

# **idol: A C++ Framework for Optimization**

## **Reference Manual**

For idol v1.0.0-beta.

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# Contents

<b>Part 1. Mixed-integer Optimization</b>	<b>3</b>
Chapter 1. Modeling a MIP with <code>idol</code>	5
1. Introduction	5
2. Example: A mixed-integer linear problem	6
3. The environment	8
4. Models	8
5. Variables	10
6. Expressions	13
7. Constraints	13
8. The objective function	14
Chapter 2. Solving problems with <code>Optimizers</code>	15
Chapter 3. Callbacks	17
Chapter 4. Writing a custom Branch-and-Bound algorithm	19
Chapter 5. Column Generation and Branch-and-Price	21
Chapter 6. Penalty alternating direction method	23
<b>Part 2. Bilevel Optimization</b>	<b>25</b>
Chapter 7. Modeling a bilevel problem	27
Chapter 8. Problems with continuous follower	29
1. The strong-duality single-level reformulation	29
2. The KKT single-level reformulation	29
3. Linearization techniques for the KKT single-level reformulation	29
4. Penalty alternating direction methods	30
Chapter 9. Problems with mixed-integer follower	33
Chapter 10. Pessimistic bilevel optimization	35
<b>Part 3. Robust Optimization</b>	<b>37</b>
Chapter 11. Modeling a robust problem	39
1. Single-stage problems	39
2. Two-stage problems	39
3. Bilevel problems with wait-and-see follower	39
Chapter 12. Deterministic reformulations	41
Chapter 13. Affine decision rules	43
Chapter 14. Column and constraint generation	45

1. Introduction	45
2. Two-stage robust problems	45
3. Example: The uncapacitated facility location problem with facility disruption	49
4. Example: The capacitated facility location problem with facility disruption	56
5. Robust bilevel problems with wait-and-see followers	56
6. Example: The uncapacitated facility location problem with wait-and-see follower and facility disruption	56
Chapter 15. K-adaptability	57
Chapter 16. Objective uncertainty	59
Bibliography	61

## Part 1

# Mixed-integer Optimization



## CHAPTER 1

# Modeling a MIP with **idol**

### Contents

<b>1. Introduction</b>	<b>5</b>
Disclaimer	6
<b>2. Example: A mixed-integer linear problem</b>	<b>6</b>
<b>3. The environment</b>	<b>8</b>
<b>4. Models</b>	<b>8</b>
<b>5. Variables</b>	<b>10</b>
5.1. Creating variables	10
5.2. Removing variables	12
5.3. Accessing variables	12
5.4. Modifying variables	13
<b>6. Expressions</b>	<b>13</b>
<b>7. Constraints</b>	<b>13</b>
7.1. Linear constraints	13
7.2. Quadratic constraints	13
7.3. SOS1 and SOS2 constraints	13
<b>8. The objective function</b>	<b>14</b>

### 1. Introduction

In many decision-making applications—ranging from logistics and finance to energy systems and scheduling—problems can be naturally modeled as mixed-integer optimization problems (MIPs). These problems combine continuous and integer variables to represent decisions under various logical, structural, or operational constraints.

In **idol**, we adopt a general and flexible framework for expressing such problems. A MIP is assumed to be of the following form:

$$\min_x \quad c^\top x + x^\top D x + c_0 \tag{1a}$$

$$\text{s.t.} \quad a_i^\top x + x^\top Q^i x \leq b_i, \quad \text{for all } i = 1, \dots, m, \tag{1b}$$

$$\ell_j \leq x_j \leq u_j, \quad \text{for all } j = 1, \dots, n, \tag{1c}$$

$$x_j \in \mathbb{Z}, \quad \text{for all } j \in J \subseteq \{1, \dots, n\}. \tag{1d}$$

Here,  $x$  is the decision variable vector, and the input data are as follows: Vector  $c \in \mathbb{Q}^n$ , matrix  $D \in \mathbb{Q}^{n \times n}$  and the constant  $c_0 \in \mathbb{Q}$  define the linear, the quadratic and the constant parts of the objective function, respectively; For each constraint with index  $i \in \{1, \dots, m\}$ , vector  $a_i$ , matrix  $Q^i \in \mathbb{Q}^{n \times n}$  and constant  $b_i$  encode the linear part, the quadratic part, and the right-hand side of the constraint respectively; Vectors  $\ell \in \mathbb{Q}^n \cup \{-\infty\}$  and  $u \in \mathbb{Q}^n \cup \{\infty\}$  are used to define lower and upper bounds on each variables; Finally, the set  $J \subseteq \{1, \dots, n\}$  specifies which variables are required to be integer.

As is customary, variables are classified depending on their type—which can be continuous, integer or binary—and bounds. This is presented in Table 1. As

TABLE 1. Terminology for variables in a MIP.

A variable $x_j$ is said ...	if it satisfies ...
integer	$j \in J$
binary	$j \in J$ and $0 \leq \ell \leq u \leq 1$
continuous	$j \notin J$
free	$l = -\infty$ and $u = \infty$
non-negative	$\ell \geq 0$
non-positive	$u \leq 0$
bounded	$-\infty < \ell \leq u < \infty$
fixed	$\ell = u$

to constraints, they are said to be linear when  $Q^i = 0$ , and quadratic otherwise. Likewise, the objective function is quadratic when  $D \neq 0$ .

A particularly important subclass of MIPs arises when both the constraints and the objective function are linear (i.e.,  $Q^i = 0$  for all  $i$  and  $D = 0$ ). In this case, the problem is known as a mixed-integer linear problem (MILP).

For many practical purposes, it is helpful to consider the continuous relaxation of a MIP. This is obtained by removing the integrality constraints (1d), allowing all variables to take real values. This relaxation is easier to solve and often provides useful bounds or insights about the original problem.

**Disclaimer.** You do not need to read every section in detail before solving your first problem. Most users can start with the example in Section 2, which demonstrates how to define a basic MILP using `idol`. Later sections dive deeper into the modeling framework, including variables, constraints, and the environment that manages them. Note that solving a model (i.e., computing an optimal point) is not covered in this chapter. This is the focus of the next chapter, where you will learn about how to use an `Optimizer` and an `OptimizerFactory`.

## 2. Example: A mixed-integer linear problem

To illustrate the modeling capabilities of `idol`, we begin with a small example which is a mixed-integer linear program (MILP). The mathematical model reads:

$$\min_x -x - 2y \quad (2a)$$

$$\text{s.t. } -x + y \leq 1, \quad (2b)$$

$$2x + 3y \leq 12, \quad (2c)$$

$$3x + 2y \leq 12, \quad (2d)$$

$$x, y \in \mathbb{Z}_{\geq 0}. \quad (2e)$$

This is a minimization problem which involves two integer variables,  $x$  and  $y$ , both constrained to be non-negative. The feasible region is defined by three linear inequalities. Figure 1 shows this region (shaded in blue), the integer-feasible points, and the direction of the objective function (represented by the vector  $-c$ ). The continuous relaxation of this problem—where  $x$  and  $y$  are allowed to take real values—has a unique solution at  $(x^*, y^*) = (2.4, 2.4)$ , with an objective value of  $-7.2$ . The original integer-constrained problem also admits a unique solution at  $(x^*, y^*) = (2, 2)$ , with objective value  $-5$ .

Modeling Problem (2) in `idol` is straightforward. In particular, if you are familiar with other optimization packages like JuMP in Julia or the Gurobi C++ API, the following code snippet should be easy to understand.

