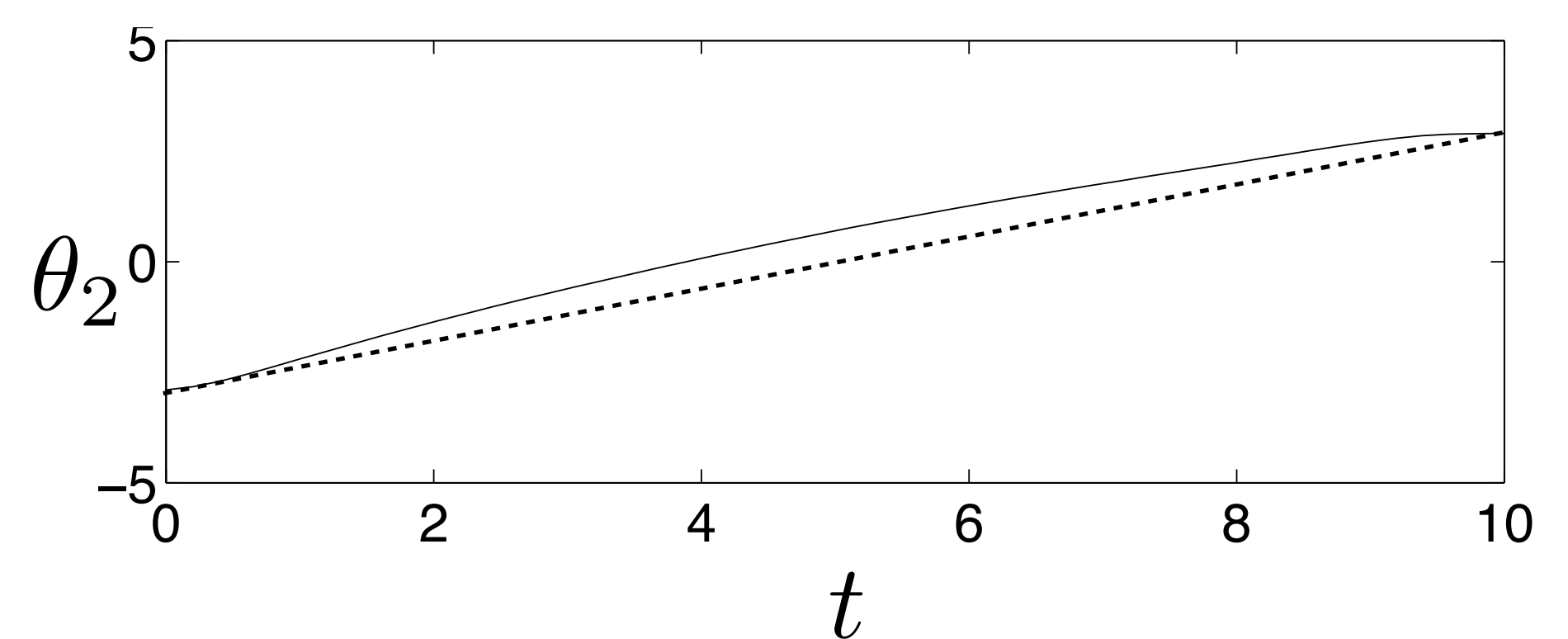
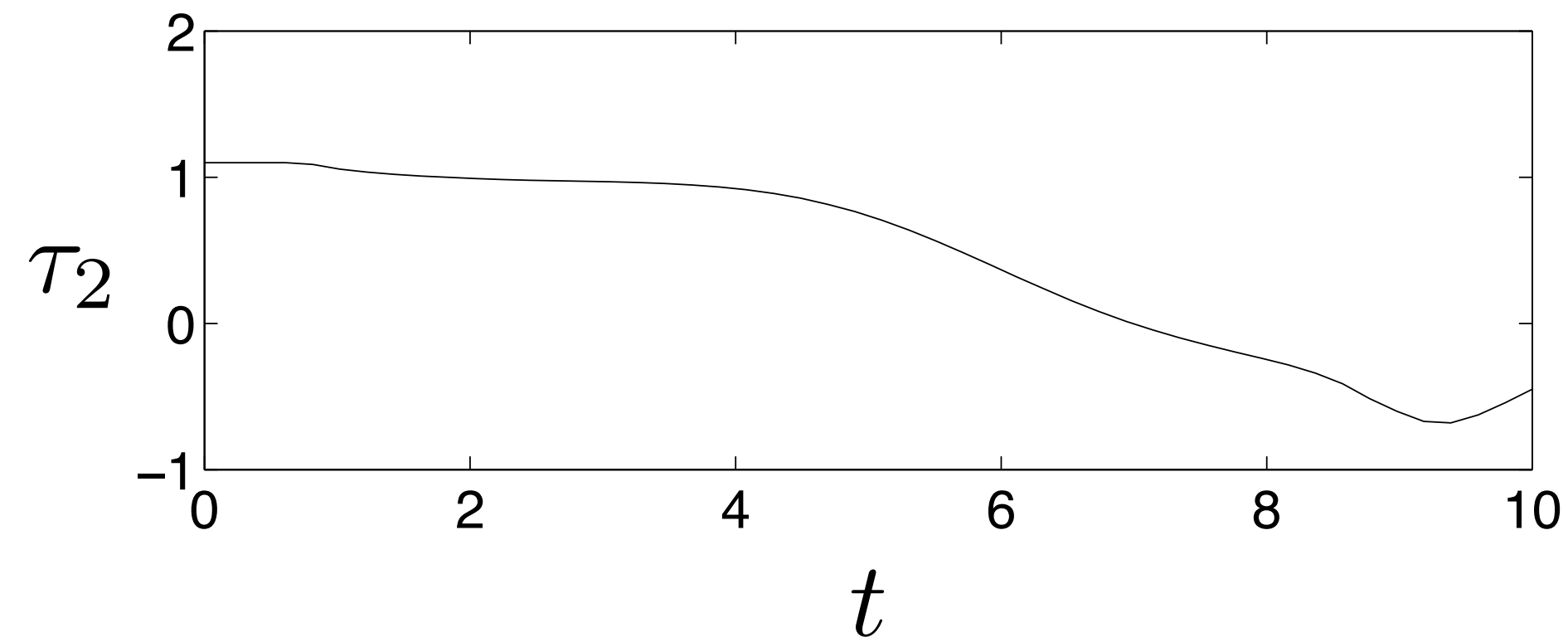
