Homework 5

MAE 598

Design Optimization

Submitted by:

Shubham M Chaudhary

ASU ID - 1219648911

The problem statement is given :

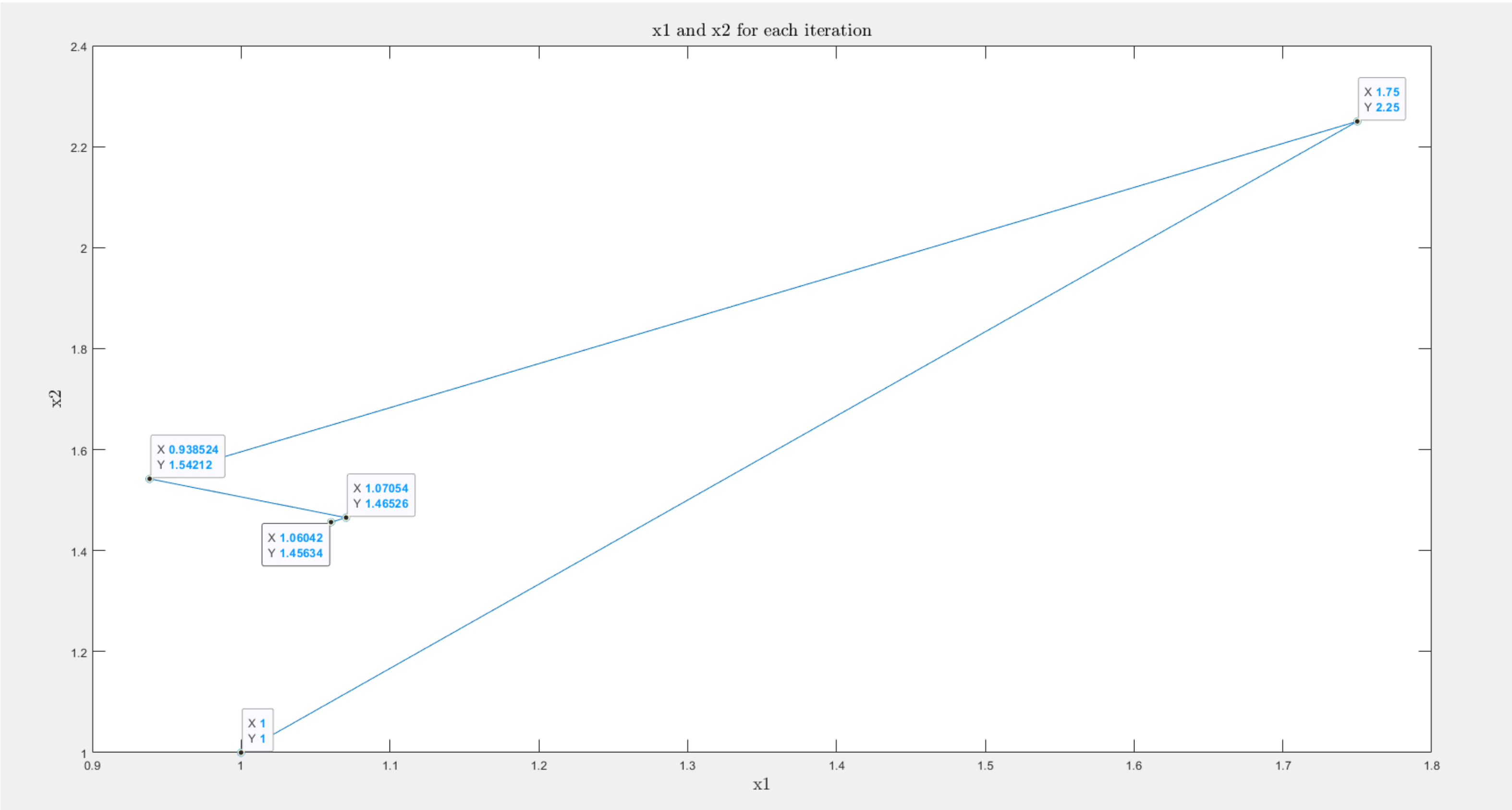
Problem 1

(100 points) Consider the following problem.

