Lectures 11 & 12: Convex Optimization

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(Slides from Stepehn Boyd)

Bibliography

- Boyd – Chapters 1-5

Mathematical optimization

(mathematical) optimization problem

$$\begin{array}{ll}\text{minimize} & f_0(x)\\ \text{subject to} & f_i(x) \le b_i, \quad i = 1, \ldots, m\end{array}$$

- $x = (x_1, \ldots, x_n)$: optimization variables
- $f_0 : \mathbf{R}^n \to \mathbf{R}$: objective function
- $f_i : \mathbf{R}^n \to \mathbf{R}$, $i = 1, \ldots, m$: constraint functions

optimal solution $x^\star$ has smallest value of f_0 among all vectors that satisfy the constraints

Solving optimization problems

general optimization problem

- very difficult to solve
- methods involve some compromise, $e.g.$, very long computation time, or not always finding the solution

exceptions: certain problem classes can be solved efficiently and reliably

- least-squares problems
- linear programming problems
- convex optimization problems

Least-squares

$$\text{minimize} \quad \|Ax - b\|_2^2$$

solving least-squares problems

- analytical solution: $x^\star = (A^TA)^{-1}A^Tb$
- reliable and efficient algorithms and software
- computation time proportional to n^2k ($A \in \mathbf{R}^{k\times n}$); less if structured
- a mature technology

using least-squares

- least-squares problems are easy to recognize
- a few standard techniques increase flexibility ($e.g.$, including weights, adding regularization terms)

Linear programming

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & a_i^T x \leq b_i, \quad i = 1, \ldots, m \end{array}$$

solving linear programs

- no analytical formula for solution
- reliable and efficient algorithms and software
- computation time proportional to $n^2 m$ if $m \geq n$; less with structure
- a mature technology

using linear programming

- not as easy to recognize as least-squares problems
- a few standard tricks used to convert problems into linear programs ($e.g.$, problems involving ℓ_1- or ℓ_∞-norms, piecewise-linear functions)

Convex optimization problem

$$\begin{array}{ll} \text{minimize} & f_0(x) \\ \text{subject to} & f_i(x) \leq b_i, \quad i = 1, \ldots, m \end{array}$$

- objective and constraint functions are convex:

$$f_i(\alpha x + \beta y) \leq \alpha f_i(x) + \beta f_i(y)$$

  if $\alpha + \beta = 1$, $\alpha \geq 0$, $\beta \geq 0$

- includes least-squares problems and linear programs as special cases

solving convex optimization problems

- no analytical solution
- reliable and efficient algorithms
- computation time (roughly) proportional to $\max\{n^3, n^2m, F\}$, where F is cost of evaluating f_i's and their first and second derivatives
- almost a technology

using convex optimization

- often difficult to recognize
- many tricks for transforming problems into convex form
- surprisingly many problems can be solved via convex optimization

Nonlinear optimization

traditional techniques for general nonconvex problems involve compromises

local optimization methods (nonlinear programming)

- find a point that minimizes f_0 among feasible points near it
- fast, can handle large problems
- require initial guess
- provide no information about distance to (global) optimum

global optimization methods

- find the (global) solution
- worst-case complexity grows exponentially with problem size

these algorithms are often based on solving convex subproblems

Brief history of convex optimization

theory (convex analysis): ca1900–1970

algorithms

- 1947: simplex algorithm for linear programming (Dantzig)
- 1960s: early interior-point methods (Fiacco & McCormick, Dikin, . . .)
- 1970s: ellipsoid method and other subgradient methods
- 1980s: polynomial-time interior-point methods for linear programming (Karmarkar 1984)
- late 1980s–now: polynomial-time interior-point methods for nonlinear convex optimization (Nesterov & Nemirovski 1994)

applications

- before 1990: mostly in operations research; few in engineering
- since 1990: many new applications in engineering (control, signal processing, communications, circuit design, . . .); new problem classes (semidefinite and second-order cone programming, robust optimization)

Outline

1. Convex Sets
2. Convex Functions
3. Convex Optimization Problems
4. ML examples
5. Duality
6. Margin-based Classification

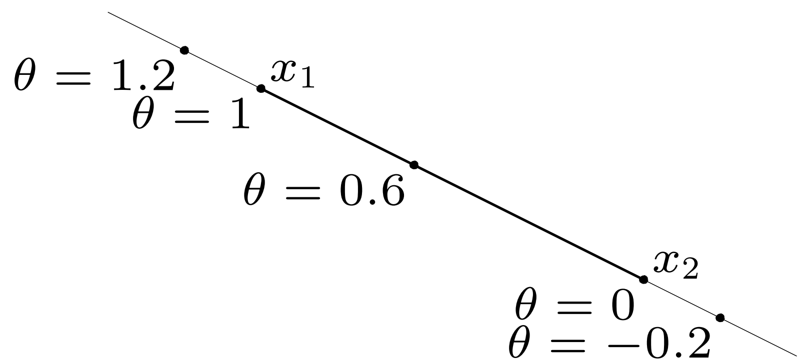
1. Convex sets

- Affine and convex sets
- Hyper-planes, half-spaces and polyhedra
- Operations that preserve convexity

Affine set

line through x_1, x_2: all points

$$x = \theta x_1 + (1 - \theta) x_2 \qquad (\theta \in \mathbf{R})$$



affine set: contains the line through any two distinct points in the set

example: solution set of linear equations $\{x \mid Ax = b\}$

(conversely, every affine set can be expressed as solution set of system of linear equations)

Convex set

line segment between x_1 and x_2: all points

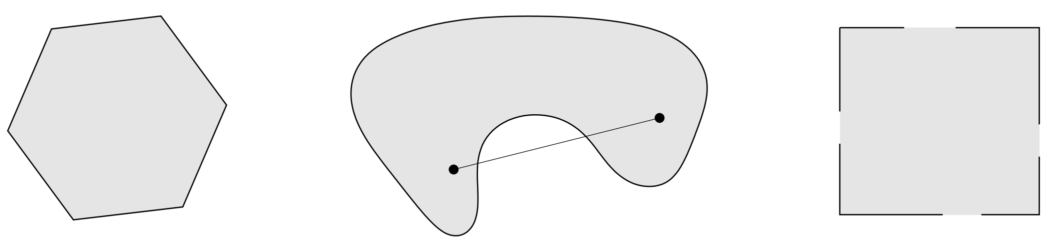
$$x = \theta x_1 + (1-\theta)x_2$$

with $0 \le \theta \le 1$

convex set: contains line segment between any two points in the set

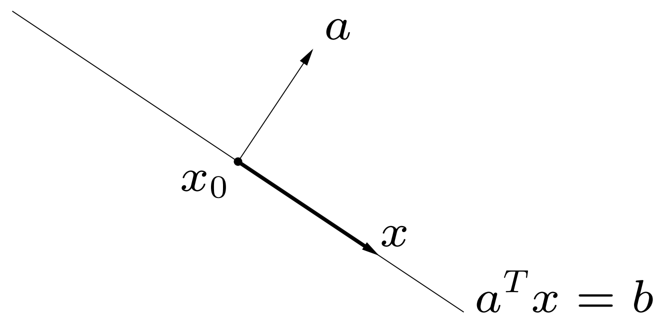
$$x_1, x_2 \in C, \quad 0 \le \theta \le 1 \quad \Longrightarrow \quad \theta x_1 + (1-\theta)x_2 \in C$$

examples (one convex, two nonconvex sets)

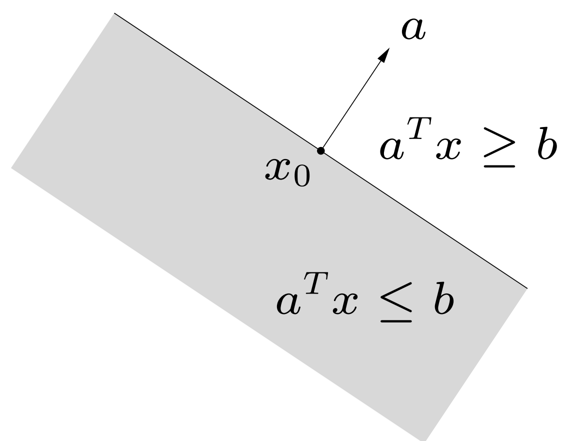


Hyperplanes and halfspaces

hyperplane: set of the form $\{x \mid a^T x = b\}$ ($a \neq 0$)



halfspace: set of the form $\{x \mid a^T x \leq b\}$ ($a \neq 0$)

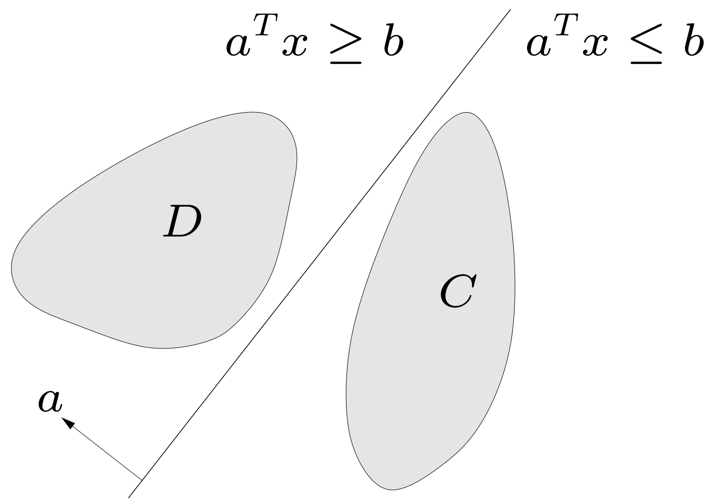


- a is the normal vector
- hyperplanes are affine and convex; halfspaces are convex

Separating hyperplane theorem

if C and D are nonempty disjoint convex sets, there exist $a \neq 0$, b s.t.