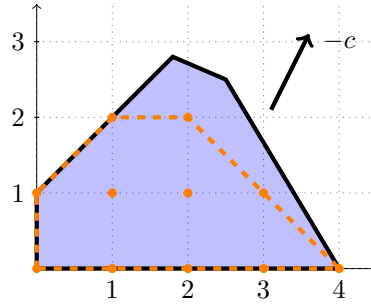


FIGURE 1. Feasible region (shaded in blue) for Problem (2), with integer-feasible points highlighted and objective direction shown.

```

1 #include <iostream>
2 #include "idol/modeling.h"
3
4 using namespace idol;
5
6 int main(int t_argc, const char** t_argv) {
7
8     Env env;
9
10    // Create a new model.
11    Model model(env);
12
13    // Create decision variables x and y.
14    const auto x = model.add_var(0, Inf, Integer, -1, "x");
15    const auto y = model.add_var(0, Inf, Integer, -2, "y");
16
17    // Create constraints.
18    const auto c1 = model.add_ctr(-x + y <= 1);
19    const auto c2 = model.add_ctr(2 * x + 3 * y <= 12);
20    const auto c3 = model.add_ctr(3 * x + 2 * y <= 12);
21
22    return 0;
23 }

```

Let's walk through this code. In Line 8, we create a new optimization environment that will store all our optimization objects such as variables or constraints. Destroying an environment automatically destroys all objects which were created with this environment. Then, in Line 11, we create an optimization model. By default, all models are for minimization problems. Decision variables are created in Lines 14 and 15. There, we set the lower bound to 0 and an infinite upper bound using the defined constant `idol::Inf`. Both variables are defined as `Integer`. Note that other types are possible, e.g., `Continuous` and `Binary`. The objective coefficients are also set in these lines by the fourth argument. The last argument corresponds to the internal name of that variable and is mainly useful for debugging. Finally, Lines 18–20 add constraints to the model to define the feasible region of the problem.

Note that, as such, we are only modeling Problem (2) here but we are not performing any optimization task so far. This is the subject of the next chapter. For the sake of completeness, however, here is how one uses the commercial solver `Gurobi` to compute a solution of this problem.

```

1     model.use(Gurobi());
2     model.optimize();
3

```



```

4  std::cout << "Status = " << model.get_status() << std::endl;
5  std::cout << "x = " << model.get_var_primal(x) << std::endl;
6  std::cout << "y = " << model.get_var_primal(y) << std::endl;

```

This prints the solution status (here, `Optimal`) and the values of the decision variables in the solution (here,  $(x^*, y^*) = (2, 2)$ ).

### 3. The environment

Any optimization object—such as variables, constraints and models—are managed through a central entity called an “optimization environment”. This environment, represented by the `Env` class, acts as a container and controller for all optimization-related objects created within its scope.

The environment has two key responsibilities:

- (1) **Lifecycle management.** When an environment is destroyed, all objects created within it are automatically deleted. This eliminates the need for manual memory management. Also, once an object is no longer referenced, it is safely cleaned up by the environment, i.e., you do not need to manually delete objects.
- (2) **Version tracking.** During the execution of an optimization program, objects like variables and constraints may appear in different models with model-specific changes. These different versions of a single object are all stored and managed in the environment.

Typically, a single environment should suffice for most applications. While `idol` technically allows the creation of multiple environments, this is strongly discouraged. Objects created in one environment must not be mixed with those from another. For example, attempting to add a variable from one environment to a model belonging to a different environment will lead to undefined behavior, often resulting in segmentation faults or program crashes.

Creating an environment is straightforward:

```

1  Env env; // Creates a new optimization environment.

```

Once initialized, you can begin creating models, variables, and constraints using this environment. All such objects will be associated with `env` and managed accordingly throughout their lifetime.

### 4. Models

Mathematical optimization problems are modeled using the `Model` class. A model is a set of variables and constraints with an objective function. It can be created by calling the constructor of the `Model` class by passing an environment as the first argument.

```

1  Env env;
2  Model model(env); // Creates an empty model.

```

Here, we first create a new optimization environment, then create an optimization model. Note that the newly created model does not contain any variable nor constraints. By default, all models are for minimization problems. Unfortunately, `idol` offers limited support for maximization problem. However, it is well known that this is not a real restriction since  $\max f(x) = -\min -f(x)$ .

Another way to create a model is by importing it from an `.mps` or an `.lp` file. To do this, you will need to rely on an external solver. In what follows, we use GLPK, which is an open-source solver which can be easily installed on your computer.

```

1 Env env;
2 auto model = GLPK::read_from_file("/path/to/some/file.mps");

```

The choice to rely on external solver is justified by the fact that, first of all, `idol` will most of the time be used in combination with such a solver to effectively solve optimization problems. Second, it is also safer to rely on existing codes with years of experience to import your model without mistake or ambiguity.

Now that we have a model imported, we can safely iterate over its variables and constraints. This can be done as follows.

```

1 for (const auto& var : model.vars()) {
2     std::cout << var.name() << std::endl;
3 }

```

Here, we use the `Model::vars()` method to get access to the variables of the model and write down their names. Note that you can also use the `operator<<(std::ostream&, const Model&)` function to print the model to the console. This can be useful for debugging.

Once we have iterated over the variables, we may want to iterate over constraints as well. To do so, we can use: the `Model::ctrs()` method for linear constraints, the `Model::qctrs()` method for quadratic constraints and the `Model::sosctrs()` method for SOS-type constraints. The next code snippet shows how to get the number of variables and constraints.

```

1     std::cout << "Number of variables: "
2               << model.vars().size() << std::endl;
3
4     std::cout << "Number of linear constraints: "
5               << model.ctrs().size() << std::endl;
6
7     std::cout << "Number of quadratic constraints: "
8               << model.qctrs().size() << std::endl;
9
10    std::cout << "Number of sos-type constraints: "
11              << model.sosctrs().size() << std::endl;

```

To get model-specific information about a variable, a constraint or the objective function, we can use methods like `Model::get_X_Y(const X&)` where `X` is an object name—like `var`, `ctr`, `qctr`, `sosctr` or `obj`—and `Y` is the data name you which to gain access—like `lb`, `type` or `column`. For instance, the following code counts the number of binary variables in the model.

```

1     unsigned int n_binary_vars = 0;
2
3     // Iterate over all variables in the model.
4     for (const auto& var : model.vars()) {
5
6         // Get the variable type in this model.
7         const auto type = model.get_var_type(var);
8
9         // Check type is binary.
10        if (type == Binary) {
11            ++n_binary_vars;
12        }
13    }
14

```

Complete details on what information you can retrieve through a model will be detailed in the following sections.

In most practical cases, you will want to avoid copying a model but, rather, pass on a reference to some auxiliary function. For that reason, the copy constructor of the `Model` class is declared as `private`. If copying a model is really what you intend to do, you should use the `Model::copy()` method and the move constructor. Here is an example.

```
1  const auto model = Gurobi::read_from_file("problem.lp");
2  auto model2 = model.copy();
```

Here, `model2` is now an independent copy of the original model and can be modified without altering its source model. Similarly, if you want to write a function that returns a model, you will have to be explicit about it to avoid unnecessary copies. See the following code.

```
1  Model read_model_from_file() {
2
3      // Read the model from the file.
4      auto model = Gurobi::read_from_file("problem.lp");
5
6      // Use std::move to avoid unnecessary copies.
7      // If a copy is intended, use Model::copy().
8      return std::move(model);
9  }
```

Moving the model instead of copying it avoids the overhead of duplicating large optimization problems.

## 5. Variables

Variables are the decision-making elements of an optimization problem. These are the quantities that we aim to determine in order to optimize an objective function, subject to a set of constraints. In `idol`, they are represented by the `Var` class.

**5.1. Creating variables.** Creating variables can be done in mainly two ways. The first one is through the `Var` constructor and the `Model::add()` method, while the second uses the `Model::add_var(...)` methods. We start with the first method which uses the `Var` constructor. This method is less direct, but more informative on how optimization objects are managed in `idol`. We focus on the following constructor:

`Var(Env&, double, double, VarType, double, std::string).`

This constructor takes six arguments. The first is the optimization environment which will store the variable's versions. The two subsequent are the lower and upper bound—possibly infinite using `idol::Inf`. Then, the type of the variable is expected—such as `idol::Continuous`, `idol::Integer` or `idol::Binary`. The linear coefficient of the variable in the objective function is the fifth argument. Finally, the last argument is the given name of the variable. For instance, the following code creates a new variable in the environment.

```
1  Var x(env, 0, Inf, Continuous, 2, "x");
```

This variable is a continuous non-negative variable with an objective coefficient of 2. It is called “x”. One important thing is that this variable does not belong to any model yet. Instead, what we have created is called the “default version” of the variable. This means that, by default, if this variable is added to a model, it will have the corresponding attributes in that model. For instance, here is a code that creates and add this variable to a model.

```

1 // Create a variable in the environment.
2 Var x(env, 0, Inf, Continuous, 2, "x");
3
4 // Add the variable to a model
5 model.add(x);

```

By default, the variable “x” is added to the model as a continuous non-negative variable with an objective coefficient of 2. Note that other constructors are also available in the `Var` class. For instance, it is also possible to provide a column associated to the variable so that it is automatically added to the LP matrix. Columns are built using the `LinExpr<Ctr>` class and can be built in a very natural way. For more details, please refer to Section 6 on expressions in `idol`. We simply give one example.

```

1 // This function is assumed to return a vector of constraints.
2 const std::vector<Ctr> ctrs = get_vector_of_ctrs();
3
4 // Create the column associated to x.
5 LinExpr<Ctr> column = -1 * c[0] + 2 * c[1] + 3 * c[2];
6
7 // Create a variable in the environment.
8 Var x(env, 0, Inf, Integer, -1, std::move(column), "x");
9
10 // Add the variable to a model.
11 model.add(x);

```

Finally, note that it is possible to avoid adding the default version to a model by overriding it as follows.

```

1 // Add the variable to a model, overriding the default version.
2 model.add(x, TempVar(0, Inf, Continuous, 2, LinExpr<Var>()));

```

Here, we notice the use of the `TempVar` class. This class is a lightweight class used to represent a variable that has yet not been created inside an environment. As such, it contains all attributes of the variable to be created but it cannot be used other than for storing these attributes and create an actual variable.

