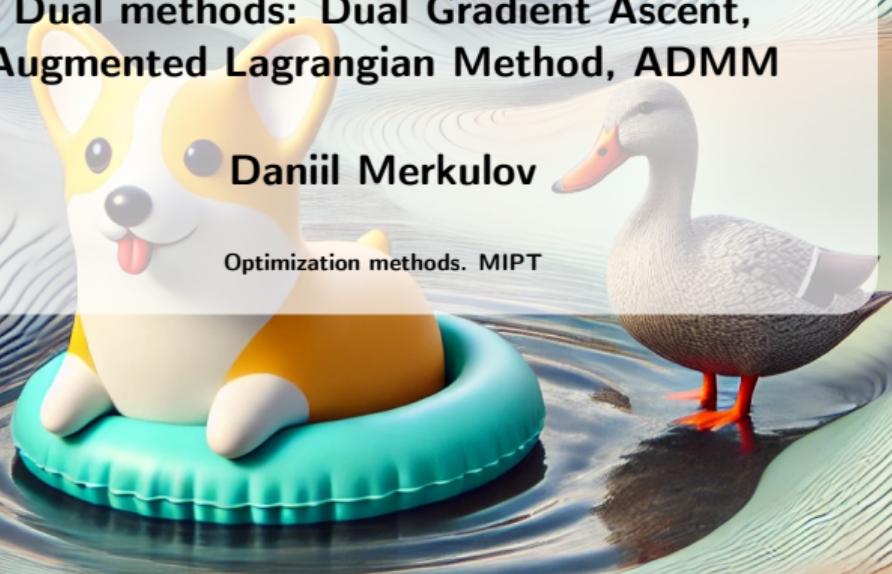




Dual methods: Dual Gradient Ascent, Augmented Lagrangian Method, ADMM



Daniil Merkulov

Optimization methods. MIPT

Introduction to dual methods

Why do we want to solve dual problems?

Primal problem

$$\begin{aligned} f_0(x) &\rightarrow \min_{x \in \mathbb{R}^n} \\ \text{s.t. } f_i(x) &\leq 0, \quad i = 1, \dots, m \\ h_i(x) &= 0, \quad i = 1, \dots, p \end{aligned}$$

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- **Dual Problems Provide Bounds.** Dual problems often offer bounds on the optimal value of the primal problem. This can be useful for assessing the quality of approximate solutions.
- **Duality Gap.** The difference between the primal and dual solutions (duality gap) provides valuable information about the solution's optimality.