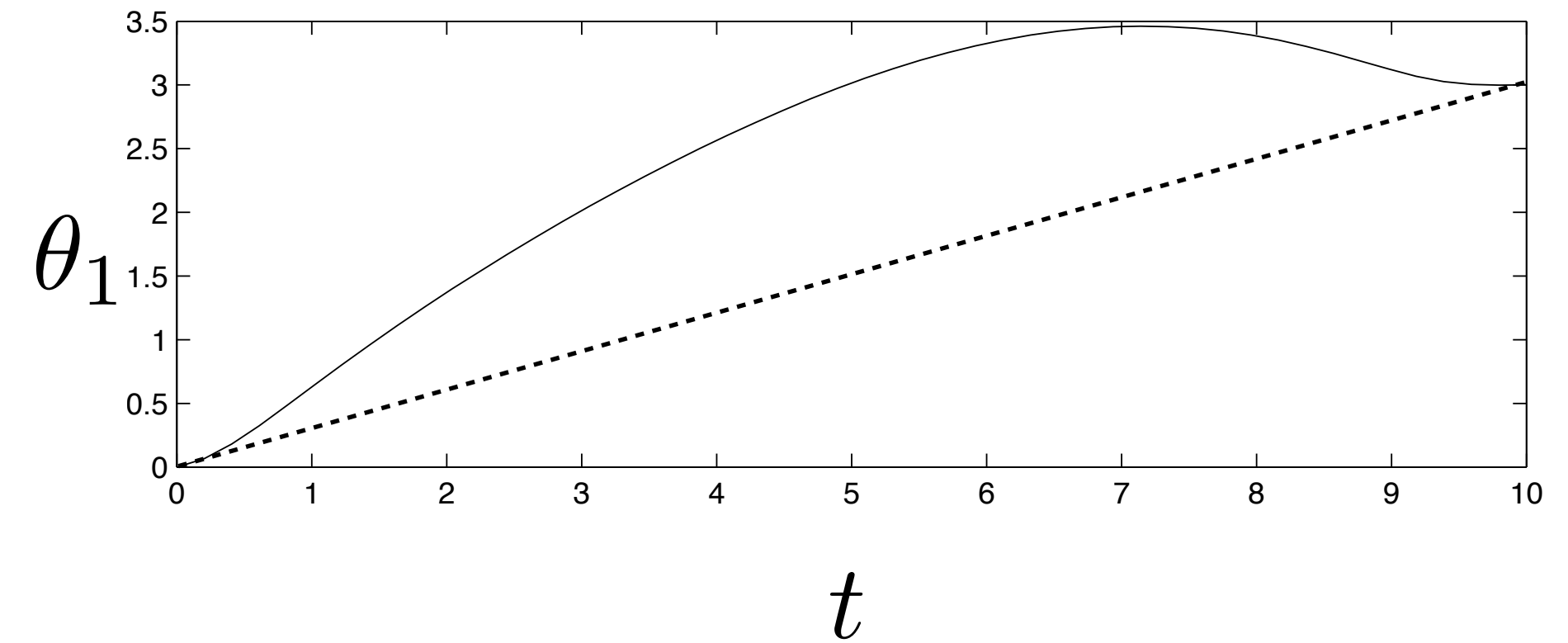
