CO 367

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September 2023

Contents

1 Introduction

1.1 Lecture 1-Preliminaries

Definition 1 (Quadratic Form)**.** Let A be a symmetric matrix and $x = \begin{pmatrix} x_1 \\ \vdots \\ x_n \end{pmatrix}$. The **quadratic form** Q of the matrix A is defined as

$$Q = x^T A x$$

Example 1. Consider the matrix $A = \begin{pmatrix} 5 & -5 \\ -5 & 1 \end{pmatrix}$. The quadratic form of A is

$$Q(x) = 5x_1^2 - 10x_1x_2 + x_2^2$$

Definition 2 (Classification of Quadratic Forms)**.** Let Q be a quadratic form of a matrix A. Then Q is

1. positive definite if $Q(x) > 0$ for all non-zero vectors x, and $Q(x) = 0$ if and only if $x = 0$. Or all eigenvalues of A are positive.
2. positive semidefinite if $Q(x) \geqslant 0$ for all vectors x, with $Q(x) = 0$ occurring for some non-zero vectors x. Or all eigenvalues of A are non-negative.
3. negative definite if $Q(x) < 0$ for all non-zero vectors x, and $Q(x) = 0$ if and only if $x = 0$. Or all eigenvalues of A are negative.
4. negative semidefinite if $Q(x) \leqslant 0$ for all vectors x, with $Q(x) = 0$ occuring for some non-zero vectors x. Or all eigenvalues of A are non-negative.
5. indefinite if $Q(x)$ can be positive or negative. Or there are positive and negative eigenvalues for A.

Definition 3 (big O and little)**.** https://www.stat.cmu.edu/ cshalizi/uADA/13/lectures/app-b.pdf

Definition 4 (differentiable based on big o and little o)**.** $https://sites.math.washington.edu/ folland/Math134/lin-approx.pdf$

Definition 5 (Inner Product Space)**.** Let $x \in \mathbb{R}^n$, represented as:

$$x = \begin{pmatrix} x_1 \\ \vdots \\ x_n \end{pmatrix}$$

The inner product space is defined as:

$$\langle x, y \rangle = x^T y = \sum_{i=1}^{n} x_i y_i \quad \text{(dot product)}$$

The angle between vectors x and y is given by $\cos(\theta) = \frac{\langle x,y \rangle}{\|x\|}$.

With corresponding norm to be the Euclidean Norm

Definition 6 (Open ball)**.** Given $\delta > 0$, $\bar{x} \in \mathbb{R}^n$, the open ball $B_\delta(\bar{x}) = \{x \in \mathbb{R}^n \ | \|x - \bar{x}\| < \delta\}$

Definition 7 (map)**.** Suppose the map $f : \mathbb{R}^n - > \mathbb{R}$.

Definition 8 (open set)**.** Let D $\subset \mathbb{R}^n$, D open set. $\forall x \in D$, $\exists \delta > 0$, s.t $B_\delta(x) \subset D$

Definition 9 (differ)**.** We define f to be in C^1, C^2 on an open set $D \subseteq \mathbb{R}^n$, denoted $f \in C^1(D), C^2(D)$, respectively, if the partial first $\frac{\partial f(x)}{\partial x_i}$ and second $\frac{\partial^2 f(x)}{\partial x_i \partial x_j}$ derivatives exist and are continuous for all i, j, respectively. We then get the gradient vector in $\mathbb{R}^n$ and the $n \times n$ symmetric Hessian matrix, respectively denoted as:

$$\nabla f(x) = \left(\frac{\partial f(x)}{\partial x_i}\right) \in \mathbb{R}^n, \quad \nabla^2 f(x) = \left[\frac{\partial^2 f(x)}{\partial x_i \partial x_j}\right] \in \mathbb{S}^n.$$

Here, $\mathbb{S}^n$ is the vector space of $n \times n$ symmetric matrices.

