

A low-poly sculpture of a Corgi dog is positioned in the center-left of the frame. It is surrounded by several yellow rubber duck toys of various sizes. The background is a plain, light-colored surface.

Proximal gradient method

Daniil Merkulov

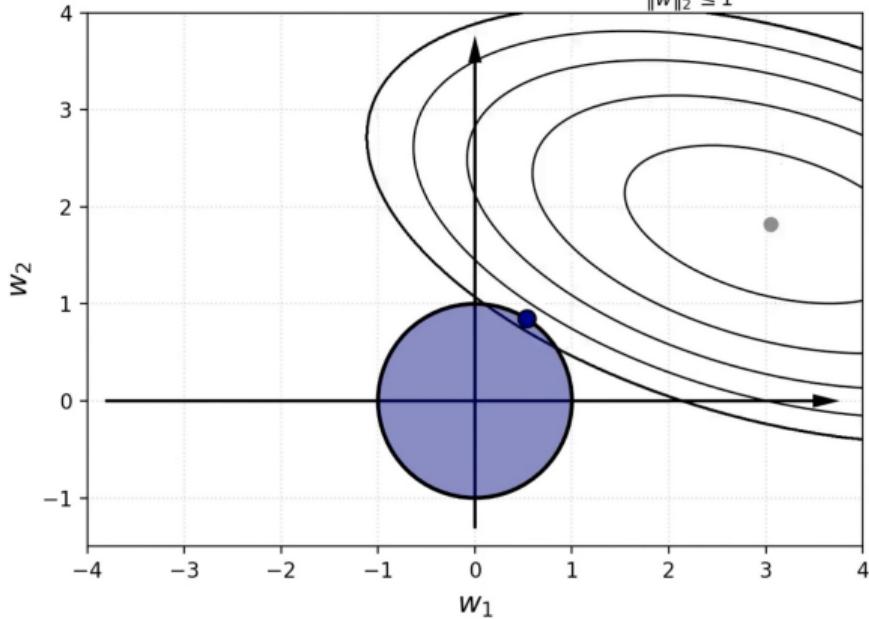
Optimization methods. MIPT

Subgradient method

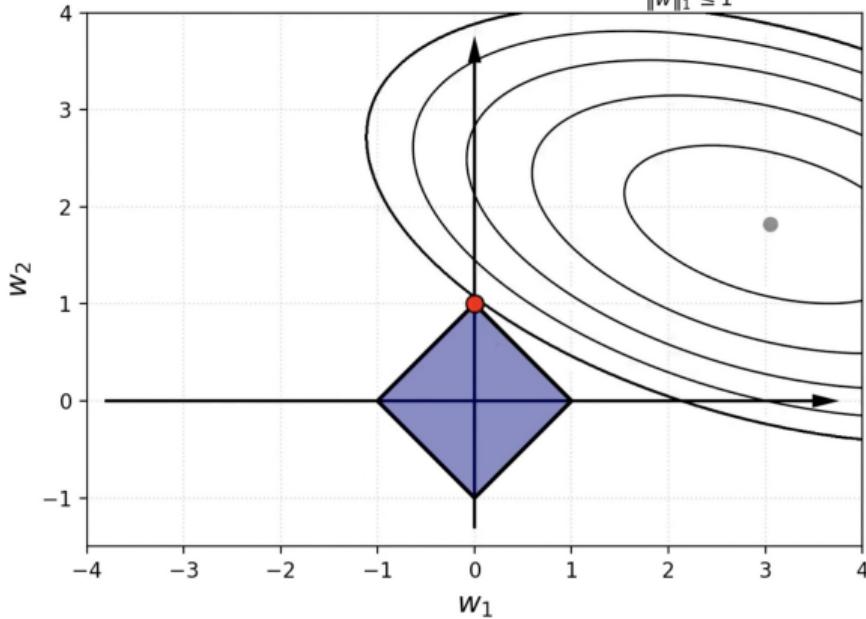
Non-smooth problems

ℓ_1 induces sparsity

ℓ_2 regularization. $\|Xw - y\|_2^2 \rightarrow \min_{\|w\|_2 \leq 1}$



ℓ_1 regularization. $\|Xw - y\|_2^2 \rightarrow \min_{\|w\|_1 \leq 1}$



@fminxyz

Subgradient method

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$$\min_{x \in \mathbb{R}^n} f(x) \quad x_{k+1} = x_k - \alpha_k g_k, \quad g_k \in \partial f(x_k)$$

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convex (non-smooth)

$$f(x_k) - f^* \sim \mathcal{O}\left(\frac{1}{\sqrt{k}}\right)$$

$$k_\varepsilon \sim \mathcal{O}\left(\frac{1}{\varepsilon^2}\right)$$

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Assume that f is G -Lipschitz and convex, then
Subgradient method converges as:

$$f(\bar{x}) - f^* \leq \frac{GR}{\sqrt{k}},$$

where

- $\alpha = \frac{R}{G\sqrt{k}}$

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- $\bar{x} = \frac{1}{k} \sum_{i=0}^{k-1} x_i$

Non-smooth convex optimization lower bounds

convex (non-smooth)	strongly convex (non-smooth)
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- Subgradient method is optimal for the problems above.
- One can use Mirror Descent (a generalization of the subgradient method to a possibly non-Euclidian distance) with the same convergence rate to better fit the geometry of the problem.
- However, we can achieve standard gradient descent rate $\mathcal{O}\left(\frac{1}{k}\right)$ (and even accelerated version $\mathcal{O}\left(\frac{1}{k^2}\right)$) if we will exploit the structure of the problem.