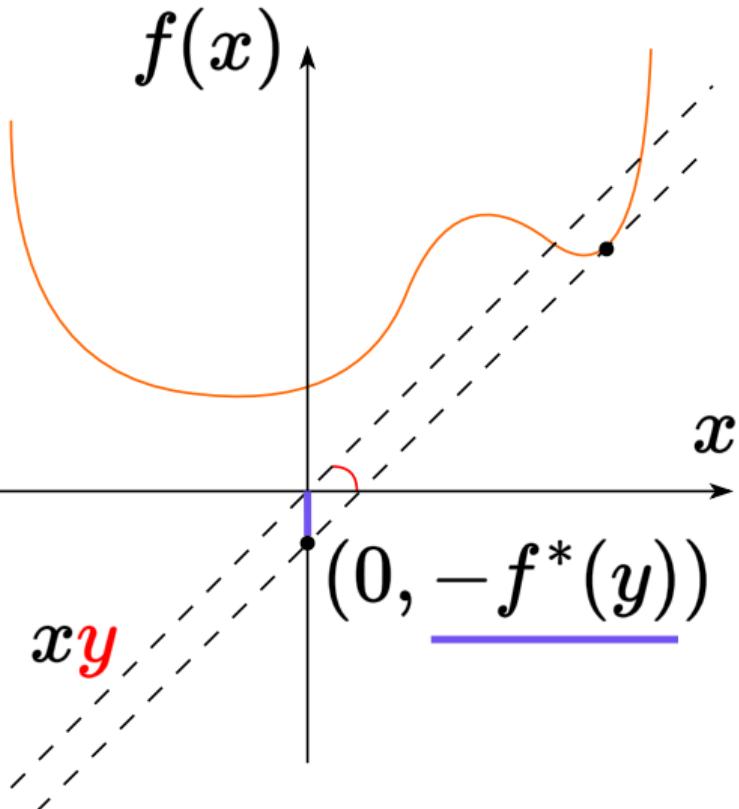
Conjugate functions

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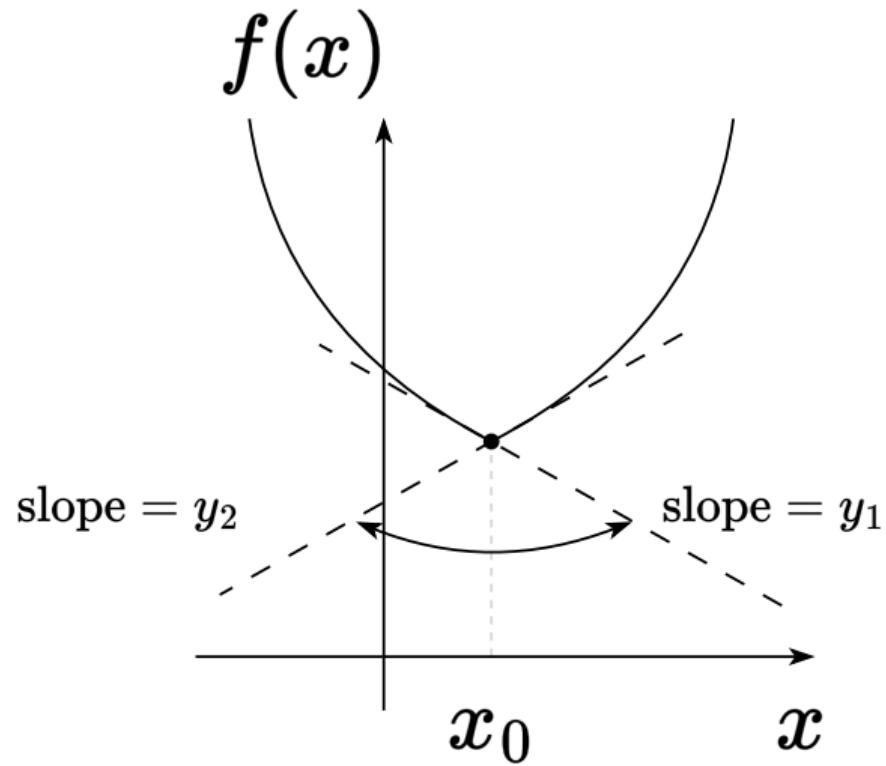
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$$f^*(y) = \max_x [y^T x - f(x)]$$

