Splitting Enables Overcoming the Curse of Dimensionality Jérôme Darbon CNRS/CMLA-Ecole Normale Supérieure de Cachan, darbon@cmla.ens-cachan.fr   Stanley Osher Mathematics, UCLA, Los Angeles, CA 90095-1555, sjo@math

$*$

Jérôme Darbon   Stanley Osher

February 29, 2016

Abstract

In this short note we briefly outline a new and remarkably fast algorithm for solving a a large class of high dimensional Hamilton-Jacobi (H-J) initial value problems arising in optimal control and elsewhere [1]. This is done without the use of grids or numerical approximations. Moreover, by using the level set method [8] we can rapidly compute projections of a point in $\mathbb{R}^n$, n large to a fairly arbitrary compact set [2]. The method seems to generalize widely beyond what will we present here to some nonconvex Hamiltonians, new linear programming algorithms, differential games and perhaps state dependent Hamiltonians.

1 Introduction

We begin with the HJ initial value problem

$$\begin{cases} \dfrac{\partial \varphi}{\partial t}(x,t) + H(\nabla_x \varphi(x,t)) = 0 & \text{in } \mathbb{R}^n \times (0,+\infty) \\ \varphi(x,0) = J(x) & \forall x \in \mathbb{R}^n. \end{cases} \tag{1}$$

We assume $J : \mathbb{R}^n \to \mathbb{R}$ is convex and one coercive, i.e., $\lim_{\|x\|_2 \to +\infty} \frac{J(x)}{\|x\|_2} = +\infty$, $H : \mathbb{R}^n \to \mathbb{R}$ is convex and positively one homogeneous (we sometimes relax all these assumptions).

A good example of this is

$$H(v) = \|v\|_2.$$

Here $\|v\|_p = (\Sigma_{i=1}^n |v_i|^p)^{\frac{1}{p}}$ for $p \geq 1$ and $\langle x, v \rangle = \Sigma_{i=1}^n x_i v_i$.

If we take for J a convex Lipschitz function having the property that, for Ω a convex compact set of $\mathbb{R}^n$

$$\begin{cases} J(x) < 0 & \text{for any } x \in \text{ int } \Omega \\ J(x) = 0 & \text{for any } x \in (\Omega \setminus \text{ int } \Omega) \\ J(x) > 0 & \text{for any } x \in (\mathbb{R}^n \setminus \Omega). \end{cases}$$

We call this level set initial data. Then the set of points for which $\varphi(x,t) = 0, \ t > 0$ are exactly those at a distance t, from the boundary of Ω. In fact given $\bar{x} \notin \Omega$, then the closest point x_{opt} from $\bar{x}$ to $(\Omega \setminus \text{ int } \Omega)$ is exactly

$$x_{\text{opt}} = \bar{x} - t\frac{\nabla \varphi(\bar{x}, t)}{\|\nabla \varphi(\bar{x}, t)\|_2}. \tag{2}$$

To solve (1) we use the Hopf formula [5]

$$\varphi(x,t) = (J^* + tH)^*(x) = -\min_{v \in R^n}\{J^*(v) + tH(v) - \langle x, v \rangle\},$$

where the Fenchel-Legendre transform $f^* : \mathbb{R}^n \to R \cup (+\infty)$ of the convex function f is defined by

$$f^*(v) = \sup_{x \in R^n} \{\langle v, x \rangle - f(x)\}.$$

Moreover, for free we get that the minimizer satisfies

$$\arg\min_{v \in \mathbb{R}^n}\{J^*(v) + tH(v) - \langle x, v \rangle\} = \nabla_x \varphi(x, t). \tag{3}$$

whenever $\varphi(\cdot, t)$ is differentiable at x. Let us note here that our algorithm computes $\varphi(x, t)$ but also $\nabla_x \varphi(x, t)$.

Also, we can use the Hopf-Lax formula [5, 6] to solve (1).

$$\varphi(x, t) = \min_{z \in \mathbb{R}^n}\left\{J(z) + tH^*\left(\frac{x - z}{t}\right)\right\} \tag{4}$$

for convex H.