Proximal operator

Proximal mapping intuition

Consider Gradient Flow ODE:

$$\frac{dx}{dt} = -\nabla f(x)$$

Explicit Euler discretization:

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Leads to ordinary Gradient Descent method

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! Proximal operator

$$\text{prox}_{f,\alpha}(x_k) = \arg \min_{x \in \mathbb{R}^n} \left[f(x) + \frac{1}{2\alpha} \|x - x_k\|_2^2 \right]$$

Proximal operator visualization

$$\text{Prox}_f(x) = \operatorname{argmin}_{x'} \frac{1}{2} \|x - x'\|^2 + f(x')$$

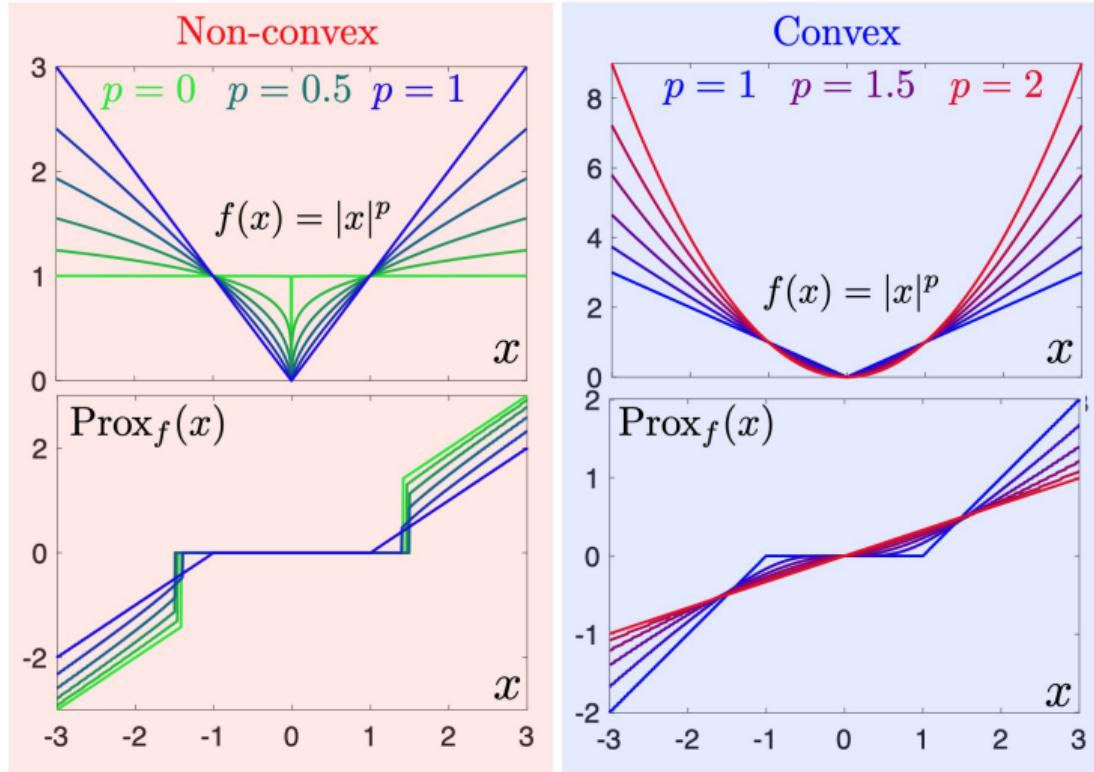


Figure 1: Source

Proximal mapping intuition

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Thus, we have a usual gradient descent with $\alpha \rightarrow 0$: $x_{k+1} = x_k - \alpha \nabla f(x_k)$

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From projections to proximity

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Proximity: Replace \mathbb{I}_S by some convex function!

$$\text{prox}_r(y) = \text{prox}_{r,1}(y) := \arg \min_x \frac{1}{2} \|x - y\|^2 + r(x)$$

Composite optimization

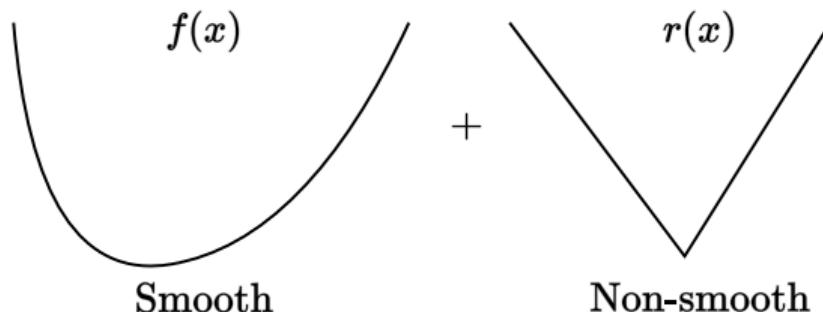
Regularized / Composite Objectives

Many nonsmooth problems take the form

$$\min_{x \in \mathbb{R}^n} \varphi(x) = f(x) + r(x)$$

- **Lasso, L1-LS, compressed sensing**

$$f(x) = \frac{1}{2} \|Ax - b\|_2^2, r(x) = \lambda \|x\|_1$$



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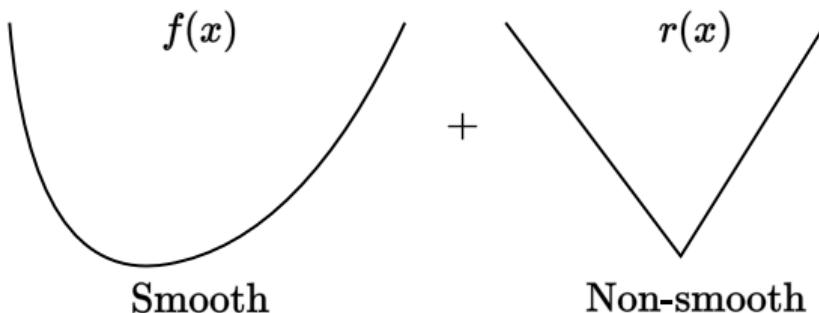
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- **Lasso, L1-LS, compressed sensing**

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- **L1-Logistic regression, sparse LR**

$$f(x) = -y \log h(x) - (1-y) \log(1-h(x)), r(x) = \lambda \|x\|_1$$



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Optimality conditions:

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Which leads to the proximal gradient method:

$$x_{k+1} = \text{prox}_{r,\alpha}(x_k - \alpha \nabla f(x_k))$$

And this method converges at a rate of $\mathcal{O}(\frac{1}{k})$!

