4. Convex optimization problems

- optimization problem in standard form
- convex optimization problems
- quasiconvex optimization
- linear optimization
- quadratic optimization
- geometric programming
- generalized inequality constraints
- semidefinite programming

Optimization problem in standard form

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

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

optimal value:

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

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

min x^2
st. x ≤ 2
-x ≤ -3

min x
st. x ≤ 5

Optimal and locally optimal points

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

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

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

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

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

- $f_0(x) = 1/x$, $\textbf{dom}\, f_0 = \mathbf{R}_{++}$: $p^\star = 0$, no optimal point **f0(x) -> 0 as x -> +inf**
- $f_0(x) = -\log x$, $\textbf{dom}\, f_0 = \mathbf{R}_{++}$: $p^\star = -\infty$ **f0(x) -> -inf as x-> +inf**
- $f_0(x) = x \log x$, $\textbf{dom}\, f_0 = \mathbf{R}_{++}$: $p^\star = -1/e$, $x = 1/e$ is optimal **See f0(x) in [0,2]**
- $f_0(x) = x^3 - 3x$, $p^\star = -\infty$, local optimum at $x = 1$ **See f0(x) in [-3,+3]**

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:

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

is an unconstrained problem with implicit constraints $a_i^T x < b_i$ **iff b_i - a_i x > 0**

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

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

- 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

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

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

example

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

denominator > 0 then x1 ≤ 0

x1 = -x2

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

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

Local and global optima

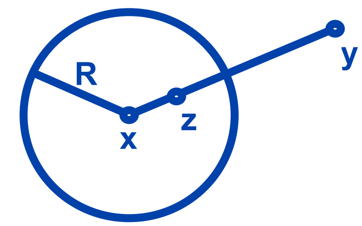
any locally optimal point of a convex problem is (globally) optimal

proof: suppose x is locally optimal, but there exists a feasible y with $f_0(y) < f_0(x)$ **(i.e., x not globally optimal)**

not in the local region

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 $\theta = R/(2\|y - x\|_2)$

then θ |y-x|_2 = R/2

not in the local region

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

z-x = θ y+(1-θ)x -x
= θ (y-x)
|z-x|_2 = θ |y-x|_2
= R/2

by convexity

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

fo(z) = fo(θ y+(1-θ)x)
≤ θ fo(y) + (1-θ) fo(x)
< θ fo(x) + (1-θ) fo(x)
... since fo(y) < fo(x)
= fo(x)

which contradicts our assumption that x is locally optimal

since we found that fo(z) < fo(x)

Optimality criterion for differentiable f_0

x is optimal if and only if it is feasible and

1st order condition for convexity
fo(y) ≥ fo(x) + dfo(x)' (y-x)

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

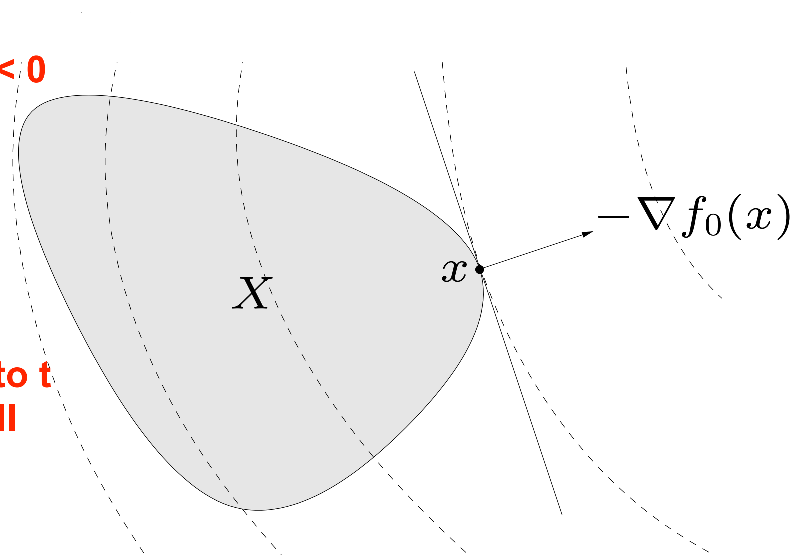
I. Assume dfo(x)' (y-x) ≥ 0
then fo(y) ≥ fo(x)
then x optimal

II. Assume x optimal and dfo(x)' (y-x) < 0
Let z(t) = t y + (1-t) x, for t in [0,1]

We will arrive to a contradiction
d/dt fo(z(t)) = dfo(t y + (1-t) x)' (y-x)
d/dt fo(z(t)) (at t=0) = dfo(x)' (y-x) < 0

Thus, fo(z(t)) decreases with respect to t (starting at t=0) and there exist a small t>0 such that: fo(z(t)) < fo(x)

Thus, x is not optimal



(If it were an unconstrained problem the optimal x would be in this region.)

