ORF307 – Optimization

19. Linear optimization review

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Today's lecture

Linear optimization review

- Formulations
- Piecewise linear optimization
- Duality
- Sensitivity analysis
- Simplex method
- Interior point methods

Formulations

Linear optimization

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

- Minimization
- Less-than ineq. constraints
- Equality constraints

x is **feasible** if it satisfies the constraints $Ax \leq b$ and $Dx = f$

The **feasible set** is the set of all feasible points

$x^\star$ is **optimal** if it is feasible and $c^T x^\star \leq c^T x$ for all feasible x

The **optimal value** is $p^\star = c^T x^\star$

Unbounded problem: $c^T x$ is unbounded below on the feasible set ($p^\star = -\infty$)

Infeasible problem: feasible set is empty ($p^\star = +\infty$)

Feasibility problems

$$\begin{array}{ll} \text{find} & x \\ \text{subject to} & Ax \leq b \\ & Dx = f \end{array} \longrightarrow \begin{array}{ll} \text{minimize} & 0 \\ \text{subject to} & Ax \leq b \\ & Dx = f \end{array}$$

Possible results

- $p^\star = 0$ if constraints are feasible (consistent). (Every feasible x is optimal)
- $p^\star = \infty$ otherwise

Standard form

Definition

$$\begin{aligned} \text{minimize} \quad & c^T x \\ \text{subject to} \quad & Ax = b \\ & x \geq 0 \end{aligned}$$

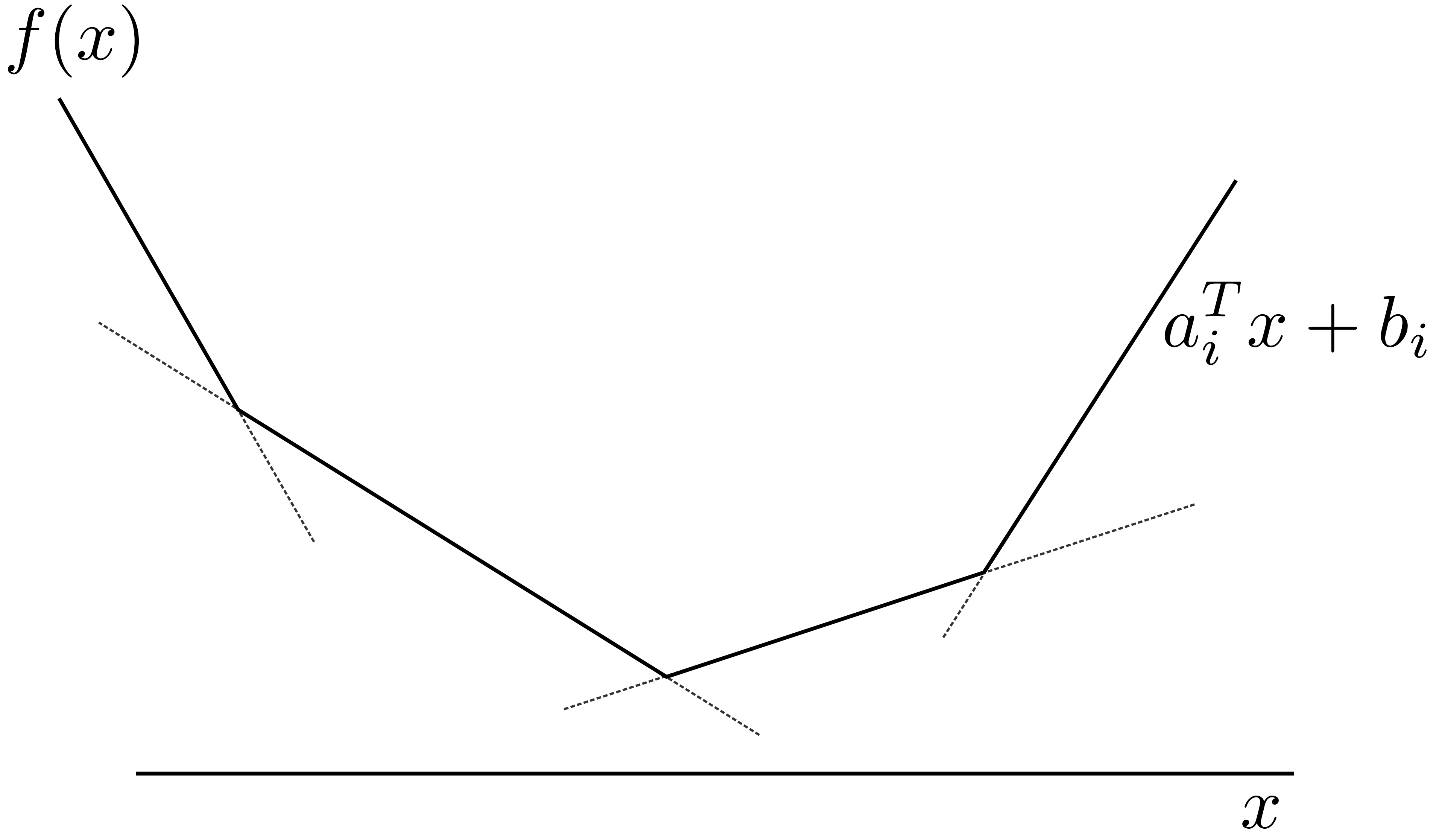
- Minimization
- Equality constraints
- Nonnegative variables

Useful to

- develop **algorithms**
- **algebraic** manipulations

Piecewise linear optimization

Piecewise-linear minimization



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

$\downarrow$

minimize $\quad t$

subject to $\quad a_i^T x + b_i \leq t, \quad i = 1, \ldots, m$

Matrix notation

minimize $\quad \tilde{c}^T \tilde{x}$

subject to $\quad \tilde{A}\tilde{x} \leq \tilde{b}$

$$\tilde{x} = \begin{bmatrix} x \\ t \end{bmatrix}, \quad \tilde{c} = \begin{bmatrix} 0 \\ 1 \end{bmatrix}, \quad \tilde{A} = \begin{bmatrix} a_1^T & -1 \\ \vdots & \vdots \\ a_m^T & -1 \end{bmatrix}, \quad \tilde{b} = \begin{bmatrix} -b_1 \\ \vdots \\ -b_m \end{bmatrix}$$

1 and infinity norms reformulations

1-norm minimization:

minimize $\|Ax - b\|_1 = \sum_i |(Ax - b)_i|$

Equivalent to:

minimize $\mathbf{1}^T u$

subject to $-u \leq Ax - b \leq u$

Absolute value of every element $(Ax - b)_i$ is bounded by a component of the **vector** u

∞-norm minimization:

minimize $\|Ax - b\|_\infty = \max_i |(Ax - b_i)_i|$

Equivalent to:

minimize t

subject to $-t\mathbf{1} \leq Ax - b \leq t\mathbf{1}$

Absolute value of every element $(Ax - b)_i$ is bounded by the same **scalar** t

Duality

Lagrangian and duality

Primal

minimize $c^T x$

subject to $Ax \leq b$

Dual

maximize $-b^T y$

subject to $A^T y + c = 0$

$y \geq 0$

Dual function

$$g(y) = \underset{x}{\text{minimize}} \left(c^T x + y^T (Ax - b)\right)$$

$$= -b^T y + \underset{x}{\text{minimize}} \left(c + A^T y\right)^T x$$

$$= \begin{cases} -b^T y & \text{if } c + A^T y = 0 \\ -\infty & \text{otherwise} \end{cases}$$

$\longrightarrow$

Lagrangian

$$L(x, y) = c^T x + y^T (Ax - b)$$

$$\nabla_x L(x, y) = c + A^T y = 0$$

Karush-Kuhn-Tucker conditions

Optimality conditions for linear optimization

Primal		Dual	
minimize	$c^T x$	maximize	$-b^T y$
subject to	$Ax \leq b$	subject to	$A^T y + c = 0$
			$y \geq 0$

Primal feasibility $\quad Ax \leq b$

Dual feasibility $\quad \nabla_x L(x, y) = A^T y + c = 0$ and $y \geq 0$

Complementary slackness $\quad y_i(Ax - b)_i = 0, \quad i = 1, \ldots, m$

General forms

Inequality form LP

minimize $c^T x$
subject to $Ax \leq b$

maximize $-b^T y$
subject to $A^T y + c = 0$
$y \geq 0$

Standard form LP

minimize $c^T x$
subject to $Ax = b$
$x \geq 0$

maximize $-b^T y$
subject to $A^T y + c \geq 0$

LP with inequalities and equalities

minimize $c^T x$
subject to $Ax \leq b$
$Dx = f$

maximize $-b^T y - f^T z$
subject to $A^T y + D^T z + c = 0$
$y \geq 0$

Weak duality

Theorem

If x, y satisfy:

- x is a feasible solution to the primal problem
- y is a feasible solution to the dual problem

$\longrightarrow$ $-b^T y \leq c^T x$

Proof

We know that $Ax \leq b$, $A^T y + c = 0$ and $y \geq 0$. Therefore,

$$0 \leq y^T(b - Ax) = b^T y - y^T Ax = c^T x + b^T y \qquad \blacksquare$$

Remark

- Any dual feasible y gives a **lower bound** on the primal optimal value
- Any primal feasible x gives an **upper bound** on the dual optimal value
- $c^T x + b^T y$ is the **duality gap**

Weak duality

Corollaries

Unboundedness vs feasibility

- Primal unbounded ($p^\star = -\infty$) $\Rightarrow$ dual infeasible ($d^\star = -\infty$)
- Dual unbounded ($d^\star = +\infty$) $\Rightarrow$ primal infeasible ($p^\star = +\infty$)

Optimality condition

If x, y satisfy:

- x is a feasible solution to the primal problem
- y is a feasible solution to the dual problem
- The duality gap is zero, *i.e.*, $c^T x + b^T y = 0$

Then x and y are **optimal solutions** to the primal and dual problem respectively

Strong duality

Primal

minimize $c^T x$

subject to $Ax = b$

$x \geq 0$

Dual

maximize $-b^T y$

subject to $A^T y + c \geq 0$

Theorem

If a linear optimization problem has an optimal solution, then

- so does its dual
- the optimal values of the primal and dual are equal

Relationship between primal and dual

	$p^\star = +\infty$	$p^\star$ finite	$p^\star = -\infty$
$d^\star = +\infty$	primal inf. dual unb.		
$d^\star$ finite		optimal values equal	
$d^\star = -\infty$	exception		primal unb. dual inf