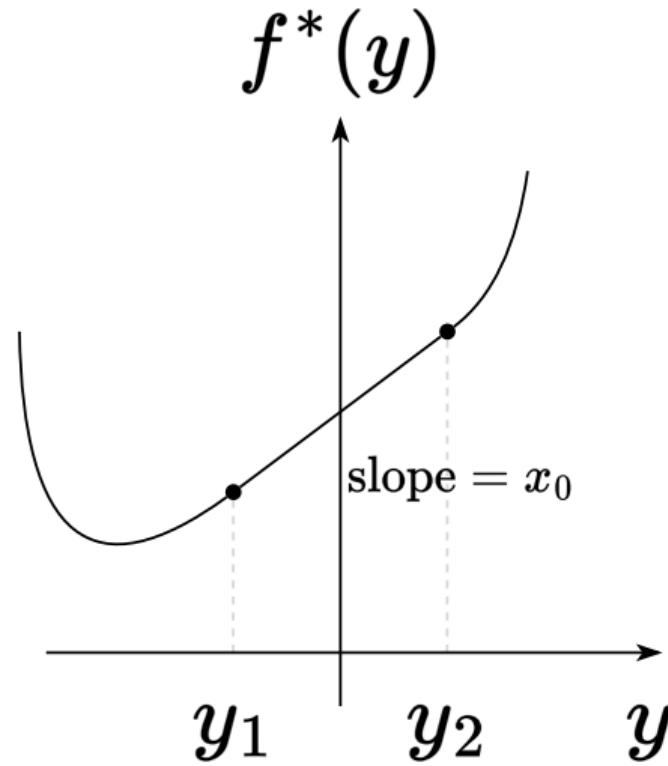
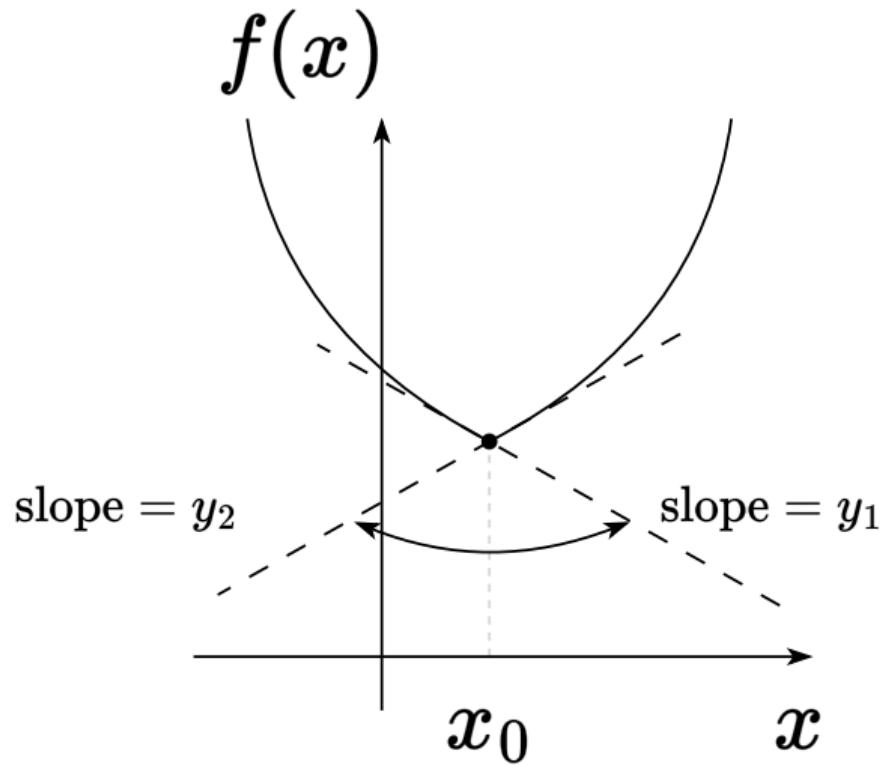
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Geometrical intuition



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- If f is strictly convex, then

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Conjugate function properties (proofs)

We will show that $x \in \partial f^*(y) \Leftrightarrow y \in \partial f(x)$, assuming that f is convex and closed.

- **Proof of \Leftarrow :** Suppose $y \in \partial f(x)$. Then $x \in M_y$, the set of maximizers of $y^T z - f(z)$ over z . But

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Clearly $y \in \partial f(x) \Leftrightarrow x \in \arg \min_z \{f(z) - y^T z\}$

Lastly, if f is strictly convex, then we know that $f(z) - y^T z$ has a unique minimizer over z , and this must be $\nabla f^*(y)$.

Dual ascent

Dual (sub)gradient method

Even if we can't derive dual (conjugate) in closed form, we can still use dual-based gradient or subgradient methods.