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

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

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

  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**

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

is equivalent to

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

- **epigraph form**: standard form convex problem is equivalent to

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

- **minimizing over some variables**

x2 not in the constraints

$$\begin{array}{ll} \text{minimize} & f_0(x_1, x_2) \\ \text{subject to} & f_i(x_1) \leq 0, \quad i = 1, \ldots, m \end{array}$$

is equivalent to

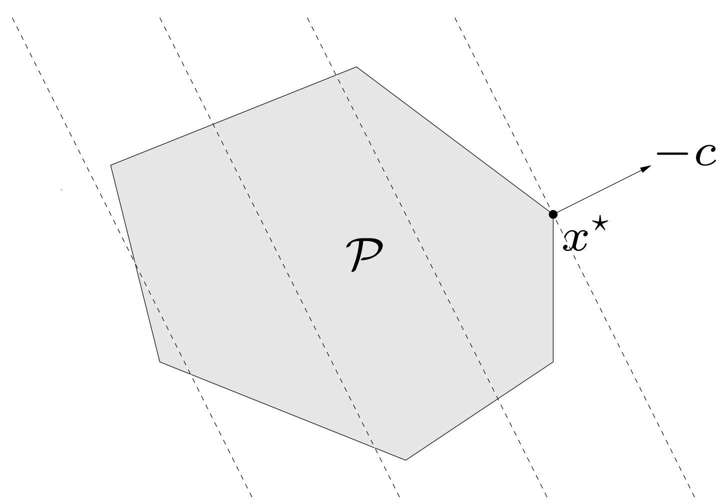
$$\begin{array}{ll} \text{minimize} & \tilde{f}_0(x_1) \\ \text{subject to} & f_i(x_1) \leq 0, \quad i = 1, \ldots, m \end{array}$$

where $\tilde{f}_0(x_1) = \inf_{x_2} f_0(x_1, x_2)$

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

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

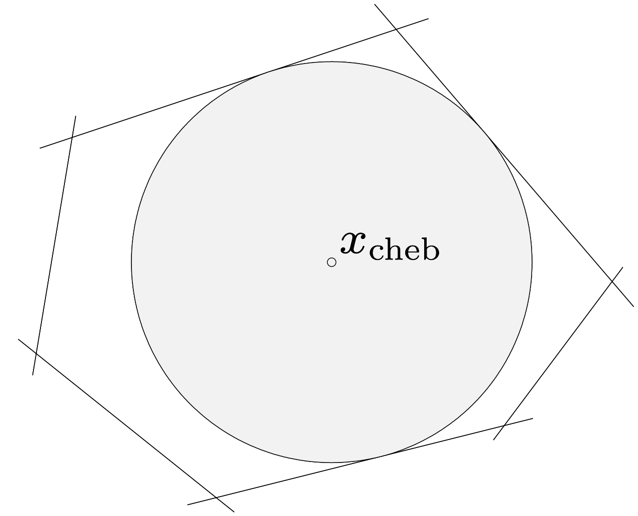
Chebyshev center of a polyhedron

Chebyshev center of

$$\mathcal{P} = \{x \mid a_i^T x \le b_i,\ i = 1, \ldots, m\}$$

is center of largest inscribed ball

$$\mathcal{B} = \{x_c + u \mid \|u\|_2 \le r\}$$



- $a_i^T x \le b_i$ for all $x \in \mathcal{B}$ if and only if

$$\sup_u \{a_i^T(x_c + u) \mid \|u\|_2 \le r\} = a_i^T x_c + r\|a_i\|_2 \le b_i$$