$$a^T x \leq b \text{ for } x \in C, \qquad a^T x \geq b \text{ for } x \in D$$



the hyperplane $\{x \mid a^T x = b\}$ separates C and D

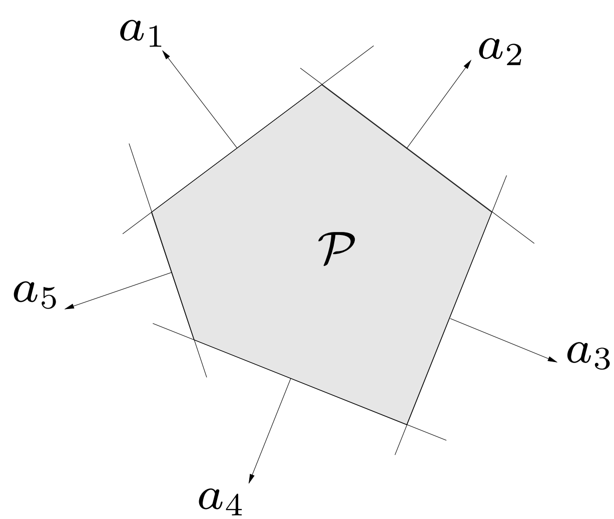
strict separation requires additional assumptions ($e.g.$, C is closed, D is a singleton)

Polyhedra

solution set of finitely many linear inequalities and equalities

$$Ax \preceq b, \qquad Cx = d$$

($A \in \mathbf{R}^{m\times n}$, $C \in \mathbf{R}^{p\times n}$, $\preceq$ is componentwise inequality)



polyhedron is intersection of finite number of halfspaces and hyperplanes

Operations that preserve convexity

practical methods for establishing convexity of a set C

1. apply definition

$$x_1, x_2 \in C, \quad 0 \le \theta \le 1 \quad \Longrightarrow \quad \theta x_1 + (1-\theta) x_2 \in C$$

2. show that C is obtained from simple convex sets (hyperplanes, halfspaces, norm balls, . . .) by operations that preserve convexity
   - intersection
   - affine functions
   - perspective function
   - linear-fractional functions

Intersection

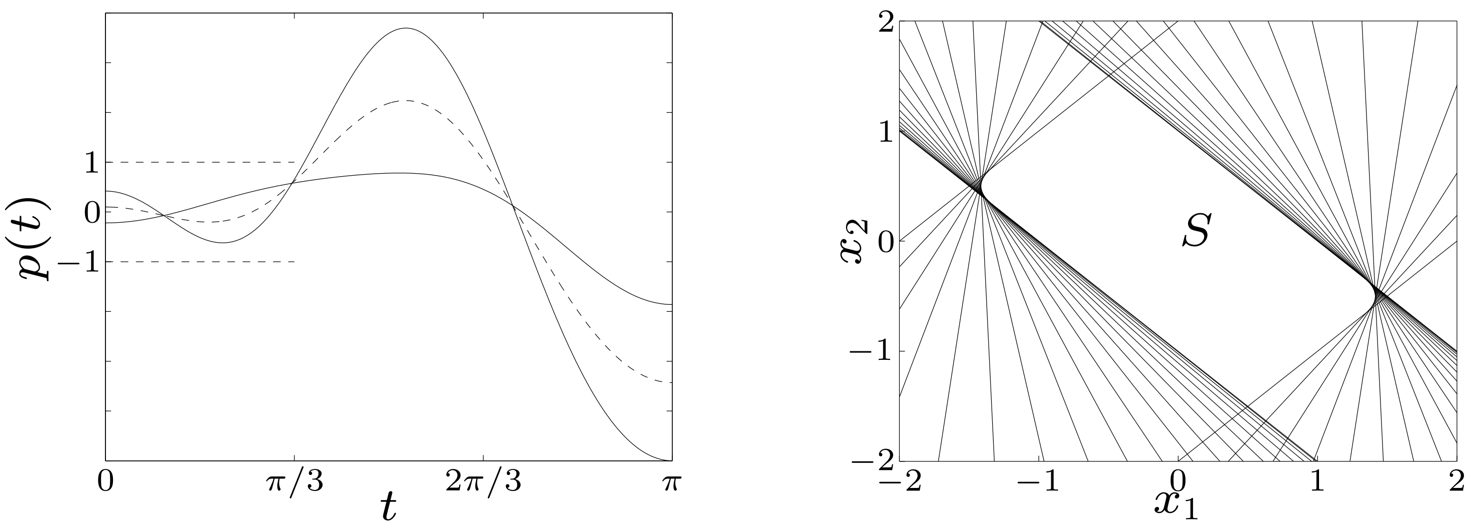
the intersection of (any number of) convex sets is convex

example:

$$S = \{x \in \mathbf{R}^m \mid |p(t)| \leq 1 \text{ for } |t| \leq \pi/3\}$$

where $p(t) = x_1 \cos t + x_2 \cos 2t + \cdots + x_m \cos mt$

for $m = 2$:



Affine function

suppose $f : \mathbf{R}^n \to \mathbf{R}^m$ is affine ($f(x) = Ax + b$ with $A \in \mathbf{R}^{m \times n}$, $b \in \mathbf{R}^m$)

- the image of a convex set under f is convex

$$S \subseteq \mathbf{R}^n \text{ convex} \quad \Longrightarrow \quad f(S) = \{f(x) \mid x \in S\} \text{ convex}$$

- the inverse image $f^{-1}(C)$ of a convex set under f is convex

$$C \subseteq \mathbf{R}^m \text{ convex} \quad \Longrightarrow \quad f^{-1}(C) = \{x \in \mathbf{R}^n \mid f(x) \in C\} \text{ convex}$$

examples

- scaling, translation, projection
- solution set of linear matrix inequality $\{x \mid x_1A_1 + \cdots + x_mA_m \preceq B\}$ (with $A_i, B \in \mathbf{S}^p$)
- hyperbolic cone $\{x \mid x^TPx \le (c^Tx)^2,\ c^Tx \ge 0\}$ (with $P \in \mathbf{S}^n_+$)

2. Convex functions

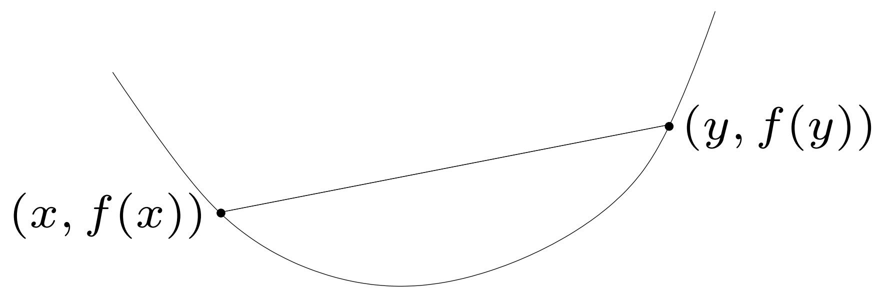
- Basic properties and examples
- Operations that preserve convexity
- Log-concave and log-convex functions

Definition

$f : \mathbf{R}^n \to \mathbf{R}$ is convex if $\mathbf{dom}\, f$ is a convex set and

$$f(\theta x + (1-\theta)y) \leq \theta f(x) + (1-\theta) f(y)$$

for all $x, y \in \mathbf{dom}\, f$, $0 \leq \theta \leq 1$



- f is concave if $-f$ is convex
- f is strictly convex if $\mathbf{dom}\, f$ is convex and

$$f(\theta x + (1-\theta)y) < \theta f(x) + (1-\theta) f(y)$$

for $x, y \in \mathbf{dom}\, f$, $x \neq y$, $0 < \theta < 1$

Examples on R

convex:

- affine: $ax + b$ on **R**, for any $a, b \in$ **R**
- exponential: e^{ax}, for any $a \in$ **R**
- powers: x^α on $\mathbf{R}_{++}$, for $\alpha \geq 1$ or $\alpha \leq 0$
- powers of absolute value: $|x|^p$ on **R**, for $p \geq 1$
- negative entropy: $x \log x$ on $\mathbf{R}_{++}$

concave:

- affine: $ax + b$ on **R**, for any $a, b \in$ **R**
- powers: x^α on $\mathbf{R}_{++}$, for $0 \leq \alpha \leq 1$
- logarithm: $\log x$ on $\mathbf{R}_{++}$

Examples on $\mathbf{R}^n$ and $\mathbf{R}^{m\times n}$

affine functions are convex and concave; all norms are convex

examples on $\mathbf{R}^n$

- affine function $f(x) = a^T x + b$
- norms: $\|x\|_p = (\sum_{i=1}^n |x_i|^p)^{1/p}$ for $p \geq 1$; $\|x\|_\infty = \max_k |x_k|$

examples on $\mathbf{R}^{m\times n}$ ($m \times n$ matrices)

- affine function

$$f(X) = \mathbf{tr}(A^T X) + b = \sum_{i=1}^m \sum_{j=1}^n A_{ij} X_{ij} + b$$

- spectral (maximum singular value) norm

$$f(X) = \|X\|_2 = \sigma_{\max}(X) = (\lambda_{\max}(X^T X))^{1/2}$$

First-order condition

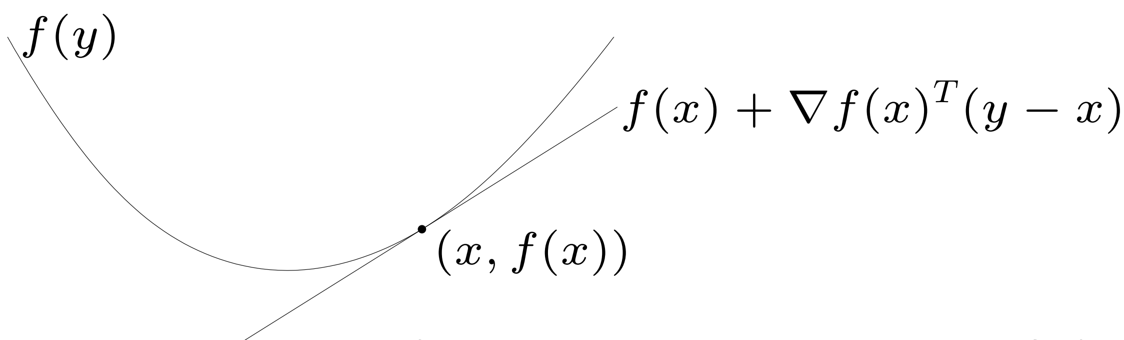
f is **differentiable** if $\mathbf{dom}\, f$ is open and the gradient

$$\nabla f(x) = \left(\frac{\partial f(x)}{\partial x_1}, \frac{\partial f(x)}{\partial x_2}, \ldots, \frac{\partial f(x)}{\partial x_n} \right)$$

exists at each $x \in \mathbf{dom}\, f$

1st-order condition: differentiable f with convex domain is convex iff

$$f(y) \geq f(x) + \nabla f(x)^T (y - x) \quad \text{for all } x, y \in \mathbf{dom}\, f$$



first-order approximation of f is global underestimator

Second-order conditions

f is **twice differentiable** if $\mathbf{dom}\, f$ is open and the Hessian $\nabla^2 f(x) \in \mathbf{S}^n$,

$$\nabla^2 f(x)_{ij} = \frac{\partial^2 f(x)}{\partial x_i \partial x_j}, \quad i, j = 1, \ldots, n,$$

exists at each $x \in \mathbf{dom}\, f$

2nd-order conditions: for twice differentiable f with convex domain

- f is convex if and only if

$$\nabla^2 f(x) \succeq 0 \quad \text{for all } x \in \mathbf{dom}\, f$$

- if $\nabla^2 f(x) \succ 0$ for all $x \in \mathbf{dom}\, f$, then f is strictly convex