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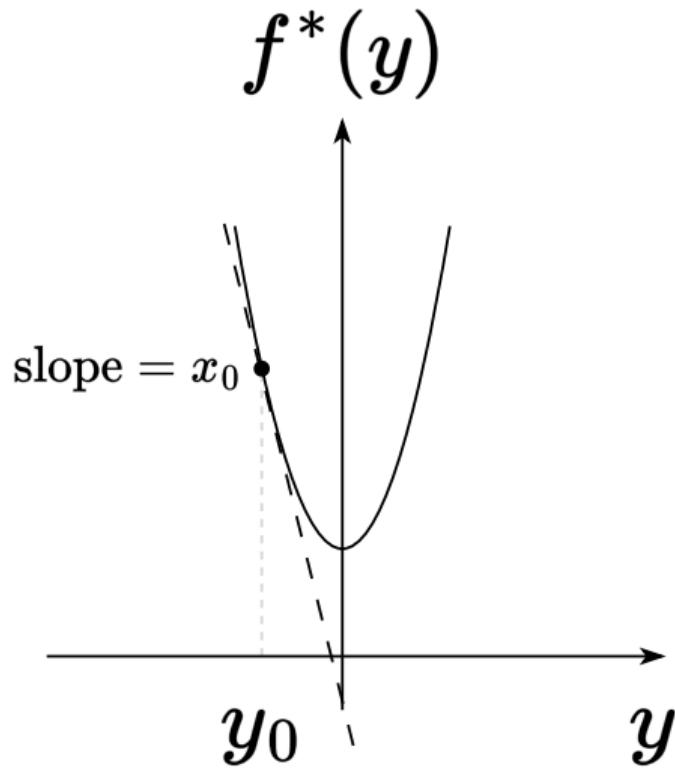
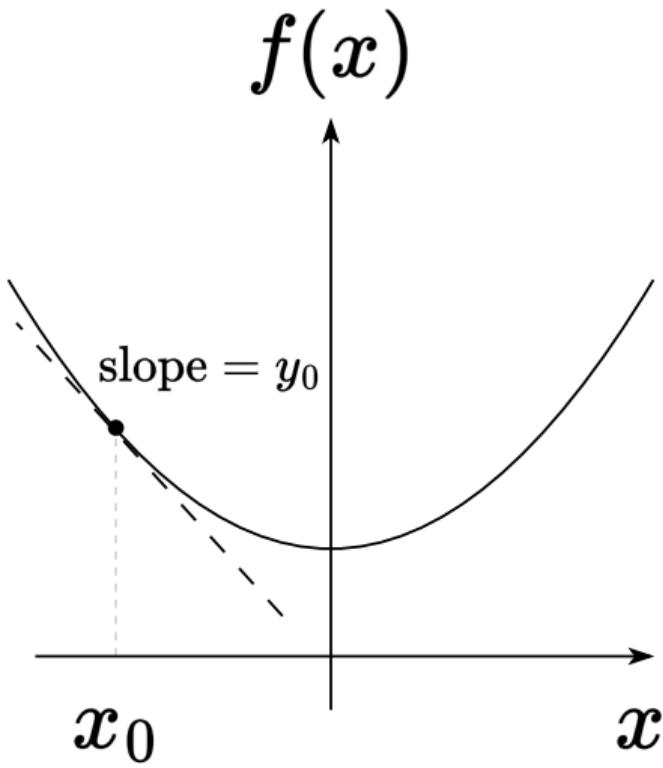
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- Proximal gradients and acceleration can be applied as they would usually.

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Adding these together, using the Cauchy-Schwarz inequality, and rearranging shows that

$$\|x_u - x_v\|^2 \leq \frac{1}{\mu} \|u - v\|^2$$

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Proof of “ \Leftarrow ”: for simplicity, call $g = f^*$ and $L = \frac{1}{\mu}$. As ∇g is Lipschitz with constant L , so is $g_x(z) = g(z) - \nabla g(x)^T z$, hence

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Let $u = \nabla f(x)$, $v = \nabla g(y)$; then $x \in \partial g^*(u)$, $y \in \partial g^*(v)$, and the above reads $(x - y)^T(u - v) \geq \frac{\|u - v\|^2}{L}$, implying the result.