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i Another form of proximal operator

$$\text{prox}_{f,\alpha}(x_k) = \text{prox}_{\alpha f}(x_k) = \arg \min_{x \in \mathbb{R}^n} \left[\alpha f(x) + \frac{1}{2} \|x - x_k\|_2^2 \right]$$

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Proximal operators examples

- $r(x) = \lambda \|x\|_1, \lambda > 0$

$$[\text{prox}_r(x)]_i = [|x_i| - \lambda|]_+ \cdot \text{sign}(x_i),$$

which is also known as soft-thresholding operator.

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Proximal operator properties

Theorem

Let $r : \mathbb{R}^n \rightarrow \mathbb{R} \cup \{+\infty\}$ be a convex function for which prox_r is defined. If there exists such an $\hat{x} \in \mathbb{R}^n$ that $r(\hat{x}) < +\infty$. Then, the proximal operator is uniquely defined (i.e., it always returns a single unique value).

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It is strongly convex, meaning it has exactly one unique minimum (the existence of \hat{x} is necessary for $r(\tilde{x}) + \frac{1}{2}\|x - \tilde{x}\|_2^2$ to take a finite value somewhere).

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Let $r : \mathbb{R}^n \rightarrow \mathbb{R} \cup \{+\infty\}$ be a convex function for which prox_r is defined. Then, for any $x, y \in \mathbb{R}^n$, the following three conditions are equivalent:

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Proof

1. Let's establish the equivalence between the first and second conditions. The first condition can be rewritten as

$$y = \arg \min_{\tilde{x} \in \mathbb{R}^d} \left(r(\tilde{x}) + \frac{1}{2} \|x - \tilde{x}\|^2 \right).$$

From the optimality condition for the convex function r , this is equivalent to:

$$0 \in \partial \left(r(\tilde{x}) + \frac{1}{2} \|x - \tilde{x}\|^2 \right) \Big|_{\tilde{x}=y} = \partial r(y) + y - x.$$

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2. From the definition of the subdifferential, for any subgradient $g \in \partial r(y)$ and for any $z \in \mathbb{R}^d$:

$$\langle g, z - y \rangle \leq r(z) - r(y).$$

In particular, this holds true for $g = x - y$.

Conversely, it is also clear: for $g = x - y$, the above relationship holds, which means $g \in \partial r(y)$.

Proximal operator properties

i Theorem

The operator $\text{prox}_r(x)$ is firmly nonexpansive (FNE)

$$\|\text{prox}_r(x) - \text{prox}_r(y)\|_2^2 \leq \langle \text{prox}_r(x) - \text{prox}_r(y), x - y \rangle$$

and nonexpansive:

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Proof

1. Let $u = \text{prox}_r(x)$, and $v = \text{prox}_r(y)$. Then, from the previous property:

$$\langle x - u, z_1 - u \rangle \leq r(z_1) - r(u)$$

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2. Substitute $z_1 = v$ and $z_2 = u$. Summing up, we get:

$$\langle x - u, v - u \rangle + \langle y - v, u - v \rangle \leq 0,$$

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4. The last point comes from simple Cauchy-Bunyakovsky-Schwarz for the last inequality.

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Let $f : \mathbb{R}^n \rightarrow \mathbb{R} \cup \{+\infty\}$ and $r : \mathbb{R}^n \rightarrow \mathbb{R} \cup \{+\infty\}$ be convex functions. Additionally, assume that f is continuously differentiable and L -smooth, and for r , prox_r is defined. Then, x^* is a solution to the composite optimization problem if and only if, for any $\alpha > 0$, it satisfies:

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Proof

1. Optimality conditions:

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2. Recall from the previous lemma:

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3. Finally,

$$x^* = \text{prox}_{\alpha r}(x^* - \alpha \nabla f(x^*)) = \text{prox}_{r,\alpha}(x^* - \alpha \nabla f(x^*))$$

Theoretical tools for convergence analysis

Convergence tools

i Theorem

Let $f : \mathbb{R}^n \rightarrow \mathbb{R}$ be an L -smooth convex function. Then, for any $x, y \in \mathbb{R}^n$, the following inequality holds:

$$f(x) + \langle \nabla f(x), y - x \rangle + \frac{1}{2L} \|\nabla f(x) - \nabla f(y)\|_2^2 \leq f(y) \text{ or, equivalently,}$$

$$\|\nabla f(y) - \nabla f(x)\|_2^2 = \|\nabla f(x) - \nabla f(y)\|_2^2 \leq 2L(f(x) - f(y) - \langle \nabla f(y), x - y \rangle)$$

Proof

1. To prove this, we'll consider another function $\varphi(y) = f(y) - \langle \nabla f(x), y \rangle$. It is obviously a convex function (as a sum of convex functions). And it is easy to verify, that it is an L -smooth function by definition, since $\nabla \varphi(y) = \nabla f(y) - \nabla f(x)$ and $\|\nabla \varphi(y_1) - \nabla \varphi(y_2)\| = \|\nabla f(y_1) - \nabla f(y_2)\| \leq L\|y_1 - y_2\|$.

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$$\varphi\left(y - \frac{1}{L} \nabla \varphi(y)\right) \leq \varphi(y) - \frac{1}{2L} \|\nabla \varphi(y)\|_2^2$$

Convergence tools

3. From the first order optimality conditions for the convex function $\nabla\varphi(y) = \nabla f(y) - \nabla f(x) = 0$. We can conclude, that for any x , the minimum of the function $\varphi(y)$ is at the point $y = x$. Therefore:

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$$\varphi(x) \leq \varphi\left(y - \frac{1}{L}\nabla\varphi(y)\right) \leq \varphi(y) - \frac{1}{2L}\|\nabla\varphi(y)\|_2^2$$

4. Now, substitute $\varphi(y) = f(y) - \langle \nabla f(x), y \rangle$:

$$f(x) - \langle \nabla f(x), x \rangle \leq f(y) - \langle \nabla f(x), y \rangle - \frac{1}{2L}\|\nabla f(y) - \nabla f(x)\|_2^2$$

$$f(x) + \langle \nabla f(x), y - x \rangle + \frac{1}{2L}\|\nabla f(x) - \nabla f(y)\|_2^2 \leq f(y)$$

$$\|\nabla f(y) - \nabla f(x)\|_2^2 \leq 2L(f(y) - f(x) - \langle \nabla f(x), y - x \rangle)$$

switch x and y $\|\nabla f(x) - \nabla f(y)\|_2^2 \leq 2L(f(x) - f(y) - \langle \nabla f(y), x - y \rangle)$

Convergence tools

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The lemma has been proved. From the first view it does not make a lot of geometrical sense, but we will use it as a convenient tool to bound the difference between gradients.