Examples

quadratic function: $f(x) = (1/2)x^T Px + q^T x + r$ (with $P \in \mathbf{S}^n$)

$$\nabla f(x) = Px + q, \qquad \nabla^2 f(x) = P$$

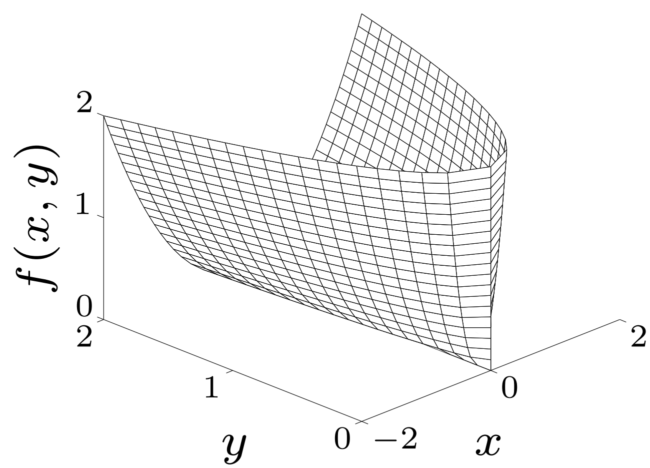
convex if $P \succeq 0$

least-squares objective: $f(x) = \|Ax - b\|_2^2$

$$\nabla f(x) = 2A^T(Ax - b), \qquad \nabla^2 f(x) = 2A^T A$$

convex (for any A)

quadratic-over-linear: $f(x, y) = x^2/y$



$$\nabla^2 f(x, y) = \frac{2}{y^3} \begin{bmatrix} y \\ -x \end{bmatrix} \begin{bmatrix} y \\ -x \end{bmatrix}^T \succeq 0$$

convex for $y > 0$

Jensen's inequality

basic inequality: if f is convex, then for $0 \leq \theta \leq 1$,

$$f(\theta x + (1-\theta)y) \leq \theta f(x) + (1-\theta)f(y)$$

extension: if f is convex, then

$$f(\mathbf{E}\, z) \leq \mathbf{E}\, f(z)$$

for any random variable z

basic inequality is special case with discrete distribution

$$\mathbf{prob}(z = x) = \theta, \qquad \mathbf{prob}(z = y) = 1 - \theta$$

Operations that preserve convexity

practical methods for establishing convexity of a function

1. verify definition (often simplified by restricting to a line)

2. for twice differentiable functions, show $\nabla^2 f(x) \succeq 0$

3. show that f is obtained from simple convex functions by operations that preserve convexity

   - nonnegative weighted sum
   - composition with affine function
   - pointwise maximum and supremum
   - composition
   - minimization
   - perspective

Positive weighted sum & composition with affine function

nonnegative multiple: αf is convex if f is convex, $\alpha \geq 0$

sum: $f_1 + f_2$ convex if f_1, f_2 convex (extends to infinite sums, integrals)

composition with affine function: $f(Ax + b)$ is convex if f is convex

examples

- log barrier for linear inequalities

$$f(x) = -\sum_{i=1}^{m} \log(b_i - a_i^T x), \qquad \mathbf{dom}\, f = \{x \mid a_i^T x < b_i, i = 1, \ldots, m\}$$

- (any) norm of affine function: $f(x) = \|Ax + b\|$

Pointwise maximum

if $f_1, \ldots, f_m$ are convex, then $f(x) = \max\{f_1(x), \ldots, f_m(x)\}$ is convex

examples

- piecewise-linear function: $f(x) = \max_{i=1,\ldots,m}(a_i^T x + b_i)$ is convex
- sum of r largest components of $x \in \mathbf{R}^n$:

$$f(x) = x_{[1]} + x_{[2]} + \cdots + x_{[r]}$$

  is convex ($x_{[i]}$ is ith largest component of x)

  proof:

$$f(x) = \max\{x_{i_1} + x_{i_2} + \cdots + x_{i_r} \mid 1 \leq i_1 < i_2 < \cdots < i_r \leq n\}$$

Pointwise supremum

if $f(x, y)$ is convex in x for each $y \in \mathcal{A}$, then

$$g(x) = \sup_{y \in \mathcal{A}} f(x, y)$$

is convex

examples

- support function of a set C: $S_C(x) = \sup_{y \in C} y^T x$ is convex
- distance to farthest point in a set C:

$$f(x) = \sup_{y \in C} \|x - y\|$$

- maximum eigenvalue of symmetric matrix: for $X \in \mathbf{S}^n$,

$$\lambda_{\max}(X) = \sup_{\|y\|_2 = 1} y^T X y$$

Composition with scalar functions

composition of $g : \mathbf{R}^n \to \mathbf{R}$ and $h : \mathbf{R} \to \mathbf{R}$:

$$f(x) = h(g(x))$$

f is convex if $\begin{array}{l} g \text{ convex, } h \text{ convex, } \tilde{h} \text{ nondecreasing} \\ g \text{ concave, } h \text{ convex, } \tilde{h} \text{ nonincreasing} \end{array}$

- proof (for $n = 1$, differentiable g, h)

$$f''(x) = h''(g(x))g'(x)^2 + h'(g(x))g''(x)$$

- note: monotonicity must hold for extended-value extension $\tilde{h}$

examples

- $\exp g(x)$ is convex if g is convex
- $1/g(x)$ is convex if g is concave and positive

Vector composition

composition of $g : \mathbf{R}^n \to \mathbf{R}^k$ and $h : \mathbf{R}^k \to \mathbf{R}$:

$$f(x) = h(g(x)) = h(g_1(x), g_2(x), \ldots, g_k(x))$$

f is convex if g_i convex, h convex, $\tilde{h}$ nondecreasing in each argument
g_i concave, h convex, $\tilde{h}$ nonincreasing in each argument

proof (for $n = 1$, differentiable g, h)

$$f''(x) = g'(x)^T \nabla^2 h(g(x)) g'(x) + \nabla h(g(x))^T g''(x)$$

examples

- $\sum_{i=1}^m \log g_i(x)$ is concave if g_i are concave and positive
- $\log \sum_{i=1}^m \exp g_i(x)$ is convex if g_i are convex

Minimization

if $f(x, y)$ is convex in (x, y) and C is a convex set, then

$$g(x) = \inf_{y \in C} f(x, y)$$

is convex

examples

- $f(x, y) = x^T A x + 2x^T B y + y^T C y$ with

$$\begin{bmatrix} A & B \\ B^T & C \end{bmatrix} \succeq 0, \qquad C \succ 0$$

  minimizing over y gives $g(x) = \inf_y f(x, y) = x^T(A - BC^{-1}B^T)x$

  g is convex, hence Schur complement $A - BC^{-1}B^T \succeq 0$

- distance to a set: $\mathbf{dist}(x, S) = \inf_{y \in S} \|x - y\|$ is convex if S is convex

Log-concave and log-convex functions

a positive function f is log-concave if $\log f$ is concave:

$$f(\theta x + (1-\theta)y) \geq f(x)^\theta f(y)^{1-\theta} \quad \text{for } 0 \leq \theta \leq 1$$

f is log-convex if $\log f$ is convex

- powers: x^a on $\mathbf{R}_{++}$ is log-convex for $a \leq 0$, log-concave for $a \geq 0$
- many common probability densities are log-concave, *e.g.*, normal:

$$f(x) = \frac{1}{\sqrt{(2\pi)^n \det \Sigma}} e^{-\frac{1}{2}(x-\bar{x})^T \Sigma^{-1}(x-\bar{x})}$$

- cumulative Gaussian distribution function Φ is log-concave

$$\Phi(x) = \frac{1}{\sqrt{2\pi}} \int_{-\infty}^{x} e^{-u^2/2}\, du$$

Properties of log-concave functions

- twice differentiable f with convex domain is log-concave if and only if

$$f(x)\nabla^2 f(x) \preceq \nabla f(x)\nabla f(x)^T$$

  for all $x \in \mathbf{dom}\, f$

- product of log-concave functions is log-concave

- sum of log-concave functions is not always log-concave

- integration: if $f : \mathbf{R}^n \times \mathbf{R}^m \to \mathbf{R}$ is log-concave, then

$$g(x) = \int f(x,y)\, dy$$

  is log-concave (not easy to show)

3. Convex optimization problems

- Optimization problem in standard form
- Convex optimization problems
- Linear Optimization
- Quadratic optimization
- Multicriterion optimization

Optimization problem in standard form

$$
\begin{array}{ll}
\text{minimize} & f_0(x) \\
\text{subject to} & f_i(x) \leq 0, \quad i = 1, \dots, m \\
& h_i(x) = 0, \quad i = 1, \dots, p
\end{array}
$$

- $x \in \mathbf{R}^n$ is the optimization variable
- $f_0 : \mathbf{R}^n \to \mathbf{R}$ is the objective or cost function
- $f_i : \mathbf{R}^n \to \mathbf{R}$, $i = 1, \dots, m$, are the inequality constraint functions
- $h_i : \mathbf{R}^n \to \mathbf{R}$ are the equality constraint functions

optimal value:

$$
p^\star = \inf\{f_0(x) \mid f_i(x) \leq 0,\ i = 1, \dots, m,\ h_i(x) = 0,\ i = 1, \dots, p\}
$$

- $p^\star = \infty$ if problem is infeasible (no x satisfies the constraints)
- $p^\star = -\infty$ if problem is unbounded below