From (4) it is easy to show that if we have k different initial value problems $i = 1, \ldots k$

$$\begin{cases} \dfrac{\partial \varphi_i}{\partial t}(x,t) + H(\nabla_x \varphi_i(x,t)) &= 0, \quad \text{in } \mathbb{R}^n \times (0, +\infty) \\ \varphi_i(x,0) &= J_i(x) \qquad \qquad \forall x \in \mathbb{R}^n \end{cases}$$

with the usual hypotheses, then (4) implies, for any $x \in \mathbb{R}^n$, $t > 0$

$$\varphi_i(x,t) = \min_{z \in R^n} \left\{ J_i(z) + tH^* \left(\frac{x-z}{t} \right) \right\}.$$

So

$$\min_{i=1,k} \varphi_i(x,t) = \min_{z \in R^n} \left\{ \min_{i=1,\ldots,k} \left\{ J_i(z) + tH^* \left(\frac{x-z}{t} \right) \right\} \right\}$$

solves the initial value problem

$$\begin{cases} \dfrac{\partial \varphi}{\partial t}(x,t) + H(\nabla_x \varphi(x,t)) &= 0, \quad \text{in } \mathbb{R}^n \times (0, +\infty) \\ \varphi(x,0) &= \min_{i=1,\ldots,k} J_i(x) \qquad \forall x \in \mathbb{R}^n. \end{cases} \tag{5}$$

This means that if $\Omega = \cup_{i=1,\ldots,k}\Omega_i$, each Ω_i is compact and convex and may overlap, then we can easily compute the set of all points at distance t from Ω which is exactly the solution to (5) where each J_i is a level set function for Ω_i. Moreover, at every point $\bar{x}$ outside of $\bar{\Omega}$ for which there is one i such that $\varphi_i(\bar{x},t) < \varphi_{i'}(\bar{x},t)$ for any $i \neq i'$, then the closest point x_{opt} to $\bar{x}$ and Ω is again

$$x_{\text{opt}} = \bar{x} - t\frac{\nabla_x \varphi_i(\bar{x},t)}{|\nabla_x \varphi_i(\bar{x},t)|}.$$

If there are several i for which $\varphi_i(\bar{x},t)$ is the minimum among all k of them, then $\nabla_x \varphi$ will be "multivalued", i.e. it will have jumps, but any of the x_{opt} defined above will be a closest point on Ω to $\bar{x}$.

2 Split Bregman

We solve the optimization problem (3) by using the split Bregman algorithm [4, 3, 9] as follows

$$v^{k+1} = \arg \min_{v \in \mathbb{R}^n} \{ J^*(v) - \langle x, v \rangle + \frac{\lambda}{2} \| d^k - v - b^k \|_2^2 \}, \tag{6}$$

$$d^{k+1} = \arg \min_{d \in \mathbb{R}^n} \left\{ tH(d) + \frac{\lambda}{2} \| d - v^{k+1} - b^k \|_2^2 \right\} \tag{7}$$

$$b^{k+1} = b^k + v^{k+1} - d^{k+1}. \tag{8}$$

Here the sequences $(v^k)_{k \in \mathbb{N}}, (d^k)_{k \in \mathbb{N}}$ both converge to $\nabla_x \varphi(x, t)$. Let us emphasize again that our numerical algorithm not only computes the solution $\varphi(x, t)$ but also computes $\nabla_x \varphi(x, t)$ when $\varphi(\cdot, t)$ is differentiable.

Both (6) and (7), up to change of variables, can be reformulated as finding the unique minimizer of

$$\arg\min_w \left\{ \alpha f(w) + \frac{1}{2} \|w - z\|_2^2 \right\}$$

which is the proximal map of f. Equation (6) can be solved if either J^* or J have easily computable proximal maps, which often occurs, especially if one of them is smooth.