Complementary slackness

Primal

minimize $\quad c^T x$

subject to $\quad Ax \leq b$

Dual

maximize $\quad -b^T y$

subject to $\quad A^T y + c = 0$

$\quad y \geq 0$

Theorem

Primal,dual feasible x, y are optimal if and only if

$$y_i(b_i - a_i^T x) = 0, \quad i = 1, \ldots, m$$

i.e., at optimum, $b - Ax$ and y have a **complementary sparsity** pattern:

$$y_i > 0 \quad \Rightarrow \quad a_i^T x = b_i$$
$$a_i^T x < b_i \quad \Rightarrow \quad y_i = 0$$

Complementary slackness

Primal

minimize $c^T x$

subject to $Ax \leq b$

Dual

maximize $-b^T y$

subject to $A^T y + c = 0$

$y \geq 0$

Proof

The duality gap at primal feasible x and dual feasible y can be written as

$$c^T x + b^T y = (-A^T y)^T x + b^T y = (b - Ax)^T y = \sum_{i=1}^{m} y_i (b_i - a_i^T x) = 0$$

Since all the elements of the sum are nonnegative, they must all be 0 ∎

For **feasible** x and y **complementary slackness** = **zero duality gap**

Example

minimize $\quad -4x_1 - 5x_2$

subject to
$$\begin{bmatrix} -1 & 0 \\ 2 & 1 \\ 0 & -1 \\ 1 & 2 \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix} \leq \begin{bmatrix} 0 \\ 3 \\ 0 \\ 3 \end{bmatrix}$$

Let's **show** that feasible $x = (1, 1)$ is optimal

Second and fourth constraints are active at x $\longrightarrow$ $y = (0, y_2, 0, y_4)$

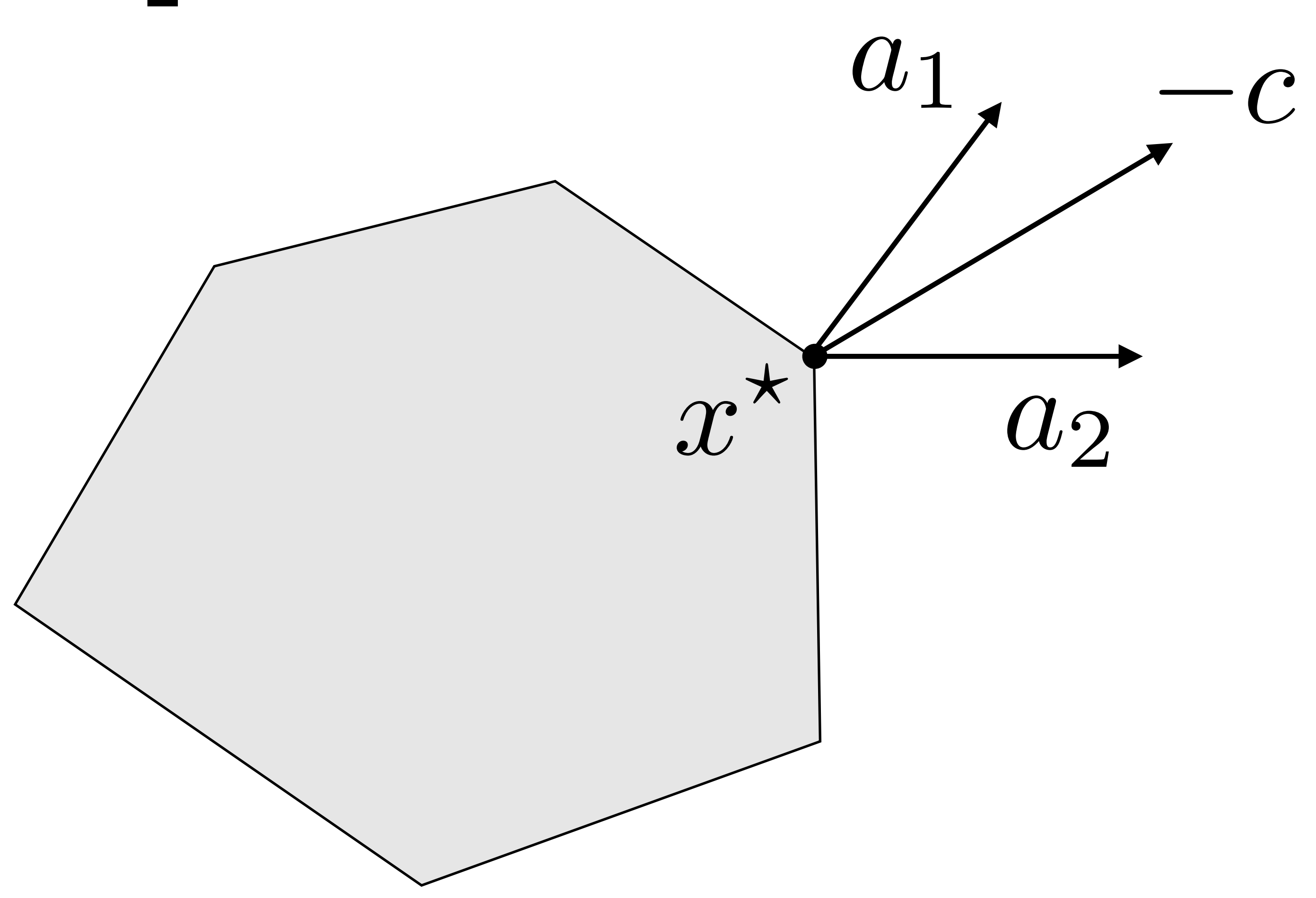
$$A^T y = -c \quad \Rightarrow \quad \begin{bmatrix} 2 & 1 \\ 1 & 2 \end{bmatrix} \begin{bmatrix} y_2 \\ y_4 \end{bmatrix} = \begin{bmatrix} 4 \\ 5 \end{bmatrix}$$
and
$$y_2 \geq 0, \quad y_4 \geq 0$$

$y = (0, 1, 0, 2)$ satisfies these conditions and proves that x is optimal

Complementary slackness is useful to recover $y^\star$ from $x^\star$

Geometric interpretation

Example in $\mathbf{R}^2$



Two active constraints at optimum: $a_1^T x^\star = b_1, \quad a_2^T x^\star = b_2$

Optimal dual solution y satisfies:

$$A^T y + c = 0, \quad y \geq 0, \quad y_i = 0 \text{ for } i \neq \{1, 2\}$$

In other words, $-c = a_1 y_1 + a_2 y_2$ with $y_1, y_2 \geq 0$

Sensitivity analysis

Changes in problem data

Goal: extract information from $x^\star, y^\star$ about their sensitivity with respect to changes in problem data

Modified LP

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

Optimal value function

$$p^\star(u) = \min\{c^T x \mid Ax = b + u,\ x \geq 0\}$$

Assumption: $p^\star(0)$ is finite

Properties

- $p^\star(u) > -\infty$ everywhere (from global lower bound)
- $p^\star(u)$ is piecewise-linear on its domain

Global sensitivity

Dual of modified LP

$$\begin{array}{ll} \text{maximize} & -(b+u)^T y \\ \text{subject to} & A^T y + c \geq 0 \end{array}$$

Global lower bound

Given $y^\star$ a dual optimal solution for $u = 0$, then

$$\begin{aligned} p^\star(u) &\geq -(b+u)^T y^\star \\ &= p^\star(0) - u^T y^\star \end{aligned}$$

(from weak duality and dual feasibility)

It holds for any u

Local sensitivity
u in neighborhood of the origin

Original LP

minimize $c^T x$
subject to $Ax = b$
$x \geq 0$

→

Optimal solution

Primal
$x_i = 0, \quad i \notin B$
$x_B^\star = A_B^{-1} b$

Dual $y^\star = -A_B^{-T} c_B$

Modified LP

minimize $c^T x$
subject to $Ax = b + u$
$x \geq 0$

Modified dual

maximize $-(b+u)^T y$
subject to $A^T y + c \geq 0$

Optimal basis does not change

Modified optimal solution

$$x_B^\star(u) = A_B^{-1}(b+u) = x_B^\star + A_B^{-1} u$$
$$y^\star(u) = y^\star$$

Derivative of the optimal value function

Modified optimal solution

$$x_B^\star(u) = A_B^{-1}(b+u) = x_B^\star + A_B^{-1}u$$
$$y^\star(u) = y^\star$$

Optimal value function

$$\begin{aligned} p^\star(u) &= c^T x^\star(u) \\ &= c^T x^\star + c_B^T A_B^{-1} u \\ &= p^\star(0) - y^{\star T} u \end{aligned}$$

(affine for small u)