Optimal and locally optimal points

x is **feasible** if $x \in \mathbf{dom}\, f_0$ and it satisfies the constraints

a feasible x is **optimal** if $f_0(x) = p^\star$; X_{opt} is the set of optimal points

x is **locally optimal** if there is an $R > 0$ such that x is optimal for

$$\begin{array}{ll} \text{minimize (over } z\text{)} & f_0(z) \\ \text{subject to} & f_i(z) \leq 0, \quad i = 1, \ldots, m, \quad h_i(z) = 0, \quad i = 1, \ldots, p \\ & \|z - x\|_2 \leq R \end{array}$$

examples (with $n = 1$, $m = p = 0$)

- $f_0(x) = 1/x$, $\mathbf{dom}\, f_0 = \mathbf{R}_{++}$: $p^\star = 0$, no optimal point
- $f_0(x) = -\log x$, $\mathbf{dom}\, f_0 = \mathbf{R}_{++}$: $p^\star = -\infty$
- $f_0(x) = x \log x$, $\mathbf{dom}\, f_0 = \mathbf{R}_{++}$: $p^\star = -1/e$, $x = 1/e$ is optimal
- $f_0(x) = x^3 - 3x$, $p^\star = -\infty$, local optimum at $x = 1$

Implicit constraints

the standard form optimization problem has an **implicit constraint**

$$x \in \mathcal{D} = \bigcap_{i=0}^{m} \mathbf{dom}\, f_i \;\cap\; \bigcap_{i=1}^{p} \mathbf{dom}\, h_i,$$

- we call $\mathcal{D}$ the **domain** of the problem
- the constraints $f_i(x) \leq 0$, $h_i(x) = 0$ are the explicit constraints
- a problem is **unconstrained** if it has no explicit constraints ($m = p = 0$)

example:

$$\text{minimize} \quad f_0(x) = -\textstyle\sum_{i=1}^{k} \log(b_i - a_i^T x)$$

is an unconstrained problem with implicit constraints $a_i^T x < b_i$

Feasibility problem

$$
\begin{array}{ll}
\text{find} & x \\
\text{subject to} & f_i(x) \leq 0, \quad i = 1, \ldots, m \\
& h_i(x) = 0, \quad i = 1, \ldots, p
\end{array}
$$

can be considered a special case of the general problem with $f_0(x) = 0$:

$$
\begin{array}{ll}
\text{minimize} & 0 \\
\text{subject to} & f_i(x) \leq 0, \quad i = 1, \ldots, m \\
& h_i(x) = 0, \quad i = 1, \ldots, p
\end{array}
$$

- $p^\star = 0$ if constraints are feasible; any feasible x is optimal
- $p^\star = \infty$ if constraints are infeasible

Convex optimization problem

standard form convex optimization problem

$$\begin{array}{ll} \text{minimize} & f_0(x) \\ \text{subject to} & f_i(x) \leq 0, \quad i = 1, \dots, m \\ & a_i^T x = b_i, \quad i = 1, \dots, p \end{array}$$

- f_0, f_1, . . . , f_m are convex; equality constraints are affine
- problem is *quasiconvex* if f_0 is quasiconvex (and f_1, . . . , f_m convex)

often written as

$$\begin{array}{ll} \text{minimize} & f_0(x) \\ \text{subject to} & f_i(x) \leq 0, \quad i = 1, \dots, m \\ & Ax = b \end{array}$$

important property: feasible set of a convex optimization problem is convex

example

$$
\begin{array}{ll}
\text{minimize} & f_0(x) = x_1^2 + x_2^2 \\
\text{subject to} & f_1(x) = x_1/(1 + x_2^2) \le 0 \\
& h_1(x) = (x_1 + x_2)^2 = 0
\end{array}
$$

- f_0 is convex; feasible set $\{(x_1, x_2) \mid x_1 = -x_2 \le 0\}$ is convex
- not a convex problem (according to our definition): f_1 is not convex, h_1 is not affine
- equivalent (but not identical) to the convex problem

$$
\begin{array}{ll}
\text{minimize} & x_1^2 + x_2^2 \\
\text{subject to} & x_1 \le 0 \\
& x_1 + x_2 = 0
\end{array}
$$

Local and global optima

any locally optimal point of a convex problem is (globally) optimal

proof: suppose x is locally optimal, but there exists a feasible y with $f_0(y) < f_0(x)$

x locally optimal means there is an $R > 0$ such that

$$z \text{ feasible}, \quad \|z - x\|_2 \leq R \quad \Longrightarrow \quad f_0(z) \geq f_0(x)$$

consider $z = \theta y + (1 - \theta)x$ with $\theta = R/(2\|y - x\|_2)$

- $\|y - x\|_2 > R$, so $0 < \theta < 1/2$
- z is a convex combination of two feasible points, hence also feasible
- $\|z - x\|_2 = R/2$ and

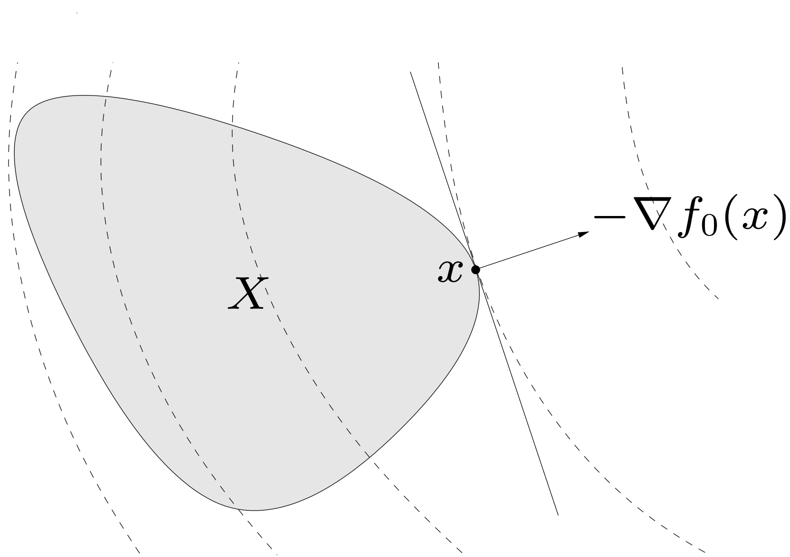
$$f_0(z) \leq \theta f_0(y) + (1 - \theta) f_0(x) < f_0(x)$$

which contradicts our assumption that x is locally optimal

Optimality criterion for differentiable f_0

x is optimal if and only if it is feasible and

$$\nabla f_0(x)^T(y - x) \geq 0 \quad \text{for all feasible } y$$



if nonzero, $\nabla f_0(x)$ defines a supporting hyperplane to feasible set X at x

- **unconstrained problem**: x is optimal if and only if

$$x \in \mathbf{dom}\, f_0, \qquad \nabla f_0(x) = 0$$

- **equality constrained problem**

$$\text{minimize} \quad f_0(x) \quad \text{subject to} \quad Ax = b$$

x is optimal if and only if there exists a ν such that

$$x \in \mathbf{dom}\, f_0, \qquad Ax = b, \qquad \nabla f_0(x) + A^T\nu = 0$$

- **minimization over nonnegative orthant**

$$\text{minimize} \quad f_0(x) \quad \text{subject to} \quad x \succeq 0$$

x is optimal if and only if

$$x \in \mathbf{dom}\, f_0, \qquad x \succeq 0, \qquad \begin{cases} \nabla f_0(x)_i \geq 0 & x_i = 0 \\ \nabla f_0(x)_i = 0 & x_i > 0 \end{cases}$$

Equivalent convex problems

two problems are (informally) **equivalent** if the solution of one is readily obtained from the solution of the other, and vice-versa

some common transformations that preserve convexity:

- **eliminating equality constraints**

$$\begin{array}{ll} \text{minimize} & f_0(x) \\ \text{subject to} & f_i(x) \leq 0, \quad i = 1, \ldots, m \\ & Ax = b \end{array}$$

  is equivalent to

$$\begin{array}{ll} \text{minimize (over } z\text{)} & f_0(Fz + x_0) \\ \text{subject to} & f_i(Fz + x_0) \leq 0, \quad i = 1, \ldots, m \end{array}$$

  where F and x_0 are such that

$$Ax = b \quad \Longleftrightarrow \quad x = Fz + x_0 \text{ for some } z$$

- **introducing equality constraints**

$$\begin{array}{ll}\text{minimize} & f_0(A_0x+b_0)\\ \text{subject to} & f_i(A_ix+b_i)\leq 0, \quad i=1,\ldots,m\end{array}$$

is equivalent to

$$\begin{array}{ll}\text{minimize (over } x,\ y_i) & f_0(y_0)\\ \text{subject to} & f_i(y_i)\leq 0, \quad i=1,\ldots,m\\ & y_i=A_ix+b_i, \quad i=0,1,\ldots,m\end{array}$$

- **introducing slack variables for linear inequalities**

$$\begin{array}{ll}\text{minimize} & f_0(x)\\ \text{subject to} & a_i^Tx\leq b_i, \quad i=1,\ldots,m\end{array}$$

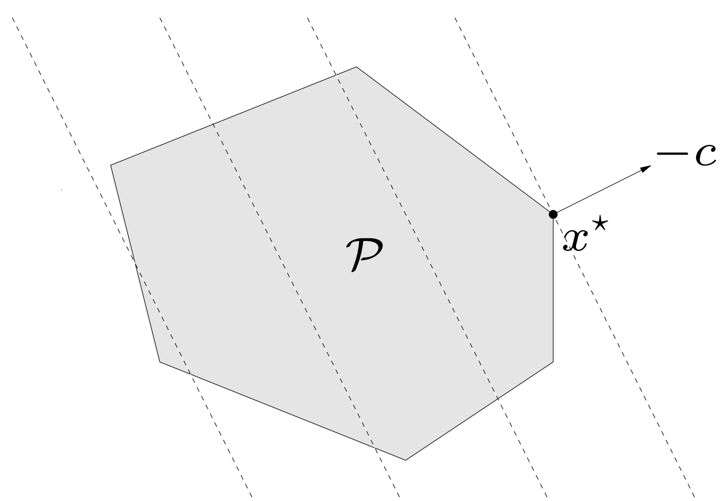
is equivalent to

$$\begin{array}{ll}\text{minimize (over } x,\ s) & f_0(x)\\ \text{subject to} & a_i^Tx+s_i=b_i, \quad i=1,\ldots,m\\ & s_i\geq 0, \quad i=1,\ldots m\end{array}$$