The second approach for creating variables is more straightforward. However, it internally is exactly the same as what we have seen so far. This can be reached using the `Model::add_var` methods from the `Model` class. The following code snippet should be easy to understand.

```

1 const auto x = model.add_var(0, Inf, Continuous, 2, "x");

```

Note that we do not need to pass the environment since the environment of the model is automatically used. Also, two operations are performed in a single call here: first, a default version is created for the variable, then the variable is added to the model. Similarly, it is also possible to add a variable with a specific column in the LP matrix.

Sometimes, you will find it more convenient to create several variables at once. This can be done by calling the `Var::make_vector` function, or the `Model::add_vars` method. These functions require one extra parameter specifying the dimension of the new variable. For instance, here is how to create a set of variables with a  $2 \times 3$  index.

```

1 // Create a 2x3 "vector" of variables.
2 const auto x = Var::make_vector(env, Dim<2>(2, 3), 0, Inf, ←
3     Continuous, "x");
4 // Add all variables

```

```

5  model.add_vector<Var, 2>(x);
6
7  // Print the first variable's name.
8  std::cout << "x_0_0 = " << x[0][0].name() << std::endl;

```

Notice that we used the `Dim` class to specify the dimensions. The `Dim` class is a template class that takes an integer as parameter. This integer specifies the number of indices for the new variable. In this case, we use 2 to specify that we want to create a two-dimensional index. Then, we give the size of each dimension by passing the appropriate arguments to the constructor of the `Dim` class, i.e., 2 and 3.

Naturally, it is also possible to achieve this goal through methods of the `Model` class. The following snippet gives an example.

```

1  const auto x = model.add_vars(Dim<2>(2,3), 0, Inf, Continuous, "↔
    x");

```

**5.2. Removing variables.** Once a variable has been added to a model, it can also be removed from it. We use the `Model::remove(const Var&)` method for this. Calling this method will remove the variable from the model and update all linear and quadratic constraints where this variable appeared. Trying to remove a variable which does not belong to a model will result in an exception being thrown. However, it is possible to check whether a model has a given variable using the `Model::has(const Var&)` method. This method returns true if and only if the variable is part of the model. Also, note that it is not possible to remove a variable which is involved in an SOS-type constraint. This is not limiting since SOS-type constraints can be removed and added again.

**5.3. Accessing variables.** Variables have two immutable attributes: a name, which is the given name at creation time of the variable and an id, which is unique in the environment. Other attributes are tied to a specific model and can be accessed through the model's methods `Model::get_var_Y` where `Y` is the name of that attribute. Next is list of methods which can be used to retrieve information about variables in a model.

**double Model::get\_var\_lb(const Var&):**

Returns the lower bound of the variable given as parameter.  
May return any value between `-idol::Inf` and `idol::Inf`.

**double Model::get\_var\_ub(const Var&):**

Returns the upper bound of the variable given as parameter.  
May return any value between `-idol::Inf` and `idol::Inf`.

**double Model::get\_var\_obj(const Var&):**

Returns the objective coefficient in the linear part of the objective function.

**VarType Model::get\_var\_type(const Var&):**

Returns the type of the variable which can be `Continuous`, `Integer` or `Binary`.

**LinExpr<Ctr> Model::get\_var\_column(const Var&):**

Returns the associated column in the LP matrix.

**unsigned int Model::get\_var\_index(const Var&):**

Returns the index of the variable.

Note that this index may change if variables are removed.

We now give an example which prints out all free variables.

```

1  for (const auto& var : model.vars()) {
2
3      const double lb = model.get_var_lb(var);
4      const double ub = model.get_var_ub(var);
5
6      if (is_neg_inf(lb) && is_pos_inf(ub)) {

```

```

7         std::cout << var.name() << " is free." << std::endl;
8     }
9
10 }

```

One final note regarding indices. Though they may change over time, e.g., if variables are removed from a model, it can still be used to access variables by using the `Model::get_var_by_index` method. The following code snippet shows an alternative way to iterate over variables in a model.

```

1     for (unsigned int i = 0, n = model.vars().size(); i < n; ++i) {
2
3         // Get the variable by index
4         const auto& var = model.get_var_by_index(i);
5
6         // Print out its name
7         std::cout << var.name() << std::endl;
8
9     }

```

**5.4. Modifying variables.** Some of the attributes of a variable may be directly changed through the model's methods `Model::set_var_Y`. Here again, `Y` is the name of the attribute you wish to modify. Here is a list of methods to be used for modifying attributes of a variable in a model.

**void Model::set\_var\_lb(const Var&, double):**

Sets the lower bound of a variable.

The new lower bound can be `-idol::Inf`, `idol::Inf` or any double in between.

**void Model::set\_var\_ub(const Var&, double):**

Sets the lower bound of a variable.

The new lower bound can be `-idol::Inf`, `idol::Inf` or any double in between.

**void Model::set\_var\_obj(const Var&, double):**

Sets the linear coefficient in the objective function.

**void Model::set\_var\_type(const Var&, VarType):**

Sets the type of a variable.

Changing the type of variable does not affect its bounds.

**void Model::set\_var\_column(const Var&, const LinExpr<Ctr>&):**

Sets the column of a variable in the LP matrix.

We end with an example which copies a model and creates its continuous relaxation.

```

1     // Copy the model.
2     auto continuous_relaxation = model.copy();
3
4     // Build the continuous relaxation.
5     for (const auto& var : model.vars()) {
6         continuous_relaxation.set_var_type(var, Continuous);
7     }

```

## 6. Expressions

### 7. Constraints

#### 7.1. Linear constraints.

#### 7.2. Quadratic constraints.

#### 7.3. SOS1 and SOS2 constraints.

**8. The objective function**

## CHAPTER 2

# Solving problems with **Optimizers**





## CHAPTER 3

# Callbacks



## CHAPTER 4

# Writing a custom Branch-and-Bound algorithm



## CHAPTER 5

# Column Generation and Branch-and-Price



## CHAPTER 6

### Penalty alternating direction method





## Part 2

# Bilevel Optimization



## CHAPTER 7

### Modeling a bilevel problem



## CHAPTER 8

### Problems with continuous follower

#### Contents

	<b>1. The strong-duality single-level reformulation</b>	<b>29</b>
	<b>2. The KKT single-level reformulation</b>	<b>29</b>
	<b>3. Linearization techniques for the KKT single-level reformulation</b>	<b>29</b>
3.1.	Using SOS1 constraints	30
3.2.	Using the big-M approach	30
<b>4.</b>	<b>Penalty alternating direction methods</b>	<b>30</b>

$$\min_{x,y} \quad c^\top x + d^\top y \quad (3a)$$

$$\text{s.t.} \quad Ax + By \geq a, \quad (3b)$$

$$y \in S(x). \quad (3c)$$

#### 1. The strong-duality single-level reformulation

#### 2. The KKT single-level reformulation

#### 3. Linearization techniques for the KKT single-level reformulation

$$\min_y \quad f^\top y \quad (4a)$$

$$\text{s.t.} \quad C^\equiv x + D^\equiv y = b^\equiv, \quad (\lambda^\equiv \in \mathbb{R}^{m_\equiv}) \quad (4b)$$

$$C^\leq x + D^\leq y \leq b^\leq, \quad (\lambda^\leq \in \mathbb{R}_{\leq 0}^{m_\leq}) \quad (4c)$$