Equation (7) can be easily solved if $H(d) = \|d\|_2$ via the shrink$_2$ operator defined by

$$\mathrm{shrink}_2(z, \alpha) = \begin{cases} \frac{z}{\|z\|_2} \max(\|z\|_2 - \alpha, 0) & \text{if } z \neq 0 \\ 0 & \text{if } z = 0 \end{cases}$$

and we have

$$\arg\min_w \left\{ \alpha \|w\|_2 + \frac{1}{2} \|w - z\|_2^2 \right\} = \mathrm{shrink}_2(z, \alpha)$$

If $H(d) = \|d\|_1$ we use shrink$_1$ operator defined as follows for any $i = 1, \ldots, n$

$$(\mathrm{shrink}_1(z, \alpha))_i = \begin{cases} z_i - \alpha & \text{if } z_i > \alpha \\ 0 & \text{if } |z_i| \leq \alpha \\ z_i + \alpha & \text{if } z_i < -\alpha \end{cases}$$

and we have

$$\arg\min_w \left\{ \alpha \|w\|_1 + \frac{1}{2} \|w - z\|_2^2 \right\} = \mathrm{shrink}_1(z, \alpha).$$

To solve (7) for more general $H(d)$ convex one homogeneous or to find the proximal map for f of that type we use the fact that H^* is the characteristic function of a closed convex set $C \subset \mathbb{R}^n$

$$H^* = I_c.$$

By using the Moreau identity [7] we realize that the proximal map of H can be obtained by projecting onto C. To do this projection, we merely solve the eikonal equation with level set initial data for C via split Bregman as above in (6), (7), (8) with $H(d) = \|d\|_2$. This is easy using the shrink$_2$ operator. We then use (2) to obtain the projection and repeat the entire iteration.

3   Numerical simulation

Numerical experiments on an Intel Laptop Core i5-5300U running at 2.3 GHz are now presented. We consider diagonal matrices D defined by $D_{ii} = 1 + \frac{1+i}{n}$ for $i = 1, \ldots, n$. We also consider matrices A defined by $A_{ii} = 2$ for $i = 1, \ldots, n$ and $A_{ij} = 1$ for $i, j = 1, \ldots, n$. Table 1 presents the average time (in seconds) to evaluate the solution over 1,000,000 samples (x, t) uniformly drawn in $[-10, 10]^n \times [0, 10]$. The convergence is remarkably rapid: 10^{-6} to 10^{-8} seconds on a standard laptop, per function evaluation. Figure 1 depicts 2-dimensional slices at different times for the (H-J) equation with a weighted ℓ_1 Hamiltonian $H = \|D \cdot \|_1$, initial data $J = \frac{1}{2}\| \cdot \|_2^2$ and $n = 8$.

n	$\|y\|_1$	$\|y\|_2$	$\|y\|_\infty$	$\|y\|_D$	$\|y\|_A$
4	6.36e-08	1.20e-07	2.69e-07	7.00e-07	8.83e-07
8	6.98e-08	1.28e-07	4.89e-07	1.07e-06	1.57e-06
12	8.72e-08	1.56e-07	7.09e-07	1.59e-06	2.23e-06
16	9.24e-08	1.50e-07	9.92e-07	2.04e-06	2.95e-06

Table 1: Time results in seconds for the average time per call for evaluting the solution of the HJ-PDE with the initial data $J = \frac{1}{2}\| \cdot \|_2^2$, several Hamiltonians and various dimensions n.

4   Summary and Future Work

We have derived a very fast and totally parallelizable method to solve a large class of high dimensional, state independent H-J initial value problems. We do this suing the Hopf formula and convex optimization via splitting, which overcomes the "curse of dimensionality". This is also done without the use of grids or numerical approximations, yielding not only the solution, but also its gradient.

We also as a step in this procedure, very rapidly compute the projections from a point in $\mathbb{R}^n$, n large, to a fairly arbitrary compact set.

In future work, we expect to extend this set of ideas to nonconvex Hamiltonians, including some that arise in differential games, to new linear programming algorithms, to fast methods for redistancing in

level set methods and, hopefully, to a wide class of state dependent Hamiltonians.

References

[1] J. Darbon and S. Osher, *Algorithms for Overcoming the Curse of Dimensionality for Certain Hamilton-Jacobi Equations Arising in Control Theory and Elsewhere* UCLA CAM report 15-50. To appear.