Linear program (LP)

$$\begin{array}{ll} \text{minimize} & c^T x + d \\ \text{subject to} & Gx \preceq h \\ & Ax = b \end{array}$$

- convex problem with affine objective and constraint functions
- feasible set is a polyhedron



Examples

diet problem: choose quantities $x_1, \ldots, x_n$ of n foods

- one unit of food j costs c_j, contains amount a_{ij} of nutrient i
- healthy diet requires nutrient i in quantity at least b_i

to find cheapest healthy diet,

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & Ax \succeq b, \quad x \succeq 0 \end{array}$$

piecewise-linear minimization

$$\text{minimize} \quad \max_{i=1,\ldots,m}(a_i^T x + b_i)$$

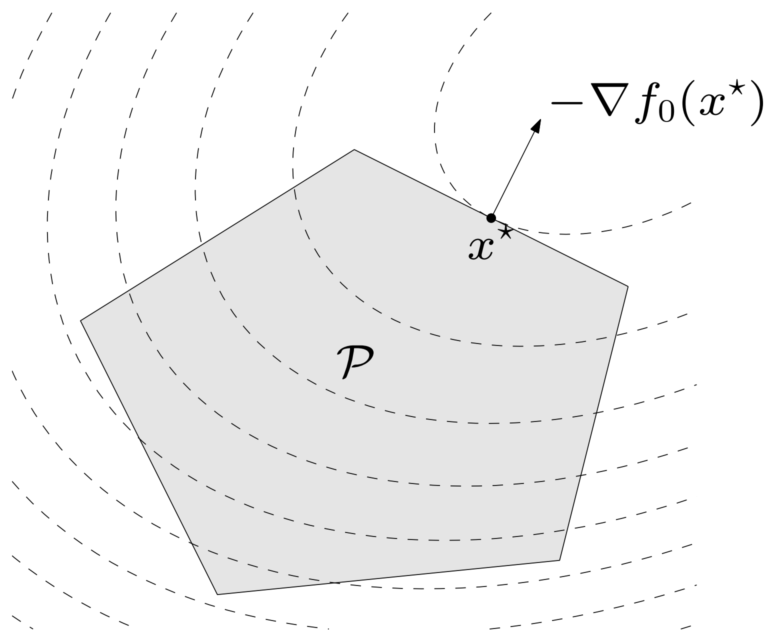
equivalent to an LP

$$\begin{array}{ll} \text{minimize} & t \\ \text{subject to} & a_i^T x + b_i \leq t, \quad i = 1, \ldots, m \end{array}$$

Quadratic program (QP)

$$\begin{array}{ll}\text{minimize} & (1/2)x^TPx + q^Tx + r \\ \text{subject to} & Gx \preceq h \\ & Ax = b\end{array}$$

- $P \in \mathbf{S}^n_+$, so objective is convex quadratic
- minimize a convex quadratic function over a polyhedron



Examples

least-squares

$$\text{minimize} \quad \|Ax - b\|_2^2$$

- analytical solution $x^\star = A^\dagger b$ ($A^\dagger$ is pseudo-inverse)
- can add linear constraints, *e.g.*, $l \preceq x \preceq u$

linear program with random cost

$$\begin{array}{ll} \text{minimize} & \bar{c}^T x + \gamma x^T \Sigma x = \mathbf{E}\, c^T x + \gamma\, \mathbf{var}(c^T x) \\ \text{subject to} & Gx \preceq h, \quad Ax = b \end{array}$$

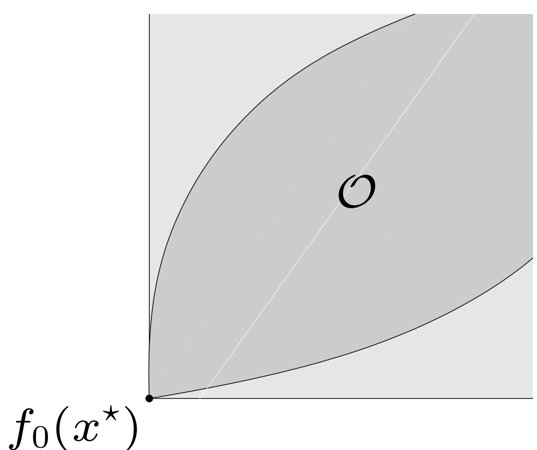
- c is random vector with mean $\bar{c}$ and covariance Σ
- hence, $c^T x$ is random variable with mean $\bar{c}^T x$ and variance $x^T \Sigma x$
- $\gamma > 0$ is risk aversion parameter; controls the trade-off between expected cost and variance (risk)

Optimal and Pareto optimal points

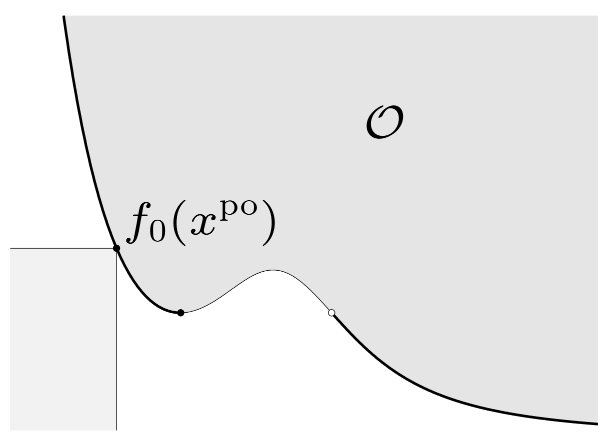
set of achievable objective values

$$\mathcal{O} = \{f_0(x) \mid x \text{ feasible}\}$$

- feasible x is **optimal** if $f_0(x)$ is the minimum value of $\mathcal{O}$
- feasible x is **Pareto optimal** if $f_0(x)$ is a minimal value of $\mathcal{O}$



$x^\star$ is optimal



x^{po} is Pareto optimal

Multicriterion optimization

vector optimization problem with $K = \mathbf{R}_+^q$

$$f_0(x) = (F_1(x), \ldots, F_q(x))$$

- q different objectives F_i; roughly speaking we want all F_i's to be small
- feasible $x^\star$ is optimal if

$$y \text{ feasible} \quad \Longrightarrow \quad f_0(x^\star) \preceq f_0(y)$$

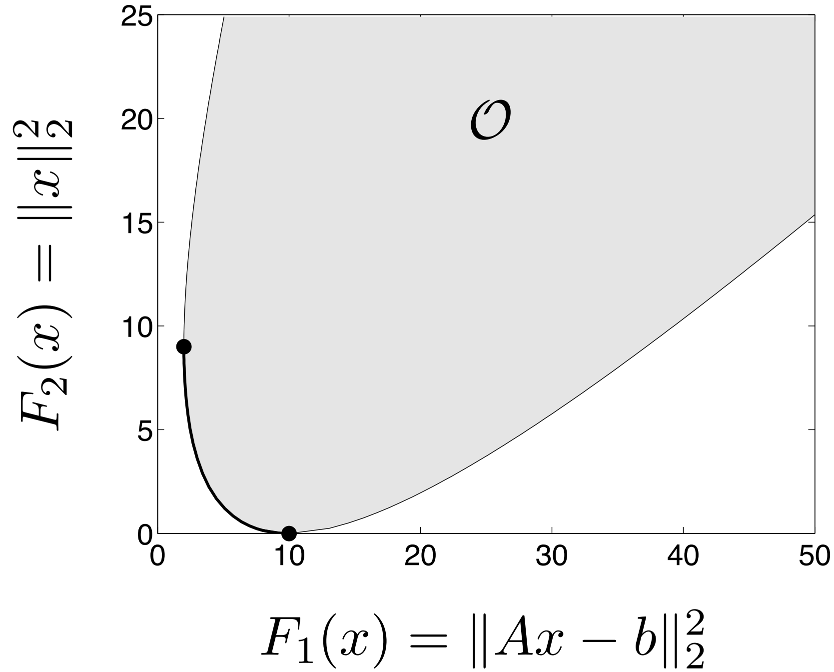
  if there exists an optimal point, the objectives are noncompeting
- feasible x^{po} is Pareto optimal if

$$y \text{ feasible}, \quad f_0(y) \preceq f_0(x^{\text{po}}) \quad \Longrightarrow \quad f_0(x^{\text{po}}) = f_0(y)$$

  if there are multiple Pareto optimal values, there is a trade-off between the objectives

Regularized least-squares

$$\text{minimize (w.r.t. } \mathbf{R}^2_+) \quad (\|Ax - b\|_2^2, \|x\|_2^2)$$



example for $A \in \mathbf{R}^{100\times 10}$; heavy line is formed by Pareto optimal points

4. ML examples

- Maximum likelihood estimation
- Logistic regression

Parametric distribution estimation

- distribution estimation problem: estimate probability density $p(y)$ of a random variable from observed values
- parametric distribution estimation: choose from a family of densities $p_x(y)$, indexed by a parameter x

maximum likelihood estimation

$$\text{maximize (over } x\text{)} \quad \log p_x(y)$$

- y is observed value
- $l(x) = \log p_x(y)$ is called log-likelihood function
- can add constraints $x \in C$ explicitly, or define $p_x(y) = 0$ for $x \notin C$
- a convex optimization problem if $\log p_x(y)$ is concave in x for fixed y

Linear measurements with IID noise

linear measurement model

$$y_i = a_i^T x + v_i, \quad i = 1, \ldots, m$$

- $x \in \mathbf{R}^n$ is vector of unknown parameters
- v_i is IID measurement noise, with density $p(z)$
- y_i is measurement: $y \in \mathbf{R}^m$ has density $p_x(y) = \prod_{i=1}^m p(y_i - a_i^T x)$

maximum likelihood estimate: any solution x of

$$\text{maximize} \quad l(x) = \sum_{i=1}^m \log p(y_i - a_i^T x)$$

(y is observed value)

examples

- Gaussian noise $\mathcal{N}(0, \sigma^2)$: $p(z) = (2\pi\sigma^2)^{-1/2} e^{-z^2/(2\sigma^2)}$,

$$l(x) = -\frac{m}{2}\log(2\pi\sigma^2) - \frac{1}{2\sigma^2}\sum_{i=1}^{m}(a_i^T x - y_i)^2$$