$$C^\geq x + D^\geq y \geq b^\geq, \quad (\lambda^\geq \in \mathbb{R}_{\geq 0}^{m_\geq}) \quad (4d)$$

$$y \leq y^\leq, \quad (\pi^\leq \in \mathbb{R}_{\leq 0}^n) \quad (4e)$$

$$y \geq y^\geq, \quad (\pi^\geq \in \mathbb{R}_{\geq 0}^n). \quad (4f)$$

$$\max_{\lambda^\equiv, \lambda^\geq, \lambda^\leq, \pi^\leq, \pi^\geq} \quad (b^\equiv - C^\equiv x)^\top \lambda^\equiv + (b^\leq - C^\leq x)^\top \lambda^\leq + (b^\geq - C^\geq x)^\top \lambda^\geq \quad (5a)$$

$$+ \sum_{j: y_j^\leq < \infty} (y_j^\leq)^\top \pi_j^\leq + \sum_{j: y_j^\geq > -\infty} (y_j^\geq)^\top \pi_j^\geq \quad (5b)$$

$$\text{s.t.} \quad (D^\equiv)^\top \lambda^\equiv + (D^\leq)^\top \lambda^\leq + (D^\geq)^\top \lambda^\geq + \pi^\leq + \pi^\geq = d, \quad (5c)$$

$$\lambda^\leq \leq 0, \lambda^\geq \geq 0, \pi^\leq \leq 0, \pi^\geq \geq 0. \quad (5d)$$

The KKT system reads

$$\begin{aligned}
\text{Primal feasibility} & \quad \begin{cases} C^{\leq}x + D^{\leq}y = b^{\leq}, \\ C^{\leq}x + D^{\leq}y \leq b^{\leq}, \\ C^{\geq}x + D^{\geq}y \geq b^{\geq}, \\ y \leq y^{\leq}, \\ y \geq y^{\geq}, \end{cases} \\
\text{Dual feasibility} & \quad \begin{cases} \lambda^{\leq} \leq 0, \\ \lambda^{\geq} \geq 0, \\ \pi^{\leq} \leq 0, \\ \pi^{\geq} \geq 0, \end{cases} \\
\text{Stationarity} & \quad \left\{ (D^{\leq})^{\top} \lambda^{\leq} + (D^{\geq})^{\top} \lambda^{\geq} + \pi^{\leq} + \pi^{\geq} = d, \right. \\
\text{Complementarity} & \quad \begin{cases} (C^{\leq}x + D^{\leq}y - b^{\leq})^{\top} \lambda^{\leq} = 0, \\ (C^{\geq}x + D^{\geq}y - b^{\geq})^{\top} \lambda^{\geq} = 0, \\ (y - y^{\leq})^{\top} \pi^{\leq} = 0, \\ (y - y^{\geq})^{\top} \pi^{\geq} = 0. \end{cases}
\end{aligned}$$

### 3.1. Using SOS1 constraints.

$$\begin{aligned}
(C^{\leq}x + D^{\leq}y - b^{\leq}) &= s^{\leq}, \\
(C^{\geq}x + D^{\geq}y - b^{\geq}) &= s^{\geq}, \\
(y - y^{\leq}) &= r^{\leq}, \\
(y - y^{\geq}) &= r^{\geq}, \\
\text{SOS1}(s_i^{\leq}, \lambda_i^{\leq}), & \quad \text{for all } i = 1, \dots, m_{\leq}, \\
\text{SOS1}(s_i^{\geq}, \lambda_i^{\geq}), & \quad \text{for all } i = 1, \dots, m_{\geq}, \\
\text{SOS1}(r_i^{\leq}, \pi_i^{\leq}), & \quad \text{for all } i = 1, \dots, n, \\
\text{SOS1}(r_i^{\geq}, \pi_i^{\geq}), & \quad \text{for all } i = 1, \dots, n.
\end{aligned}$$

### 3.2. Using the big-M approach.

$$\begin{aligned}
M_i^{\leq} u_i^{\leq} &\leq \lambda^{\leq} \leq 0, \quad N_i^{\leq} (1 - u_i^{\leq}) \leq C^{\leq}x + D^{\leq}y - b^{\leq} \leq 0, \quad \text{for all } i = 1, \dots, m_{\leq}, \\
M_i^{\geq} u_i^{\geq} &\geq \lambda^{\geq} \geq 0, \quad N_i^{\geq} (1 - u_i^{\geq}) \geq C^{\geq}x + D^{\geq}y - b^{\geq} \geq 0, \quad \text{for all } i = 1, \dots, m_{\geq}, \\
O_j^{\leq} v_j^{\leq} &\leq \pi^{\leq} \leq 0, \quad P_j^{\leq} (1 - v_j^{\leq}) \leq y - y^{\leq} \leq 0, \quad \text{for all } j = 1, \dots, n, \\
O_j^{\geq} v_j^{\geq} &\geq \pi^{\geq} \geq 0, \quad P_j^{\geq} (1 - v_j^{\geq}) \geq y - y^{\geq} \geq 0, \quad \text{for all } j = 1, \dots, n, \\
u^{\leq} &\in \{0, 1\}^{m_{\leq}}, \quad u^{\geq} \in \{0, 1\}^{m_{\geq}}, \quad v^{\leq} \in \{0, 1\}^n, \quad v^{\geq} \in \{0, 1\}^n.
\end{aligned}$$

## 4. Penalty alternating direction methods

CtrType		
LessOrEqual	$M_i^{\leq} \leftarrow \text{get\_ctr\_dual\_lb}(c)$	$N_i^{\leq} \leftarrow \text{get\_ctr\_slack\_lb}(c)$
GreaterOrEqual	$M_i^{\geq} \leftarrow \text{get\_ctr\_dual\_ub}(c)$	$N_i^{\geq} \leftarrow \text{get\_ctr\_slack\_ub}(c)$

Var	
$O_j^{\leq} \leftarrow \text{get\_var\_ub\_dual\_lb}(y)$	$P_j^{\leq} \leftarrow y^{\geq} - y^{\leq}$
$O_j^{\geq} \leftarrow \text{get\_var\_lb\_dual\_ub}(y)$	$P_j^{\geq} \leftarrow y^{\leq} - y^{\geq}$

TABLE 1. Function calls made to the `BoundProvider` to linearize a KKT single-level reformulation with the big-M approach.





## CHAPTER 9

### Problems with mixed-integer follower



## CHAPTER 10

# Pessimistic bilevel optimization



## Part 3

# Robust Optimization



## CHAPTER 11

# Modeling a robust problem

### Contents

	<b>1. Single-stage problems</b>	<b>39</b>
	<b>2. Two-stage problems</b>	<b>39</b>
	<b>3. Bilevel problems with wait-and-see follower</b>	<b>39</b>

### 1. Single-stage problems

#### 2. Two-stage problems

$$\min_{x \in X} c^\top x + \max_{u \in U} \min_{y \in Y(x, u)} d^\top y$$

$$X := \left\{ x \in \tilde{X} : Ax \geq a \right\}$$

$$Y(x, u) := \left\{ y \in \tilde{Y} : Cx + Dy + E(x)u \geq b \right\}$$

$$U := \left\{ u \in \tilde{U} : Fu \leq g \right\}$$

$$\min_{x, x_0} c^\top x + x_0$$

$$\text{s.t. } x \in X,$$

$$\forall x \in X, \exists y \in Y(x, u), x_0 \geq d^\top y.$$

### 3. Bilevel problems with wait-and-see follower

$S(x)$  the set of optimal solutions to the follower problem

$$\min_{y \in Y(x, u)} f^\top y.$$

$$\min_{x \in X} c^\top x + \max_{u \in U} \min_y \left\{ d^\top y : y \in S(x, u), Gx + Hy + Ju \geq g \right\}.$$

$$\min_{x, x_0} c^\top x + x_0$$

$$\text{s.t. } x \in X,$$

$$\forall x \in X, \exists y \in S(x, u), x_0 \geq d^\top y, Gx + Hy + Ju \geq h.$$





