

An active-set convex QP solver based on regularized KKT systems

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Outline

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- 2 Motivation
- 3 SQOPT
- 4 QPBLU
- 5 Regularization
- 6 QPBLUR
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An active-set convex QP solver based on regularized KKT systems

Implementations of the simplex method depend on “**basis repair**” to steer around near-singular basis matrices, and KKT-based QP solvers must deal with near-singular KKT systems. However, few sparse-matrix packages have the required **rank-revealing features** (we know of [LUSOL](#), [MA48](#), [MA57](#), and [HSL_MA77](#)).

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For convex QP, we explore the idea of **avoiding singular KKT systems** by applying **primal and dual regularization** to the QP problem. A simplified **single-phase active-set algorithm** can then be developed. Warm starts are straightforward from any given active set, and the range of applicable KKT solvers expands.

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QPBLUR is a prototype QP solver that makes use of the block-LU KKT updates in **QPBLU** (Hanh Huynh’s PhD dissertation, 2008) but employs regularization and the simplified active-set algorithm. The aim is to provide a new QP subproblem solver for **SNOPT** for problems with many degrees of freedom. Numerical results confirm the robustness of the single-phase regularized QP approach.

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Motivation (SNOPT)

Motivation: SNOPT

SNOPT: an SQP method for constrained NLP (Gill, Murray, S 2005)

SQOPT: an active-set method

Solves a sequence of convex QP problems

$$\begin{aligned} \min_x \quad & c^T x + \frac{1}{2} x^T H x \\ & Ax = b, \quad l \leq x \leq u, \end{aligned}$$

where c , H , A , b change (less and less)

Initially H diagonal

Later $H \leftarrow G^T H G, \quad G = (I + dv^T)$

Convex QP Solvers

Interior	Active-set	
LOQO		
HOPDM	SQOPT	reduced-Hessian
QPB	QPA	
CPLEX	QPBLU	
IPOPT	QPBLUR	

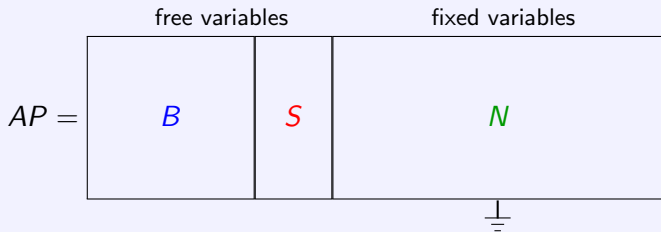
All based on KKT systems (except SQOPT)

SQOPT

SQOPT

$$\min c^T x + \frac{1}{2} x^T H x \quad \text{st} \quad Ax = b, \quad l \leq x \leq u$$

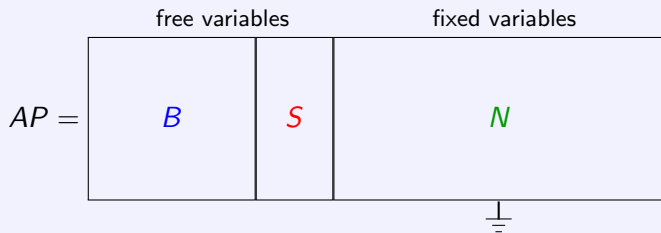
Reduced-gradient method (active-set method)



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→ ←
degrees of freedom

SQOPT

Any active-set method solves for search direction in Free variables:

$$\begin{pmatrix} H_F & A_F^T \\ A_F & 0 \end{pmatrix} \begin{pmatrix} \Delta x_F \\ \Delta y \end{pmatrix} \approx \begin{pmatrix} r_1 \\ r_2 \end{pmatrix}$$

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Reduced-gradient method uses a **specific ordering** (Gill et al. 1990):

$$A_F = (B \quad S) \quad \rightarrow \quad \begin{pmatrix} H_{BB} & B^T & H_{BS} \\ B & & S \\ H_{SB} & S^T & H_{SS} \end{pmatrix}$$

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$$Z^T H Z = H_{SS} - (\dots)(\dots)^{-1}(\dots)^T$$

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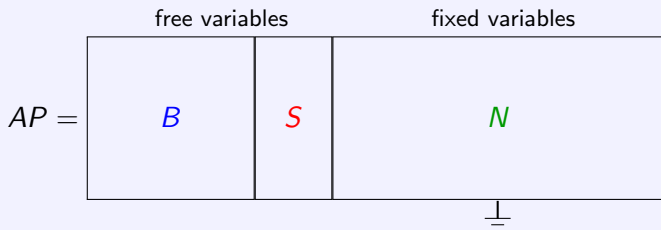
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Likely to be **dense** \Rightarrow **Need to work with original KKT system**

SQOPT limitation

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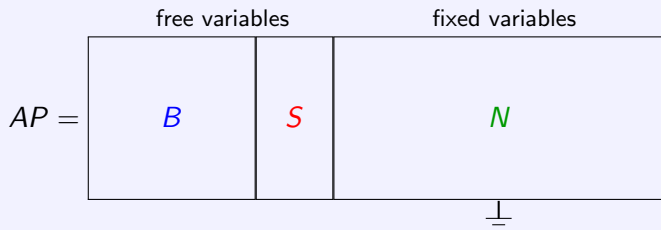
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Reduced-gradient method