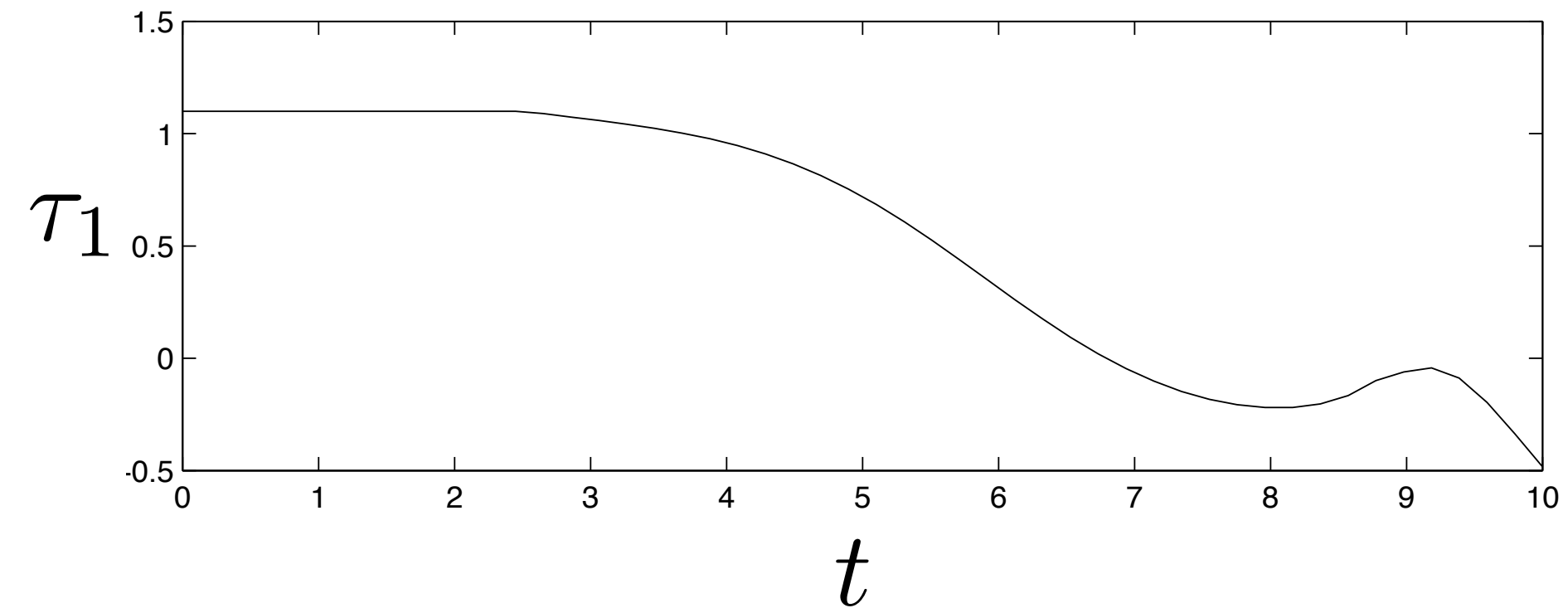
Note: does not go to 0

