

Conic Optimization Refresher

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from mosek cookbook

October 25, 2022

1 Types of Cones

Conic optimization is a class of convex optimization problems. The geneneral form of a conic optimization problem is:

$$\begin{aligned} & \text{maximize } \mathbf{c}^T \mathbf{x} \\ & \text{subject to } \mathbf{Ax} + \mathbf{b} \in \mathcal{K} \end{aligned}$$

where \mathcal{K} is a product of the following basic types of cones:

- **Linear cone:**

$$\mathbb{R}, \mathbb{R}_+^n, 0$$

- **Quadratic cone and rotated quadratic cone:**

The quadratic cone is the set

$$\mathcal{Q}^n = \left\{ x \in \mathbb{R} \mid x_1 \geq \sqrt{x_2^2 + \cdots + x_n^2} \right\}$$

The rotated quadratic cone is the set

$$\mathcal{Q}_r^n = \left\{ x \in \mathbb{R} \mid 2x_1x_2 \geq x_3^2 + \cdots + x_n^2, x_1, x_2 \geq 0 \right\}$$

Together the union of these two cones covers the class of SOCO (second-order cone optimization) problems which includes all QO (quadratic optimization) and QCQO (quadratically constrained quadratic optimization) problems as well.

- **Primal power cone:**

$$\mathcal{P}_n^{\alpha, 1-\alpha} = \left\{ x \in \mathbb{R}^n \mid x_1^\alpha x_2^{1-\alpha} \geq \sqrt{x_3^2 + \cdots + x_n^2}, x_1, x_2 \geq 0 \right\}$$

- **Primal exponential cone:**

$$K_{\text{exp}} = \left\{ x \in \mathbb{R}^3 \mid x_1 \geq x_2 \exp\left(\frac{x_3}{x_2}\right), x_1, x_2 \geq 0 \right\}$$

- **Semidefinite cone:**

$$\mathcal{S}_+^n = \{X \in \mathbb{R}^{n \times n} | X \text{ is symmetric positive semidefinite}\}$$

Semidefinite cones model SDO problems.

Each of these cones allow formulating different types of convex constraints.

2 Selection of Conic Constraints

Examples of real world constraints (financial) and how to convert them to conic form.

2.1 Maximum function

Model the maximum constraint $\max(x_1, x_2, \dots, x_n) \leq c$ using n linear constraints introduces with an auxiliary variable t :

$$\begin{aligned} t &\leq c, \\ t &\geq x_1, \\ &\vdots \\ t &\geq x_n. \end{aligned} \tag{1}$$

For example we can write the constraints $\max(x_i, 0) \leq c_i, 1, \dots, n$ as

$$\mathbf{t} \leq \mathbf{c}, \mathbf{t} \geq \mathbf{x}, \mathbf{t} \geq \mathbf{0},$$

where \mathbf{t} is an n -dimensional vector.

2.2 Positive and negative part

A special case of modeling the maximum function is to model the positive part x^+ and the negative part x^- of a variable x . We define these as $x^+ = \max(x, 0)$ and $x^- = \max(-x, 0)$. Model them explicitly with the above methodology and the inequalities $x^+ = \max(x, 0)$ and $x^- = \max(-x, 0)$, or implicitly with the constraints:

$$\begin{aligned} x &= x^+ - x^-, \\ x^+, x^- &\geq 0. \end{aligned}$$

Note, there is still a degree of freedom in both the implicit and explicit magnitudes of x^+ and x^- . In the explicit case we have inequalities and in the implicit case only the difference of the variables is constrained. Ultimately it is possible for both x^+ and x^- to be positive, allowing optimal solutions where $x^+ = \max(x, 0)$ and $x^- = \max(-x, 0)$ does not hold.

Theoretically we can introduce a complementarity constraint $x^+x^- = 0$ (or $\langle \mathbf{x}^+, \mathbf{x}^- \rangle = 0$) but that is non-convex/ can't be modeled. There are two workarounds to ensure that $x^+ = \max(x, 0)$ and $x^- = \max(-x, 0)$ hold the optimal solution: 1) penalize the magnitude of the two solutions, so if both are positive in any one solution, the solver could always improve the objective by reducing them until either one becomes zero. 2) formulate a mixed integer problem.

2.3 Absolute value

We can model the absolute value constraint $|x| \leq c$ by using the maximum function observing that $|x| = \max(x, -x)$:

$$-c \leq x \leq c$$

Or you could use a quadratic cone:

$$(c, x) \in \mathcal{Q}^2$$

2.4 Sum of largest elements

The sum of the m largest elements of a vector \mathbf{x} is the optimal solution of the LO problem:

$$\begin{aligned} & \text{maximize } \mathbf{x}^T \mathbf{z} \\ & \text{subject to } \mathbf{1}^T \mathbf{z} = m, \\ & \mathbf{0} \leq \mathbf{z} \leq \mathbf{1} \end{aligned}$$

Here \mathbf{x} cannot be a variable as this would result in a nonlinear objective. Looking at the dual of the problem:

$$\begin{aligned} & \text{minimize } mt + \mathbf{1}^T \mathbf{u} \\ & \text{subject to } \mathbf{u} + t \geq \mathbf{x}, \\ & \mathbf{u} \geq 0. \end{aligned}$$

This is the same problem as $\min_t mt + \sum_i \max(0, x_i - t)$, in which x can be a variable and thus optimized.