Definition 10 (General Nonlinear opt. function NLO)**.** The general problem of nonlinear optimization, denoted NLO, is defined as follows: Given C^2-smooth functions $f, g_i, h_j : D \subseteq \mathbb{R}^n \to \mathbb{R}$ for $i = 1, \ldots, m$ and $j = 1, \ldots, p$, where D is an open subset of $\mathbb{R}^n$, the objective is to find the optimal value p^* and an optimum x^* of NLO, represented as:

$$p^* := \min f(x) \text{s.t.} \quad g_i(x) \leqslant 0, \quad \forall i = 1, \ldots, m h_j(x) = 0, \quad \forall j = 1, \ldots, p x \in D$$

If f, g_i, h_i are all **affine** function and D=R^2, then we have an LP

Definition 11 (affine)**.**

$$f(x) = Ax + b \tag{1}$$

where b≠0

Definition 12 (Types of Minimality)**.** Consider $f : \mathbb{R}^n \to \mathbb{R}$ and $D \subset \mathbb{R}^n$. Then $\bar{x} \in D$ is:

- a *global minimizer* for f on D if $f(\bar{x}) \leqslant f(x)$ for all $x \in D$.
- a *strict global minimizer* for f on D if $f(\bar{x}) < f(x)$ for all $x \in D$ where $x \neq \bar{x}$.
- a *local minimizer* for f on D if there exists $\delta > 0$ such that $f(\bar{x}) \leqslant f(x)$ for all $x \in D \cap B_\delta(\bar{x})$.
- a *strict local minimizer* for f on D if there exists $\delta > 0$ such that $f(\bar{x}) < f(x)$ for all $x \in D \cap B_\delta(\bar{x})$ where $x \neq \bar{x}$.

1.2 Lecture 2

Definition 13 (General NLO/NLP)**.** A **Non-linear Optimization Problem** (NLP) is of the following form:

$$\underbrace{p^*}_{\text{Optimal Value}} = \min \underbrace{f(x)}_{Objective function}$$

s.t.

$$g(x) = (g_i(x)) \leqslant 0 \in \mathbb{R}^m$$
$$h(x) = (h_j(x)) = 0 \in \mathbb{R}^p$$

Example 2.

$$\min (x_1 - 2)^2 + (x_2 - 1)^2$$

s.t.

$$x_1^2 - x_2 \leqslant 0 \tag{$g_1(x) \leqslant 0$}$$
$$x_1 + x_2 - 2 \leqslant 0 \tag{$g_2(x) \leqslant 0$}$$

Definition 14 (Contour)**.** For $\alpha \in \mathbb{R}$, the **contour** of a function f is

$$C_\alpha = \{x \in \mathbb{R}^n : f(x) = \alpha\}$$

Definition 15 (Feasible Set)**.** The **feasible set** is

$$F = \{x \in \mathbb{R}^n : g(x) \leqslant 0, h(x) = 0, x \in D\}$$

(Is D the domain??)

Definition 16 (Gradient)**.** The **gradient** of f is

$$\nabla f(x) = \begin{pmatrix} \frac{\partial f(x)}{\partial x_1} \\ \vdots \\ \frac{\partial f(x)}{\partial x_n} \end{pmatrix}$$

For the optimal solution x^*, we have

$$\alpha \nabla f(x^*) = \lambda_1 \nabla g_1(x^*) + \lambda_2 \nabla g_2(x^*)$$

for some $\alpha, \lambda_1, \lambda_2 \in \mathbb{R}$.

We will see later that we can choose $\alpha = 1$ and we need $\lambda_1 \geqslant 0, \lambda_2 \geqslant 0$.

Example 3 (Max-cut Problem)**.** Given a weighted graph $G = (\underbrace{V}_{\text{vertices}}, \underbrace{E}_{\text{edges}}, \underbrace{w}_{\text{weight}})$, a **cut** is $U \subseteq V, U \neq \varnothing$.

The objective function

$$\max \quad \frac{1}{2} \sum_{\substack{i \in U, j \notin U \\ (i,j) \in E}} w_{i,j}$$

maximizes the sum of edges in a cut.