  ML estimate is LS solution

- Laplacian noise: $p(z) = (1/(2a))e^{-|z|/a}$,

$$l(x) = -m\log(2a) - \frac{1}{a}\sum_{i=1}^{m}|a_i^T x - y_i|$$

  ML estimate is ℓ_1-norm solution

- uniform noise on $[-a, a]$:

$$l(x) = \begin{cases} -m\log(2a) & |a_i^T x - y_i| \le a, \quad i = 1, \ldots, m \\ -\infty & \text{otherwise} \end{cases}$$

  ML estimate is any x with $|a_i^T x - y_i| \le a$

Logistic regression

random variable $y \in \{0, 1\}$ with distribution

$$p = \mathbf{prob}(y = 1) = \frac{\exp(a^T u + b)}{1 + \exp(a^T u + b)}$$

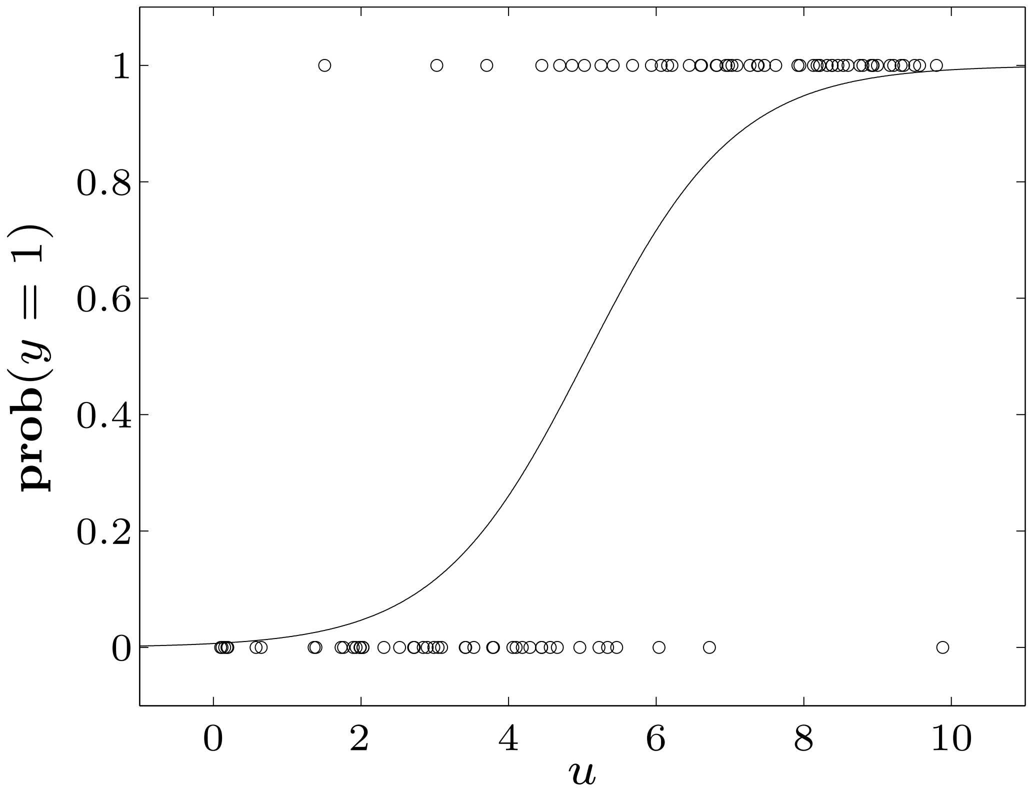
- a, b are parameters; $u \in \mathbf{R}^n$ are (observable) explanatory variables
- estimation problem: estimate a, b from m observations (u_i, y_i)

log-likelihood function (for $y_1 = \cdots = y_k = 1$, $y_{k+1} = \cdots = y_m = 0$):

$$\begin{aligned} l(a, b) &= \log \left(\prod_{i=1}^{k} \frac{\exp(a^T u_i + b)}{1 + \exp(a^T u_i + b)} \prod_{i=k+1}^{m} \frac{1}{1 + \exp(a^T u_i + b)} \right) \\ &= \sum_{i=1}^{k} (a^T u_i + b) - \sum_{i=1}^{m} \log(1 + \exp(a^T u_i + b)) \end{aligned}$$

concave in a, b

example ($n = 1$, $m = 50$ measurements)



- circles show 50 points (u_i, y_i)
- solid curve is ML estimate of $p = \exp(au + b)/(1 + \exp(au + b))$

5. Duality

- Lagrange dual problem
- Weak and strong duality
- Geometric interpretation
- Optimality (KKT) conditions
- Duality and problem reformulations

Lagrangian

standard form problem (not necessarily convex)

$$\begin{array}{ll} \text{minimize} & f_0(x) \\ \text{subject to} & f_i(x) \leq 0, \quad i = 1, \dots, m \\ & h_i(x) = 0, \quad i = 1, \dots, p \end{array}$$

variable $x \in \mathbf{R}^n$, domain $\mathcal{D}$, optimal value $p^\star$

Lagrangian: $L : \mathbf{R}^n \times \mathbf{R}^m \times \mathbf{R}^p \to \mathbf{R}$, with $\mathbf{dom}\, L = \mathcal{D} \times \mathbf{R}^m \times \mathbf{R}^p$,

$$L(x, \lambda, \nu) = f_0(x) + \sum_{i=1}^{m} \lambda_i f_i(x) + \sum_{i=1}^{p} \nu_i h_i(x)$$

- weighted sum of objective and constraint functions
- λ_i is Lagrange multiplier associated with $f_i(x) \leq 0$
- ν_i is Lagrange multiplier associated with $h_i(x) = 0$

Lagrange dual function

Lagrange dual function: $g : \mathbf{R}^m \times \mathbf{R}^p \to \mathbf{R}$,

$$\begin{array}{rcl} g(\lambda,\nu) & = & \inf_{x\in\mathcal{D}} L(x,\lambda,\nu) \\ & = & \inf_{x\in\mathcal{D}} \left(f_0(x) + \sum_{i=1}^m \lambda_i f_i(x) + \sum_{i=1}^p \nu_i h_i(x) \right) \end{array}$$

g is concave, can be $-\infty$ for some λ, ν

lower bound property: if $\lambda \succeq 0$, then $g(\lambda,\nu) \le p^\star$

proof: if $\tilde{x}$ is feasible and $\lambda \succeq 0$, then

$$f_0(\tilde{x}) \ge L(\tilde{x},\lambda,\nu) \ge \inf_{x\in\mathcal{D}} L(x,\lambda,\nu) = g(\lambda,\nu)$$

minimizing over all feasible $\tilde{x}$ gives $p^\star \ge g(\lambda,\nu)$

(Example)

Least-norm solution of linear equations

$$\begin{array}{ll} \text{minimize} & x^T x \\ \text{subject to} & Ax = b \end{array}$$

dual function

- Lagrangian is $L(x, \nu) = x^T x + \nu^T (Ax - b)$
- to minimize L over x, set gradient equal to zero:

$$\nabla_x L(x, \nu) = 2x + A^T \nu = 0 \quad \Longrightarrow \quad x = -(1/2) A^T \nu$$

- plug in in L to obtain g:

$$g(\nu) = L((-1/2)A^T \nu, \nu) = -\frac{1}{4} \nu^T A A^T \nu - b^T \nu$$

  a concave function of ν

lower bound property: $p^\star \geq -(1/4)\nu^T A A^T \nu - b^T \nu$ for all ν

(Example)

Standard form LP

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & Ax = b, \quad x \succeq 0 \end{array}$$

dual function

- Lagrangian is

$$\begin{aligned} L(x, \lambda, \nu) &= c^T x + \nu^T (Ax - b) - \lambda^T x \\ &= -b^T \nu + (c + A^T \nu - \lambda)^T x \end{aligned}$$

- L is affine in x, hence

$$g(\lambda, \nu) = \inf_x L(x, \lambda, \nu) = \begin{cases} -b^T \nu & A^T \nu - \lambda + c = 0 \\ -\infty & \text{otherwise} \end{cases}$$

g is linear on affine domain $\{(\lambda, \nu) \mid A^T \nu - \lambda + c = 0\}$, hence concave

lower bound property: $p^\star \geq -b^T \nu$ if $A^T \nu + c \succeq 0$

(Example)

Equality constrained norm minimization

$$\begin{array}{ll} \text{minimize} & \|x\| \\ \text{subject to} & Ax = b \end{array}$$

dual function

$$g(\nu) = \inf_x (\|x\| - \nu^T Ax + b^T \nu) = \begin{cases} b^T \nu & \|A^T \nu\|_* \leq 1 \\ -\infty & \text{otherwise} \end{cases}$$

where $\|v\|_* = \sup_{\|u\| \leq 1} u^T v$ is dual norm of $\| \cdot \|$

proof: follows from $\inf_x (\|x\| - y^T x) = 0$ if $\|y\|_* \leq 1$, $-\infty$ otherwise

- if $\|y\|_* \leq 1$, then $\|x\| - y^T x \geq 0$ for all x, with equality if $x = 0$
- if $\|y\|_* > 1$, choose $x = tu$ where $\|u\| \leq 1$, $u^T y = \|y\|_* > 1$:

$$\|x\| - y^T x = t(\|u\| - \|y\|_*) \to -\infty \quad \text{as } t \to \infty$$

lower bound property: $p^\star \geq b^T \nu$ if $\|A^T \nu\|_* \leq 1$

The dual problem

Lagrange dual problem

$$\begin{array}{ll} \text{maximize} & g(\lambda, \nu) \\ \text{subject to} & \lambda \succeq 0 \end{array}$$

- finds best lower bound on $p^\star$, obtained from Lagrange dual function
- a convex optimization problem; optimal value denoted $d^\star$
- λ, ν are dual feasible if $\lambda \succeq 0$, $(\lambda, \nu) \in \mathbf{dom}\, g$
- often simplified by making implicit constraint $(\lambda, \nu) \in \mathbf{dom}\, g$ explicit

example: standard form LP and its dual (page 5–5)

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & Ax = b \\ & x \succeq 0 \end{array} \qquad\qquad \begin{array}{ll} \text{maximize} & -b^T \nu \\ \text{subject to} & A^T \nu + c \succeq 0 \end{array}$$

