

Problem 1. Let $f : \mathbb{R}^2 \rightarrow \mathbb{R}$ be a function given by

$$f(x, y) = xe^{-x^2-y^2}$$

whose gradient and Hessian are given respectively by

$$(\nabla f)(x, y) = e^{-x^2-y^2} [1 - 2x^2; -2xy]$$

and

$$(\nabla^2 f)(x, y) = e^{-x^2-y^2} \begin{bmatrix} 4x^3 - 6x & 4x^2y - 2y \\ 4x^2y - 2y & 4xy^2 - 2x \end{bmatrix}.$$

1. At the k -th iterate x_k , let

$$B_k = (\nabla^2 f)(x_k) + \delta_k I_2,$$

where $\delta_k \geq 0$ is chosen so that the minimal eigenvalue of B_k is not less than 10^{-5} . Write a matlab[®] function named B_k to generate such B_k for a given x_k :

$$B_k = \text{B_k}(x_k).$$

2. At the k -th iterate x_k , for a given trust region radius Δ_k consider solving the problem

$$\min_{p \in \mathbb{R}^n} m(p) = f(x_k) + \nabla f(x_k)^T p + \frac{1}{2} p^T B_k p \quad \text{subject to} \quad \|p\| \leq \Delta_k.$$

Write a matlab[®] function named Dogleg which implements the Dogleg method of finding an approximated value of the exact minimizer p_k^* :

$$p_k = \text{Dogleg}(x_k, B_k, \Delta_k).$$

3. Write a matlab[®] function named algorithm41 to implement Algorithm 4.1 (together with Dogleg of obtaining p_k) in the textbook/slides:

$$x_{\text{final}} = \text{algorithm41}(x_0, \Delta_0, \hat{\Delta}, \eta, \varepsilon, N),$$

where

- x_0 is the initial guess of the minimizer of f ,
- Δ_0 is the initial guess of the trust region radius,
- $\hat{\Delta}$ is the upper bound for trust region radius,
- η is the parameter which is used to judge if we will step forward ($x_{k+1} = x_k + p_k$),
- ε and N are the parameters for the stopping criteria: go on to the next step if $k \leq N$ and $\|\nabla f(x_k)\|_\infty > \varepsilon [1 + f(x_k)]$.
- x_{final} is the last iterate of the sequence.

4. Try various initial guess x_0 and Δ_0 (with $\hat{\Delta} = 10^{-2}$, $\eta = 0.1$, $\varepsilon = 10^{-5}$ and $N = 10^4$) to observe the performance of the trust region method.