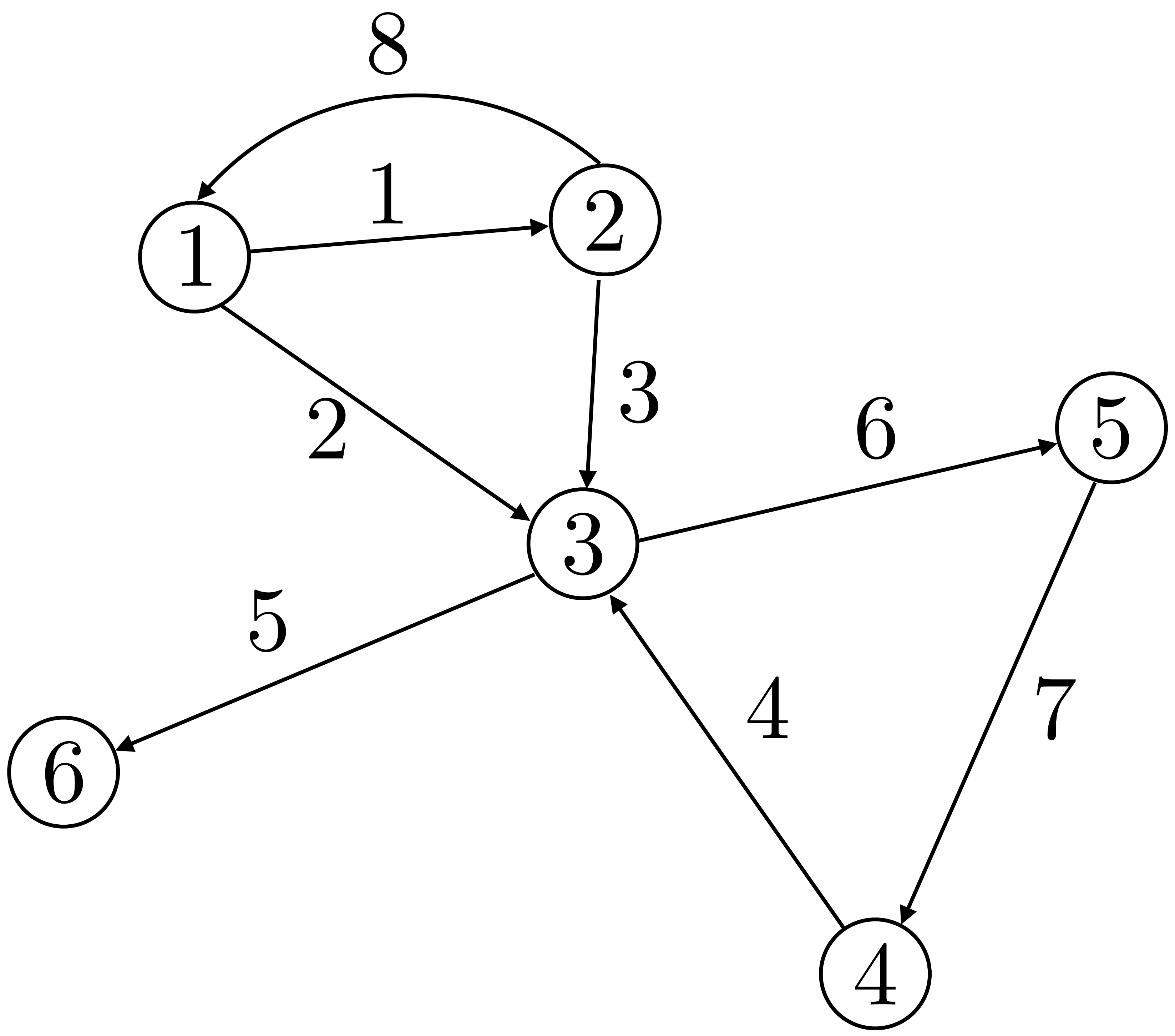
Local derivative

$$\nabla p^\star(u) = -y^\star$$

($y^\star$ are the **shadow prices**)

Network flow optimization

Arc-node incidence matrix



$m \times n$ matrix A with entries

$$A_{ij} = \begin{cases} 1 & \text{if arc } j \text{ starts at node } i \\ -1 & \text{if arc } j \text{ ends at node } i \\ 0 & \text{otherwise} \end{cases}$$

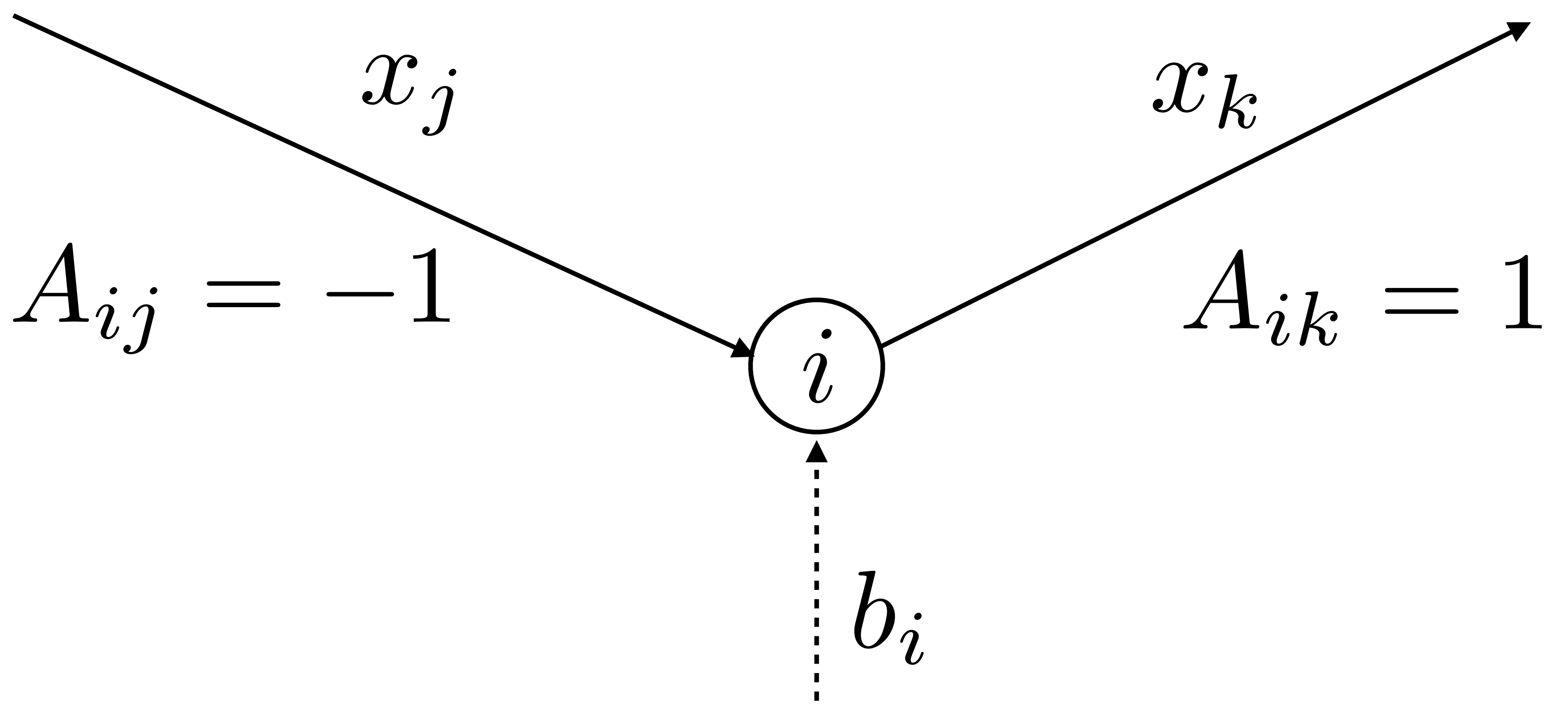
Note Each column has one -1 and one 1

$$A = \begin{bmatrix} 1 & 1 & 0 & 0 & 0 & 0 & 0 & -1 \\ -1 & 0 & 1 & 0 & 0 & 0 & 0 & 1 \\ 0 & -1 & -1 & -1 & 1 & 1 & 0 & 0 \\ 0 & 0 & 0 & 1 & 0 & 0 & -1 & 0 \\ 0 & 0 & 0 & 0 & 0 & -1 & 1 & 0 \\ 0 & 0 & 0 & 0 & -1 & 0 & 0 & 0 \end{bmatrix}$$

External supply

supply vector $b \in \mathbf{R}^m$

- b_i is the external supply at node i (if $b_i < 0$, it represents demand)
- We must have $\mathbf{1}^T b = 0$ (total supply = total demand)



Balance equations

$$\sum_{j=1}^{n} A_{ij} x_j = (Ax)_i = b_i, \quad \text{for all } i \quad \longrightarrow \quad Ax = b$$

$(Ax)_i$: Total leaving flow

b_i: Supply

Minimum cost network flow problem

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

- c_i is unit cost of flow through arc i
- Flow x_i must be nonnegative
- u_i is the maximum flow capacity of arc i
- Many network optimization problems are just special cases

Integrality theorem

Given a polyhedron $P = \{x \in \mathbf{R}^n \mid Ax = b, \quad x \geq 0\}$

where

- A is totally unimodular
- b is an integer vector

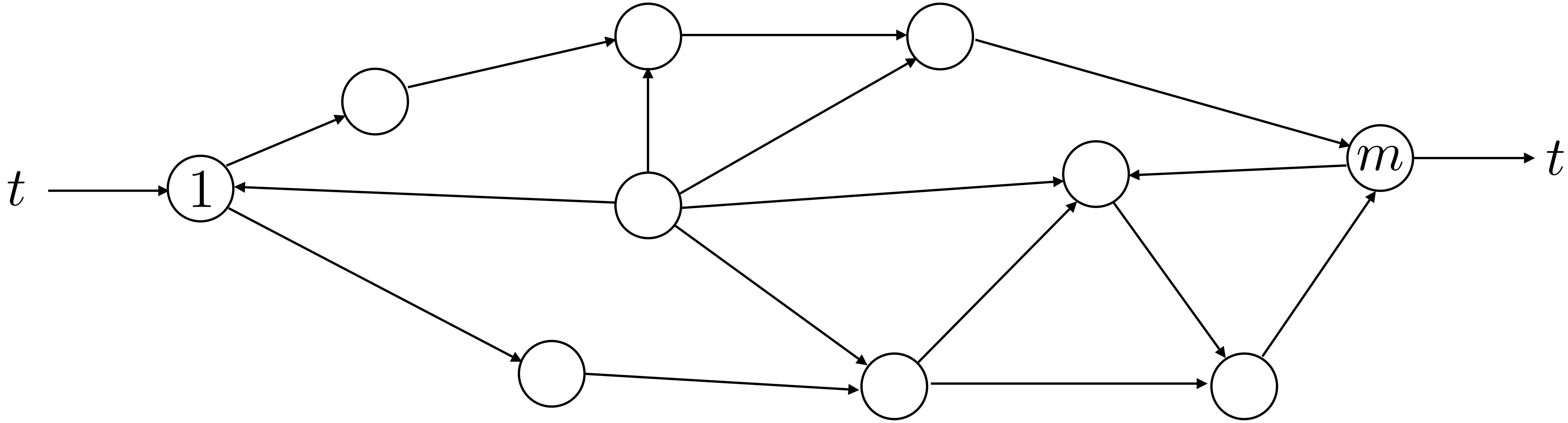
$\longrightarrow$ all the extreme points of P are integer vectors.