Convergence tools

Theorem

Let $f : \mathbb{R}^n \rightarrow \mathbb{R}$ be continuously differentiable on \mathbb{R}^n . Then, the function f is μ -strongly convex if and only if for any $x, y \in \mathbb{R}^d$ the following holds:

$$\text{Strongly convex case } \mu > 0 \quad \langle \nabla f(x) - \nabla f(y), x - y \rangle \geq \mu \|x - y\|^2$$

$$\text{Convex case } \mu = 0 \quad \langle \nabla f(x) - \nabla f(y), x - y \rangle \geq 0$$

Proof

1. We will only give the proof for the strongly convex case, the convex one follows from it with setting $\mu = 0$. We start from necessity. For the strongly convex function

$$f(y) \geq f(x) + \langle \nabla f(x), y - x \rangle + \frac{\mu}{2} \|x - y\|_2^2$$

$$f(x) \geq f(y) + \langle \nabla f(y), x - y \rangle + \frac{\mu}{2} \|x - y\|_2^2$$

$$\text{sum} \quad \langle \nabla f(x) - \nabla f(y), x - y \rangle \geq \mu \|x - y\|^2$$

Convergence tools

2. For the sufficiency we assume, that $\langle \nabla f(x) - \nabla f(y), x - y \rangle \geq \mu \|x - y\|^2$. Using Newton-Leibniz theorem $f(x) = f(y) + \int_0^1 \langle \nabla f(y + t(x - y)), x - y \rangle dt$:

Convergence tools

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$$f(x) - f(y) - \langle \nabla f(y), x - y \rangle = \int_0^1 \langle \nabla f(y + t(x - y)), x - y \rangle dt - \langle \nabla f(y), x - y \rangle$$

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Thus, we have a strong convexity criterion satisfied

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$$\text{switch } x \text{ and } y \quad - \langle \nabla f(x), x - y \rangle \leq - \left(f(x) - f(y) + \frac{\mu}{2} \|x - y\|_2^2 \right)$$

Proximal Gradient Method. Convex case

Convergence

i Theorem

Consider the proximal gradient method

$$x_{k+1} = \text{prox}_{\alpha r}(x_k - \alpha \nabla f(x_k))$$

For the criterion $\varphi(x) = f(x) + r(x)$, we assume:

- f is convex, differentiable, $\text{dom}(f) = \mathbb{R}^n$, and ∇f is Lipschitz continuous with constant $L > 0$.
- r is convex, and $\text{prox}_{\alpha r}(x_k) = \arg \min_{x \in \mathbb{R}^n} [\alpha r(x) + \frac{1}{2} \|x - x_k\|_2^2]$ can be evaluated.

Proximal gradient descent with fixed step size $\alpha = 1/L$ satisfies

$$\varphi(x_k) - \varphi^* \leq \frac{L\|x_0 - x^*\|^2}{2k},$$

Proximal gradient descent has a convergence rate of $O(1/k)$ or $O(1/\varepsilon)$. This matches the gradient descent rate!
(But remember the proximal operation cost)

Convergence

Proof

1. Let's introduce the **gradient mapping**, denoted as $G_\alpha(x)$, acts as a "gradient-like object":

$$x_{k+1} = \text{prox}_{\alpha r}(x_k - \alpha \nabla f(x_k))$$

$$x_{k+1} = x_k - \alpha G_\alpha(x_k).$$

where $G_\alpha(x)$ is:

$$G_\alpha(x) = \frac{1}{\alpha} (x - \text{prox}_{\alpha r}(x - \alpha \nabla f(x)))$$

Observe that $G_\alpha(x) = 0$ if and only if x is optimal. Therefore, G_α is analogous to ∇f . If x is locally optimal, then $G_\alpha(x) = 0$ even for nonconvex f . This demonstrates that the proximal gradient method effectively combines gradient descent on f with the proximal operator of r , allowing it to handle non-differentiable components effectively.

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2. We will use smoothness and convexity of f for some arbitrary point x :

$$\text{smoothness } f(x_{k+1}) \leq f(x_k) + \langle \nabla f(x_k), x_{k+1} - x_k \rangle + \frac{L}{2} \|x_{k+1} - x_k\|_2^2$$

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$$\begin{aligned}\text{convexity } f(x) &\geq f(x_k) + \langle \nabla f(x_k), x - x_k \rangle \\&\leq f(x) - \langle \nabla f(x_k), x - x_k \rangle + \langle \nabla f(x_k), x_{k+1} - x_k \rangle + \frac{\alpha^2 L}{2} \|G_\alpha(x_k)\|_2^2\end{aligned}$$

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Convergence

- Now we will use a proximal map property, which was proven before:

Convergence

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$$x_{k+1} = \text{prox}_{\alpha r}(x_k - \alpha \nabla f(x_k)) \quad \Leftrightarrow \quad x_k - \alpha \nabla f(x_k) - x_{k+1} \in \partial \alpha r(x_{k+1})$$

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Since $x_{k+1} - x_k = -\alpha G_\alpha(x_k)$ $\Rightarrow \alpha G_\alpha(x_k) - \alpha \nabla f(x_k) \in \partial \alpha r(x_{k+1})$

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$$G_\alpha(x_k) - \nabla f(x_k) \in \partial r(x_{k+1})$$

4. By the definition of the subgradient of convex function r for any point x :

Convergence

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$$x_{k+1} = \text{prox}_{\alpha r}(x_k - \alpha \nabla f(x_k)) \Leftrightarrow x_k - \alpha \nabla f(x_k) - x_{k+1} \in \partial \alpha r(x_{k+1})$$