Convergence guarantees

The following results hold from combining the last fact with what we already know about gradient descent: (This is ignoring the role of A , and thus reflects the case when the singular values of A are all close to 1. To be more precise, the step sizes here should be: $\frac{\mu}{\sigma_{\max}(A)^2}$ (first case) and $\frac{2}{\frac{\sigma_{\max}(A)^2}{\mu} + \frac{\sigma_{\min}(A)^2}{L}}$ (second case).)

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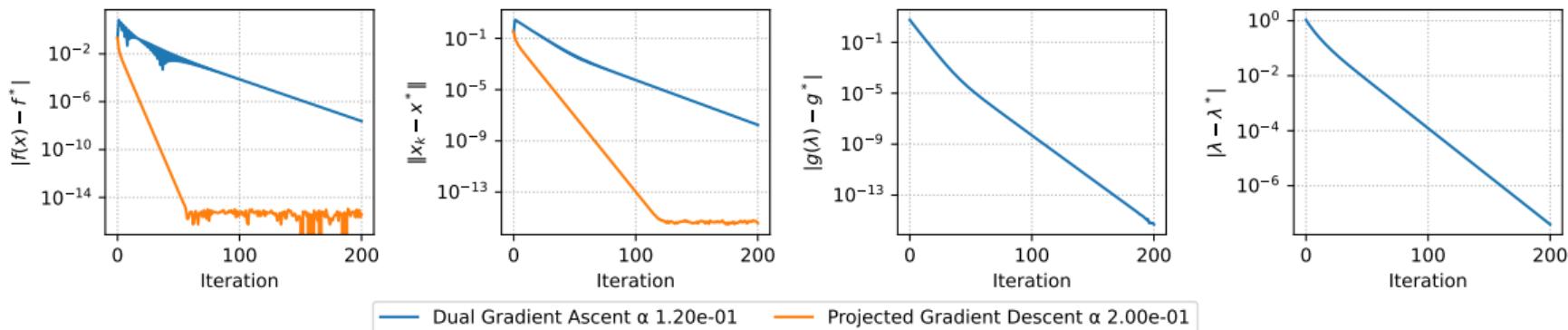
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- Note that this describes convergence in the dual. Convergence in the primal requires more assumptions

Example: equality constrained quadratic minimization.

$$f(x) = \frac{1}{2}x^T Ax - b^T x \rightarrow \min_{x \in \mathbb{R}^n} \quad \text{subject to} \quad Cx = d, \quad A \in \mathbb{S}_+^n, C \in \mathbb{R}^{m \times n}, m < n.$$

Quadratic constrained optimization. $n=10, m=5, \mu=1, L=10$.

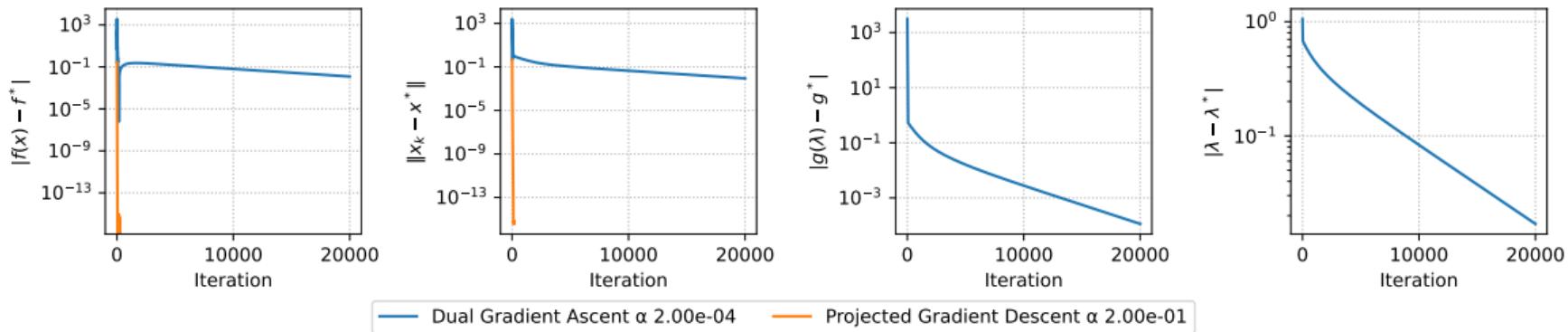


We need to find a minimum of a quadratic function in some linear subspace, defined by the solution of linear equation $Cx = d$. This is a conditional optimization problem, we start from strongly convex setting.