$$\begin{aligned} \min\ f &= x_1^2 + (x_2 - 3)^2 \\ \text{s.t. } g_1 &= x_2^2 - 2x_1 \le 0 \\ g_2 &= (x_2 - 1)^2 + 5x_1 - 15 \le 0 \end{aligned}$$

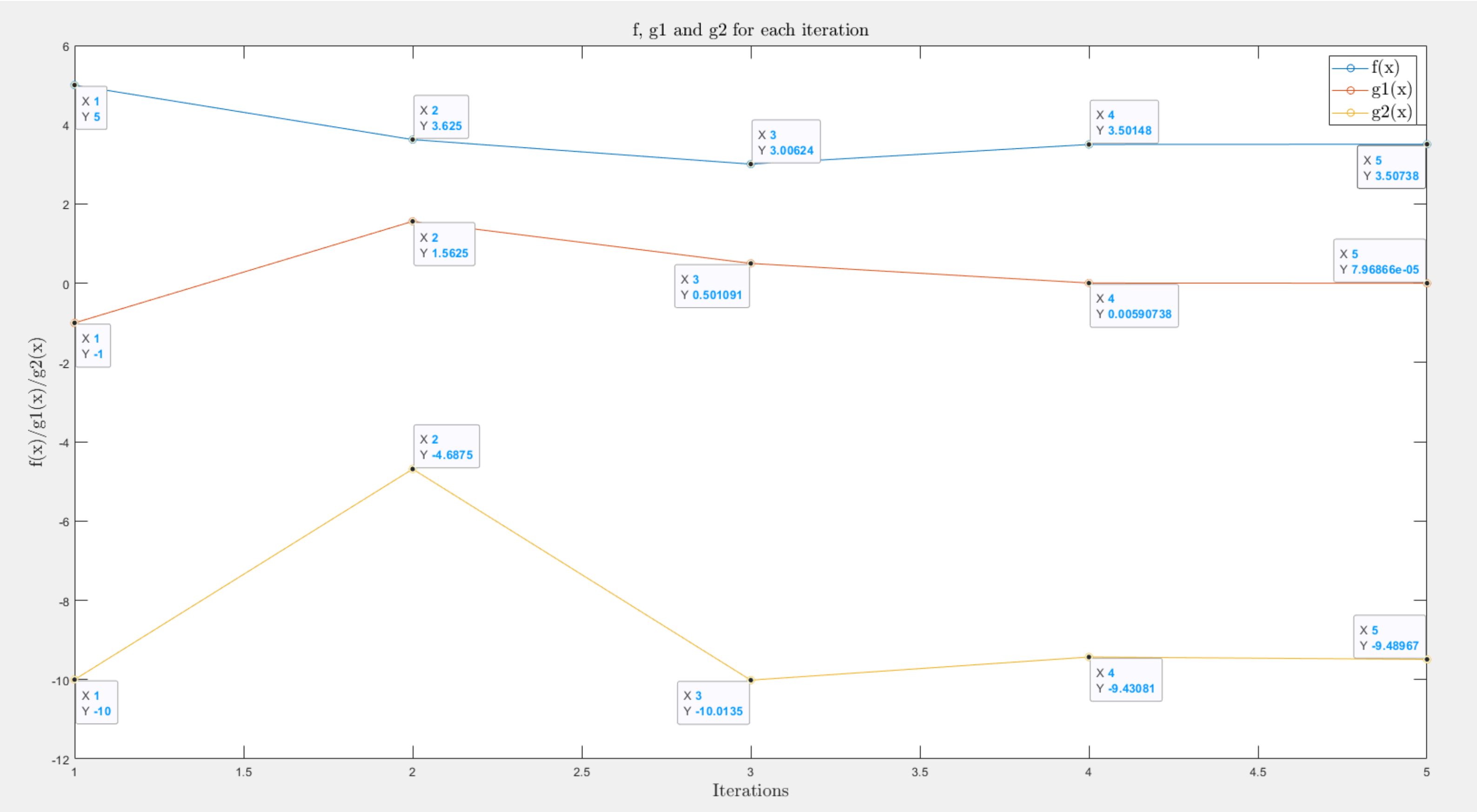
Implement an SQP algorithm with line search to solve this problem, starting from $\mathbf{x}_0 = (1, 1)^T$. Incorporate the QP subproblem. Use BFGS approximation for the Hessian of the Lagrangian. Use the merit function and Armijo Line Search to find the step size.