Since $x_{k+1} - x_k = -\alpha G_\alpha(x_k)$ $\Rightarrow \alpha G_\alpha(x_k) - \alpha \nabla f(x_k) \in \partial \alpha r(x_{k+1})$
 $G_\alpha(x_k) - \nabla f(x_k) \in \partial r(x_{k+1})$

4. By the definition of the subgradient of convex function r for any point x :

$$r(x) \geq r(x_{k+1}) + \langle g, x - x_{k+1} \rangle, \quad g \in \partial r(x_{k+1})$$

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Convergence

- Using $\varphi(x) = f(x) + r(x)$ we can now prove extremely useful inequality, which will allow us to demonstrate monotonic decrease of the iteration:

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6. Using $\varphi(x) = f(x) + r(x)$ we can now prove extremely useful inequality, which will allow us to demonstrate monotonic decrease of the iteration:

$$\varphi(x_{k+1}) \leq \varphi(x) - \langle G_\alpha(x_k), x - x_k \rangle - \langle G_\alpha(x_k), \alpha G_\alpha(x_k) \rangle + \frac{\alpha^2 L}{2} \|G_\alpha(x_k)\|_2^2$$

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$$\begin{aligned}\varphi(x_{k+1}) &\leq \varphi(x) - \langle G_\alpha(x_k), x - x_k \rangle - \langle G_\alpha(x_k), \alpha G_\alpha(x_k) \rangle + \frac{\alpha^2 L}{2} \|G_\alpha(x_k)\|_2^2 \\ \varphi(x_{k+1}) &\leq \varphi(x) + \langle G_\alpha(x_k), x_k - x \rangle + \frac{\alpha}{2} (\alpha L - 2) \|G_\alpha(x_k)\|_2^2\end{aligned}$$

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$$\alpha \leq \frac{1}{L} \Rightarrow \frac{\alpha}{2} (\alpha L - 2) \leq -\frac{\alpha}{2}$$

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7. Now it is easy to verify, that when $x = x_k$ we have monotonic decrease for the proximal gradient algorithm:

$$\varphi(x_{k+1}) \leq \varphi(x_k) - \frac{\alpha}{2} \|G_\alpha(x_k)\|_2^2$$

Convergence

8. When $x = x^*$:

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Convergence

8. When $x = x^*$:

$$\varphi(x_{k+1}) \leq \varphi(x^*) + \langle G_\alpha(x_k), x_k - x^* \rangle - \frac{\alpha}{2} \|G_\alpha(x_k)\|_2^2$$

$$\varphi(x_{k+1}) - \varphi(x^*) \leq \langle G_\alpha(x_k), x_k - x^* \rangle - \frac{\alpha}{2} \|G_\alpha(x_k)\|_2^2$$

Convergence

8. When $x = x^*$:

$$\begin{aligned}\varphi(x_{k+1}) &\leq \varphi(x^*) + \langle G_\alpha(x_k), x_k - x^* \rangle - \frac{\alpha}{2} \|G_\alpha(x_k)\|_2^2 \\ \varphi(x_{k+1}) - \varphi(x^*) &\leq \langle G_\alpha(x_k), x_k - x^* \rangle - \frac{\alpha}{2} \|G_\alpha(x_k)\|_2^2 \\ &\leq \frac{1}{2\alpha} [2\langle \alpha G_\alpha(x_k), x_k - x^* \rangle - \|\alpha G_\alpha(x_k)\|_2^2]\end{aligned}$$

Convergence

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Convergence

9. Now we write the bound above for all iterations $i \in 0, k - 1$ and sum them:

Which is a standard $\frac{L\|x_0 - x^*\|_2^2}{2k}$ with $\alpha = \frac{1}{L}$, or, $\mathcal{O}\left(\frac{1}{k}\right)$ rate for smooth convex problems with Gradient Descent!

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9. Now we write the bound above for all iterations $i \in 0, k - 1$ and sum them:

$$\sum_{i=0}^{k-1} [\varphi(x_{i+1}) - \varphi(x^*)] \leq \frac{1}{2\alpha} [\|x_0 - x^*\|_2^2 - \|x_k - x^*\|_2^2]$$

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10. Since $\varphi(x_k)$ is a decreasing sequence, it follows that:

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$$\sum_{i=0}^{k-1} \varphi(x_k) = k\varphi(x_k) \leq \sum_{i=0}^{k-1} \varphi(x_{i+1})$$

Which is a standard $\frac{L\|x_0 - x^*\|_2^2}{2k}$ with $\alpha = \frac{1}{L}$, or, $\mathcal{O}\left(\frac{1}{k}\right)$ rate for smooth convex problems with Gradient Descent!

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$$\begin{aligned}\sum_{i=0}^{k-1} \varphi(x_k) &= k\varphi(x_k) \leq \sum_{i=0}^{k-1} \varphi(x_{i+1}) \\ \varphi(x_k) &\leq \frac{1}{k} \sum_{i=0}^{k-1} \varphi(x_{i+1})\end{aligned}$$

Which is a standard $\frac{L\|x_0 - x^*\|_2^2}{2k}$ with $\alpha = \frac{1}{L}$, or, $\mathcal{O}\left(\frac{1}{k}\right)$ rate for smooth convex problems with Gradient Descent!

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$$\begin{aligned}\sum_{i=0}^{k-1} \varphi(x_k) &= k\varphi(x_k) \leq \sum_{i=0}^{k-1} \varphi(x_{i+1}) \\ \varphi(x_k) &\leq \frac{1}{k} \sum_{i=0}^{k-1} \varphi(x_{i+1}) \\ \varphi(x_k) - \varphi(x^*) &\leq \frac{1}{k} \sum_{i=0}^{k-1} [\varphi(x_{i+1}) - \varphi(x^*)] \leq \frac{\|x_0 - x^*\|_2^2}{2\alpha k}\end{aligned}$$

Which is a standard $\frac{L\|x_0 - x^*\|_2^2}{2k}$ with $\alpha = \frac{1}{L}$, or, $\mathcal{O}\left(\frac{1}{k}\right)$ rate for smooth convex problems with Gradient Descent!