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Quadratic constrained optimization. $n=10$, $m=5$, $\mu=0.001$, $L=10$.



Situation is getting worse as soon as we loose strong convexity, the dual convergence will still be linear, but the rate is very low.

Dual decomposition

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Here $x = (x_1, \dots, x_B) \in \mathbb{R}^n$ divides into B blocks of variables, with each $x_i \in \mathbb{R}^{n_i}$. We can also partition A accordingly:

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Simple but powerful observation, in calculation of subgradient, is that the minimization decomposes into B separate problems:

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Can think of these steps as:

- **Broadcast:** Send u to each of the B processors, each optimizes in parallel to find x_i .

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$$\min_x \sum_{i=1}^B f_i(x_i) \quad \text{subject to} \quad Ax = b$$

Here $x = (x_1, \dots, x_B) \in \mathbb{R}^n$ divides into B blocks of variables, with each $x_i \in \mathbb{R}^{n_i}$. We can also partition A accordingly:

$$A = [A_1 \dots A_B], \text{ where } A_i \in \mathbb{R}^{m \times n_i}$$

Simple but powerful observation, in calculation of subgradient, is that the minimization decomposes into B separate problems:

$$\begin{aligned} x^{\text{new}} &\in \arg \min_x \left(\sum_{i=1}^B f_i(x_i) + u^T A x \right) \\ \Rightarrow x_i^{\text{new}} &\in \arg \min_{x_i} (f_i(x_i) + u^T A_i x_i), \quad i = 1, \dots, B \end{aligned}$$

$$x_i^k \in \arg \min_{x_i} (f_i(x_i) + (u^{k-1})^T A_i x_i), \quad i = 1, \dots, B$$

$$u^k = u^{k-1} + \alpha_k \left(\sum_{i=1}^B A_i x_i^k - b \right)$$

Can think of these steps as:

- **Broadcast:** Send u to each of the B processors, each optimizes in parallel to find x_i .
- **Gather:** Collect $A_i x_i$ from each processor, update the global dual variable u .

Inequality constraints

Consider the optimization problem:

$$\min_x \sum_{i=1}^B f_i(x_i) \quad \text{subject to} \quad \sum_{i=1}^B A_i x_i \leq b$$

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- The primal update step:

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$$u^k = \left(u^{k-1} + \alpha_k \left(\sum_{i=1}^B A_i x_i^k - b \right) \right)_+$$

where $(u)_+$ denotes the positive part of u , i.e., $(u)_+ = \max\{0, u_i\}$, for $i = 1, \dots, m$.

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- **System Overview:** Consider a system with B units, where each unit independently chooses its decision variable x_i , which determines how to allocate its goods.

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 - Never let prices get negative; hence the use of the positive part notation $(\cdot)_+$.

Augmented Lagrangian method

Augmented Lagrangian method aka method of multipliers

Dual ascent disadvantage: convergence requires strong conditions. Augmented Lagrangian method transforms the primal problem:

$$\begin{aligned} & \min_x f(x) + \frac{\rho}{2} \|Ax - b\|^2 \\ & \text{s.t. } Ax = b \end{aligned}$$

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Dual gradient ascent: The iterative updates are given by:

$$\begin{aligned} x_k &= \arg \min_x \left[f(x) + (u_{k-1})^T Ax + \frac{\rho}{2} \|Ax - b\|^2 \right] \\ u_k &= u_{k-1} + \rho(Ax_k - b) \end{aligned}$$

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Notice step size choice $\alpha_k = \rho$ in dual algorithm. Why?