## CHAPTER 12

# Deterministic reformulations



## CHAPTER 13

### **Affine decision rules**



## CHAPTER 14

# Column and constraint generation

### Contents

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<b>1. Introduction</b>	<b>45</b>
<b>2. Two-stage robust problems</b>	<b>45</b>
2.1. Problem statement and assumptions	45
2.2. The procedure	46
2.3. Solving the separation problem with continuous second stage	47
2.4. Solving the separation problem with mixed-integer second stage	49
2.5. Initializing the scenario pool	49
<b>3. Example: The uncapacitated facility location problem with facility disruption</b>	<b>49</b>
3.1. Modeling the robust UFLP with facility disruption in idol	50
3.2. Preparing the column-and-constraint optimizer	52
3.3. Solving the separation problem	52
<b>4. Example: The capacitated facility location problem with facility disruption</b>	<b>56</b>
4.1. Problem statement	56
<b>5. Robust bilevel problems with wait-and-see followers</b>	<b>56</b>
<b>6. Example: The uncapacitated facility location problem with wait-and-see follower and facility disruption</b>	<b>56</b>
6.1. Solving the separation problem	56

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### 1. Introduction

### 2. Two-stage robust problems

#### 2.1. Problem statement and assumptions.

$$\min_{x \in X} c^\top x + \max_{u \in U} \min_{y \in Y(x, u)} d^\top y \quad (8)$$

$$X := \left\{ x \in \tilde{X} : Ax \geq a \right\}$$

$$Y(x, u) := \left\{ y \in \tilde{Y} : Cx + Dy + E(x)u \geq b \right\}$$

$$U := \left\{ u \in \tilde{U} : Fu \leq g \right\}$$

ASSUMPTION 1. *Problem (8) either has a solution or is infeasible.*

Note that a sufficient condition for Assumption 1 to hold is that the uncertainty set  $U$  is nonempty and that, for all  $u \in U$ , the set  $\{(x, y) : x \in X, y \in Y(x, u)\}$  is compact, possibly empty.

**2.2. The procedure.** At each iteration  $K$ , the CCG algorithm solves the so-called restricted master problem which consists in solving Problem (8) having replaced the uncertainty set  $U$  by a discrete subset of scenarios  $\{u^1, \dots, u^K\}$ . This problem can be formulated as

$$\min_{x \in X, x_0, y^1, \dots, y^K \in \tilde{Y}} c^\top x + x_0 \quad (9a)$$

$$\text{s.t. } x_0 \geq d^\top y^k, \quad \text{for all } k = 1, \dots, K, \quad (9b)$$

$$Cx + Dy^k + E(x)u^k \geq b, \quad \text{for all } k = 1, \dots, K. \quad (9c)$$

Note that vectors  $u^k$  with  $k = 1, \dots, K$  are inputs of this model. Also note that the algorithm requires (at least) one initial scenario  $u^1$  so that the master problem (9) is lower bounded. Several strategies exist to find this initial scenario and are discussed in Section 2.5.

HL

discuss unboundedness

Now, let  $(x, x_0, y^1, \dots, y^K)$  denote a solution to the restricted master problem (9). We need to check that the point  $x$  is feasible for Problem (8), i.e., that for all  $u \in U$ , there exists  $y \in Y(x, u)$ , otherwise identify a scenario  $u$  for which  $Y(x, u)$  is empty. This is called the “feasibility separation”. If  $x$  is a feasible first-stage decision, we need to check that the optimal objective value of the restricted master problem (9)  $c^\top x + x_0$  is, indeed, the correct cost associated to  $x$ , i.e., that for all  $u \in U$ , there exists  $y \in Y(x, u)$  such that  $d^\top y \leq x_0$ , otherwise identify a scenario  $u \in U$  with  $\min_y \{f^\top y : y \in Y(x, u)\} > x_0$ . This is called the “optimality separation”.

$$v_{\text{feas}} := \max_{u \in U} \min_{y, z} \left\{ z : y \in \tilde{Y}, z \geq 0, Cx + Dy + E(x)u + ze \geq b \right\}. \quad (10)$$

$$- \min_{u \in U, y, z} -z$$

$$\text{s.t. } (y, z) \in \arg \min_{\bar{y}, \bar{z}} \left\{ \bar{z} : \bar{y} \in \tilde{Y}, \bar{z} \geq 0, Cx + D\bar{y} + E(x)\bar{u} + \bar{z}e \geq b \right\}.$$

$$v_{\text{opt}} := \max_{u \in U} \min_y \left\{ f^\top y : y \in \tilde{Y}, Cx + Dy + E(x)u \geq b \right\}. \quad (12)$$

$c^\top x + v_{\text{opt}}$  is an upper bound on the optimal objective function value of Problem (8).

$$- \min_{u \in U, y} -f^\top y$$

$$\text{s.t. } y \in \arg \min_{\bar{y}} \left\{ f^\top \bar{y} : \bar{y} \in \tilde{Y}, Cx + D\bar{y} + E(x)\bar{u} \geq b \right\}.$$

So far, we discussed a sort of “two-step” separation strategy: first, checking feasibility, then optimality. Actually, this two-step strategy can be replaced by solving a single optimization problem. We call this approach “Farkas separation”. Given a current first-stage decision  $x$  and a second-stage cost estimate  $x_0$ , one solves the bilevel problem

$$\max_{u \in U} \min_{y, z} \left\{ z : y \in \tilde{Y}, z \geq 0, d^\top y - z \leq x_0, Cx + Dy + E(x)u + ze \geq b \right\}$$

HL: Actually, we get an UB if  $y$  is feasible for the second stage... and the dual is directly bounded...

REMARK 1.

HL: Comment on the name “Farkas separation”.

### 2.3. Solving the separation problem with continuous second stage.

In this section, we focus on the specific case in which  $\tilde{Y} = \mathbb{R}^{n_y}$ . In particular, we discuss different ways to solve the separation problem.

#### 2.3.1. Optimality separation.

HL: todo: recall max-min formulation with  $\tilde{Y} = \mathbb{R}^{n_y}$

*KKT-based separation.* Recall the second-stage primal problem

$$\begin{aligned} \min_y \quad & d^\top y \\ \text{s.t.} \quad & Cx + Dy + E(x)u \geq b. \end{aligned}$$

Because it is linear, the KKT conditions are both necessary and sufficient. Hence, any point  $(y, \lambda)$  is a primal-dual solution to the second-stage problem if and only if it satisfies the following KKT system:

$$Cx + Dy + E(x)u \geq b, \quad D^\top \lambda = d, \quad \lambda \geq 0, \quad (Cx + Dy + E(x)u - b)^\top \lambda = 0.$$

In the seminal paper Zeng and Zhao (2013), the authors propose to replace the second-stage problem by its KKT conditions. The resulting separation problem then reads

$$\max_{u, y, \lambda} \quad d^\top y \tag{15a}$$

$$\text{s.t.} \quad u \in U, \tag{15b}$$

$$Cx + Dy + E(x)u \geq b, \tag{15c}$$

$$D^\top \lambda = d, \quad \lambda \geq 0, \tag{15d}$$

$$(Cx + Dy + E(x)u - b)^\top \lambda = 0. \tag{15e}$$

This problem is a bilinear optimization problem which can be solved using standard nonlinear techniques. An alternative approach is to linearize constraints (15e) by introducing auxiliary binary variables. However, this approach requires to compute bounds on the dual variables  $\lambda$  which, to the best of our knowledge, cannot be efficiently done without exploiting problem-specific knowledge. Nevertheless, this additional work has been shown to be beneficial since solving the resulting mixed-integer linear problem is typically easier than solving the nonlinear problem. Now, assume that you know that there always exists dual solutions which satisfy  $\lambda \leq M$  for some diagonal matrix  $M \geq 0$ . Then, the complementarity constraints (15e) can be replaced by

$$0 \leq \lambda \leq Mz, \quad 0 \leq Cx + Dy + E(x)u - b \leq M \circ (e - z), \quad z \in \{0, 1\}^{m_y}.$$

One final note. In practice, choosing a wrong value for  $M$  may result in a CCG scheme which is no longer convergent. Hence, it is necessary that the bounds  $M$  be valid. On the contrary, choosing a too large value for  $M$  leads to bad performance.

*Duality-based separation.* Recall the primal second-stage problem

$$\begin{aligned} \min_y \quad & d^\top y \\ \text{s.t.} \quad & Cx + Dy + E(x)u \geq b. \end{aligned}$$

Assume that it is feasible and bounded. Then, it attains the same optimal objective value as its dual

$$\begin{aligned} \max_{\lambda} \quad & (b - Cx - E(x)u)^\top \lambda \\ \text{s.t.} \quad & D^\top \lambda = d, \\ & \lambda \geq 0. \end{aligned}$$



*Duality-KKT-based separation.*

HL: Dualize inner min, take KKT of the max over  $u$ .