The Results are given below:



The most optimal point is at x1 = 1.06042 and x2 = 1.45634 and at that point f = 3.5075, g1 = 0 and g2 = -9.4898.

The plots of f, g1 and g2 for each iterations is given in figure below.



The Matlab code id given below:

```
%%%%%%%%%%%%%% Main Entrance %%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
%%%%%%%%%%%%%% By Max Yi Ren and Emrah Bayrak %%%%%%%%%%%%%%%%%%%%%%%%%%%%%

% Instruction: Please read through the code and fill in blanks
% (marked by ***). Note that you need to do so for every involved
% function, i.e., m files.

%% Optional overhead
clear; % Clear the workspace
close all; % Close all windows

%% Optimization settings
% Here we specify the objective function by giving the function handle to a
% variable, for example:
f = @(x)objective(x); % replace with your objective function
% In the same way, we also provide the gradient of the
% objective:
df = @(x)objectiveg(x); % replace accordingly

g = @(x)constraint(x);
dg = @(x)constraintg(x);
```

```
% Note that explicit gradient and Hessian information is only optional.
% However, providing these information to the search algorithm will save
% computational cost from finite difference calculations for them.

% % Specify algorithm
opt.alg = 'myqp'; % 'myqp' or 'matlabqp'

% Turn on or off line search. You could turn on line search once other
% parts of the program are debugged.
opt.linesearch = true; % false or true

% Set the tolerance to be used as a termination criterion:
opt.eps = 1e-3;

% Set the initial guess:
x0 = [1;1];

% Feasibility check for the initial point.
if max(g(x0)>0)
    errordlg('Infeasible intial point! You need to start from a feasible
one!');
    return
end
%% Run optimization
% Run your implementation of SQP algorithm. See mysqp.m
solution = mysqp(f, df, g, dg, x0, opt);

%% Report
report(solution,f,g);

%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%



%%%%%%%%%%%%%% Sequential Quadratic Programming Implementation with BFGS
%%%%%%%%%%%%%%%%
%%%%%%%%%%%%%% By Max Yi Ren and Emrah Bayrak %%%%%%%%%%%%%%%%%%%%%%%%%%%%%


%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
```

%Objective functions:

```
function f = objective(x)
f = x(1)^2 + (x(2)-3)^2;
end


function df = objectiveg(x)
df = zeros(1,2);
df(1) = 2*x(1);
df(2) = 2*(x(2)-3);
end
```

```
function g = constraint(x)
g = zeros(2,1);
g(1) = x(2)^2 - 2*x(1);
g(2) = (x(2)-1)^2 + 5*x(1) - 15;
end


function dg = constraintg(x)
dg = zeros(2,2);
dg(1,1) = -2;
dg(1,2) = 2*x(2);
dg(2,1) = 5;
dg(2,2) = 2*(x(2)-1);
end
```