Formulating as an NLP, we introduce variables $x_i \in \{\pm 1\}, i = 1, \ldots, n$. Then the Max-cut problem (MC) is as follows:

$$\max \quad \frac{1}{2} \sum_{ij \in E} w_{ij}(1 - x_i x_j)$$

Why 1/2 s.t.

$$x_i \in \{\pm 1\} \quad (\text{equivalent to } x_i^2 = 1) \quad \forall i = 1, \ldots, n$$

This works because

$$1 - x_i x_j = \begin{cases} 0 & \text{if } x_i = x_j \quad (i, j \text{ in the same set, } U \text{ or } U^c) \\ 2 & \text{otherwise} \end{cases}$$

MC is a **quadratically constrained quadratic program** (QOP) since each constraint $x_i \in \{-1, 1\}$ is equivalent to the quadratic constraint $x_i^2 = 1$. Note that MC is an NP-hard problem.

2 Unconstrained Optimization

2.1 Lecture 2

Example 4 (Simplest Case - No Constraints)**.** Let $\Omega \subseteq \mathbb{R}^n$ be an open set. Assume f is sufficiently smooth (differentiable) then the NLP with no constraints is

$$\min_{x \in \Omega} \quad f(x)$$

Theorem 1 (Taylor's Theorem on the real line)**.** Let $f:(a,b)\to\mathbb{R}$, and $\bar{x},x\in(a,b)$, then there exists z strictly between $x,\bar{x}$ such that

$$f(x)=f(\bar{x})+f'(\bar{x})(x-\bar{x})+\frac{f''(z)}{2}(x-\bar{x})^2$$

or equivalently

$$f(\bar{x}+\delta x)=\underbrace{f(x)+f'(x)\delta x}_{\text{Linear approximation}}+o(|\delta x|)(\text{little O})$$

Lemma 1 (Directional Derivative)**.** Let $f:\mathbb{R}^n\to\mathbb{R},\bar{x},d\in\mathbb{R}^n$ where d is the direction. We define

$$\phi(\epsilon)=f(\bar{x}+\epsilon d):\mathbb{R}\to\mathbb{R}$$

Then the **directional derivative**, denoted $f'(x;d)$ of f at x at the direction d is

$$f'(x;d)=\phi'(0)=\lim_{\epsilon\to 0}\frac{f(x+\epsilon d)-f(x)}{\epsilon}=\nabla f(x)^T d$$

Example 5. Let $f(x,y,z)=x^2z+y^3z^2-xyz$ with $d=\begin{pmatrix}-1\\0\\3\end{pmatrix}$ Then the **directional derivative** in the direction d is

$$\nabla f(x,y,z)^T d=\begin{pmatrix}2xz-yz\\3y^2z^2-xz\\x^2+2y^3z-xy\end{pmatrix}^T\begin{pmatrix}-1\\0\\3\end{pmatrix}=-2xz+yz+3x^2+6y^3z-3xy$$

Corollary 1. Let $f:(a,b)\to\mathbb{R}$

1. If $\bar{x}$ is a **local minimizer** of f on (a,b), then $f'(\bar{x})=0$ and $f''(\bar{x})\geqslant 0$.
2. If $f(\bar{x})=0,f''(\bar{x})>0$ then $\bar{x}$ is a **strict local minimizer** of f.

Definition 17 (Hessian)**.** The **Hessian** of f at $x=\begin{pmatrix}x_1\\\vdots\\x_n\end{pmatrix}$ is the matrix

$$\nabla^2 f(x)=\begin{pmatrix}\frac{\partial f(x)}{\partial x_1^2} & \frac{\partial f(x)}{\partial x_1\partial x_2} & \cdots & \frac{\partial f(x)}{\partial x_1\partial x_n}\\ \frac{\partial f(x)}{\partial x_2\partial x_1} & \frac{\partial f(x)}{\partial x_2^2} & \cdots & \frac{\partial f(x)}{\partial x_2\partial x_n}\\ \vdots & \vdots & \ddots & \vdots\\ \frac{\partial f(x)}{\partial x_n\partial x_1} & \frac{\partial f(x)}{\partial x_n\partial x_2} & \cdots & \frac{\partial f(x)}{\partial x_n^2}\end{pmatrix}$$

2.2 Lecture 3

Definition 18 (Matrix Norm)**.**

$$\|Q\|=max_{\|x\|=1}\|Qx\|=\text{Largest singular value of A}$$

Recall: Using Taylor ser