Since x_k minimizes the function:

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over x , we have the stationarity condition:

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This represents the stationarity condition for the original primal problem; under mild conditions, $Ax_k - b \rightarrow 0$ as $k \rightarrow \infty$, so the KKT conditions are satisfied in the limit and x_k, u_k converge to the solutions.

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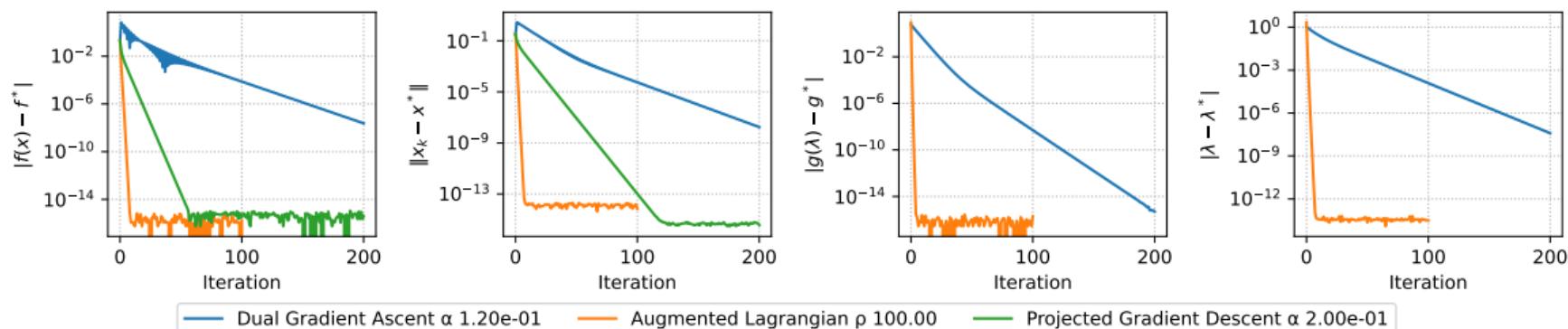
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- **Advantage:** The augmented Lagrangian gives better convergence.
- **Disadvantage:** We lose decomposability! (Separability is ruined)

Example: equality constrained quadratic minimization.

$$f(x) = \frac{1}{2}x^T Ax - b^T x \rightarrow \min_{x \in \mathbb{R}^n} \quad \text{subject to} \quad Cx = d, \quad A \in \mathbb{S}_+^n, C \in \mathbb{R}^{m \times n}, m < n.$$

Quadratic constrained optimization. $n=10, m=5, \mu=1, L=10$.

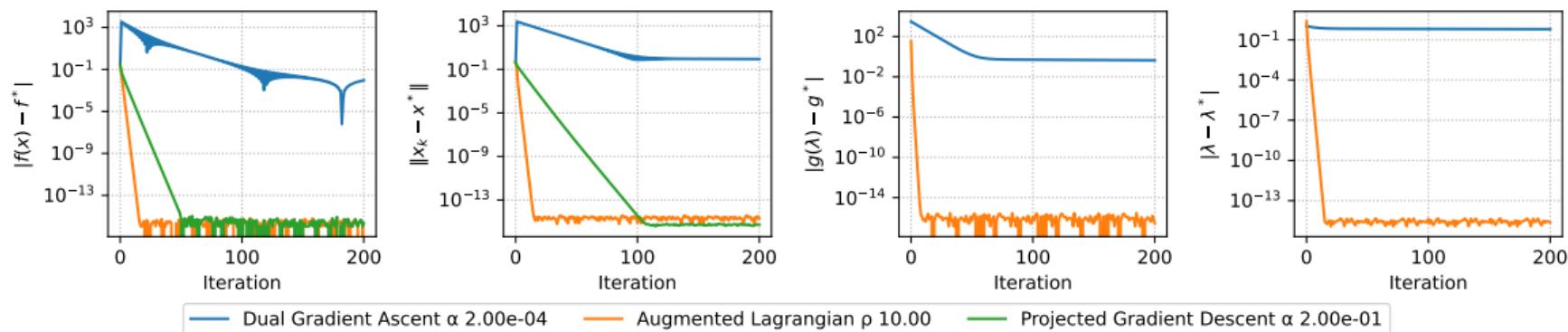


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Introduction to ADMM

Alternating Direction Method of Multipliers (ADMM)

Alternating direction method of multipliers or ADMM aims for the best of both worlds. Consider the following optimization problem:

Minimize the function:

$$\min_{x,z} f(x) + g(z)$$

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where $\rho > 0$ is a parameter. The augmented Lagrangian for this problem is defined as:

$$L_\rho(x, z, u) = f(x) + g(z) + u^T(Ax + Bz - c) + \frac{\rho}{2} \|Ax + Bz - c\|^2$$

Alternating Direction Method of Multipliers (ADMM)

ADMM repeats the following steps, for $k = 1, 2, 3, \dots$:

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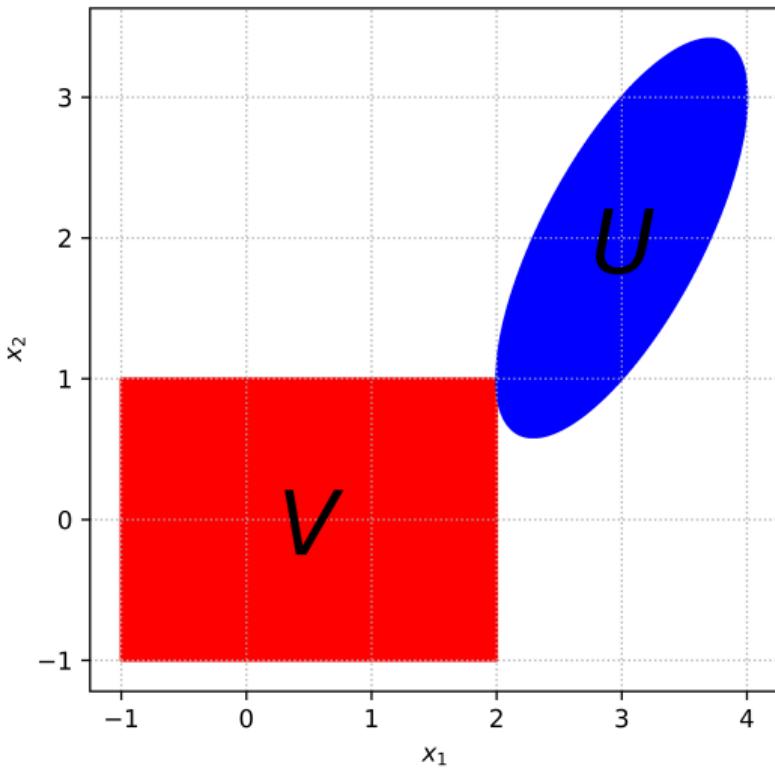
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Note: The usual method of multipliers would replace the first two steps by a joint minimization:

$$(x^{(k)}, z^{(k)}) = \arg \min_{x,z} L_\rho(x, z, u^{(k-1)})$$

Example: Alternating Projections



Consider finding a point in the intersection of convex sets $U, V \subseteq \mathbb{R}^n$:

$$\min_x I_U(x) + I_V(x)$$

To transform this problem into ADMM form, we express it as:

$$\min_{x,z} I_U(x) + I_V(z) \quad \text{subject to} \quad x - z = 0$$

Each ADMM cycle involves two projections:

$$x_k = \arg \min_x P_U(z_{k-1} - w_{k-1})$$

$$z_k = \arg \min_z P_V(x_k + w_{k-1})$$

$$w_k = w_{k-1} + x_k - z_k$$

Sources

- Ryan Tibshirani. Convex Optimization 10-725