2.3.2. *Feasibility separation.*

HL: todo: add max-min formulation with  $\tilde{Y} = \mathbb{R}^{n_y}$

$$Y^+(x, u) := \{(y, z) : Cx + Dy + E(x)u + ze \geq b, \quad z \geq 0\}.$$

$$\max_{u \in U} \min_{(y, s) \in Y^+(x, x_0, u)} z.$$

*KKT-based separation.*

HL: todo

*Duality-based separation.*

HL: todo

2.3.3. *Avoiding optimality separation.*

HL: todo: recall max-min formulation with  $\tilde{Y} = \mathbb{R}^{n_y}$

$$Y^{*+}(x, x_0, u) := \{(y, z) : x_0 + z \geq d^\top y, \quad Cx + Dy + E(x)u + ze \geq b, \quad z \geq 0\}.$$

$$\max_{u \in U} \min_{(y, s) \in Y^{*+}(x, x_0, u)} z.$$

*KKT-based separation.*

$$\min_{y, z} z, \tag{18a}$$

$$\text{s.t.} \quad x_0 + z \geq d^\top y, \tag{18b}$$

$$Cx + Dy + E(x)u + ze \geq b, \tag{18c}$$

$$z \geq 0. \tag{18d}$$

The dual reads

$$\max_{\lambda, \lambda_0, \mu} -x_0 \lambda_0 + (b - Cx - E(x)u)^\top \lambda \tag{19a}$$

$$\text{s.t.} \quad D^\top \lambda - d \lambda_0 = 0, \tag{19b}$$

$$\lambda_0 + e^\top \lambda + \mu = 1, \tag{19c}$$

$$\lambda_0, \lambda, \mu \geq 0. \tag{19d}$$

Complementarity constraints are given as

$$(x_0 + z - d^\top y) \lambda_0 = 0, \quad (Cx + Dy + E(x)u + ze - b)^\top \lambda = 0, \quad z \mu = 0.$$

*Duality-based separation.*

HL: todo

*Duality-based separation for 0/1 uncertainty sets.* In the special case where the uncertainty set is either a binary set, i.e.,  $U \subseteq \{0, 1\}^{n_u}$ , or a polytope whose extreme points are all binary, i.e.,  $\text{vert}(U) \subseteq \{0, 1\}^{n_u}$ , Ayoub and Poss (2016) develop an alternative approach to solve the separation problem. Consider again the dual problem (19). The authors exploit the fact that worst-case scenarios are always extreme points of the uncertainty set. Hence, the separation problem can be modeled

as

$$\max_{u, \lambda, \lambda_0} \quad -x_0 \lambda_0 + (b - Cx - E(x)u)^\top \lambda \quad (20a)$$

$$\text{s.t.} \quad D^\top \lambda - d\lambda_0 = 0, \quad \lambda, \lambda_0 \geq 0, \quad \lambda + \lambda_0 \leq 1, \quad (20b)$$

$$u \in U \cap \{0, 1\}^{n_u}. \quad (20c)$$

Then, observe that products between  $u_k$  and  $\lambda_i$  can be linearized exactly using the following constraints ensuring  $w_{ik} = \lambda_i u_k$

$$0 \leq w_{ik} \leq \lambda_i, \quad w_{ik} \leq u_k, \quad w_{ik} \geq \lambda_i - 1 + u_k, \quad (21)$$

for all  $i = 1, \dots, m_y$  and all  $k = 1, \dots, n_u$ . Overall, the separation problem is given by

$$\begin{aligned} \max_{u, \lambda, \lambda_0, w} \quad & -x_0 \lambda_0 + (b - Cx)^\top \lambda - \sum_{i=1}^{m_y} \sum_{k=1}^{n_u} E_{ik}(x) w_{ij} \\ \text{s.t.} \quad & (20b)-(20c), (21). \end{aligned}$$

#### 2.4. Solving the separation problem with mixed-integer second stage.

We now consider the general case in which  $\tilde{Y} = \mathbb{R}^{p_y} \times \mathbb{Z}^{n_y - p_y}$ .

HL: Approaches are

- MibS
- CCG Anirudh with big-M and warning with ref to new paper
- Farkas and cut generation with binary uncertainty set (new)

#### 2.5. Initializing the scenario pool.

##### 2.5.1. Min and max initialization.

HL: todo

##### 2.5.2. User scenarios.

HL: todo

##### 2.5.3. The zero-th iteration.

HL: Omitting epigraph to get one  $x \in X$  and separate.

### 3. Example: The uncapacitated facility location problem with facility disruption

We consider an uncapacitated facility location problem (UFLP) in which facilities are subject to uncertain disruptions as studied in Cheng et al. (2021). To that end, let  $V_1$  be a set of facilities location and let  $V_2$  be a set customers. For each facility  $i \in V_1$ , we let  $f_i$  denote the opening cost and  $q_i$  its capacity. Each customer  $j \in V_2$  is associated to a given demand  $d_j$  and a marginal penalty for unmet demand  $p_j$ . Each connection  $(i, j) \in V_1 \times V_2$  has a unitary transportation cost noted  $c_{ij}$ . The deterministic uncapacitated facility location problem can be modeled as

$$\min_{x, y, z} \quad \sum_{i \in V_1} f_i x_i + \sum_{i \in V_1} \sum_{j \in V_2} c_{ij} d_j y_{ij} + \sum_{j \in V_2} p_j d_j z_j \quad (23a)$$

$$\text{s.t.} \quad \sum_{i \in V_1} y_{ij} + z_j = 1, \quad \text{for all } j \in V_2, \quad (23b)$$

$$y_{ij} \leq x_i, \quad \text{for all } i \in V_1, \text{ for all } j \in V_2, \quad (23c)$$

$$y_{ij} \geq 0, z_j \geq 0, \quad \text{for all } i \in V_1, j \in V_2, \quad (23d)$$

$$x_i \in \{0, 1\}, \quad \text{for all } i \in V_1. \quad (23e)$$

The uncertain ingredient of the problem under consideration is that some facilities can be made unavaible. If this is the case, we say that a given facility is disrupted. We consider the binary budgeted knapsack uncertainty set

$$U := \left\{ u \in \{0, 1\}^{|V_1|} : \sum_{i \in V_1} u_i \leq \Gamma \right\},$$

where, for all facility  $i \in V_1$ ,  $u_i = 1$  if and only if facility  $i$  is disrupted. The parameter  $\Gamma$  controls the maximum number of facilities which can be disrupted at the same time and is part of the model. As it typically occurs in real-world applications, we assume that facilities have to be planned before any disruption can be anticipated while deciding the operational decisions of serving customers from facilities can be delayed at a later instant, where disrupted facilities are known. Hence, the two-stage robust problem reads

$$\min_{x \in \{0, 1\}^{|V_1|}} \left\{ \sum_{i \in V_1} f_i x_i + \max_{u \in U} \min_{y \in Y(x, u)} \sum_{i \in V_1} \sum_{j \in V_2} c_{ij} y_{ij} \right\},$$

where the second-stage feasible set  $Y(x, u)$  is defined for a given first-stage decision  $x \in \{0, 1\}^{|V_1|}$  and a given scenario  $u \in U$  as

$$Y(x, u) := \left\{ y \in \mathbb{R}^{|V_1| \times |V_2|} : (23b)-(23d) \text{ and } y_{ij} \leq 1 - u_i, \text{ for all } i \in V_1 \right\}.$$

The goal of this example is to show how to implement a CCG algorithm to solve this problem. To do this, we first need to describe how the adversarial problem can be solved. This is the subject of the next section.