since sup_u (a_i u) = |a_i|_2 by norm duality

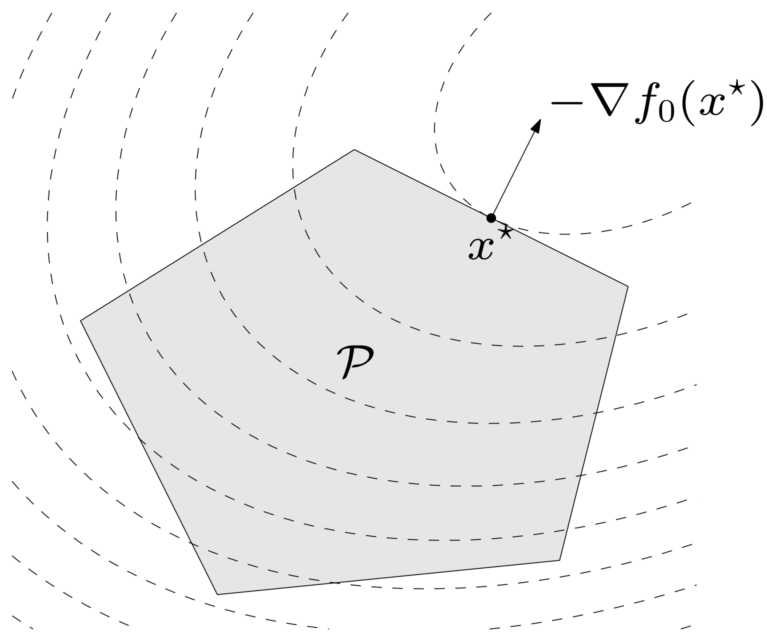
- hence, x_c, r can be determined by solving the LP

$$\begin{array}{ll} \text{maximize} & r \\ \text{subject to} & a_i^T x_c + r\|a_i\|_2 \le b_i, \quad i = 1, \ldots, m \end{array}$$

Quadratic program (QP)

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

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



Examples

1/2 |A x - b|_2^2
= 1/2 (A x - b)' (A x - b)
= 1/2 x' A' A x - b' A x + constant

Making gradient = 0
A' A x* - A b = 0
x* = (A' A)^-1 A b

least-squares

$$\text{minimize } 1/2 \|Ax - b\|_2^2$$

- 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

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

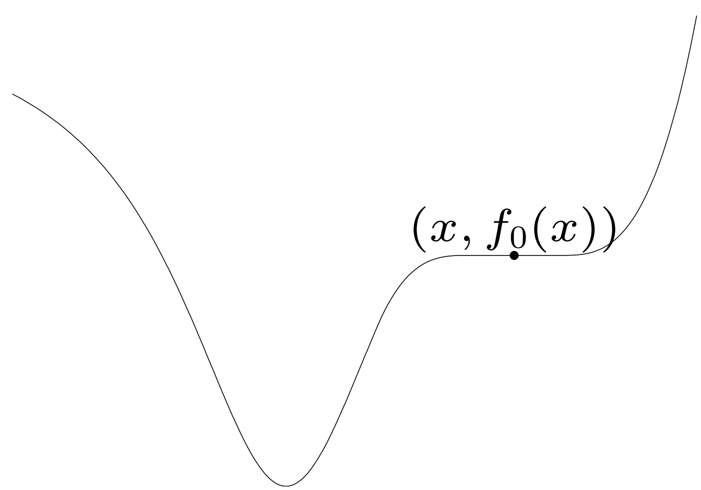
- c is random vector with mean $\bar{c}$ and covariance Σ
- hence, $c^T x$ is random variable with mean $\bar{c}^T x$ and variance $x^T \Sigma x$
- $\gamma > 0$ is risk aversion parameter; controls the trade-off between expected cost and variance (risk)

Quasiconvex optimization

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

with $f_0 : \mathbf{R}^n \to \mathbf{R}$ quasiconvex, $f_1, \ldots, f_m$ convex

can have locally optimal points that are not (globally) optimal



convex representation of sublevel sets of f_0

if f_0 is quasiconvex, there exists a family of functions ϕ_t such that:

- $\phi_t(x)$ is convex in x for fixed t
- t-sublevel set of f_0 is 0-sublevel set of ϕ_t, *i.e.*,

$$f_0(x) \le t \quad \Longleftrightarrow \quad \phi_t(x) \le 0$$

example

$$f_0(x) = \frac{p(x)}{q(x)}$$

with p convex, q concave, and $p(x) \ge 0$, $q(x) > 0$ on $\mathbf{dom}\, f_0$

can take $\phi_t(x) = p(x) - tq(x)$:

- for $t \ge 0$, ϕ_t convex in x
- $p(x)/q(x) \le t$ if and only if $\phi_t(x) \le 0$

p(x) ≤ t q(x)
p(x) - t q(x) ≤ 0

quasiconvex optimization via convex feasibility problems

$$\phi_t(x) \le 0, \qquad f_i(x) \le 0, \quad i = 1, \ldots, m, \qquad Ax = b \tag{1}$$

- for fixed t, a convex feasibility problem in x
- if feasible, we can conclude that $t \ge p^\star$; if infeasible, $t \le p^\star$

Bisection method for quasiconvex optimization

given $l \le p^\star$, $u \ge p^\star$, tolerance $\epsilon > 0$.
repeat
1. $t := (l + u)/2$.
2. Solve the convex feasibility problem (1).
3. **if** (1) is feasible, $u := t$; **else** $l := t$.

until $u - l \le \epsilon$.