Weak and strong duality

weak duality: $d^\star \leq p^\star$

- always holds (for convex and nonconvex problems)
- can be used to find nontrivial lower bounds for difficult problems

  for example, solving the SDP

$$\begin{array}{ll} \text{maximize} & -\mathbf{1}^T\nu \\ \text{subject to} & W + \mathbf{diag}(\nu) \succeq 0 \end{array}$$

  gives a lower bound for the two-way partitioning problem on page 5–7

strong duality: $d^\star = p^\star$

- does not hold in general
- (usually) holds for convex problems
- conditions that guarantee strong duality in convex problems are called **constraint qualifications**

Slater's constraint qualification

strong duality holds for a convex problem

$$\begin{array}{ll} \text{minimize} & f_0(x) \\ \text{subject to} & f_i(x) \leq 0, \quad i = 1, \ldots, m \\ & Ax = b \end{array}$$

if it is strictly feasible, *i.e.*,

$$\exists x \in \mathbf{int}\, \mathcal{D}: \qquad f_i(x) < 0, \quad i = 1, \ldots, m, \qquad Ax = b$$

- also guarantees that the dual optimum is attained (if $p^\star > -\infty$)
- can be sharpened: *e.g.*, can replace $\mathbf{int}\, \mathcal{D}$ with $\mathbf{relint}\, \mathcal{D}$ (interior relative to affine hull); linear inequalities do not need to hold with strict inequality, ...
- there exist many other types of constraint qualifications

Inequality form LP

primal problem

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & Ax \preceq b \end{array}$$

dual function

$$g(\lambda) = \inf_x \left((c + A^T\lambda)^T x - b^T\lambda \right) = \begin{cases} -b^T\lambda & A^T\lambda + c = 0 \\ -\infty & \text{otherwise} \end{cases}$$

dual problem

$$\begin{array}{ll} \text{maximize} & -b^T\lambda \\ \text{subject to} & A^T\lambda + c = 0, \quad \lambda \succeq 0 \end{array}$$

- from Slater's condition: $p^\star = d^\star$ if $A\tilde{x} \prec b$ for some $\tilde{x}$
- in fact, $p^\star = d^\star$ except when primal and dual are infeasible

Quadratic program

primal problem (assume $P \in \mathbf{S}^n_{++}$)

$$\begin{array}{ll} \text{minimize} & x^T P x \\ \text{subject to} & Ax \preceq b \end{array}$$

dual function

$$g(\lambda) = \inf_x \left(x^T P x + \lambda^T (Ax - b)\right) = -\frac{1}{4}\lambda^T A P^{-1} A^T \lambda - b^T \lambda$$

dual problem

$$\begin{array}{ll} \text{maximize} & -(1/4)\lambda^T A P^{-1} A^T \lambda - b^T \lambda \\ \text{subject to} & \lambda \succeq 0 \end{array}$$

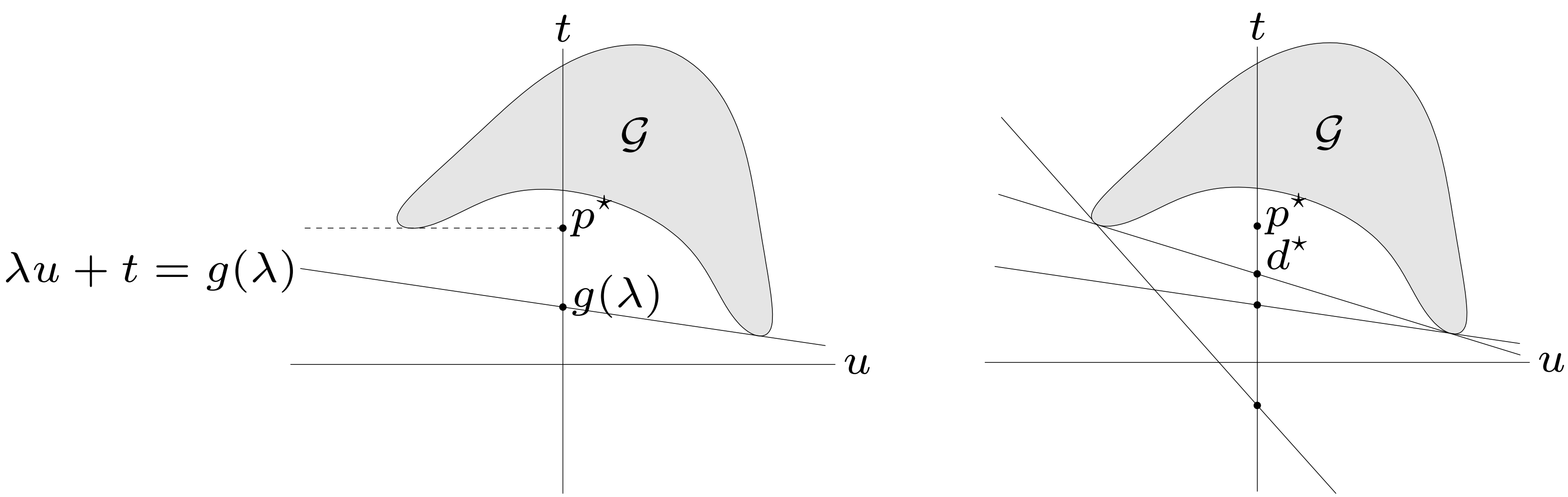
- from Slater's condition: $p^\star = d^\star$ if $A\tilde{x} \prec b$ for some $\tilde{x}$
- in fact, $p^\star = d^\star$ always

Geometric interpretation

for simplicity, consider problem with one constraint $f_1(x) \le 0$

interpretation of dual function:

$$g(\lambda) = \inf_{(u,t)\in\mathcal{G}} (t + \lambda u), \qquad \text{where} \quad \mathcal{G} = \{(f_1(x), f_0(x)) \mid x \in \mathcal{D}\}$$



- $\lambda u + t = g(\lambda)$ is (non-vertical) supporting hyperplane to $\mathcal{G}$
- hyperplane intersects t-axis at $t = g(\lambda)$

Complementary slackness

assume strong duality holds, $x^\star$ is primal optimal, $(\lambda^\star, \nu^\star)$ is dual optimal

$$\begin{aligned} f_0(x^\star) = g(\lambda^\star, \nu^\star) &= \inf_x \left(f_0(x) + \sum_{i=1}^m \lambda_i^\star f_i(x) + \sum_{i=1}^p \nu_i^\star h_i(x) \right) \\ &\leq f_0(x^\star) + \sum_{i=1}^m \lambda_i^\star f_i(x^\star) + \sum_{i=1}^p \nu_i^\star h_i(x^\star) \\ &\leq f_0(x^\star) \end{aligned}$$

hence, the two inequalities hold with equality

- $x^\star$ minimizes $L(x, \lambda^\star, \nu^\star)$
- $\lambda_i^\star f_i(x^\star) = 0$ for $i = 1, \ldots, m$ (known as complementary slackness):

$$\lambda_i^\star > 0 \Longrightarrow f_i(x^\star) = 0, \qquad f_i(x^\star) < 0 \Longrightarrow \lambda_i^\star = 0$$

Karush-Kuhn-Tucker (KKT) conditions

the following four conditions are called KKT conditions (for a problem with differentiable f_i, h_i):

1. primal constraints: $f_i(x) \leq 0$, $i = 1, \ldots, m$, $h_i(x) = 0$, $i = 1, \ldots, p$
2. dual constraints: $\lambda \succeq 0$
3. complementary slackness: $\lambda_i f_i(x) = 0$, $i = 1, \ldots, m$
4. gradient of Lagrangian with respect to x vanishes:

$$\nabla f_0(x) + \sum_{i=1}^{m} \lambda_i \nabla f_i(x) + \sum_{i=1}^{p} \nu_i \nabla h_i(x) = 0$$

from page 5–17: if strong duality holds and x, λ, ν are optimal, then they must satisfy the KKT conditions

KKT conditions for convex problem

if $\tilde{x}$, $\tilde{\lambda}$, $\tilde{\nu}$ satisfy KKT for a convex problem, then they are optimal:

- from complementary slackness: $f_0(\tilde{x}) = L(\tilde{x}, \tilde{\lambda}, \tilde{\nu})$
- from 4th condition (and convexity): $g(\tilde{\lambda}, \tilde{\nu}) = L(\tilde{x}, \tilde{\lambda}, \tilde{\nu})$

hence, $f_0(\tilde{x}) = g(\tilde{\lambda}, \tilde{\nu})$

if **Slater's condition** is satisfied:

x is optimal if and only if there exist λ, ν that satisfy KKT conditions

- recall that Slater implies strong duality, and dual optimum is attained
- generalizes optimality condition $\nabla f_0(x) = 0$ for unconstrained problem

example: water-filling (assume $\alpha_i > 0$)

$$\begin{array}{ll} \text{minimize} & -\sum_{i=1}^n \log(x_i + \alpha_i) \\ \text{subject to} & x \succeq 0, \quad \mathbf{1}^T x = 1 \end{array}$$

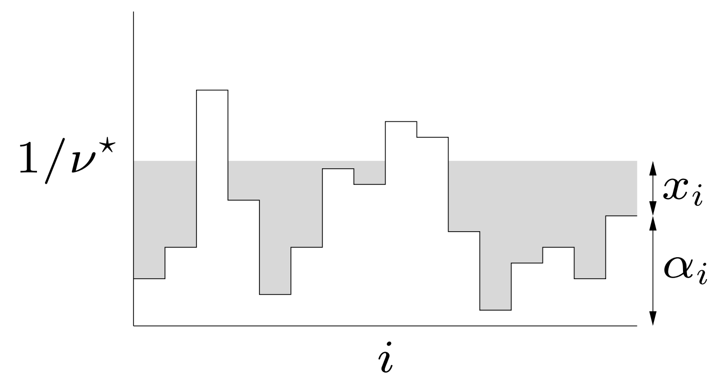
x is optimal iff $x \succeq 0$, $\mathbf{1}^T x = 1$, and there exist $\lambda \in \mathbf{R}^n$, $\nu \in \mathbf{R}$ such that

$$\lambda \succeq 0, \qquad \lambda_i x_i = 0, \qquad \frac{1}{x_i + \alpha_i} + \lambda_i = \nu$$