**3.1. Modeling the robust UFLP with facility disruption in idol.** As presented in Chapter 11, we first need to model the deterministic model (23). To this end, we will use the method `Problems::FLP::read_instance_2021_Cheng_et_al(const std::string&)` to read an instance file from Cheng et al. (2021). Such instances can be found at [https://drive.google.com/drive/folders/1Gy\\_guJIuLv52ruY89m4Tgrz49FiMspzn?usp=sharing](https://drive.google.com/drive/folders/1Gy_guJIuLv52ruY89m4Tgrz49FiMspzn?usp=sharing). With this, we can read an instance as follows.

```
1  const auto instance = Problems::FLP::←
    read_instance_2021_Cheng_et_al("/path/to/instance.txt");
2  const unsigned int n_customers = instance.n_customers();
3  const unsigned int n_facilities = instance.n_facilities();
```

The deterministic model is rather straightforward to model.

```
1  Env env;
2  Model model(env);
3
4  // Create variables
5  const auto x = model.add_vars(Dim<1>(n_facilities),
6                                0, 1, Binary, 0, "x");
7  const auto y = model.add_vars(Dim<2>(n_facilities, n_customers),
8                                0, Inf, Continuous, 0, "y");
9  const auto z = model.add_vars(Dim<1>(n_customers),
10                                0, Inf, Continuous, 0, "z");
11
12 // Create assignment constraints
13 for (auto j : Range(n_customers)) {
14     auto lhs = idol_Sum(i, Range(n_facilities), y[i][j]) + z[j];
15     model.add_ctr(lhs <= instance.capacity(i));
16 }
17
18 // Create activation constraints
```

```

19   for (auto i : Range(n_facilities)) {
20       for (auto j : Range(n_customers)) {
21           model.add_ctr(y[i][j] <= x[i]);
22       }
23   }
24
25   // Create objective function
26   auto objective =
27       idol_Sum(i, Range(n_facilities),
28               instance.fixed_cost(i) * x[i] +
29               idol_Sum(j, Range(n_customers),
30                       instance.per_unit_transportation_cost(i,j) *
31                           instance.demand(j) * y[i][j]
32                   ) +
33               idol_Sum(j, Range(n_customers),
34                       instance.per_unit_penalty(j) * instance.demand(j) * z[j]
35                   );
36   model.set_obj_expr(std::move(objective));

```

Next, we need to declare the two-stage structure, i.e., describe what variable and what constraint is part of the second-stage problem. This is done through the `Bilevel::Description` class. By default, all variables and constraints are defined as first-stage variables and constraints. Here, the second-stage variables are  $y$  and  $z$  while all constraints are second-stage constraints. Hence, the following code snippet.

```

1   Bilevel::Description bilevel_description(env);
2   for (auto j : Range(n_customers)) {
3       bilevel_description.make_lower_level(z[j]);
4       for (auto i : Range(n_facilities)) {
5           bilevel_description.make_lower_level(y[i][j]);
6       }
7   }

```

Note that, here, we do not define any coupling constraint.

To end our modeling of the robust UFLP, we need to define two more things: the uncertainty set and the uncertain coefficients in the second-stage. Let's start with the uncertainty set. Here, we use  $\Gamma = 2$ .

```

1   Model uncertainty_set(env);
2   const double Gamma = 2;
3   const auto u = uncertainty_set.add_vars(Dim<1>(n_facilities),
4                                           0, 1, Binary, 0, "u");
5   uncertainty_set.add_ctr(
6       idol_Sum(i, Range(n_facilities), u[i]) <= Gamma
7   );

```

Finally, we need to describe where this parameter appears in the deterministic model. We do this through the `Robust::Description` class. To do this, we will first need to identify the constraints which are uncertain, i.e., the activation constraints (23c). We can do so, e.g., by relying on the indices of the constraints within the model we just created. Indeed, we know that the constraint " $y_{ij} \leq x_i$ " has an index equal to  $|V_1| + i|V_2| + j$  for all  $i \in V_1$  and all  $j \in V_2$ . Another way could have been to store these constraints in a separate container or to rely on the constraints' name. In the uncertain version, the activation constraint " $y_{ij} \leq x_i$ " is changed by adding the term " $-x_i u_i$ " to it. Hence, the following code snippet.

```

1   Robust::Description robust_description(uncertainty_set);
2   for (auto i : Range(n_facilities)) {
3       for (auto j : Range(n_customers)) {
4

```

```

5      // Get activation constraint (i,j)
6      const auto index = n_customers + i * n_customers + j;
7      const auto& c = model.get_ctr_by_index(index);
8
9      // Add uncertain term
10     robust_description.set_uncertain_mat_coeff(c, x[i], u[i]);
11 }
12 }

```

In a nutshell, the call to `Robust::Description::set_uncertain_mat_coeff` tells `idol` that an uncertain coefficient for  $x$  should be added and equals  $u_i$ , i.e.,

$$y_{ij} - x_i \leq 0 \quad \longrightarrow \quad y_{ij} - x_i + x_i u_i \leq 0.$$

That's it, our robust UFLP is now completely modeled in `idol`.

**3.2. Preparing the column-and-constraint optimizer.** We are now ready to create our optimizer for solving problem (23). For CCG, the optimizer has an optimizer factory called `Robust::ColumnAndConstraintGeneration` which can be used as follows.

```

1      auto ccg = Robust::ColumnAndConstraintGeneration(
2                      robust_description,
3                      bilevel_description
4                  );

```

As you can see, it is necessary to provide both the bilevel description—so that `idol` knows what variables and constraints are in the first- or second-stage—, and the robust description—so that uncertain coefficients as well as the uncertainty set are also known. When we are done configuring the CCG algorithm, we will be able to call the `Model::use` method to set up the optimizer factory and the `Model::optimize` method to solve the problem.

```

1      // Once we are done configuring ccg
2      model.use(ccg);
3      model.optimize();

```

Before we can do so, we need to at least give some information on how to solve each optimization problems that appear as a sub-problem in the CCG algorithm. There are essentially two types of problems to solve: the master problem and the adversarial problem. For the master problem, we will simply use `Gurobi`. We do this through the following code.

```

1      ccg.with_master_optimizer(Gurobi());

```

Then, we need to describe how to solve the adversarial problem, a.k.a., the separation problem. This is the subject of the next section.

**3.3. Solving the separation problem.** During the CCG algorithm, at every iteration, the master problem is solved. If the master problem is infeasible, we know that the original two-stage robust problem is infeasible. Otherwise, let  $(x, y^1, \dots, y^k)$  for some  $k$  corresponding to the number of scenarios present in the master problem. Given this point, and a current estimate on the second-stage costs  $x_0$ , we need to show that either  $x$  is a feasible first-stage decision with a second-stage cost no more than  $x_0$ , or exhibit a scenario  $\hat{u} \in U$  such that either  $Y(x, \hat{u}) = \emptyset$  or the best second-stage decision  $y^*$  given  $x$  and  $\hat{u}$  is such that  $d^\top y^* > x_0$ .

We describe five different ways to perform this separation exactly and one heuristic approach along with their implementation in `idol`. Note that, in the case of the UFLP, the second-stage problem is always feasible. Thus, we “only” need to check that  $x$  is an optimal first-stage decision.

### 3.3.1. Optimality separation.

*Duality-based separation.* The first approach is the well-known duality-based approach which consists in replacing the second-stage primal problem by its dual and linearize products between dual and uncertain variables in the objective function. Let's see how it's done. First, since the second-stage problem is always feasible and bounded, the primal problem attains the same objective value as its dual. Hence, the primal second-stage problem can be replaced by its dual problem

$$\max_{\alpha, \beta, \gamma, \delta} \sum_{j \in V_2} \alpha_j + \sum_{i \in V_1} \sum_{j \in V_2} x_i (1 - u_i) \beta_{ij} \quad (24a)$$

$$\text{s.t. } \alpha_j + \beta_{ij} + \gamma_{ij} = c_{ij} d_j, \quad \text{for all } i \in V_1, j \in V_2, \quad (24b)$$

$$\alpha_j + \delta_j = p_j d_j, \quad \text{for all } j \in V_2, \quad (24c)$$

$$\alpha_j \in \mathbb{R}, \beta_{ij} \leq 0, \gamma_{ij} \geq 0, \delta_j \geq 0, \quad \text{for all } i \in V_1, j \in V_2. \quad (24d)$$

Hence, the separation problem reads

$$\begin{aligned} \max_{u, \alpha, \beta, \gamma, \delta} \quad & \sum_{j \in V_2} \alpha_j + \sum_{i \in V_1} \sum_{j \in V_2} x_i (1 - u_i) \beta_{ij} \\ \text{s.t.} \quad & u \in U, (24b)-(24d). \end{aligned}$$

To implement this technique in *idol*, we can use the `Bilevel::MinMax::StrongDuality` optimizer factory. It can be configured as follows.

```
1 auto duality_based = Bilevel::MinMax::StrongDuality();
2 duality_based.with_optimizer(Gurobi());
3
4 ccg.add_optimality_separation_optimizer(duality_based);
```

By doing so, the optimizer factory `duality_based` will be called every time a new separation problem needs to be solved. Note that, as such, we did not provide any bounds on the dual variables. Hence, the dualized model will be solved as a nonlinear problem by *Gurobi*; see also Chapter 9 on bilevel problems with continuous lower-level problems. However, computational experiments have shown that linearizing those terms is beneficial whenever possible. Hence, we now show how such bounds can be passed and exploited by *idol*.