Proximal Gradient Method. Strongly convex case

Convergence

i Theorem

Consider the proximal gradient method

$$x_{k+1} = \text{prox}_{\alpha r}(x_k - \alpha \nabla f(x_k))$$

For the criterion $\varphi(x) = f(x) + r(x)$, we assume:

- f is μ -strongly convex, differentiable, $\text{dom}(f) = \mathbb{R}^n$, and ∇f is Lipschitz continuous with constant $L > 0$.
- r is convex, and $\text{prox}_{\alpha r}(x_k) = \arg \min_{x \in \mathbb{R}^n} [\alpha r(x) + \frac{1}{2} \|x - x_k\|_2^2]$ can be evaluated.

Proximal gradient descent with fixed step size $\alpha \leq 1/L$ satisfies

$$\|x_{k+1} - x^*\|_2^2 \leq (1 - \alpha\mu)^k \|x_0 - x^*\|_2^2$$

This is exactly gradient descent convergence rate. Note, that the original problem is even non-smooth!

Convergence

Proof

1. Considering the distance to the solution and using the stationary point lemma:

Convergence

Proof

1. Considering the distance to the solution and using the stationary point lemma:

$$\|x_{k+1} - x^*\|_2^2 = \|\text{prox}_{\alpha f}(x_k - \alpha \nabla f(x_k)) - x^*\|_2^2$$

Convergence

Proof

1. Considering the distance to the solution and using the stationary point lemm:

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4. Due to convexity of f : $f(x_k) - f(x^*) - \langle \nabla f(x^*), x_k - x^* \rangle \geq 0$. Therefore, if we use $\alpha \leq \frac{1}{L}$:

$$\|x_{k+1} - x^*\|_2^2 \leq (1 - \alpha\mu) \|x_k - x^*\|^2,$$

which is exactly linear convergence of the method with up to $1 - \frac{\mu}{L}$ convergence rate.

Accelerated Proximal Method

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Let $x_0 = y_0 \in \text{dom}(r)$. For $k \geq 1$:

$$x_k = \text{prox}_{\alpha_k h}(y_{k-1} - \alpha_k \nabla f(y_{k-1}))$$
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$$\varphi(x_k) - \varphi^* \leq \frac{2L\|x_0 - x^*\|^2}{k^2}.$$

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- Same computational cost as ordinary prox-grad
- Convergence rate theoretically optimal

Numerical experiments

Quadratic case

$$f(x) = \frac{1}{2m} \|Ax - b\|_2^2 + \lambda \|x\|_1 \rightarrow \min_{x \in \mathbb{R}^n}, \quad A \in \mathbb{R}^{m \times n}, \quad \lambda \left(\frac{1}{m} A^T A \right) \in [\mu; L].$$

Linear Least Squares with ℓ_1 Regularization (LASSO).
m=1000, n=100, $\lambda=0$, $\mu=0$, $L=10$. Optimal sparsity: 0.0e+00

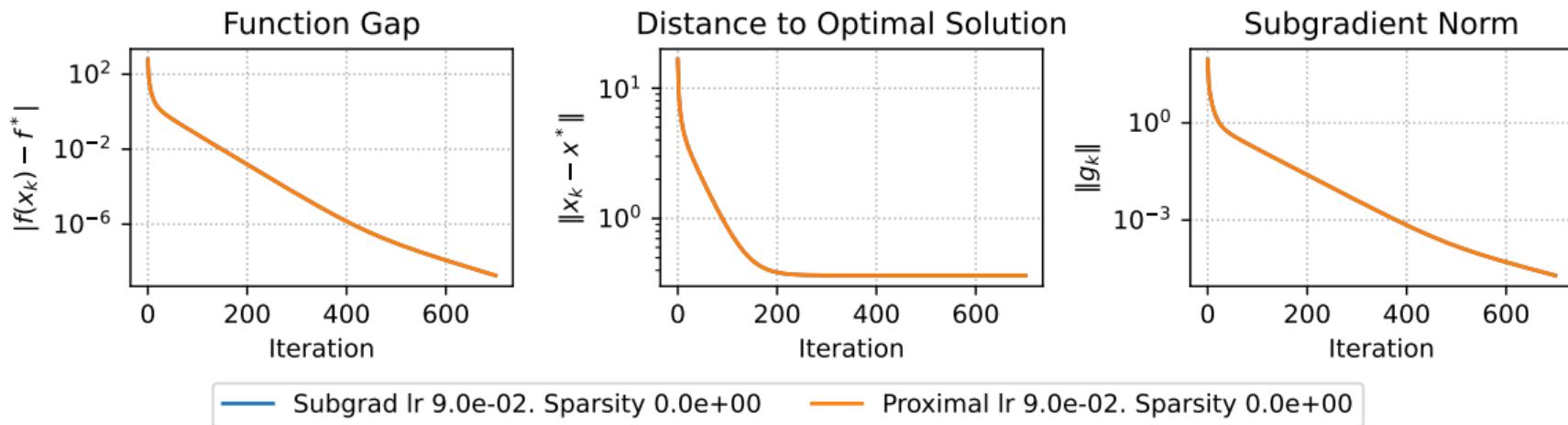


Figure 2: Smooth convex case. Sublinear convergence, no convergence in domain, no difference between subgradient and proximal methods