---

requires exactly $\lceil \log_2((u - l)/\epsilon) \rceil$ iterations (where u, l are initial values)

Linear-fractional program

$$\begin{array}{ll} \text{minimize} & f_0(x) \\ \text{subject to} & Gx \preceq h \\ & Ax = b \end{array}$$

linear-fractional program

$$f_0(x) = \frac{c^T x + d}{e^T x + f}, \qquad \mathbf{dom}\, f_0(x) = \{x \mid e^T x + f > 0\}$$

- a quasiconvex optimization problem; can be solved by bisection

Second-order cone programming

$$\begin{array}{ll} \text{minimize} & f^T x \\ \text{subject to} & \|A_i x + b_i\|_2 \leq c_i^T x + d_i, \quad i = 1, \ldots, m \\ & Fx = g \end{array}$$

($A_i \in \mathbf{R}^{n_i \times n}$, $F \in \mathbf{R}^{p \times n}$)

- inequalities are called second-order cone (SOC) constraints:

$$(A_i x + b_i, c_i^T x + d_i) \in \text{second-order cone in } \mathbf{R}^{n_i+1}$$

(example)

Robust linear programming

the parameters in optimization problems are often uncertain, $e.g.$, in an LP

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

there can be uncertainty in c, a_i, b_i

two common approaches to handling uncertainty (in a_i, for simplicity)

- deterministic model: constraints must hold for all $a_i \in \mathcal{E}_i$

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

- stochastic model: a_i is random variable; constraints must hold with probability η

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

(example continues)

deterministic approach via SOCP

- choose an ellipsoid as $\mathcal{E}_i$:

$$\mathcal{E}_i = \{\bar{a}_i + P_i u \mid \|u\|_2 \leq 1\} \qquad (\bar{a}_i \in \mathbf{R}^n, \quad P_i \in \mathbf{R}^{n \times n})$$

center is $\bar{a}_i$, semi-axes determined by singular values/vectors of P_i

- robust LP

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

is equivalent to the SOCP

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & \bar{a}_i^T x + \|P_i^T x\|_2 \leq b_i, \quad i = 1, \ldots, m \end{array}$$

(follows from $\sup_{\|u\|_2 \leq 1} (\bar{a}_i + P_i u)^T x = \bar{a}_i^T x + \|P_i^T x\|_2$)

a_i’x is constant wrt u, only analyze (P_i u)’x
sup_{|u|_2 ≤ 1} u’ P_i’ x = |P_i’ x|_2 by norm duality

stochastic approach via SOCP

- assume a_i is Gaussian with mean $\bar{a}_i$, covariance Σ_i ($a_i \sim \mathcal{N}(\bar{a}_i, \Sigma_i)$)
- $a_i^T x$ is Gaussian r.v. with mean $\bar{a}_i^T x$, variance $x^T \Sigma_i x$; hence

$$\textbf{prob}(a_i^T x \leq b_i) = \Phi\left(\frac{b_i - \bar{a}_i^T x}{\|\Sigma_i^{1/2} x\|_2}\right)$$

where $\Phi(x) = (1/\sqrt{2\pi}) \int_{-\infty}^{x} e^{-t^2/2}\, dt$ is CDF of $\mathcal{N}(0,1)$

- robust LP

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

with $\eta \geq 1/2$, is equivalent to the SOCP

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & \bar{a}_i^T x + \Phi^{-1}(\eta) \|\Sigma_i^{1/2} x\|_2 \leq b_i, \quad i = 1, \ldots, m \end{array}$$

Geometric programming

monomial function

$$f(x) = cx_1^{a_1} x_2^{a_2} \cdots x_n^{a_n}, \qquad \textbf{dom}\, f = \mathbf{R}_{++}^n$$

with $c > 0$; exponent a_i can be any real number

posynomial function: sum of monomials

$$f(x) = \sum_{k=1}^{K} c_k x_1^{a_{1k}} x_2^{a_{2k}} \cdots x_n^{a_{nk}}, \qquad \textbf{dom}\, f = \mathbf{R}_{++}^n$$

geometric program (GP)