Proof

- All extreme points are basic feasible solutions with $x_B = A_B^{-1}b$ and $x_i = 0,\ i \neq B$
- A_B^{-1} has integer components because of total unimodularity of A
- b has also integer components
- Therefore, also x is integral ∎

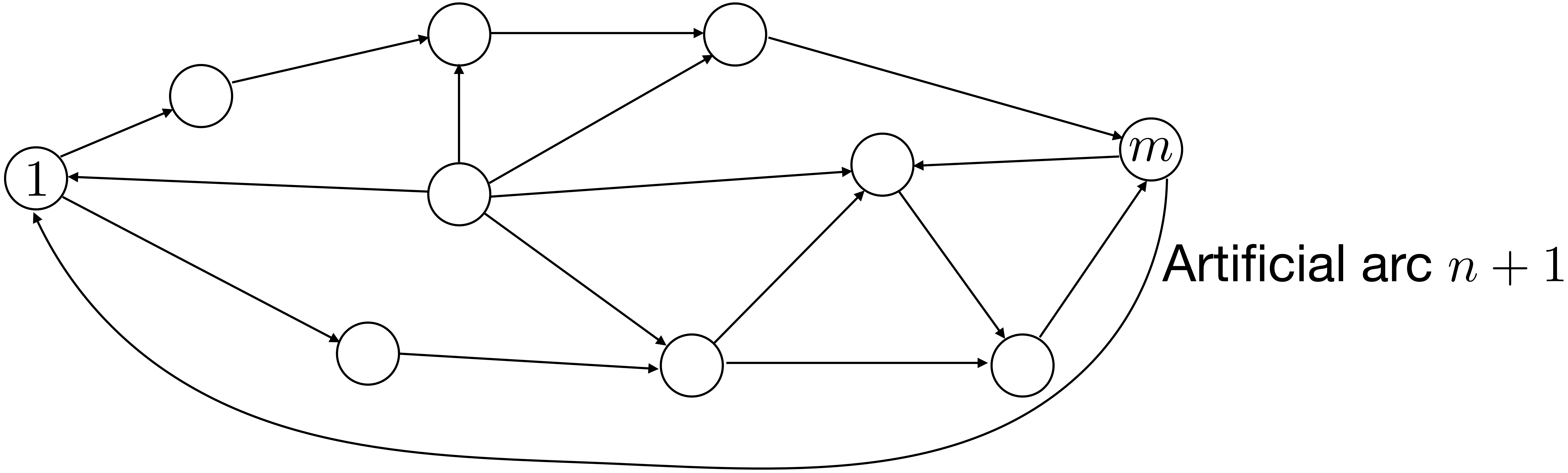
Maximum flow problem

Goal maximize flow from node 1 (source) to node m (sink) through the network



$$\begin{array}{ll} \text{maximize} & t \\ \text{subject to} & Ax = te \\ & 0 \leq x \leq u \end{array} \qquad e = (1, 0, \ldots, 0, -1)$$

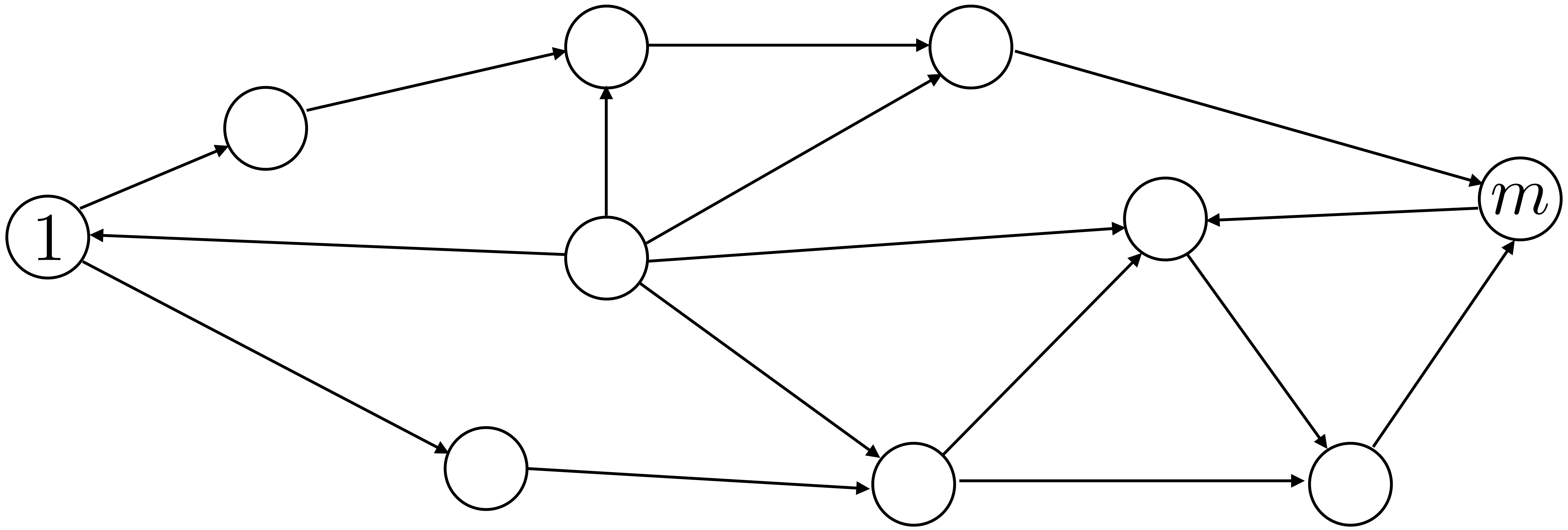
Maximum flow as minimum cost flow



$$\begin{array}{ll} \text{minimize} & -t \\ \text{subject to} & \begin{bmatrix} A & -e \end{bmatrix} \begin{bmatrix} x \\ t \end{bmatrix} = 0 \\ & 0 \le \begin{bmatrix} x \\ t \end{bmatrix} \le \begin{bmatrix} u \\ \infty \end{bmatrix} \end{array}$$

Shortest path problem

Goal Find the shortest path between nodes 1 and m



paths can be represented as vectors $x \in \{0,1\}^n$

Formulation

$$
\begin{array}{ll}
\text{minimize} & c^T x \\
\text{subject to} & Ax = e \\
& x \in \{0,1\}^n
\end{array}
$$

- c_j is the "length" of arc j
- $e = (1, 0, \ldots, 0, -1)$
- Variables are binary (include or not arc in path)

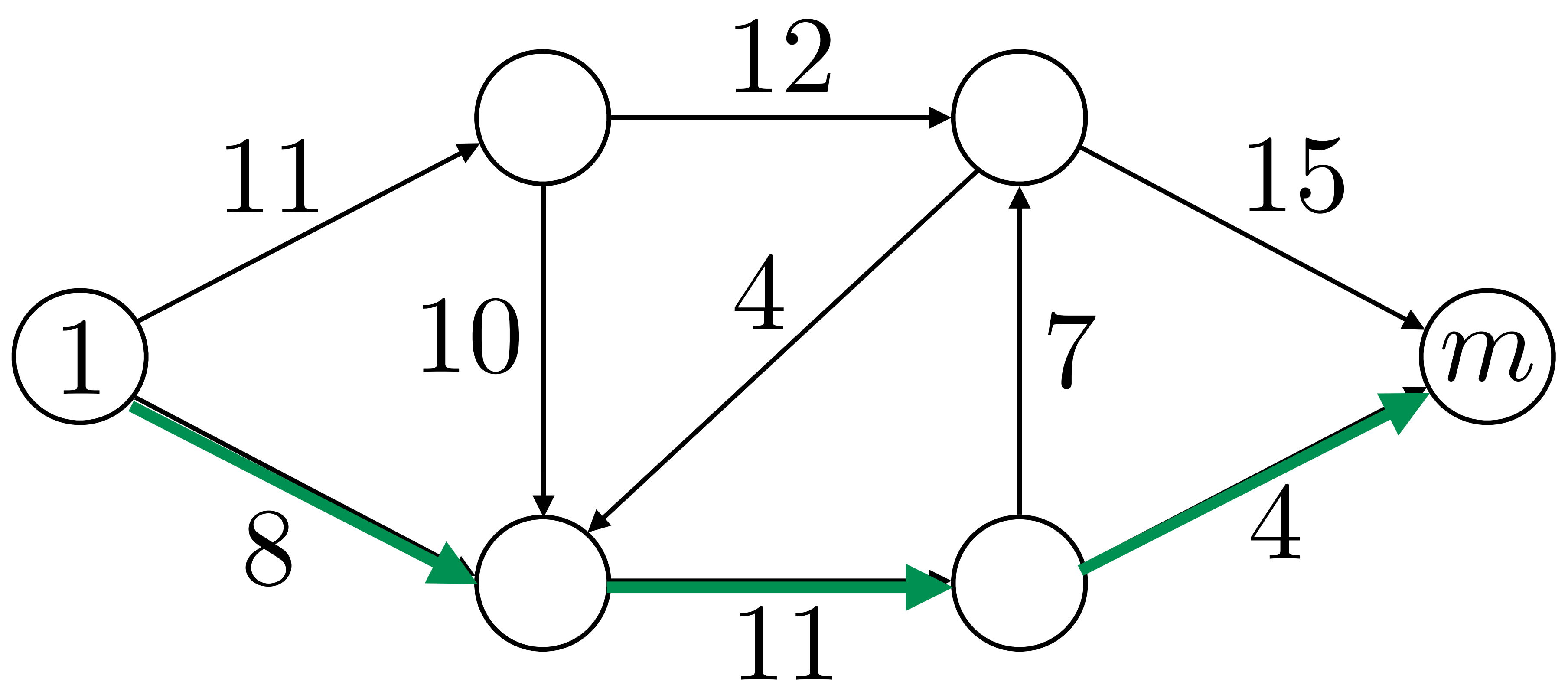
Shortest path as minimum cost flow

Relaxation

$$\begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & Ax = e \\ & x \in \{0,1\}^n \end{array} \longrightarrow \begin{array}{ll} \text{minimize} & c^T x \\ \text{subject to} & Ax = e \\ & 0 \leq x \leq 1 \end{array}$$