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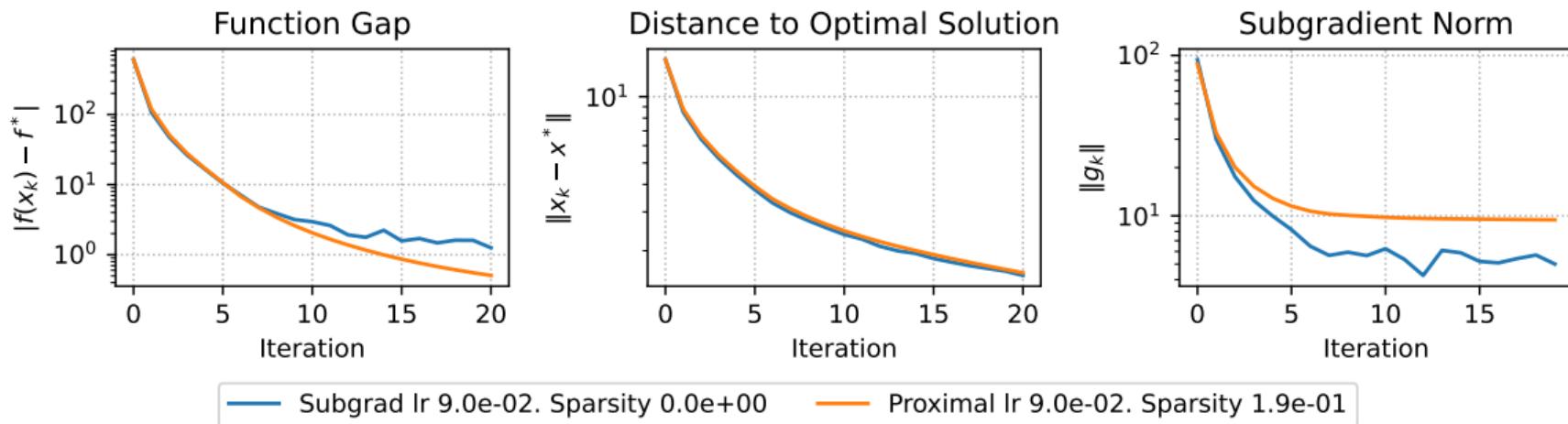


Figure 3: Non-smooth convex case. Sublinear convergence. At the beginning, the subgradient method and proximal method are close.

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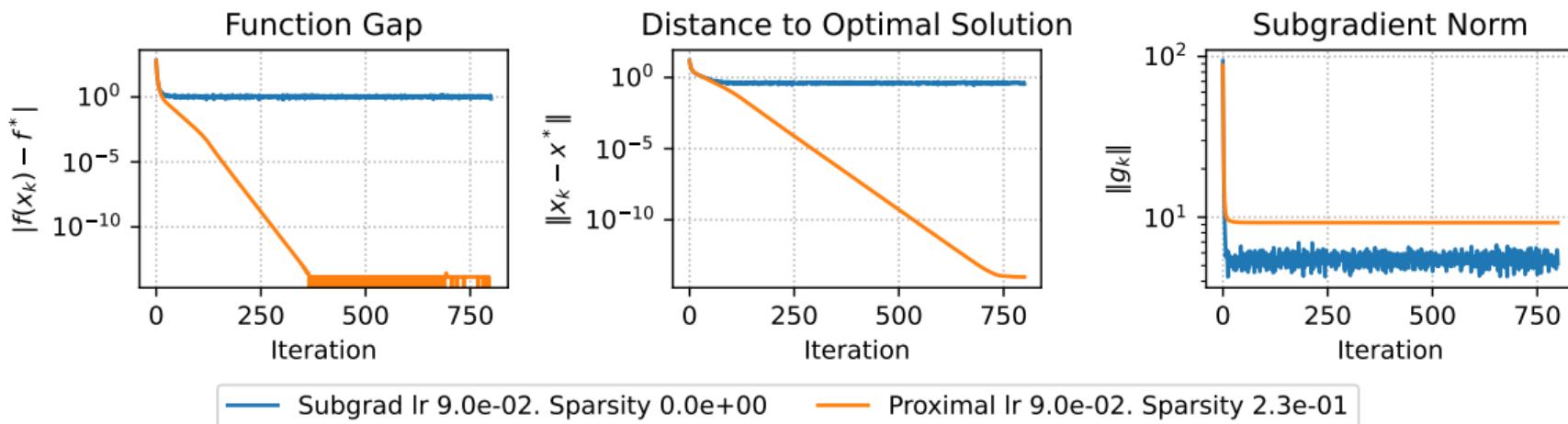


Figure 4: Non-smooth convex case. If we take more iterations, the proximal method converges with the constant learning rate, which is not the case for the subgradient method. The difference is tremendous, while the iteration complexity is the same.

Binary logistic regression

$$f(x) = \frac{1}{m} \sum_{i=1}^m \log(1 + \exp(-b_i(A_i x))) + \lambda \|x\|_1 \rightarrow \min_{x \in \mathbb{R}^n}, \quad A_i \in \mathbb{R}^n, \quad b_i \in \{-1, 1\}$$

Binary Logistic Regression with ℓ_1 Regularization.
 $m=300$, $n=50$, $\lambda=0.1$. Optimal sparsity: 8.6e-01