It is shown in appendix B.1 of Cheng et al. (2021) that a dual solution always exists with  $\beta_{ij} \geq \min\{0, d_j(c_{ij} - p_j)\} =: M_{ij}$ . Thus, we can linearize the products  $w_{ij} := u_i \beta_{ij}$  by introducing binary variables  $v_{ij}$  such that

$$M_{ij} v_{ij} \leq w_{ij} \leq 0, \quad \beta_{ij} \leq w_{ij} \leq \beta_{ij} - M_{ij}(1 - v_{ij}), \quad v_{ij} \in \{0, 1\}, \quad (25)$$

for all  $i \in V_1$  and all  $j \in V_2$ . Note that *idol* can do this automatically. To use this feature, we simply need to provide these bounds to *idol*. As discussed in Chapter 9, this can be done by means of a child class of the `Reformulators::KKT::BoundProvider` class which will return the necessary bounds. Here is one possible implementation. Note that the only bounds which need to be returned in this case are those on  $\beta$  since  $\beta$  is the variable involved in a product.

```
1 class UFLPBondProvider
2 : public idol::Reformulators::KKT::BoundProvider {
3 public:
4     // TODO
5 };
```

The complete code for configuring the CCG algorithm reads as follows.

```
1 auto ccg = Robust::ColumnAndConstraintGeneration(
2     robust_description,
3     bilevel_description
```

```

4         );
5
6     ccg.with_master_optimizer(Gurobi());
7
8     auto duality_based = Bilevel::MinMax::StrongDuality();
9     duality_based.with_optimizer(Gurobi());
10    duality_based.with_bound_provider(UFLPBoundProvider());
11
12    ccg.add_optimality_separation_optimizer(duality_based);
13
14    model.use(ccg);
15    model.optimize();

```

With this code, the dualized model is now being linearized before being solved by Gurobi, i.e., it is solved as a mixed-integer linear problem. Note that there is also a third way to solve the dualized model which is by means of SOS1 constraints. This can be implemented by using the following code.

```

1     auto duality_based = Bilevel::MinMax::StrongDuality();
2     duality_based.with_optimizer(Gurobi());
3     duality_based.with_sos1_constraints();

```

*KKT-based separation.* Another way to solve the separation problem is to exploit the KKT optimality conditions of the second-stage problem. These conditions are necessary and sufficient for a primal-dual point to be optimal for the second-stage primal and dual problems. These conditions are stated as

$$\begin{aligned}
 \text{primal feasibility} &= \begin{cases} \sum_{i \in V_1} y_{ij} + z_j = 1, & \text{for all } j \in V_2, \\ y_{ij} \leq x_i(1 - u_i), & \text{for all } i \in V_1, \text{ for all } j \in V_2, \\ y_{ij} \geq 0, z_j \geq 0, & \text{for all } i \in V_1, j \in V_2, \end{cases} \\
 \text{dual feasibility} &= \begin{cases} \alpha_j + \beta_{ij} + \gamma_{ij} = c_{ij}d_j, & \text{for all } i \in V_1, j \in V_2, \\ \alpha_j + \delta_j = p_jd_j, & \text{for all } j \in V_2, \end{cases} \\
 \text{stationarity} &= \begin{cases} \alpha_j \in \mathbb{R}, \beta_{ij} \leq 0, \gamma_{ij} \geq 0, \delta_j \geq 0, & \text{for all } i \in V_1, j \in V_2. \end{cases} \\
 \text{complementarity} &= \begin{cases} \beta_{ij}(y_{ij} - x_i(1 - u_i)) = 0, & \text{for all } i \in V_1, \text{ for all } j \in V_2, \\ \gamma_{ij}y_{ij} = 0, & \text{for all } i \in V_1, \text{ for all } j \in V_2, \\ \delta_jz_j = 0, & \text{for all } i \in V_1, \text{ for all } j \in V_2. \end{cases}
 \end{aligned} \tag{26}$$

Hence, the separation problem can be formulated as

$$\max_{u, y, \alpha, \beta, \gamma, \delta} \{d^\top y : u \in U, (26)\}.$$

To implement this technique in `idol`, we can use the `Bilevel::KKT` optimizer factory. It can be configured as follows.

```

1     auto kkt = Bilevel::KKT();
2     kkt.with_optimizer(Gurobi());
3
4     ccg.add_optimality_separation_optimizer(kkt);

```

By doing so, the optimizer factory `kkt` will be called every time a new separation problem needs to be solved. Note that, as such, we did not provide any bounds on the dual variables. Hence, the KKT reformulation will be solved as a nonlinear problem by Gurobi. However, it is well-known that linearizing the complementarity constraints with binary variables yields much better performance. Hence, we now show how such bounds can be passed and exploited by `idol`.

Recall from the previous section that there always exists a dual solution such that  $\beta_{ij} \geq \min\{0, d_j(c_{ij} - p_j)\}$ . From that, we easily show that there exists a dual

solution satisfying

$$\begin{aligned} 0 &\leq \alpha_j \leq p_j d_j, & \text{for all } j \in V_2, \\ 0 &\geq \beta_{ij} \geq \min\{0, d_j(c_{ij} - p_j)\}, & \text{for all } i \in V_1, \text{ for all } j \in V_2, \\ 0 &\leq \gamma_{ij} \leq c_{ij} d_j + \max\{0, d_j(p_j - c_{ij})\}, & \text{for all } i \in V_1, \text{ for all } j \in V_2, \\ 0 &\leq \delta_j \leq p_j d_j, & \text{for all } j \in V_2. \end{aligned}$$

We also have the trivial bounds

$$\begin{aligned} 0 &\leq y_{ij} \leq 1, & \text{for all } i \in V_1, j \in V_2, \\ 0 &\leq z_j \leq 1, & \text{for all } j \in V_2, \\ 0 &\leq x_i(1 - u_i) - y_{ij} \leq 1, & \text{for all } i \in V_1, \text{ for all } j \in V_2. \end{aligned}$$

With these, the complementarity constraints can be linearized by means of binary variables. In the following code snippet, we enrich our implementation of the `UFLPBoundProvider` class so that it returns bounds for all dual variables.

```
1 // TODO ...
```

The complete code for configuring the CCG algorithm reads as follows.

```
1 auto ccg = Robust::ColumnAndConstraintGeneration(
2     robust_description,
3     bilevel_description
4 );
5
6 ccg.with_master_optimizer(Gurobi());
7
8 auto kkt = Bilevel::KKT();
9 kkt.with_optimizer(Gurobi());
10 kkt.with_bound_provider(UFLPBoundProvider());
11
12 ccg.add_optimality_separation_optimizer(kkt);
13
14 model.use(ccg);
15 model.optimize();
```

With this code, the KKT single-level reformulation is now being linearized before being solved by Gurobi, i.e., it is solved as a mixed-integer linear problem. Note that there is also a third way to solve the KKT reformulation which is by means of SOS1 constraints. This can be implemented by using the following code.

```
1 auto ktk = Bilevel::KKT();
2 kkt.with_optimizer(Gurobi());
3 kkt.with_sos1_constraints();
```

*Separation by the external bilevel solver MibS.*

HL: todo

*Heuristic separation with PADM.*

HL: todo

*3.3.2. Avoiding optimality separation.*

*KKT-based separation.*

HL: todo

*KKT-based separation for 0/1 uncertainty sets.*

HL: todo

*Heuristic separation with PADM.*

HL: todo



#### 4. Example: The capacitated facility location problem with facility disruption

**4.1. Problem statement.** We now consider a capacitated variant of the facility location problem studied in the previous section. This problem can be modeled as model (23) with the following additional constraint:

$$\sum_{j \in V_2} d_j y_{ij} \leq q_i, \quad \text{for all } i \in V_1.$$

#### 5. Robust bilevel problems with wait-and-see followers

#### 6. Example: The uncapacitated facility location problem with wait-and-see follower and facility disruption

##### 6.1. Solving the separation problem.

##### 6.1.1. *Optimality separation.*

## CHAPTER 15

# **K-adaptability**



## CHAPTER 16

# Objective uncertainty



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