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

with f_i posynomial, h_i monomial

Geometric program in convex form

change variables to $y_i = \log x_i$, and take logarithm of cost, constraints

- monomial $f(x) = cx_1^{a_1} \cdots x_n^{a_n}$ transforms to

$$\log f(e^{y_1}, \ldots, e^{y_n}) = a^T y + b \qquad (b = \log c)$$

- posynomial $f(x) = \sum_{k=1}^K c_k x_1^{a_{1k}} x_2^{a_{2k}} \cdots x_n^{a_{nk}}$ transforms to

$$\log f(e^{y_1}, \ldots, e^{y_n}) = \log \left(\sum_{k=1}^K e^{a_k^T y + b_k} \right) \qquad (b_k = \log c_k)$$

- geometric program transforms to convex problem

$$\begin{array}{ll} \text{minimize} & \log \left(\sum_{k=1}^K \exp(a_{0k}^T y + b_{0k}) \right) \\ \text{subject to} & \log \left(\sum_{k=1}^K \exp(a_{ik}^T y + b_{ik}) \right) \leq 0, \quad i = 1, \ldots, m \\ & Gy + d = 0 \end{array}$$

Generalized inequality constraints

convex problem with generalized inequality constraints

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

- $f_0 : \mathbf{R}^n \to \mathbf{R}$ convex; $f_i : \mathbf{R}^n \to \mathbf{R}^{k_i}$ K_i-convex w.r.t. proper cone K_i
- same properties as standard convex problem (convex feasible set, local optimum is global, etc.)

conic form problem: special case with affine objective and constraints

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & Fx + g \preceq_K 0 \\ & Ax = b \end{array}$$

extends linear programming ($K = \mathbf{R}^m_+$) to nonpolyhedral cones

Semidefinite program (SDP)

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & x_1 F_1 + x_2 F_2 + \cdots + x_n F_n + G \preceq 0 \\ & Ax = b \end{array}$$

with F_i, $G \in \mathbf{S}^k$

- inequality constraint is called linear matrix inequality (LMI)
- includes problems with multiple LMI constraints: for example,

$$x_1 \hat{F}_1 + \cdots + x_n \hat{F}_n + \hat{G} \preceq 0, \qquad x_1 \tilde{F}_1 + \cdots + x_n \tilde{F}_n + \tilde{G} \preceq 0$$

  is equivalent to single LMI

$$x_1 \begin{bmatrix} \hat{F}_1 & 0 \\ 0 & \tilde{F}_1 \end{bmatrix} + x_2 \begin{bmatrix} \hat{F}_2 & 0 \\ 0 & \tilde{F}_2 \end{bmatrix} + \cdots + x_n \begin{bmatrix} \hat{F}_n & 0 \\ 0 & \tilde{F}_n \end{bmatrix} + \begin{bmatrix} \hat{G} & 0 \\ 0 & \tilde{G} \end{bmatrix} \preceq 0$$

(example)

Eigenvalue minimization

$$\text{minimize} \quad \lambda_{\max}(A(x))$$

where $A(x) = A_0 + x_1 A_1 + \cdots + x_n A_n$ (with given $A_i \in \mathbf{S}^k$)

equivalent SDP

$$\begin{array}{ll} \text{minimize} & t \\ \text{subject to} & A(x) \preceq tI \end{array}$$

- variables $x \in \mathbf{R}^n$, $t \in \mathbf{R}$
- follows from

$$\lambda_{\max}(A) \leq t \quad \Longleftrightarrow \quad A \preceq tI$$

(example)

Matrix norm minimization

$$\text{minimize} \quad \|A(x)\|_2 = \left(\lambda_{\max}(A(x)^T A(x))\right)^{1/2}$$

where $A(x) = A_0 + x_1 A_1 + \cdots + x_n A_n$ (with given $A_i \in \mathbf{R}^{p\times q}$)

equivalent SDP

$$\begin{array}{ll} \text{minimize} & t \\ \text{subject to} & \begin{bmatrix} tI & A(x) \\ A(x)^T & tI \end{bmatrix} \succeq 0 \end{array}$$

- variables $x \in \mathbf{R}^n$, $t \in \mathbf{R}$
- constraint follows from

$$\|A\|_2 \le t \iff A^T A \preceq t^2 I, \quad t \ge 0$$

$$\iff \begin{bmatrix} tI & A \\ A^T & tI \end{bmatrix} \succeq 0$$

Let X = [W B;
B' C]
Schur complement:
D = C - B' W^-1 B

If W in S_++ then
X in S_+ if and only if D in S_+

Assume this is X and you will see