Nonlinear optimal control



Nonlinear optimal control

Trajectories



Difference of convex programming

Difference of convex programming

$$\begin{aligned} &\text{minimize} && f_0(x) - g_0(x) \\ &\text{subject to} && f_i(x) - g_i(x) \leq 0, \quad i = 1, \dots, m \end{aligned}$$

**Difference of
convex functions**

where f_i and g_i are convex

Very powerful

it can represent any twice differentiable function

Hard

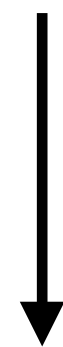
nonconvex problem unless g_i are affine

Difference of convex programming

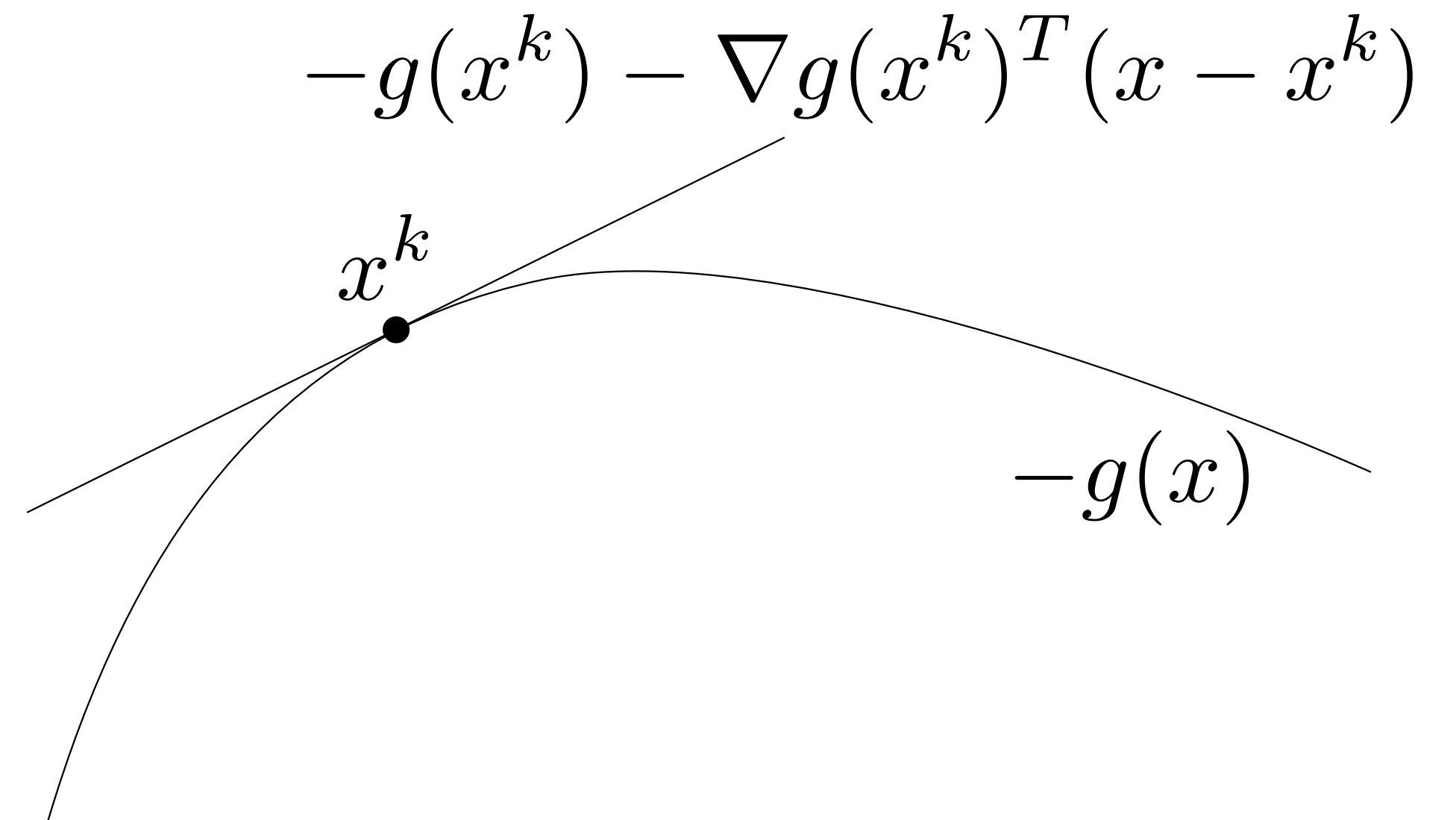
Convexification

Convexify $f(x) - g(x)$

$$f(x) - \hat{g}(x) = f(x) - g(x^k) - \nabla g(x^k)^T (x - x^k)$$



$$f(x) - g(x) \leq f(x) - \hat{g}(x)$$



Remarks

- True objective better than convexified objective

- True feasible set contains convexified feasible set



**No trust region
needed**

Difference of convex programming

Iterations

Convex-concave procedure

1. Convexify: form $\hat{g}_i(x) = g_i(x^k) + \nabla g_i(x^k)^T(x - x^k)$ for $i = 0, \dots, m$

2. Solve to obtain x^{k+1}

$$\begin{aligned} &\text{minimize} && f_0(x) - \hat{g}_0(x) \\ &\text{subject to} && f_i(x) - \hat{g}_i(x) \leq 0 \end{aligned}$$

Remarks

It always converges to a stationary point (it might be a maximum)

Path planning example

Find shortest path connecting a and b in \mathbf{R}^d

Avoid circles centered at c_j with radius r_j with $j = 1, \dots, m$

minimize L

subject to $x_0 = a, \quad x_n = b$

path lengths ——— $\|x_i - x_{i-1}\|_2 \leq L/n, \quad i = 1, \dots, n$

obstacle constraints ——— $\|x_i - c_j\|_2 \geq r_j, \quad i = 1, \dots, n, \quad j = 1, \dots, m$
(not convex)