Extreme points satisfy $x_i \in \{0, 1\}$

Example (arc costs shown)



$$c = (11, 8, 10, 12, 4, 11, 7, 15, 4)$$

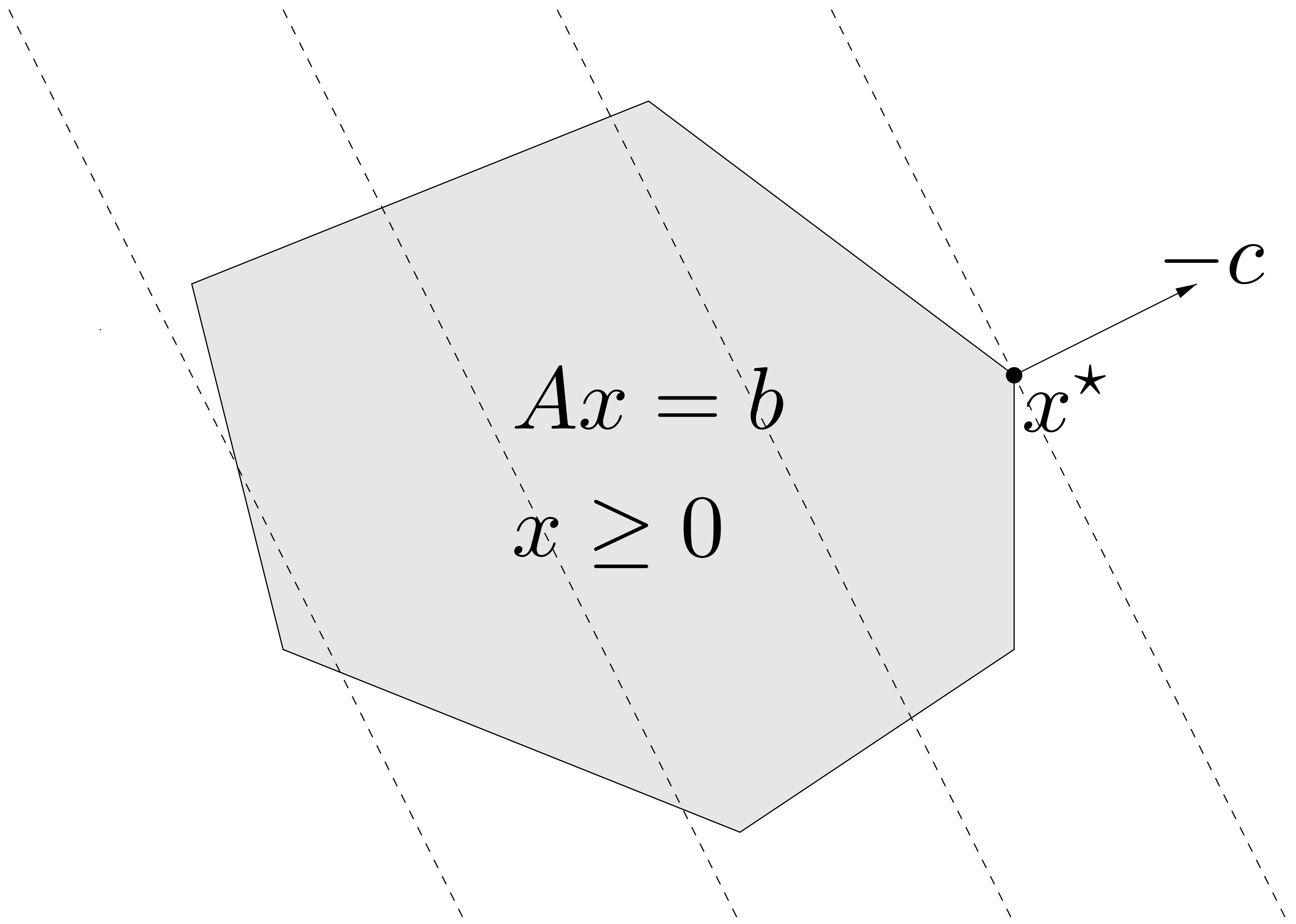
$$x^\star = (0, 1, 0, 0, 0, 1, 0, 0, 1)$$

$$c^T x^\star = 24$$

Simplex method

Optimality of extreme points

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



If
- P has at least one extreme point
- There exists an optimal solution $x^\star$

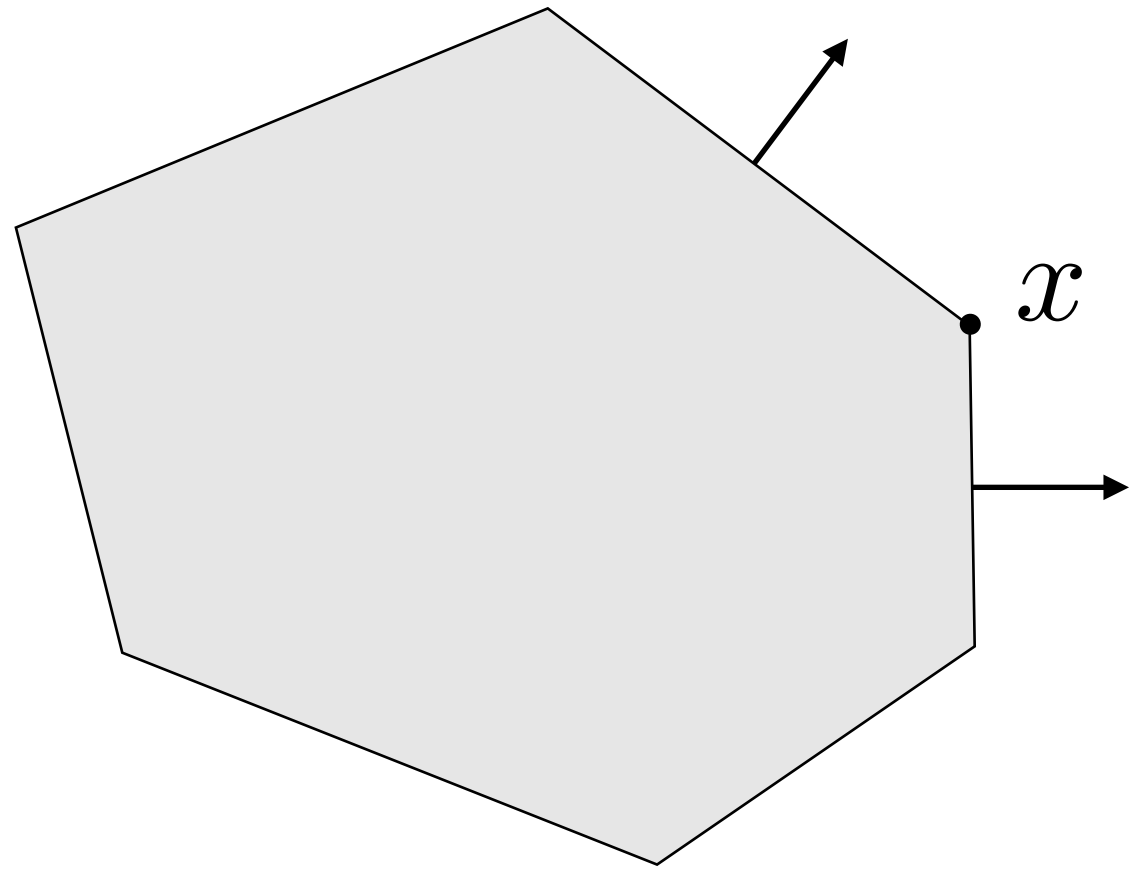
Then, there exists an optimal solution which is an **extreme point** of P

We only need to search between **extreme points**

Equivalence

Theorem

Given a nonempty polyhedron $P = \{x \mid Ax = b,\ x \geq 0\}$



Let $x \in P$

x is a **vertex** $\iff$ x is an **extreme point** $\iff$ x is a **basic feasible solution**

Constructing basic solution

1. Choose any m independent columns of A: $A_{B(1)}, \ldots, A_{B(m)}$
2. Let $x_i = 0$ for all $i \neq B(1), \ldots, B(m)$
3. Solve $Ax = b$ for the remaining $x_{B(1)}, \ldots, x_{B(m)}$

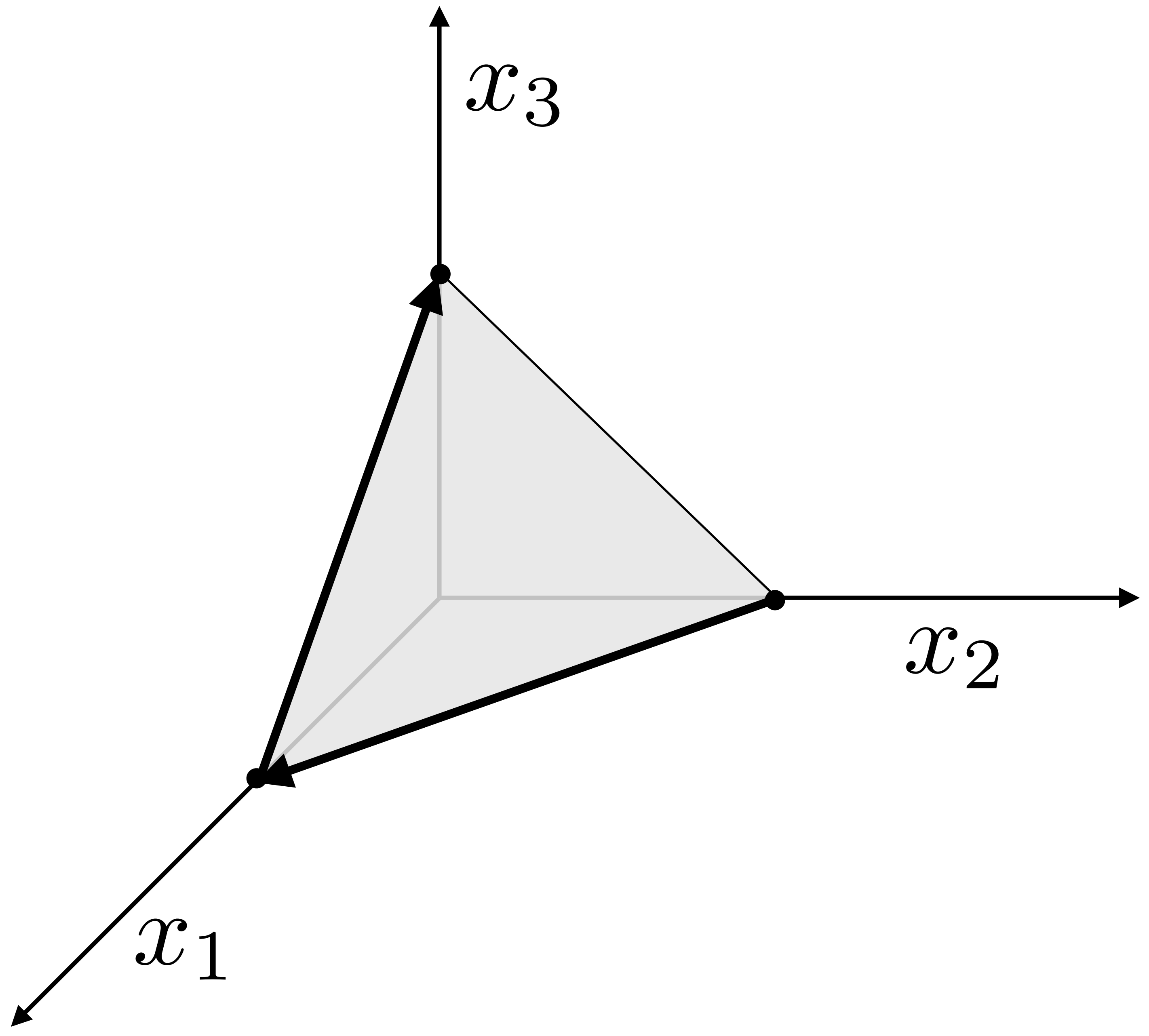
Basis matrix — Basis columns — Basic variables

$$A_B = \begin{bmatrix} | & | & & | \\ A_{B(1)} & A_{B(2)} & \ldots & A_{B(m)} \\ | & | & & | \end{bmatrix}, \quad x_B = \begin{bmatrix} x_{B(1)} \\ \vdots \\ x_{B(m)} \end{bmatrix} \longrightarrow \text{Solve} \quad A_B x_B = b$$

If $x_B \geq 0$, then x is a **basic feasible solution**

Conceptual algorithm

- Start at corner
- Visit neighboring corner that improves the objective



How does the cost change?