%Mysqp function:

```
function solution = mysqp(f, df, g, dg, x0, opt)
    % Set initial conditions

    x = x0; % Set current solution to the initial guess

    % Initialize a structure to record search process
    solution = struct('x',[]);
    solution.x = [solution.x, x]; % save current solution to solution.x

    % Initialization of the Hessian matrix
    W = eye(numel(x));              % Start with an identity Hessian matrix
    % Initialization of the Lagrange multipliers
    mu_old = zeros(size(g(x)));     % Start with zero Lagrange multiplier
estimates
    % Initialization of the weights in merit function
    w = zeros(size(g(x)));          % Start with zero weights

    % Set the termination criterion
    gnorm = norm(df(x) + mu_old'*dg(x)); % norm of Largangian gradient

    while gnorm>opt.eps % if not terminated

        % Implement QP problem and solve
        if strcmp(opt.alg, 'myqp')
            % Solve the QP subproblem to find s and mu (using your own
method)
            [s, mu_new] = solveqp(x, W, df, g, dg);
        else
            % Solve the QP subproblem to find s and mu (using MATLAB's
solver)
            qpalg = optimset('Algorithm', 'active-set', 'Display', 'off');
            [s,~,~,~,lambda] = quadprog(W,[df(x)]',dg(x),-g(x),[], [], [],
[], x0,  qpalg);
            mu_new = lambda.ineqlin;
        end

        % opt.linesearch switches line search on or off.
        % You can first set the variable "a" to different constant values
and see how it
        % affects the convergence.
```

```
        if opt.linesearch
            [a, w] = lineSearch(f, df, g, dg, x, s, mu_old, w);
        else
            a = 0.1;
        end

        % Update the current solution using the step
        dx = a*s;                   % Step for x
        x = x + dx;                 % Update x using the step

        % Update Hessian using BFGS. Use equations (7.36), (7.73) and
(7.74)
        % Compute y_k
        y_k = [df(x) + mu_new'*dg(x) - df(x-dx) - mu_new'*dg(x-dx)]';
        % Compute theta
        if dx'*y_k >= 0.2*dx'*W*dx
            theta = 1;
        else
            theta = (0.8*dx'*W*dx)/(dx'*W*dx-dx'*y_k);
        end
        % Compute  dg_k
        dg_k = theta*y_k + (1-theta)*W*dx;
        % Compute new Hessian
        W = W + (dg_k*dg_k')/(dg_k'*dx) - ((W*dx)*(W*dx)')/(dx'*W*dx);

        % Update termination criterion:
        gnorm = norm(df(x) + mu_new'*dg(x)); % norm of Largangian gradient
        mu_old = mu_new;

        % save current solution to solution.x
        solution.x = [solution.x, x];
    end
end

%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
```

%Linesearch function:

```
%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%

%The following code performs line search on the merit function

%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%

% Armijo line search
function [a, w] = lineSearch(f, df, g, dg, x, s, mu_old, w_old)
    t = 0.1; % scale factor on current gradient: [0.01, 0.3]
    b = 0.8; % scale factor on backtracking: [0.1, 0.8]
    a = 1; % maximum step length

    D = s;                  % direction for x

    % Calculate weights in the merit function using eaution (7.77)
    w = max(abs(mu_old), 0.5*(w_old+abs(mu_old)));
    % terminate if line search takes too long
    count = 0;
    while count<100
        % Calculate phi(alpha) using merit function in (7.76)
```

```
        phi_a = f(x + a*D) + w'*abs(min(0, -g(x+a*D)));

        % Caluclate psi(alpha) in the line search using phi(alpha)
        phi0 = f(x) + w'*abs(min(0, -g(x)));         % phi(0)
        dphi0 = df(x)*D + w'*((dg(x)*D).*(g(x)>0)); % phi'(0) change df to
df'
        psi_a = phi0 +  t*a*dphi0;                   % psi(alpha)
        % stop if condition satisfied
        if phi_a<psi_a
            break;
        else
            % backtracking
            a = a*b;
            count = count + 1;
        end
    end
end

%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%
```