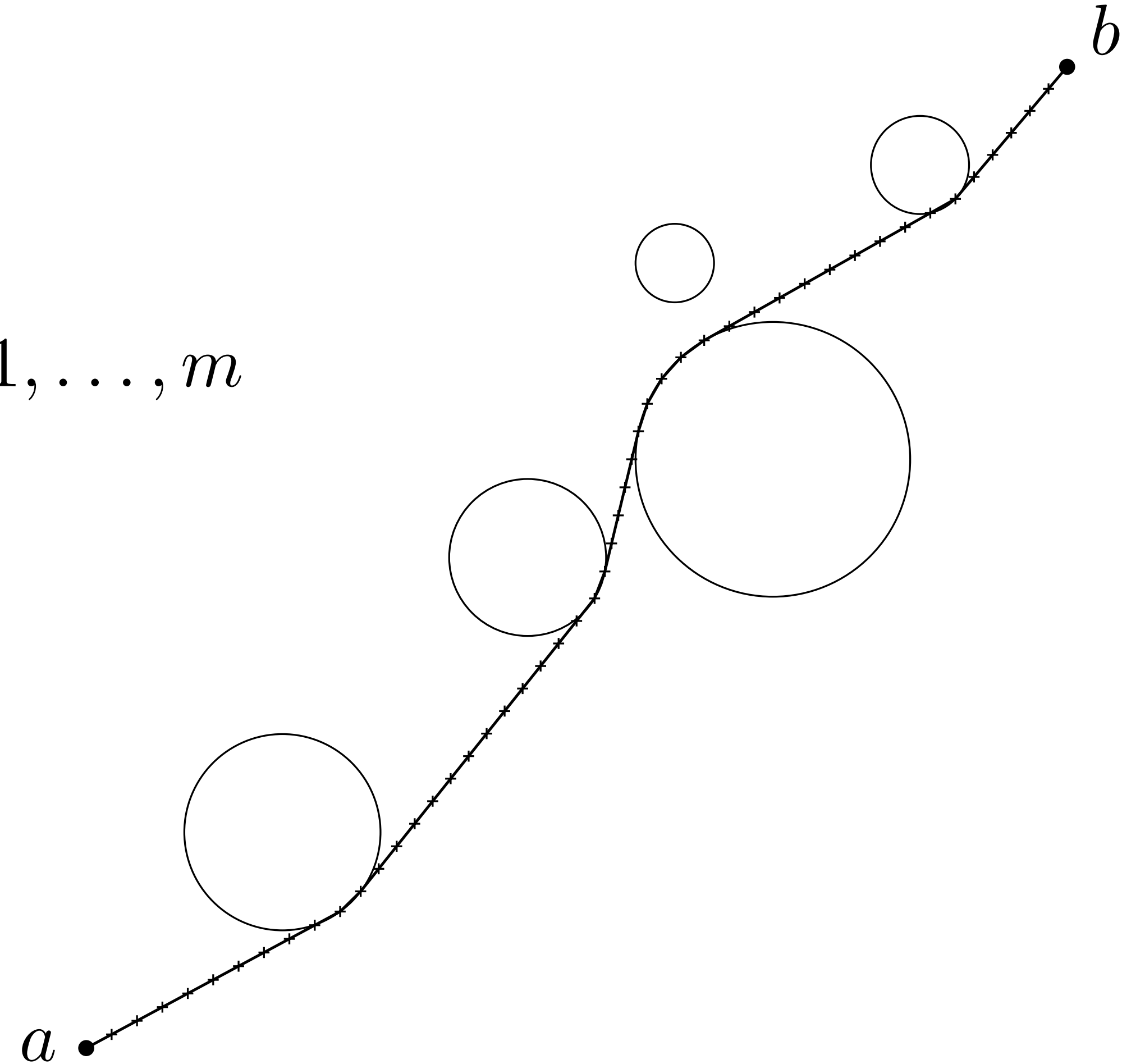
Path planning example

$$\begin{aligned} &\text{minimize} && L \\ &\text{subject to} && x_0 = a, \quad x_n = b \\ & && \|x_i - x_{i-1}\|_2 \leq L/n, \quad i = 1, \dots, n \\ & && \|x_i - c_j\|_2 \geq r_j, \quad i = 1, \dots, n, \quad j = 1, \dots, m \end{aligned}$$

Dimension: $d = 2$

Steps: $n = 50$

It converges in 26 iterations (convex problems)



Sequential convex programming

Today, we learned to:

- **Familiarize** with concepts of sequential convex programming
- **Develop** trust region algorithms
- **Build** convex approximations of nonlinear/nonsmooth functions
- **Develop** regularized trust region methods to account for infeasibility
- **Recognize** difference-of-convex programs and **apply** convex-concave procedure

Next lecture

- Conclusions and the role of optimization