Cost improvement

$$c^T(x + \theta d) - c^T x = \theta c^T d$$

New cost

Old cost

We call $\bar{c}_j$ the **reduced cost** of (introducing) variable x_j in the basis

$$\bar{c}_j = c^T d = \sum_{i=1}^{n} c_j d_j = c_j + c_B^T d_B = c_j - c_B^T A_B^{-1} A_j$$

Optimality conditions

Theorem

Let x be a basic feasible solution associated with basis B

Let $\bar{c}$ be the vector of reduced costs.

If $\bar{c} \geq 0$, then x is **optimal**

Remark

This is a **stopping criterion** for the simplex algorithm.

If the **neighboring solutions** do not improve the cost, we are done

Single simplex iteration

1. Compute the reduced costs $\bar{c}$
   - Solve $A_B^T p = c_B$
   - $\bar{c} = c - A^T p$
2. If $\bar{c} \geq 0$, x **optimal. break**
3. Choose j such that $\bar{c}_j < 0$
4. Compute search direction d with $d_j = 1$ and $A_B d_B = -A_j$
5. If $d_B \geq 0$, the problem is **unbounded** and the optimal value is $-\infty$. **break**
6. Compute step length $\theta^\star = \min_{\{i \in B | d_i < 0\}} \left(-\frac{x_i}{d_i} \right)$
7. Define y such that $y = x + \theta^\star d$
8. Get new basis $\bar{B}$ (i exits and j enters)

Bottleneck
Two linear systems

→

Matrix inversion lemma trick
$\approx n^2$ per iteration
(very cheap)

How many iterations do we need?

Complexity of the simplex method

We do **not know any polynomial version of the simplex method**, no matter which pivoting rule we pick. → Still **open research question!**

Worst-case

There are problem instances where the simplex method will run an **exponential number of iterations** in terms of the dimensions, e.g. 2^n

Good news: average-case
Practical performance is very good. On average, it stops in n iterations.

Interior point method

Optimality conditions

Primal

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

Dual

$$\begin{array}{ll} \text{maximize} & -b^T y \\ \text{subject to} & A^T y + c = 0 \\ & y \geq 0 \end{array}$$

KKT conditions

$$\begin{aligned} Ax + s - b &= 0 \\ A^T y + c &= 0 \\ s_i y_i &= 0, \quad i = 1, \dots, m \\ s, y &\geq 0 \end{aligned}$$

$$S = \begin{bmatrix} s_1 & & & \\ & s_2 & & \\ & & \ddots & \\ & & & s_m \end{bmatrix} \qquad Y = \begin{bmatrix} y_1 & & & \\ & y_2 & & \\ & & \ddots & \\ & & & y_m \end{bmatrix}$$

$$\implies SY\mathbf{1} = 0$$

Main idea

$$h(x,s,y) = \begin{bmatrix} Ax + s - b \\ A^T y + c \\ SY\mathbf{1} \end{bmatrix} = 0 \qquad \begin{aligned} S &= \mathbf{diag}(s) \\ Y &= \mathbf{diag}(y) \end{aligned}$$

$$s, y \geq 0$$

- Apply variants of Newton's method to solve $h(x,s,y) = 0$
- Enforce $s, y > 0$ (strictly) at every iteration
- **Motivation** avoid getting stuck in "corners"

Issue

Pure **Newton's step** does not allow significant progress towards $h(x,s,y) = 0$ **and** $x, y \geq 0$.

Smoothed optimality conditions

Optimality conditions

$$
\begin{aligned}
Ax + s - b &= 0 \\
A^T y + c &= 0 \\
s_i y_i &= \tau \\
s, y &\geq 0
\end{aligned}
$$

← Same τ for every pair

Same optimality conditions for a “smoothed” version of our problem

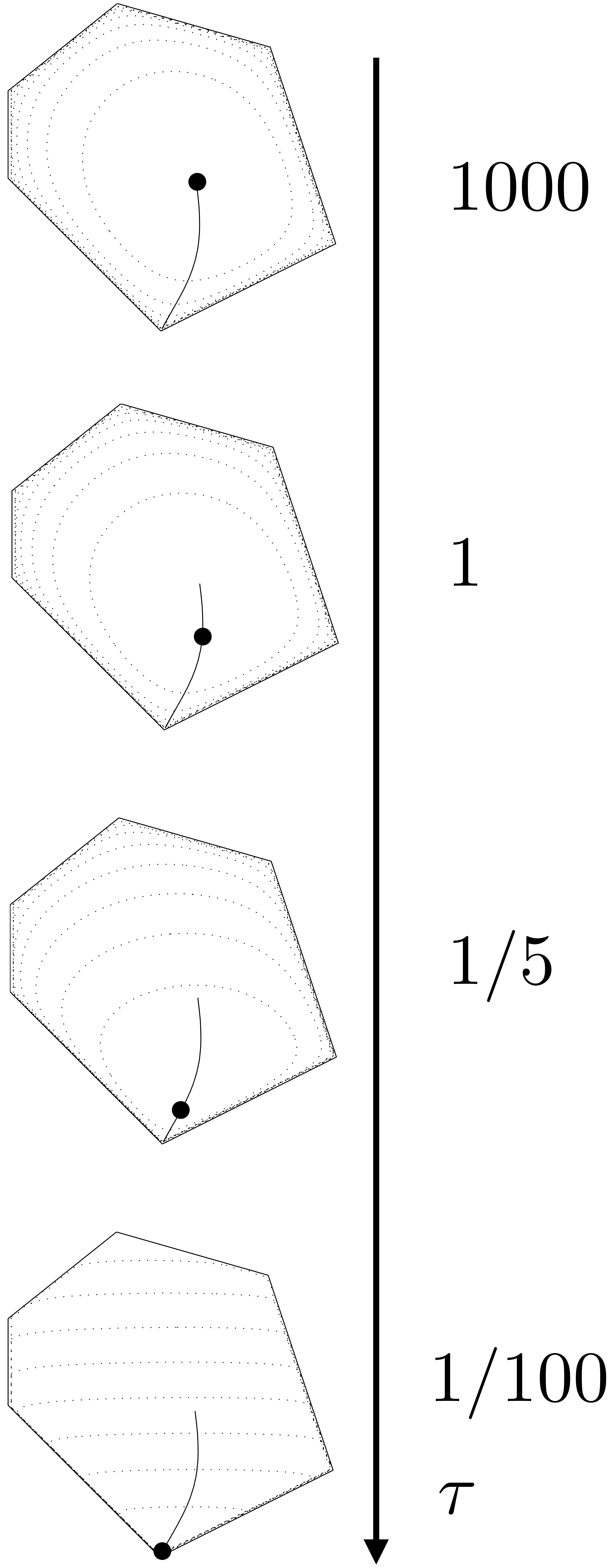
Central path

minimize $\quad c^T x - \tau \sum_{i=1}^m \log(s_i)$
subject to $\quad Ax + s = b$

Set of points $(x^\star(\tau), s^\star(\tau), y^\star(\tau))$
with $\tau > 0$ such that

$$Ax + s - b = 0$$
$$A^T y + c = 0$$
$$s_i y_i = \tau$$
$$s, y \geq 0$$

Analytic Center
$\tau \to \infty$



Main idea

Follow central path as $\tau \to 0$

Newton's method for smoothed optimality conditions

Smoothed optimality conditions

$$h_\tau(x, s, y) = \begin{bmatrix} Ax + s - b \\ A^T y + c \\ SY\mathbf{1} - \tau\mathbf{1} \end{bmatrix} = 0$$

$$s, y \geq 0$$

Linear system

$$\begin{bmatrix} 0 & A & I \\ A^T & 0 & 0 \\ S & 0 & Y \end{bmatrix} \begin{bmatrix} \Delta y \\ \Delta x \\ \Delta s \end{bmatrix} = \begin{bmatrix} -r_p \\ -r_d \\ -SY + \tau\mathbf{1} \end{bmatrix}$$

Line search to enforce $x, s > 0$

$$(x, s, y) \leftarrow (x, s, y) + \alpha(\Delta x, \Delta s, \Delta y)$$

Algorithm step

Linear system

$$\begin{bmatrix} 0 & A & I \\ A^T & 0 & 0 \\ S & 0 & Y \end{bmatrix} \begin{bmatrix} \Delta y \\ \Delta x \\ \Delta s \end{bmatrix} = \begin{bmatrix} -r_p \\ -r_d \\ -SY\mathbf{1} + \sigma\mu\mathbf{1} \end{bmatrix}$$

