Complexity Guarantees for Polyak Steps with Momentum

Mathieu Barré, Adrien Taylor and Alexandre d'Aspremont



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(Drori & Teboulle 2014), (Lessard, Recht & Packard 2016), (Taylor, Hendrickx & Glineur 2017), and a few others.

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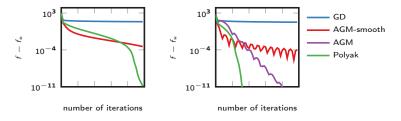


Figure: Regularized logistic regression. Left: regularization parameter 10^{-7} . Right: regularization parameter 10^{-4} .

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Looking for the smallest $\rho \ge 0$ such that $\|x_{k+1} - x_*\|^2 \le \rho \|x_k - x_*\|^2$.

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Problem : Infinite dimensional

Work with discrete version of f (Drori & Teboulle 2014), (Taylor, Hendrickx & Glineur 2017).

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Optimization problem can be relaxed and cast to a SDP.

$$\begin{split} \rho &:= & \text{maximize} \quad 1 + 4 \frac{f_k - f_*}{G_k} \frac{GX_k}{X_k} + 4 \frac{(f_k - f_*)^2}{G_k X_k} \\ & \text{subject to} \quad f_k - f_* + GX_k + \frac{1}{2L} G_k + \frac{\mu}{2(1 - \frac{\mu}{L})} \left(X_k + \frac{2}{L} GX_k + \frac{1}{L^2} G_k \right) \leq 0 \\ & f_* - f_k + \frac{1}{2L} G_k + \frac{\mu}{2(1 - \frac{\mu}{L})} \left(X_k + \frac{2}{L} GX_k + \frac{1}{L^2} G_k \right) \leq 0 \\ & \left(\begin{array}{c} X_k & GX_k \\ GX_k & G_k \end{array} \right) \geq 0 \end{split}$$

in the variables $X_k, G_k, GX_k, f_k, f_* \in \mathbb{R}$.

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Problem : nonlinear objective.

Performance Estimation approach on Polyak steps Add $\gamma = 2 \frac{f_k - f_*}{G_k}$ as constraint.

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For every step size value γ , we can solve the linear SDP

$$\rho(\gamma) := \max. \quad 1 + 2\gamma GX_k + 2(f_k - f_*)\gamma \\
\text{s.t.} \quad f_k - f_* + GX_k + \frac{1}{2L}G_k + \frac{\mu}{2(1 - \frac{\mu}{L})} \left(X_k + \frac{2}{L}GX_k + \frac{1}{L^2}G_k\right) \le 0 \\
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G_k\gamma = 2(f_k - f_*)
\end{cases}$$

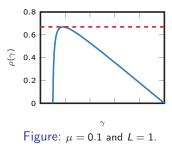
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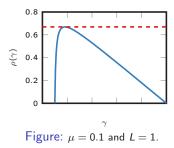


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(see the paper for an explicit expression of $\rho(\gamma)$)

Limit of worst case analysis

One can show $\rho = \left(\frac{L-\mu}{L+\mu}\right)^2$.

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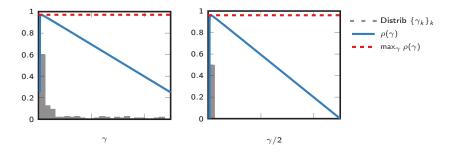


Figure: Empirical distribution of stepsizes $\{\gamma_k\}_k$. Left : Classical Polyak. Right : Variant with extra 2.

Introduce strong convexity estimate in Accelerated gradient descent with momentum (Nesterov 2018).

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Algorithm 2 Accelerated gradient method with Polyak steps momentum

Input: $x_0 \in \mathbb{R}^n$, $f_* \in \mathbb{R}$, L smoothness constant. $y_0 = x_0$, for $k \ge 0$ do $y_{k+1} = x_k - \frac{1}{L} \nabla f(x_k)$ $\tilde{\mu}_k = \frac{\|\nabla f(y_{k+1})\|^2}{2(f(y_{k+1}) - f_*)}$ and $\beta_k = \frac{\sqrt{L} - \sqrt{\tilde{\mu}_k}}{\sqrt{L} + \sqrt{\tilde{\mu}_k}}$ $x_{k+1} = y_{k+1} + \beta_k(y_{k+1} - y_k)$ end for Output: y_{k+1}

Complexity bounds (B., Taylor, d'Aspremont 2020) $f(y_N) - f_* \le C \left(1 + \sqrt[4]{\frac{\mu}{L}}\right)^{-N}$

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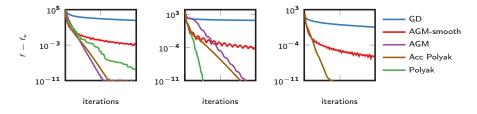


Figure: Numerical experiments on Musk Dataset. Left : Linear reg. Middle : Log reg. Right : LASSO.

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- A step in the direction of (proved) simple and fully adaptive accelerated algorithm.

Thanks!

Happy to answer (almost live) questions

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