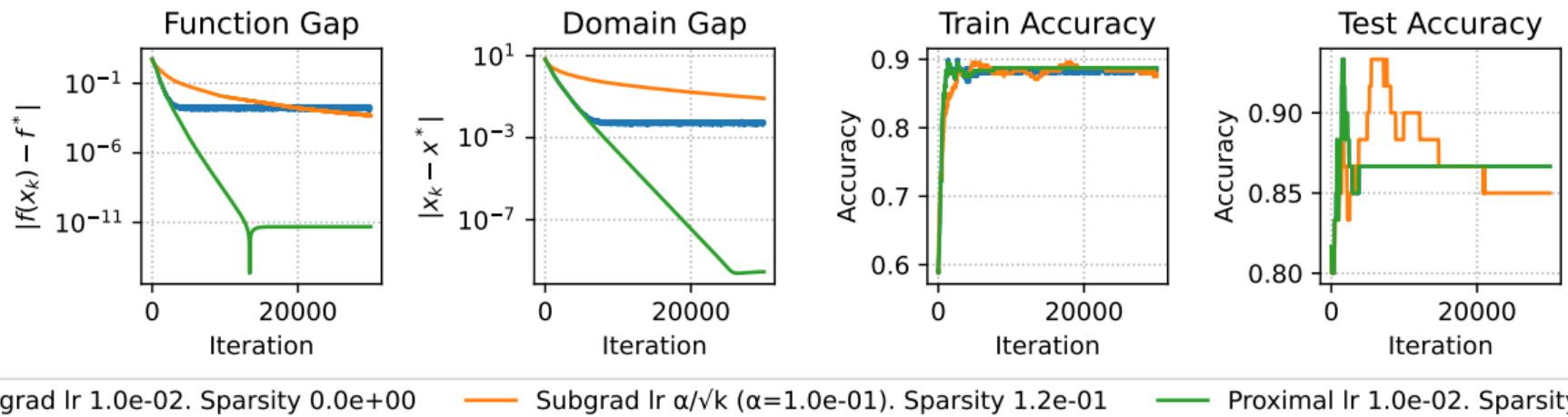
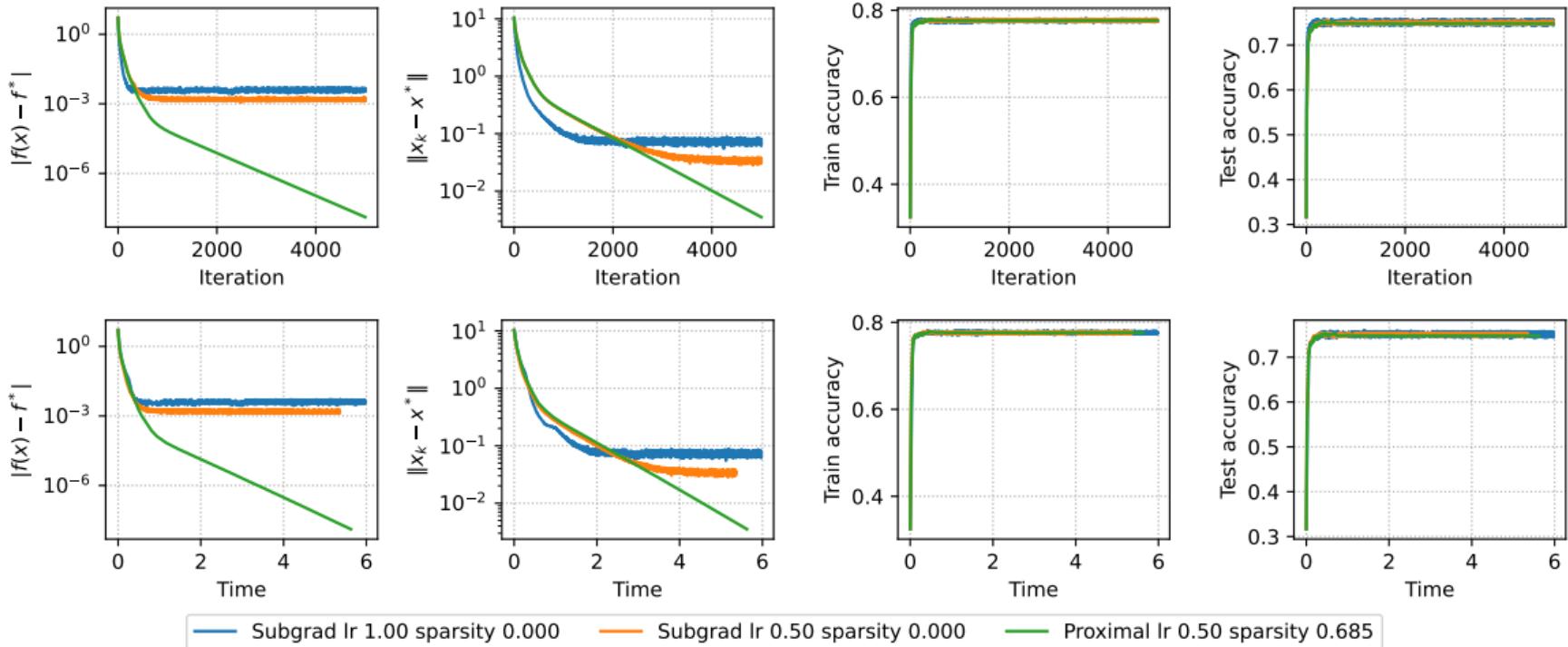


Figure 5: Logistic regression with ℓ_1 regularization

Softmax multiclass regression

Convex multiclass regression. lam=0.01.



Example: ISTA

Iterative Shrinkage-Thresholding Algorithm (ISTA)

ISTA is a popular method for solving optimization problems involving L1 regularization, such as Lasso. It combines gradient descent with a shrinkage operator to handle the non-smooth L1 penalty effectively.

- **Algorithm:**

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- **Application:**

- Efficient for sparse signal recovery, image processing, and compressed sensing.

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FISTA improves upon ISTA's convergence rate by incorporating a momentum term, inspired by Nesterov's accelerated gradient method.

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- **Application:**

- Especially useful for large-scale problems in machine learning and signal processing where the L1 penalty induces sparsity.

Example: Matrix Completion

Solving the Matrix Completion Problem

Matrix completion problems seek to fill in the missing entries of a partially observed matrix under certain assumptions, typically low-rank. This can be formulated as a minimization problem involving the nuclear norm (sum of singular values), which promotes low-rank solutions.

- **Problem Formulation:**

$$\min_X \frac{1}{2} \|P_\Omega(X) - P_\Omega(M)\|_F^2 + \lambda \|X\|_*,$$

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- **Application:**

- Widely used in recommender systems, image recovery, and other domains where data is naturally matrix-formed but partially observed.

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- Proximal gradient method for a composite problem with an L -smooth convex function f and a convex proximal friendly function r has the same convergence as the gradient descent method for the function f . The smoothness/non-smoothness properties of r do not affect convergence.
- It seems that by putting $f = 0$, any nonsmooth problem can be solved using such a method. Question: is this true?

If we allow the proximal operator to be inexact (numerically), then it is true that we can solve any nonsmooth optimization problem. But this is not better from the point of view of theory than solving the problem by subgradient descent, because some auxiliary method (for example, the same subgradient descent) is used to solve the proximal subproblem.

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- Further reading: Proximal operator splitting, Douglas-Rachford splitting, Best approximation problem, Three operator splitting.