OK if

What if

10000

1M

2000

1M

100000

10M

QPBLU

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F90 convex QP solver based on block-LU updates of K

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- L_0, U_0 from LUSOL, MA57, PARDISO, SuperLU, UMFPACK

Singular KKTs

MA27, MA57, ..., HSL_MA87 are rank-revealing if $u \geq 0.25$ (say)

For semidefinite QP,

$$K = \begin{pmatrix} D_1 & & A_1^T \\ & A_2 & A_2^T \\ A_1 & & \end{pmatrix}, \quad D_1 \succ 0$$

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Theorem. K is nonsingular iff

$\begin{pmatrix} A_1 & A_2 \end{pmatrix}$ has full row rank

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KKT Repair not yet implemented

Regularization

Regularization

- PDQ1 Interior method for LP (S 1996), OSL (S and Tomlin 1996)

$$\begin{aligned} \min_{x,y} \quad & c^T x + \frac{1}{2} \gamma \|x\|^2 + \frac{1}{2} \delta \|y\|^2 \\ & Ax + \delta y = b, \quad l \leq x \leq u \end{aligned}$$

Indefinite LDL^T on KKT is stable if γ, δ sufficiently large

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- **HOPDM** Interior method for QP (Altman and Gondzio 1999)
Smaller perturbation via *dynamic proximal point* terms:

$$\frac{1}{2}(x - x_k)^T R_p (x - x_k), \quad \frac{1}{2}(y - y_k)^T R_d (y - x_y)$$

QPBLUR

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- Can use Hanh's block-LU updates without change

Strategy

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MATLAB implementation

- Scale problem

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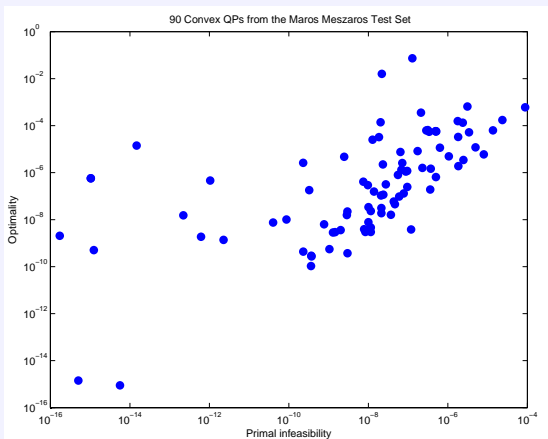
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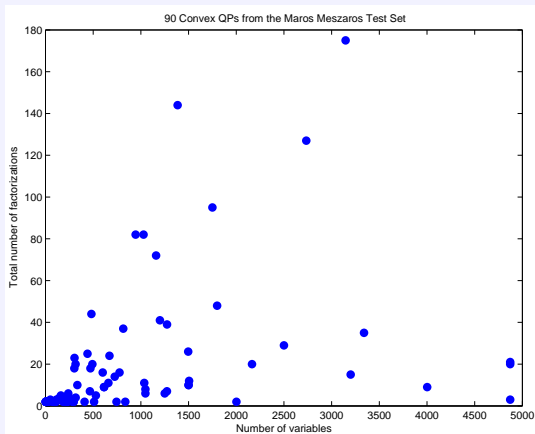
Numerical Results

Accuracy of solutions



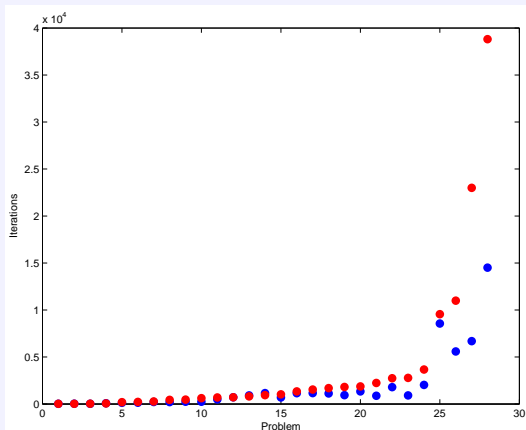
Residuals for 90 Mészáros QP test problems

KKT factorizations



No. of factorizations on 90 Mészáros QP test problems

Infeasible problems



No. of iterations on 28 infeasible LP test problems (Netlib lpi_XXX)

● $\mu \searrow 10^{-12}$ ● $\mu \equiv 1$

$$\left(\min c^T x + \frac{1}{2} x^T H x + \frac{1}{2} \delta x^T x + \frac{1}{2} \mu y^T y \quad Ax + \mu y = b, \dots \right)$$

Conclusions

QPBLUR Pros and Cons

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Advantages

- Can start from any active set
(hence good for warm starts in SNOPT)

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- Tiny regularization risks ill-conditioned KKT
(but so far so good)

References

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Further results (and F90 implementation)
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