%Solve QP function:

```
%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%

%The following code solves the QP subproblem using active set strategy

%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%%

function [s, mu0] = solveqp(x, W, df, g, dg)
    % Implement an Active-Set strategy to solve the QP problem given by
    % min      (1/2)*s'*W*s + c'*s
    % s.t.     A*s-b <= 0
    %
    % where As-b is the linearized active contraint set

    % Strategy should be as follows:
    % 1-) Start with empty working-set
    % 2-) Solve the problem using the working-set
    % 3-) Check the constraints and Lagrange multipliers
    % 4-) If all constraints are staisfied and Lagrange multipliers are
positive, terminate!
    % 5-) If some Lagrange multipliers are negative or zero, find the most
negative one
    %     and remove it from the active set
    % 6-) If some constraints are violated, add the most violated one to
the working set
    % 7-) Go to step 2


    % Compute c in the QP problem formulation
    c = [df(x)]';

    % Compute A in the QP problem formulation
    A0 = dg(x);

    % Compute b in the QP problem formulation
    b0 = -g(x);
```

```
% Initialize variables for active-set strategy
stop = 0;            % Start with stop = 0
% Start with empty working-set
A = [];          % A for empty working-set
b = [];          % b for empty working-set
% Indices of the constraints in the working-set
active = [];     % Indices for empty-working set

while ~stop  % Continue until stop = 1
    % Initialize all mu as zero and update the mu in the working set
    mu0 = zeros(size(g(x)));
    % Extract A corresponding to the working-set
    A = A0(active,:);
    % Extract b corresponding to the working-set
    b = b0(active);

    % Solve the QP problem given A and b
    [s, mu] = solve_activeset(x, W, c, A, b);
    % Round mu to prevent numerical errors (Keep this)
    mu = round(mu*1e12)/1e12;

    % Update mu values for the working-set using the solved mu values
    mu0(active) = mu;

    % Calculate the constraint values using the solved s values
    gcheck = A0*s-b0;

    % Round constraint values to prevent numerical errors (Keep this)
    gcheck = round(gcheck*1e12)/1e12;

    % Variable to check if all mu values make sense.
    mucheck = 0;        % Initially set to 0

    % Indices of the constraints to be added to the working set
    Iadd = [];                % Initialize as empty vector
    % Indices of the constraints to be added to the working set
    Iremove = [];             % Initialize as empty vector

    % Check mu values and set mucheck to 1 when they make sense
    if (numel(mu) == 0)
        % When there no mu values in the set
        mucheck = 1;          % OK
    elseif min(mu) > 0
        % When all mu values in the set positive
        mucheck = 1;          % OK
    else
        % When some of the mu are negative
        % Find the most negaitve mu and remove it from acitve set
        [~,Iremove] = min(mu);  % Use Iremove to remove the constraint
    end

    % Check if constraints are satisfied
    if max(gcheck) <= 0
        % If all constraints are satisfied
        if mucheck == 1
            % If all mu values are OK, terminate by setting stop = 1
            stop = 1;
        end
    else
```

```
            % If some constraints are violated
            % Find the most violated one and add it to the working set
            [~,Iadd] = max(gcheck); % Use Iadd to add the constraint
        end
        % Remove the index Iremove from the working-set
        active = setdiff(active, active(Iremove));
        % Add the index Iadd to the working-set
        active = [active, Iadd];

        % Make sure there are no duplications in the working-set (Keep
this)
        active = unique(active);
    end
end
```

%Solve active set function:

```
function [s, mu] = solve_activeset(x, W, c, A, b)
    % Given an active set, solve QP

    % Create the linear set of equations given in equation (7.79)
    M = [W, A'; A, zeros(size(A,1))];
    U = [-c; b];
    U1 = transpose(U);
    sol = M\U;           % Solve for s and mu
    s = sol(1:numel(x));                % Extract s from the solution
    mu = sol(numel(x)+1:numel(sol));    % Extract mu from the solution
end
```

%Report function:

```
function a = report(solution,f,g)
fig = 1;
a = solution.x;
figure(fig)
fig = fig+1;
cla
plot(a(1,:),a(2,:),'-o');
ti=title('x1 and x2 for each iteration');
set(ti,'Interpreter','latex');
set(ti,'FontSize',15);
x=xlabel('x1');
set(x,'Interpreter','latex');
set(x,'FontSize',15);
y=ylabel('x2');
set(y,'Interpreter','latex');
set(y,'FontSize',15);
hold off;
f1 = [];
g1 = [];
g2 = [];
for i = 1:5
f1(i) = f(solution.x(:,i));
gi = g(solution.x(:,i));
g1(i) = gi(1);
g2(i) = gi(2);
```

```
end
disp(g1);
disp(g2);
figure(fig)
fig = fig+1;
cla
iter = [1 2 3 4 5];
plot(iter,f1,'-o',iter,g1,'-o',iter,g2,'-o');
ti=title('f, g1 and g2 for each iteration');
L=legend({'f(x)','g1(x)','g2(x)'});
set(L,'Interpreter','latex');
set(L,'FontSize',15);
set(L,'Location','northeast');
set(ti,'Interpreter','latex');
set(ti,'FontSize',15);
x=xlabel('Iterations');
set(x,'Interpreter','latex');
set(x,'FontSize',15);
y=ylabel('f(x)/g1(x)/g2(x)');
set(y,'Interpreter','latex');
set(y,'FontSize',15);
hold off;
end
```