Duality measure

$$\mu = \frac{s^T y}{m}$$

Centering parameter

$\sigma \in [0, 1]$

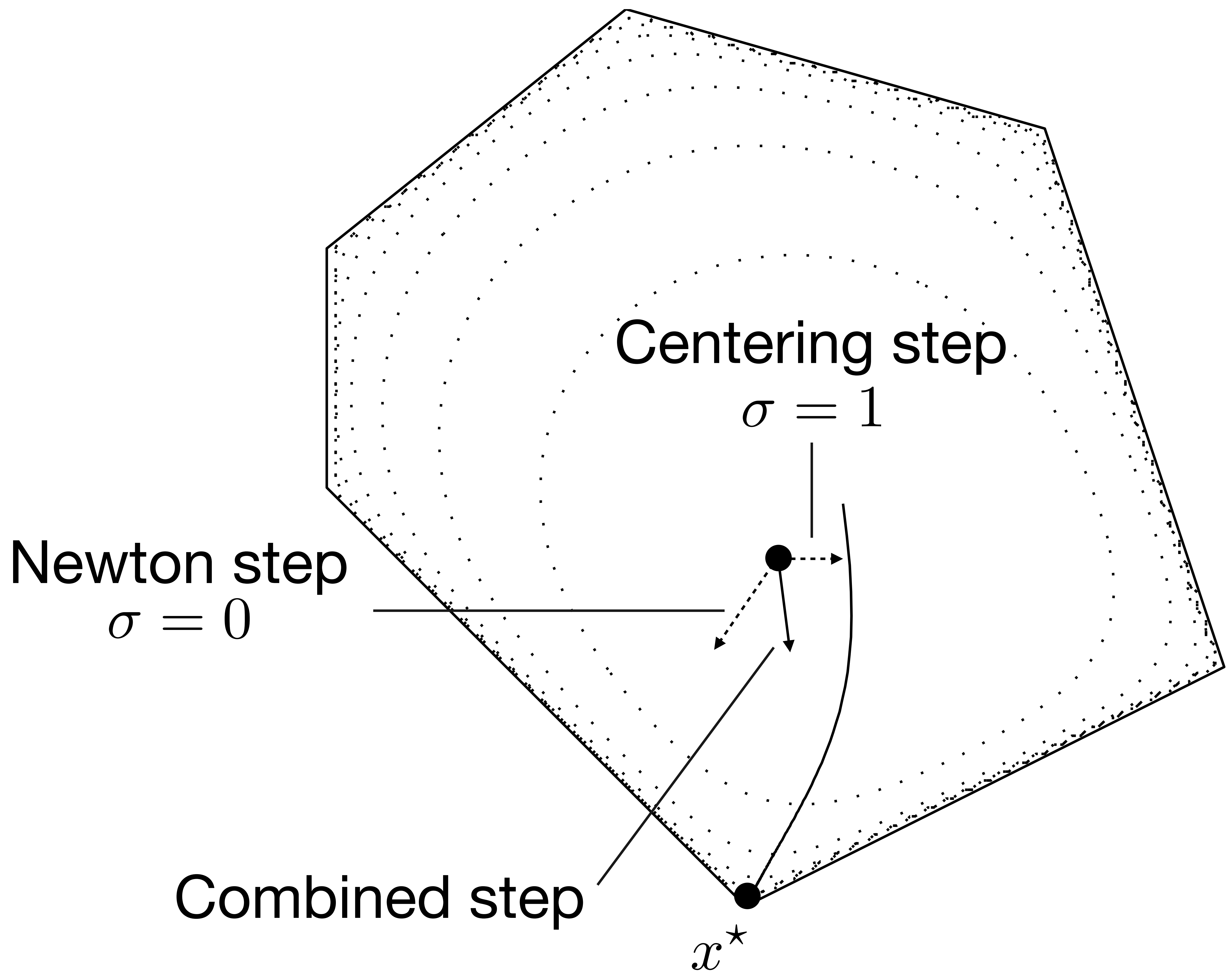
$\sigma = 0 \quad \Rightarrow$ Newton step

$\sigma = 1 \quad \Rightarrow$ Centering step towards $(x^\star(\mu), s^\star(\mu), y^\star(\mu))$

Line search to enforce $x, s > 0$

$$(x, s, y) \leftarrow (x, s, y) + \alpha(\Delta x, \Delta s, \Delta y)$$

Path-following algorithm idea



Centering step

Moves towards the **central path** and is usually biased towards $s, y > 0$. **No progress** on duality measure μ

Newton step

Moves towards the **zero duality measure** μ. Quickly violates $s, y > 0$.

Combined step

Best of both, with longer steps.

Convergence

Mehrotra's algorithm

No convergence theory → Examples where it **diverges** (rare!)

Fantastic convergence **in practice** → Fewer than 30 iterations

Theoretical iteration complexity

Alternative versions (slower than Mehrotra) converge in $O(\sqrt{n})$ iterations → **Operations** $O(n^{3.5})$

Average iteration complexity

Average iterations complexity is $O(\log n)$ → $O(n^3 \log n)$

Interior-point vs simplex

Comparison between interior-point method and simplex

Primal simplex

- Primal feasibility

↓

- Zero duality gap
- Dual feasibility

Dual simplex

- Dual feasibility

↓

- Zero duality gap
- Primal feasibility

Primal-dual interior-point

- Interior condition

↓

- Primal feasibility
- Dual feasibility
- Zero duality gap

Simplex	Primal-dual interior-point
Exponential worst-case complexity	**Polynomial worst-case complexity**
Requires feasible point	**Allows infeasible start**
Can be warm-started	**Cannot be warm-started**

Which algorithm should I use?

Dual simplex

- Small-to-medium problems
- Repeated solves with varying constraints

Interior-point (barrier)

- Medium-to-large problems
- Sparse structured problems

How do solvers with multiple options decide?

Concurrent Optimization

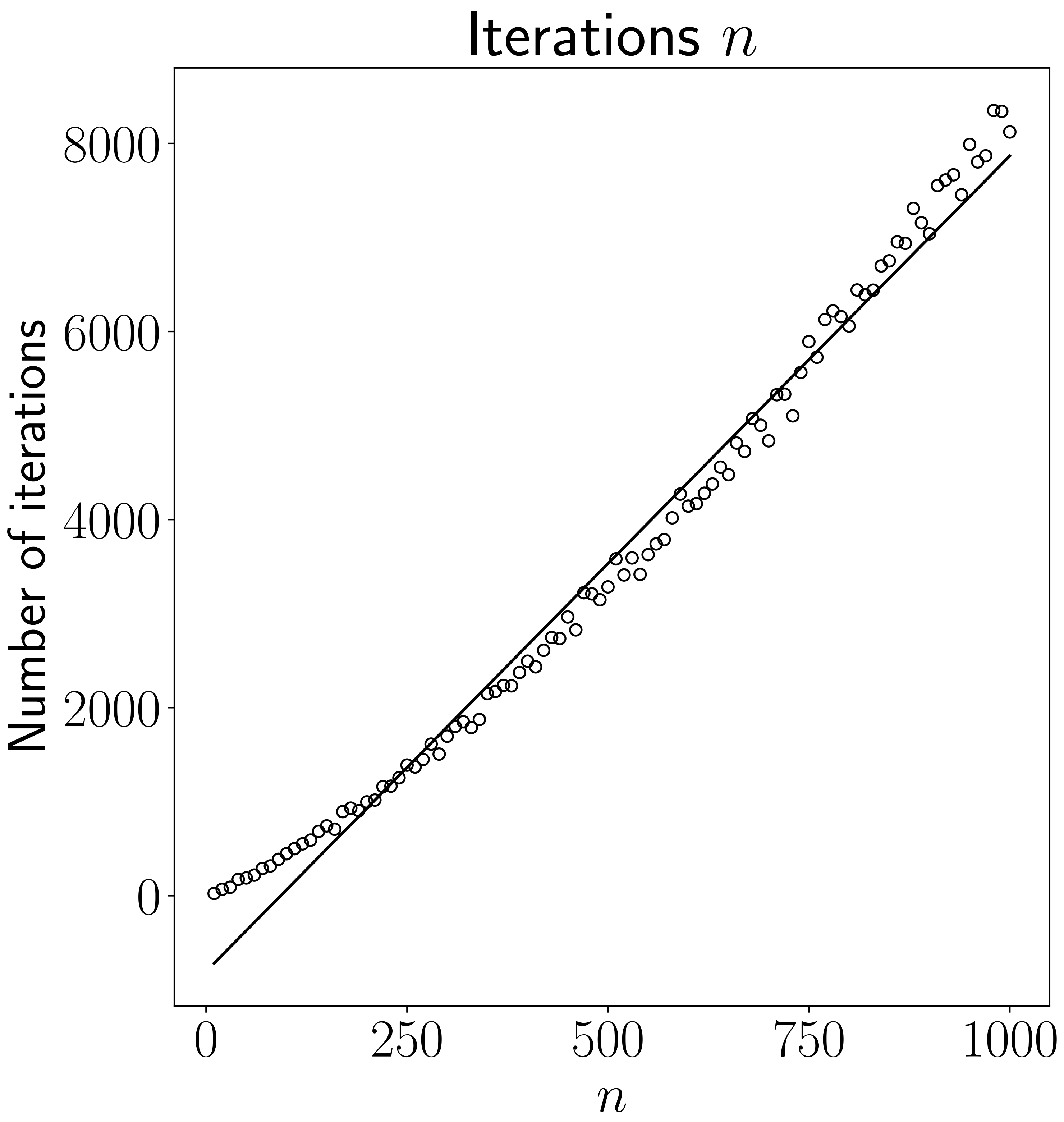
Why not both? (crossover)

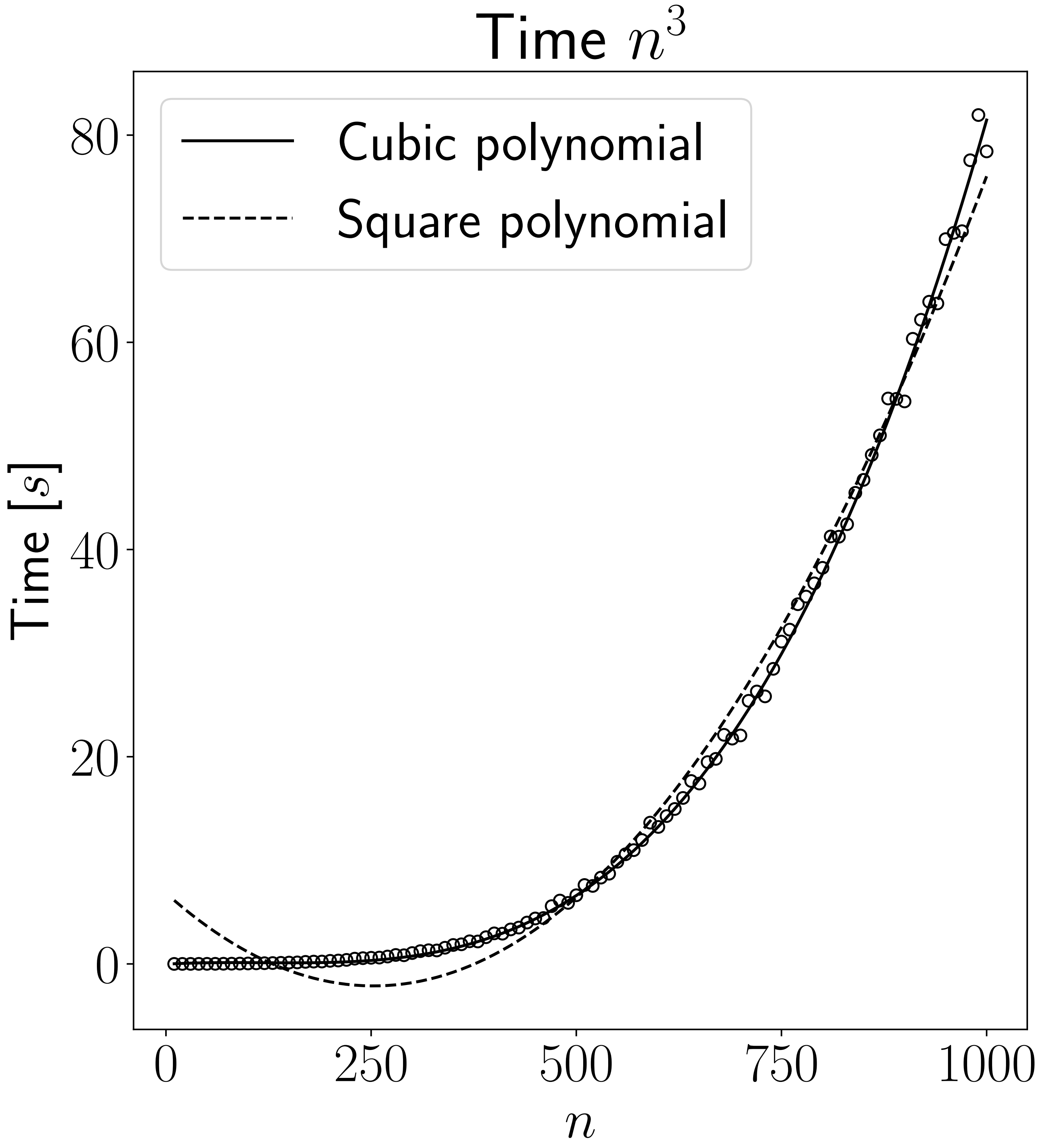
Interior-point → Few simplex steps

Average simplex complexity

Random LPs

minimize	$c^T x$	n variables
subject to	$Ax \leq b$	$3n$ constraints





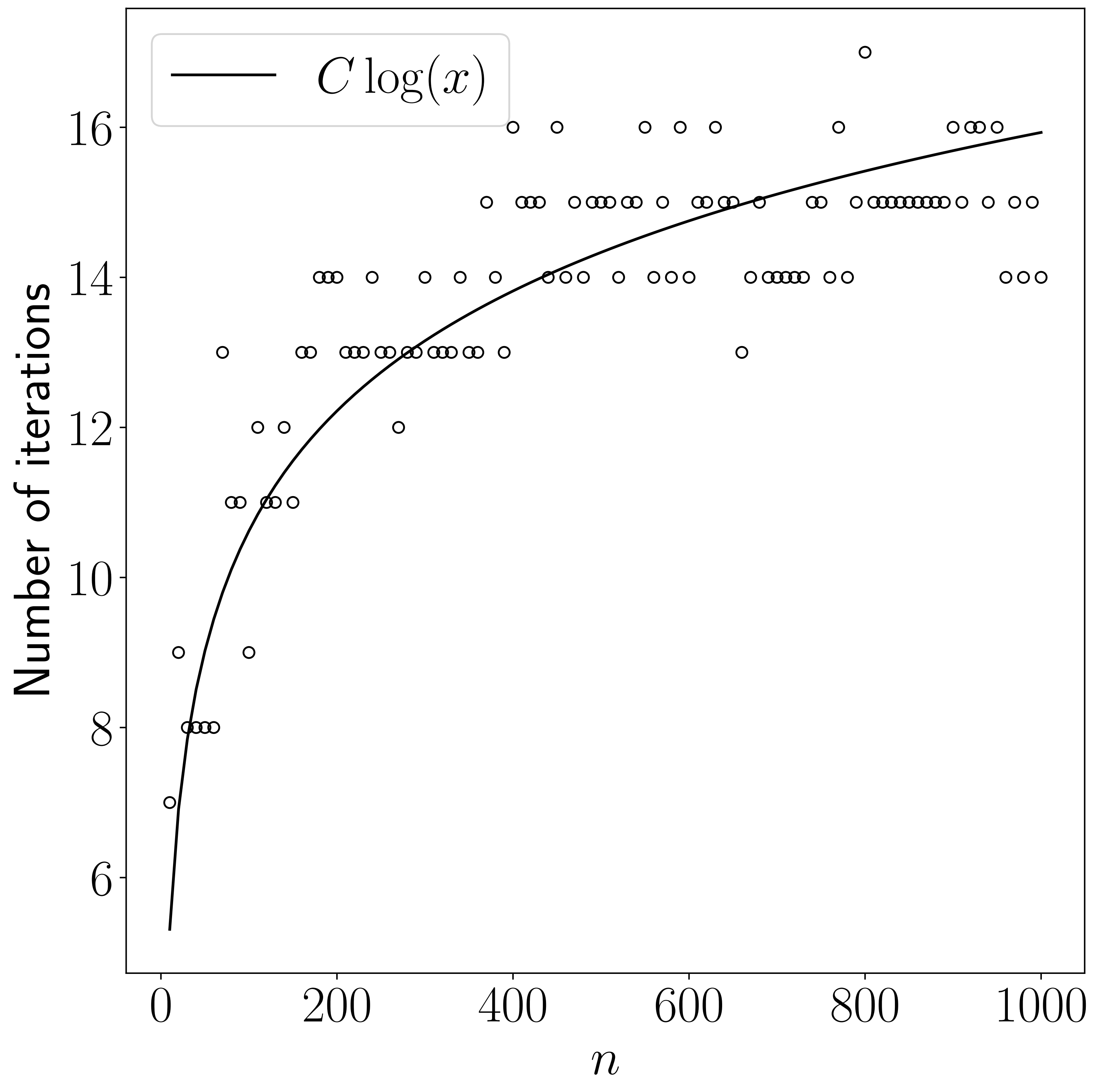
Average interior-point complexity

Random LPs

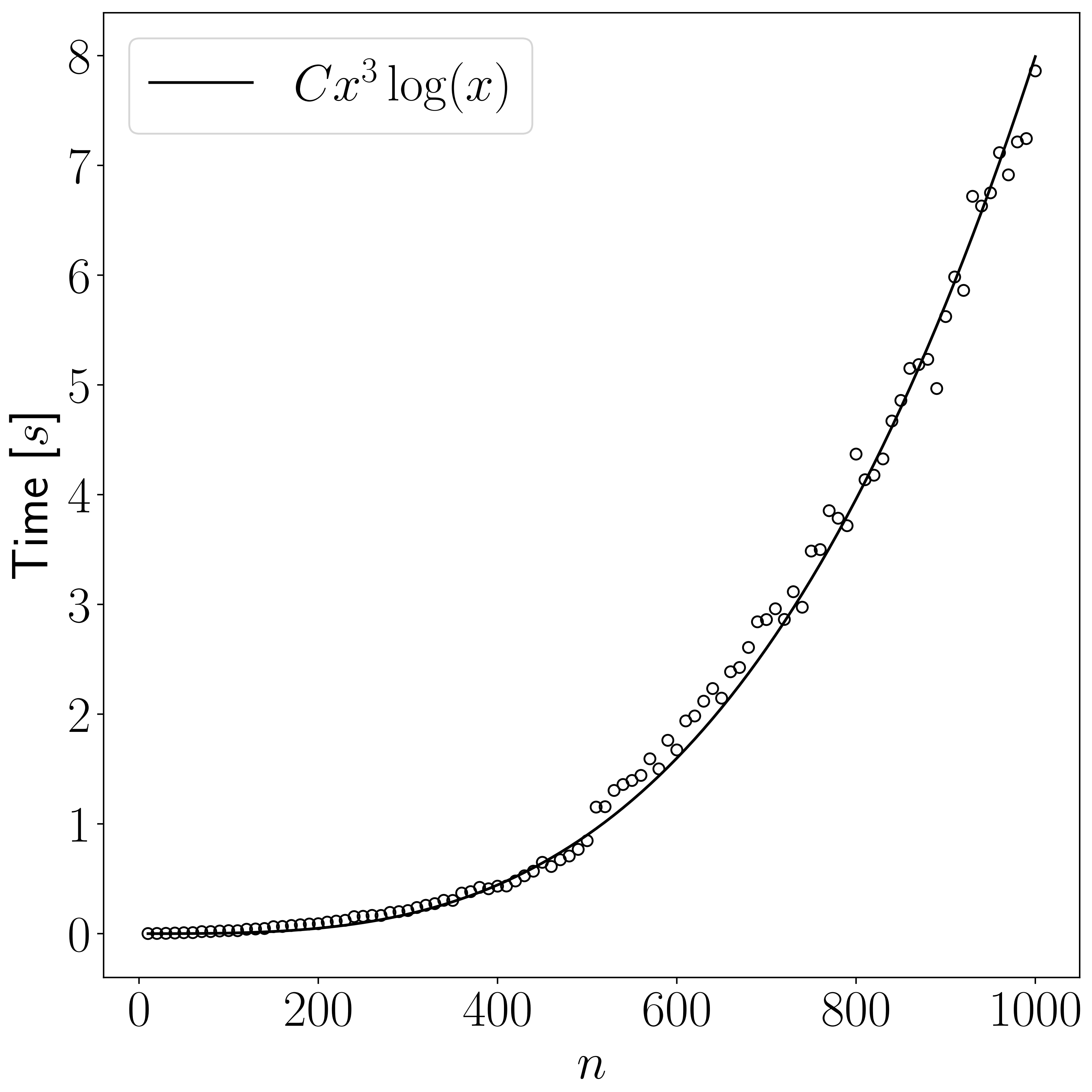
minimize $c^T x$
subject to $Ax \leq b$

n variables
$3n$ constraints

Iterations: $O(\log n)$



Time: $O(n^3 \log n)$



Questions

Next lecture

- Integer optimization