- if $\nu < 1/\alpha_i$: $\lambda_i = 0$ and $x_i = 1/\nu - \alpha_i$
- if $\nu \geq 1/\alpha_i$: $\lambda_i = \nu - 1/\alpha_i$ and $x_i = 0$
- determine ν from $\mathbf{1}^T x = \sum_{i=1}^n \max\{0, 1/\nu - \alpha_i\} = 1$

interpretation

- n patches; level of patch i is at height α_i
- flood area with unit amount of water
- resulting level is $1/\nu^\star$



Duality and problem reformulations

- equivalent formulations of a problem can lead to very different duals
- reformulating the primal problem can be useful when the dual is difficult to derive, or uninteresting

common reformulations

- introduce new variables and equality constraints
- make explicit constraints implicit or vice-versa
- transform objective or constraint functions

  $e.g.$, replace $f_0(x)$ by $\phi(f_0(x))$ with ϕ convex, increasing

Introducing new variables and equality constraints

$$\text{minimize} \quad f_0(Ax+b)$$

- dual function is constant: $g = \inf_x L(x) = \inf_x f_0(Ax+b) = p^\star$
- we have strong duality, but dual is quite useless

reformulated problem and its dual

$$\begin{array}{ll} \text{minimize} & f_0(y) \\ \text{subject to} & Ax+b-y=0 \end{array} \qquad\qquad \begin{array}{ll} \text{maximize} & b^T\nu - f_0^*(\nu) \\ \text{subject to} & A^T\nu = 0 \end{array}$$

dual function follows from

$$\begin{aligned} g(\nu) &= \inf_{x,y}(f_0(y) - \nu^T y + \nu^T Ax + b^T\nu) \\ &= \begin{cases} -f_0^*(\nu) + b^T\nu & A^T\nu = 0 \\ -\infty & \text{otherwise} \end{cases} \end{aligned}$$

(Example)

norm approximation problem: minimize $\|Ax - b\|$

$$\begin{array}{ll} \text{minimize} & \|y\| \\ \text{subject to} & y = Ax - b \end{array}$$

can look up conjugate of $\|\cdot\|$, or derive dual directly

$$\begin{aligned} g(\nu) &= \inf_{x,y}(\|y\| + \nu^T y - \nu^T Ax + b^T\nu) \\ &= \begin{cases} b^T\nu + \inf_y(\|y\| + \nu^T y) & A^T\nu = 0 \\ -\infty & \text{otherwise} \end{cases} \\ &= \begin{cases} b^T\nu & A^T\nu = 0, \quad \|\nu\|_* \le 1 \\ -\infty & \text{otherwise} \end{cases} \end{aligned}$$

(see page 5–4)

dual of norm approximation problem

$$\begin{array}{ll} \text{maximize} & b^T\nu \\ \text{subject to} & A^T\nu = 0, \quad \|\nu\|_* \le 1 \end{array}$$

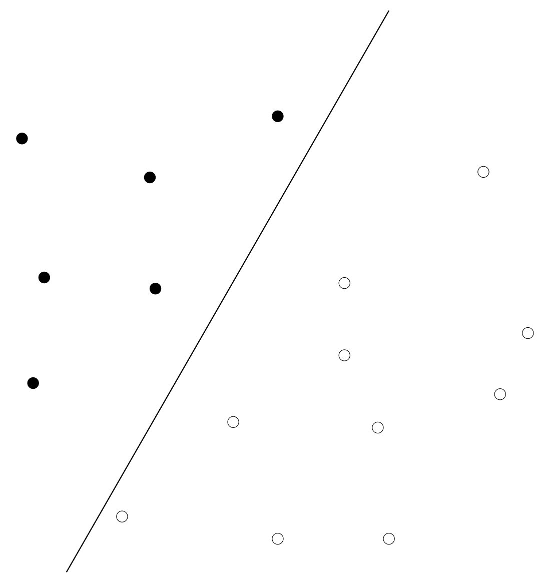
6. Margin-based classification

- Linear classification
- Robust linear classification
- SVM

Linear discrimination

separate two sets of points $\{x_1, \ldots, x_N\}$, $\{y_1, \ldots, y_M\}$ by a hyperplane:

$$a^T x_i + b > 0, \quad i = 1, \ldots, N, \qquad a^T y_i + b < 0, \quad i = 1, \ldots, M$$



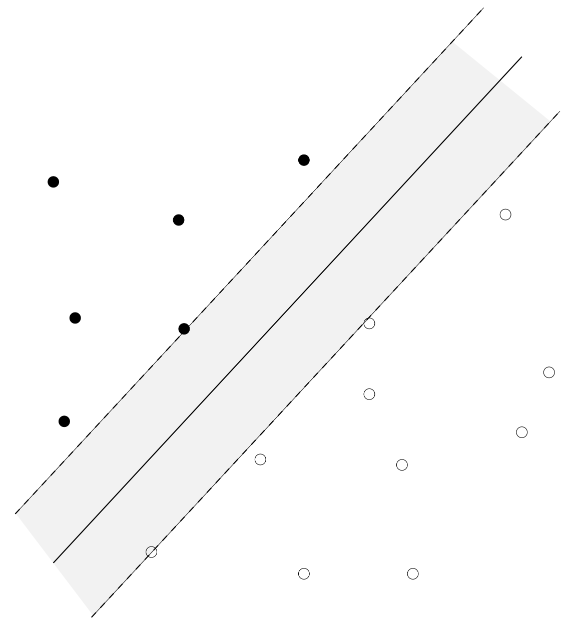
homogeneous in a, b, hence equivalent to

$$a^T x_i + b \geq 1, \quad i = 1, \ldots, N, \qquad a^T y_i + b \leq -1, \quad i = 1, \ldots, M$$

a set of linear inequalities in a, b

Robust linear discrimination

(Euclidean) distance between hyperplanes



$$\begin{aligned}\mathcal{H}_1 &= \{z \mid a^T z + b = 1\} \\ \mathcal{H}_2 &= \{z \mid a^T z + b = -1\}\end{aligned}$$

is $\mathbf{dist}(\mathcal{H}_1, \mathcal{H}_2) = 2/\|a\|_2$

to separate two sets of points by maximum margin,

$$\begin{array}{ll}\text{minimize} & (1/2)\|a\|_2 \\ \text{subject to} & a^T x_i + b \geq 1, \quad i = 1, \ldots, N \\ & a^T y_i + b \leq -1, \quad i = 1, \ldots, M\end{array} \tag{1}$$

(after squaring objective) a QP in a, b

Lagrange dual of maximum margin separation problem (1)

$$\begin{array}{ll} \text{maximize} & \mathbf{1}^T\lambda + \mathbf{1}^T\mu \\ \text{subject to} & 2\left\|\sum_{i=1}^N \lambda_i x_i - \sum_{i=1}^M \mu_i y_i\right\|_2 \le 1 \\ & \mathbf{1}^T\lambda = \mathbf{1}^T\mu, \quad \lambda \succeq 0, \quad \mu \succeq 0 \end{array} \qquad (2)$$

from duality, optimal value is inverse of maximum margin of separation

interpretation

- change variables to $\theta_i = \lambda_i/\mathbf{1}^T\lambda$, $\gamma_i = \mu_i/\mathbf{1}^T\mu$, $t = 1/(\mathbf{1}^T\lambda + \mathbf{1}^T\mu)$
- invert objective to minimize $1/(\mathbf{1}^T\lambda + \mathbf{1}^T\mu) = t$

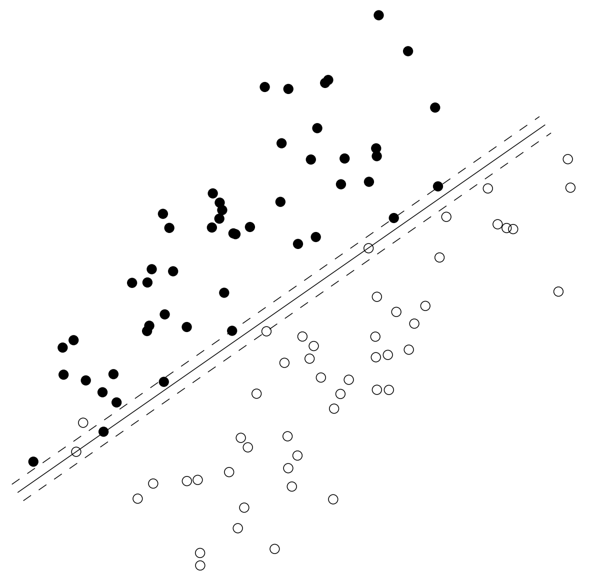
$$\begin{array}{ll} \text{minimize} & t \\ \text{subject to} & \left\|\sum_{i=1}^N \theta_i x_i - \sum_{i=1}^M \gamma_i y_i\right\|_2 \le t \\ & \theta \succeq 0, \quad \mathbf{1}^T\theta = 1, \quad \gamma \succeq 0, \quad \mathbf{1}^T\gamma = 1 \end{array}$$

optimal value is distance between convex hulls

Approximate linear separation of non-separable sets

$$
\begin{array}{ll}
\text{minimize} & \mathbf{1}^T u + \mathbf{1}^T v \\
\text{subject to} & a^T x_i + b \geq 1 - u_i, \quad i = 1, \ldots, N \\
& a^T y_i + b \leq -1 + v_i, \quad i = 1, \ldots, M \\
& u \succeq 0, \quad v \succeq 0
\end{array}
$$

- an LP in a, b, u, v
- at optimum, $u_i = \max\{0, 1 - a^T x_i - b\}$, $v_i = \max\{0, 1 + a^T y_i + b\}$
- can be interpreted as a heuristic for minimizing #misclassified points



Support vector classifier

$$\begin{array}{ll}\text{minimize} & \|a\|_2 + \gamma(\mathbf{1}^T u + \mathbf{1}^T v) \\ \text{subject to} & a^T x_i + b \geq 1 - u_i, \quad i = 1, \ldots, N \\ & a^T y_i + b \leq -1 + v_i, \quad i = 1, \ldots, M \\ & u \succeq 0, \quad v \succeq 0\end{array}$$

produces point on trade-off curve between inverse of margin $2/\|a\|_2$ and classification error, measured by total slack $\mathbf{1}^T u + \mathbf{1}^T v$

same example as previous page, with $\gamma = 0.1$: