1 General

line search conditions (1st and 2nd order), how to choose step length and direction:

sufficient decrease, proportional to α_k step length and directional derivative $\nabla f_k^T p_k$:

$$f_{k+1}^T \leq f_k + c_1 \alpha_k \nabla f_k^T p_k \tag{1}$$
$$\nabla f_k^T p_k \leq 0 \; //by\ construction \tag{2}$$

curvature:

$$\nabla f_{k+1}^T p_k \geq c_2 \nabla f_k^T p_k \tag{3}$$
$$\frac{\partial \phi(\alpha_k)}{\partial \alpha_k} \geq \frac{\partial \phi(0)}{\partial \alpha_k} \tag{4}$$
$$c_1, \alpha_k \in (0,1) \tag{5}$$
$$0 < c_1 < c_2 < 1 \tag{6}$$

$$\begin{aligned} \text{where :} f_k &= f(x_k) \\ f_{k+1} &= f(x_k + \alpha_k p_k) \\ \phi(\alpha_k) &= f(x_k + \alpha_k p_k) \\ \frac{\partial \phi(\alpha_k)}{\partial \alpha_k} &= \nabla f_{k+1}^T p_k \\ \frac{\partial \phi(0)}{\partial \alpha_k} &= \nabla f_k^T p_k //initial\ slope \end{aligned}$$

strong Wolfe curvature condition, to restrict large positive derivative:

$$|\nabla f_{k+1}^T p_k| \leq c_2 |\nabla f_k^T p_k| \tag{7}$$

Form of search direction:

$$p_k = -B_k^{-1} \nabla f_k \tag{8}$$

B_k symmetric, non-singular, postive definite $\implies p_k$ is a descent direction:

$$\nabla f_k^T (-B_k^{-1} \nabla f_k) < 0 \tag{9}$$

Goldstein condition (may miss minimizer of f):

$$f_k + (1-c)\alpha_k \nabla f_k^T p_k \leq f_{k+1} \leq f_k + c\alpha \nabla f_k^T p_k \tag{10}$$

$$c \in (0, \frac{1}{2}) \tag{11}$$

Algorithm 1: Line Search

$f, x, d, c_1, \alpha, \beta$**:** function, x, direction, gradient threshold, initial step length, contraction

α **:** found step length

```
1 while f(x + αd) > f(x) + c1 α ∇f(x)^T d do
2     α ← α * β
3 return α
```

2 Quasi Newton

2.1 BFGS

properties: $O(n^2)$, self correcting, slightly more iterations than Newton Method, linear convergence order and superlinear rate of convergence

secant equation:

$$\begin{aligned} B_{k+1}(x_{k+1} - x_k) &= \nabla f_{k+1} - \nabla f_k \\ B_{k+1} s_k &= y_k \\ s_k &= \alpha_k p_k \\ y_k &= \nabla f_{k+1} - \nabla f_k \\ B_{k+1} &:= \text{approx. Hessian} \end{aligned}$$

$$\begin{aligned} B_{k+1} &\succ 0 \\ s_k^T B_{k+1} s_k &= s^T y_k > 0 \end{aligned}$$

Proof.

$$\begin{aligned} y_k^T s_k &= (\nabla f_{k+1} - \nabla f_k)^T s_k \\ \nabla f_{k+1}^T s_k &\geq c_2 \nabla f_k^T s_k \\ (\nabla f_{k+1} - \nabla f_k)^T s_k &\geq c_2 \nabla f_k^T s_k - \nabla f_k^T s_k \\ y_k^T s_k &\geq (c_2 - 1) \nabla f_k^T s_k \end{aligned}$$

$$c_2 < 1, s_k \text{ is a descent dir} \implies s_k^T y_k > 0$$

Curvature condition holds. □

constrain B by solving:

$$\begin{aligned} &\min_B ||B - B_k|| \\ &s.t.\ B = B^T, B s_k = y_k \end{aligned}$$

similarly, constrain B's inverse, H where it satisfy secant equation:

$$\begin{aligned} H_{k+1} y_k &= s_k \\ &\min_H ||H - H_k|| \\ &s.t.\ H = H^T, H y_k = s_k \end{aligned}$$

using weighted Frobenius norm:

$$||A||_W := ||W^{1/2}AW^{1/2}||_F$$
$$||X||_F := (\sum_i \sum_j (X_{ij})^2)^{1/2}$$

solved weight matrix W satisfy $Ws_k = y_k$ solution given by:

$$\begin{aligned} H_{k+1} &= (I - \rho_k s_k y_k^T) H_k (I - \rho_k y_k s_k^T) \\ &\quad + \rho_k s_k^T s_k \\ \rho_k &= \frac{1}{y_k^T s_k} \end{aligned}$$

W is the average Hessian $\bar{G}$:

$$\bar{G} = \int_0^1 \nabla^2 f(x_k + \tau \alpha_k p_k) d\tau$$

initial H_0 can be chosen approximately (eg: finite differences, I)

Algorithm 2: BFGS Algorithm

$H_0, x_0, \epsilon > 0$**:** inverse Hessian approx., initial point, convergence tolerance
x **:** solution

$k \leftarrow 0$
$p_k \leftarrow -B^{-1}\nabla f(x_k) = -H\nabla f(x_k)$
while $||\nabla f_k|| > \epsilon$ **do**
    $\alpha_k \leftarrow$ LineSearch(..)
    $x_{k+1} \leftarrow x_k + \alpha_k p_k$
    $s_k \leftarrow x_{k+1} - x_k$
    $y_k \leftarrow \nabla f_{k+1} - \nabla f_k$
    $\rho_k \leftarrow \frac{1}{y_k^T s_k}$
    $H_{k+1} \leftarrow (I - \rho_k s_k y_k^T) H_k (I - \rho_k y_k s_k^T) + \rho_k s_k s_k^T$
    $k \leftarrow k + 1$
return x

using Sherman-Morrison-Woodbury formula to obtain Hessian update equation:

$$B_{k+1} = B_k - \frac{B_k s_k s_k^T B_k}{s_k^T B_k s_k} + \frac{y_k y_k^T}{y_k^T s_k}$$

proper line search is required so that BFGS algo captures curvature information

inaccurate line search can be used to reduce computation cost

3 Trust Region Methods

idea:

- models local behaviour of the objective function (eg: 2nd order Taylor series)
- set local region to explore, then simultaneously find direction and step size to take
- region size adaptively set using results from previous iterations
- step may fail due to inadequately set region, which need to be adjusted
- superlinear convergence when approximate model Hessian is equal to true Hessian

using 2nd order Taylor series model with symmetric matrix approximating Hessian

$$\min_{p \in \mathbb{R}^n} m_k(p) = f_k + g_k^T p + \frac{1}{2} p^T B_k p,\ st.\ ||p|| \leq \Delta_k$$

$$\Delta_k := \text{trust region radiius}$$

$$g_k = \nabla f(x_k)$$

$$B_k \succeq 0$$

full step is ($p_k = -B_k^{-1} g_k$) taken when $B \succ 0$ and $||B_k^{-1} g_k|| \leq \Delta_k$

evaluate goodness of model with actual function by:

$$\rho_k = \frac{f(x_k) - f(x_k + p_k)}{m_k(0) - m_k(p_k)}$$

$$action \leftarrow \begin{cases} \text{expand trust region} & , \rho_k \approx 1\ (agreement) \\ \text{shrink trust region} & , \rho_k < 0 + \text{thresh} \\ \text{keep trust region} & , o/w \end{cases}$$

Algorithm 3: Trust Region Algorithm

$k \leftarrow 0$
while $||\nabla f_k|| > \epsilon$ **do**
  $p_k \leftarrow \underset{p}{\operatorname{argmin}}\, f_k + g_k^T p + \frac{1}{2} p^T B_k p,\ st.\ ||p|| \leq \Delta_k$
  $\rho_k = \frac{f(x_k) - f(x_k + p_k)}{m_k(0) - m_k(p_k)} // ratiotest$
  //change trust region for next iterate
  if $\rho_k < \gamma(: \frac{1}{4})$ **then**
    $\Delta_{k+1} \leftarrow \alpha(: \frac{1}{4}) \Delta_k // shrink$
  else if $\rho_k > \beta(: \frac{3}{4})$ *and* $||p_k|| == \Delta_k$ **then**
    $\Delta_{k+1} \leftarrow min(2\Delta_k, \hat{\Delta}) // expand$
  else
    $\Delta_{k+1} \leftarrow \Delta_k // keep$
  //accept/reject for current iterate
  if $\rho_k > \eta(: \in [0, \frac{1}{4}))$ **then**
    $x_{k+1} \leftarrow x_k + p_k$
  else
    $x_{k+1} \leftarrow x_k$

Minimizer of the 2nd order Taylor series satisfy the following as a global solution for trust region iff:

$$(B + \lambda I) p^* = -g$$

complementary slackness:

$$\lambda(\Delta - ||p^*||) = 0$$

$$(B + \lambda I) \succeq 0$$

$$\lambda \geq 0$$

$\lambda \geq 0 \implies p$ parallel to negative gradient of model

Solving 2nd order Taylor series using approx methods:

- dogleg
- 2-D subspace minimization
- conjugate gradient based, effective when B large, sparse

These reduce at least as much as Cauchy Point.

Cauchy Point (sufficient reduction in model value): Use 1st order approx. of model and gradient descent to get get next iterate, bounded within trust region.

3.1 Dogleg method

if $B \succ 0$:
$p^B = -B^{-1} g$

$p^* = p^B$ if $\Delta \geq \|p^B\|$
$p^U = \frac{-g^T g}{g^T B g} g$ (intermediate point along direction of steepest descent)
Resulting algo, interpolate between p^U and p^B:

$$\tilde{p}(\tau) = \begin{cases} \tau p^U & , \tau \in [0, 1] \\ p^U + (\tau - 1)(p^B - p^U) & , \tau \in [1, 2] \end{cases}$$

$$B \succ 0 \implies \|\tilde{p}(\tau)\| \text{increases wrt. } \tau \wedge \\ m(\tilde{p}(\tau)) \text{decreases wrt. } \tau$$

if $\|p^B\| \leq \Delta$: p chosen at p^B
else p chosen at intersection of $\tilde{p}(\tau)$ and trust region boudnary by solving:
$\|p^U + (\tau - 1)(p^B - p^U)\|^2 = \|\Delta^2\|$
$p_k^S = \operatorname*{argmin}_p f_k + g_k^T p, \|p\| \leq \Delta_k$
$\tau_k = \operatorname*{argmin}_{\tau \geq 0} m_k(\tau p_k^S), \|\tau p_k^S\| \leq \Delta_k$
$p_k^S = \frac{-\Delta_k g_k|}{\|g_k\|}$
$p_k^C = \tau_k p_k^S$
$p_k^C = -\tau_k \frac{\Delta_k g_k}{\|g_k\|}$

$$\tau_k = \begin{cases} 1 & , g_k^T B_k g_k \leq 0 \\ min(\frac{\|g_k|^3}{\Delta_k g_k^T B_k g_k}, 1) & , o/w \end{cases}$$

3.2 Iterative Solution

Idea: solve subproblem $\min_{\|p\| \leq \Delta} m(p)$ by applying Newton's method to find λ that matches trust region radius. This is slightly more accurate per step compared to Dogleg. Use $(B + \lambda I)p^* = -g$ to solve $\min_{\|p\| \leq \Delta} m(p)$ for λ.

If $\lambda = 0$ and $(B + \lambda I)p^* = -g, \|p^*\| \leq \Delta$ and $(B + \lambda I) \succeq 0$: return λ
Else: find λ s.t. $(B + \lambda I) \succeq 0$ and $\|p(\lambda)\| = \Delta, p(\lambda) = -(B + \lambda I)^{-1} g$. Solve and return λ.

Solve $\|p(\lambda)\| - \Delta = 0, \lambda > \lambda_1$ via Newton's method (root finding). Approx. this to nearly a linear problem for easy solving:

Algorithm 4: Subproblem Algo

for $l = 0, 1, ..$ **do**
- solve $B + \lambda^l I = R^T R$
- $R^T R p_l = -g$
- $R^T q_l = p_l$
- $\lambda^{l+1} \leftarrow \lambda^l + (\frac{\|p_l\|}{\|q_l\|})^2 (\frac{\|p_l\| - \Delta)}{\Delta})$ check $\lambda \geq \lambda_1$

4 Conjugate Gradient

4.1 linear method

Assuming unconstrained problem with strict convex quadratic objective function:

$$\frac{1}{2}x^T Ax - b^T x, A \succ 0, A^T = A$$

$\nabla(\frac{1}{2}x^T Ax - b^T x) = Ax - b$, thus $\min_x x^T Ax - b^T x$ transformed to $Ax - b = 0$.

$x_{k+1} = x_k + \alpha_k p_k$, solve for α:

$\frac{\partial}{\partial \alpha}(\frac{1}{2}(x_k + \alpha_k p_k)^T A(x_k + \alpha_k p_k) - b^T(x_k + \alpha_k p_k)) = 0$

$r_k = Ax - b$

$\alpha_k = \frac{-p_k^T r_k}{p_k^T A p_k}$

4.2 Conjugate Direction

Search directions linearly independent wrt. A.

$$(\forall i \neq j) p_i^T A p_j = 0$$

Properties:

- Residual elimnated one direction at a time, resulting in max of n iterations.
- Optimal if Hessian is diagonal, if not can try preconditioning.
- Current residual is orthogonal to all previous search directions.
- Any set of conjugate directions can be used (eg: eigenvectors, Gram-Schmidt)

Expanding subspace minimizer:
Using conjugate directions to generate sequence $\{x\}$, then:
$r_k^T p_i = 0, \forall i < k$, x_k is minimizer of $\frac{1}{2}x^T Ax - b^T x$ over $\{x | x = x_0 + span\{p_0, ...p_{k-1}\}$

Proof.

$\tilde{x} = x_0 + \sum_i \sigma_i p_i$

$\tilde{x}$ minimizes over $\{x_0 + span\{p_0, ...p_{k-1}\}\} \iff r(\tilde{x})^T p_i = 0$

$h(\sigma) = \phi(\tilde{x})$

$\phi(x) = \frac{1}{2}x^T Ax - b^T x$

h is also strictly convex quadratic,
with unique σ^* satisfying:

$\frac{\partial h(\sigma^*)}{\partial \sigma_i} = 0, i = [0, k-1]$

$\frac{\partial h(\sigma^*)}{\partial \sigma_i} = \nabla\phi(\tilde{x})^T p_i = 0, i = [0, k-1]$

$\nabla\phi(x) = Ax - b = r$

$r(\tilde{x})^T p_i = 0, i = [0, k-1]$

□

$p_i^T r_k = 0, i = [0, k-1]$ via induction:

Proof.

base case : $x_1 = x_0 + \alpha_0 p_0$ minimizes ϕ along p_0

$\implies r_1^T p_0 = 0$

case: $r_{k-1}^T p_i = 0, i = [0, k-2]$:

$r_k = r_{k-1} + \alpha_{k-1} A p_{k-1}$

$p_{k-1}^T r_k = p_{k-1}^T r_{k-1} + \alpha_{k-1} p_{k-1}^T A p_{k-1} = 0$(by construction)

A-conjugate $\implies p_{k-1}^T A p_{k-1}$

case: $\forall i = [0, k-2] : p_i^T r_k = 0$

$p_i^T r_k = p_i^T r_{k-1} + \alpha_{k-1} p_i^T A p_{k-1}$

$p_i^T r_{k-1} = 0(by induction hypothesis$

$\alpha_{k-1} p_i^T A p_{k-1} = 0(conjugacy)$

$p_i^T r_k = 0, i = [0, k-1]$

□

4.3 Conjugate Gradient Method

Idea:

- uses only previous search direction to compute current search direction
- p_k set to linear combination of $-r_k$ and p_{k-1}
- impose $p_k^T A p_{k-1} = 0$

$$\begin{aligned}
p_k &= -r_k + \beta_k p_{k-1} \\
p_{k-1}^T A p_k &= -p_{k-1}^T A r_k + \beta p_{k-1}^T A p_{k-1} \\
0 &= -p_{k-1}^T A r_k + \beta p_{k-1}^T A p_{k-1} \\
\beta &= \frac{p_{k-1}^T A r_k}{p_{k-1}^T A p_{k-1}} \\
p_0 &= -(Ax_0 - b) = -r_0
\end{aligned}$$

Algorithm 5: Basic Conjugate Gradient Algorithm

$r_0 \leftarrow Ax_0 - b$
$p_0 = -r_0$
for $k = [0, ..n-1]$ **do**
  if $r_k == 0$ **then**
    return x_k
  else
    $\alpha_k \leftarrow \frac{-r_k^T p_k}{p_k^T A p_k} = \frac{r_k^T r_k}{p_k^T A p_k}$
    $x_{k+1} \leftarrow x_k + \alpha_k p_k$
    $r_{k+1} \leftarrow A x_{k+1} - b$
    $\beta_{k+1} \leftarrow \frac{p_k^T A r_{k+1}}{p_k^T A p_k} = \frac{r_{k+1}^T r_{k+1}}{r_k^T r_k}$
    $p_{k+1} \leftarrow -r_{k+1} + \beta_{k+1} p_k$

p_k and r_k is within krylov subspace:
$K(r_0; k) = span\{r_0, Ar_0, ..A^k r_0\}$
if $r_k \neq 0$:
$r_k^T r_i = 0, i = [0, k-1]$
$span\{r_0, .., r_k\} = span\{r_0, Ar_0, .., A^k r_0\}$
$span\{p_0, .., p+k\} = span\{r_0, Ar_0, .., A^k r_0\}$
$p_k^T A p_i = 0, i = [0, k-1]$
then, $\{x_k\} \rightarrow x^*$ in at most n steps.

Simplification:

$$\begin{aligned}
&p_{k+1} \leftarrow -r_{k+1} + \beta_{k+1} p_k \\
&\alpha_k \leftarrow \frac{-r_k^T p_k}{p_k^T A p_k} \\
&\alpha_k \leftarrow \frac{-r_k^T(-r_k + \beta_k p_{k-1})}{p_k^T A p_k} \\
&(\forall i = [0, k-1]) r_k^T p_i = 0 \implies \beta_k r_k^T p_{k-1} = 0 \\
&\alpha_k \leftarrow \frac{r_k^T r_k}{p_k^T A p_k} \text{ (simplified)}
\end{aligned}$$

$$\begin{aligned}
&r_{k+1} = r_k + \alpha_k A p_k \\
&A p_k = \frac{r_{k+1} - r_k}{\alpha_k} \\
&\beta = \frac{p_k^T A r_{k+1}}{p_k^T A p_k} \\
&p_k^T A p_k = p_k^T \frac{r_{k+1} - r_k}{\alpha_k} = \frac{-p_k^T r_k}{\alpha} \text{(conjugacy)} \\
&p_k^T A p_k = -\frac{(-r_k + \beta_k p_{k-1})^T r_k}{\alpha} = \frac{r_k^T r_k}{\alpha} \text{(conjugacy)} \\
&p_k^T A r_{k+1} = r_{k+1}^T A p_k \\
&p_k^T A r_{k+1} = r_{k+1}^T \frac{r_{k+1} - r_k}{\alpha_k} \\
&r_k \in span\{p_k, p_{k-1}\} \text{ and } r_{k+1}^T p_i = 0, i = [0, k] \implies \\
&p_k^T A r_{k+1} = \frac{r_{k+1}^T r_{k+1}}{\alpha_k} \\
&\beta_{k+1} \leftarrow \frac{r_{k+1}^T r_{k+1}}{r_k^T r_k} \text{ (simplified)}
\end{aligned}$$

4.4 Nonlinear Method

Minimize general convex function or nonlinear function. Variants: FR, PR.

4.4.1 FR (Fletcher Reaves)

Modify linear CG by:

- replace residual by gradient of nonlinear objective, $r_k \rightarrow \nabla f_k$
- replace α_k computation by a linear search to find approx. minimum along search direction of f

Equivalent to linear CG if objective is strongly convex quadratic.

Linear search for α_k with strong Wolfe condition to ensure p_k's are descent directions wrt. objective function.

4.4.2 PR

Replace β_{k+1} computation in FR with:

$$\beta_{k+1}^{PR} \leftarrow \frac{\nabla f_{k+1}^T(\nabla f_{k+1} - \nabla f_k)}{\nabla f_k^T \nabla f_k}$$
$$\beta_{k+1}^{+} \leftarrow \max(\beta_{k+1}^{PR}, 0)$$

5 Proximal Algorithm

Idea:

- reliance on easy to evaluate proximal operators
- separability allows parallel evaluation
- generalization of projection based algorithms

$$prox_{\lambda f}(v) = \operatorname*{argmin}_x f(x) + \frac{1}{2\lambda}\|x - v\|_2^2$$

Resolvent of subdifferential operator:

$$z = prox_{\lambda f}(x) \implies z \in (I + \lambda \partial f)^{-1}(x)$$
$$(I + \lambda \partial f)^{-1} := \text{resolvent of operator } \partial f$$

5.1 Proximal Gradient Method

Solve $\min_x g(x) + f(x)$, where f, g are closed, convex functions and f differentiable

$$x^* = prox_{\lambda^k g}(x^k - \lambda^k \nabla f(x^k))$$
$$= \operatorname*{argmin}_x g(x) + \frac{1}{2\lambda^k}\|x - (x^k - \lambda^k \nabla f(x^k))\|_2^2$$

tradeoff between g and and gradient step

$g = I_C(x) \implies$ projected gradient step

$g = 0 \implies$ gradient descent

$f = 0 \implies$ proximal minimization

Relation to Pixed Point:
x^* is a fixed point solution of $\min_x g(x) + f(x)$ iff $0 \in \nabla f(x^*) + \partial g(x^*)$ iff $x^* = (I + \lambda \partial g)^{-1}(I - \lambda \nabla f)(x^*)$

Forward Euler, Backward Euler stepping is same as the proximal gradient iteration, $prox_{\lambda^k g}(x^k - \lambda^k \nabla f(x^k))$

5.2 Accelerated Proximal Gradient Method

Introduce extrapolation:

$$y^{k+1} = x^k + w^k(x^k - x^{k-1})$$
$$x^{k+1} = prox_{\lambda^k g}(y^{k+1} - \lambda^k \nabla f(y^{k+1}))$$
$$w^k \in [0, 1)$$

Example: $w^k = \frac{k}{k+3}, w^0 = 0, \lambda^k \in (0, 1/L], L :=$ Lipschitz constant of ∇f, *or* λ^k found via line search. Line search for λ^k (Beck and Teboulle):

Algorithm 6: Proximal Gradient Algorithm

$\hat{f}(x,y) := f(y) + \nabla f(y)^T(x-y) + \frac{1}{2\lambda}\|x-y\|_2^2$
while *True* **do**
  $z = prox_{\lambda g}(y^k - \lambda \nabla f(y^k))$
  if $f(x) \leq \hat{f}(z, y^k)$ **then**
    break
  $\lambda = \beta\lambda$
return $\lambda^k := \lambda, x^{k+1} := z$

5.3 Types of Proximal Operators

- quadratic functions

$$f = \frac{1}{2}\|.\|_x^2 \implies prox_{\lambda f}(v) = (\frac{1}{1+\lambda})v$$
$$f = \frac{1}{2}x^TAx + b^Tx + c, A \in S_+^n \implies$$
$$prox_{\lambda f}(v) = (I+\lambda)^{-1}(v - \lambda b)$$

- unconstrained problem: use gradient methods such as Newton, Quasi-Newton

- constrained: use projected subgradient for non-smooth, projected gradient or interior method for smooth

- separable function: if scalar, may be solved analytically, eg: L1 norm separable to:

$$f(x) = |x| \implies prox_{\lambda f}(v) = \begin{cases} v - \lambda, & v \geq \lambda \\ 0, & |v| \leq \lambda \\ v + \lambda, & v \leq -\lambda \end{cases}$$

$$f(x) = -log(x) \implies prox_{\lambda f}(v) = \frac{v + \sqrt{v^2 + 4\lambda}}{2}$$

- general scalar function
  - localization: using a subgradient oracle and bisection algorithm
  - twice continuously differentiable: guarded Newton method

- polyhedra constraint, quadratic objective: solve as QP problem
  - duality to reduce number of variables to solve if possible
  - gram matrix caching
  - affine constraint($Ax = b$): use pseudo-inverse, A^+:

$$\Pi_C(v) = v - A^+(Av - b)$$
$$A \in R^{m\times n}, m < n \implies A^+ = A^T(AA^T)^{-1}$$
$$A \in R^{m\times n}, m > n \implies A^+ = (A^TA)^{-1}A^T$$

  - hyperplane constaint($a^Tx = b$):

$$\Pi_C(v) = v + (\frac{b - a^Tb}{\|a\|_2^2})a$$

  - halfspace

$$\Pi_C(v) = v - \frac{max(a^Tv - b, 0)}{\|a\|_2^2}a$$

  - box($l \leq x \leq u$)

$$\Pi_C(v)_k = min(max(v_k, l_k), u_k)$$

  - probability simplex($1^Tx = 1, x \geq 0$) bisection algo on ν:

$$\Pi_C(v) = (v - \nu 1)_+$$
$$\text{intial } [l_k, u_k] = [\max_i v_i - 1, \max_i vi]$$

    analytically solve when bounded in between 2 adjacent v˙i's

- cones (κ: proper cone) problem of the form:

$$min_x \|x - v\|_2^2$$
$$s.t. : x \in \kappa$$

$$x \in \kappa$$
$$v = x - \lambda$$
$$\lambda \in \kappa^*$$
$$\lambda^T x = 0$$

  - cone $C = \mathbb{R}_+^n$

$$\Pi_C(v) = v_+$$

  - 2nd order cone $C = \{(x,t) \in \mathbb{R}^{n+1} : \|x\|_2 \leq t\}$

$$\Pi_C(v,s) = \begin{cases} 0, & \|v\|_2 \leq -s \\ (v,s), & \|v\|_2 \leq s \\ \frac{1}{2}(1 + \frac{s}{\|v\|_2})(v, \|v\|_2), & \|v\|_2 \geq |s| \end{cases}$$

  - PSD cone S_+^n

$$\Pi_C(V) = \sum_i (\lambda_i)_+ u_i u_i^T$$
$$V = \sum_i \lambda_i u_i u_i^T \ (eigendecomp)$$

  - exponential cone
    Todo
- pointwise supremum
  - max function
  - support function
- norms
  - L2
  - L1
  - L-inf
  - elastic net
  - sum of norms
  - matrix norm
- sublevel set
- epigraph
- matrix functions Todo

6 Subgradient Method

todo