[2] J. Darbon and S. Osher, *Fast projections onto compact sets in high dimensions using the level set method, Hopf formulas and optimization.* To appear.

[3] R. Glowinski and A. Marrocco, *Sur l'approximation par éléments finis d'ordre, et la resolution par pénalzation-dualité, d'une classe de problemémes de Dirichlet non-linéares*, C.R. hebd. Séanc. Acad. Sci., Paris 278, série A, (1974), pp. 1649-1652.

[4] T. Goldstein and S. Osher, *The Split Bregman Method for L_1 Regularized Problems*, SIAM J. on Imaging Science, v.2, (2), 2009, pp. 323-343.

[5] E. Hopf, *Generalized Solutions of Nonlinear Equations of the First Order*, J. Math. Mech., v.14, (1965), pp. 951-973.

[6] P. D. Lax, *Hyperbolic Systems of Conservation Laws and the Mathematical Theory of Conservation Laws*, SIAM, 1973

[7] J.-J. Moreau. *Proximité et dualité dans un espace hilbertien.* Bulletin Spc. Math. France, 93, pp. 273–299, 1965.

[8] S. Osher and J.A. Sethian, *Fronts Propagating with Curvature Dependent Speech: Algorithms Based on Hamilton-Jacobi Formulations*, J. Comput. Phys., v.79, (1), (1988), pp. 12-49.

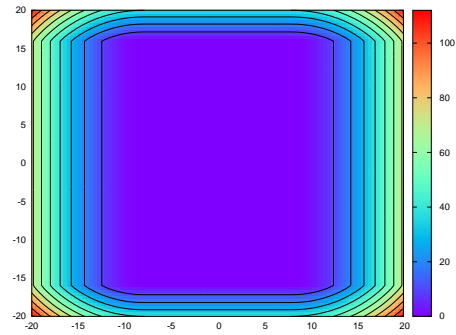[9] S. Osher and W. Yin, *Error Forgetting of Bregman Iteration*, J. Sci. Comput., v.54, (2), (2013), pp. 684-695.
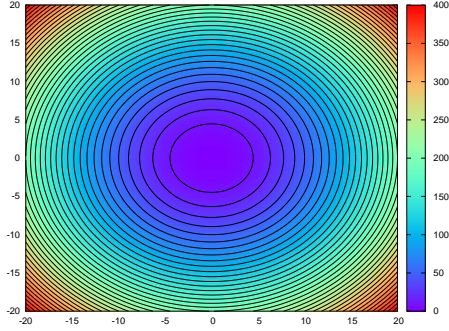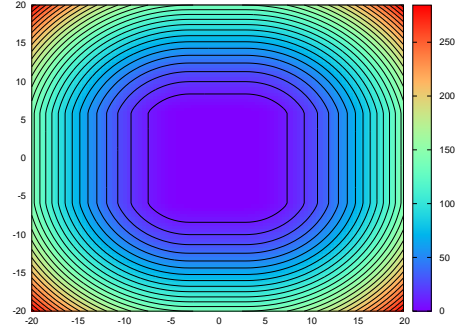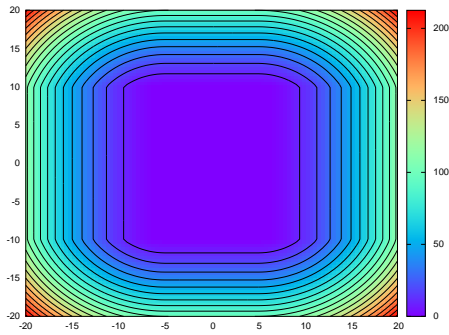
Figure 1: Evaluation of the solution $\phi((x_1, x_2, 0, 0, 0, 0, 0, 0)^\dagger, t)$ of the HJ-PDE with initial data $J = \frac{1}{2}\| \cdot \|_2^2$ and Hamiltonian $H = \|D \cdot \|_1$ for $(x_1, x_2) \in [-20, 20]^2$ for different times t. Plots for $t = 0, 3, 5, 8$ and respectively depicted in (a), (b), (c) and (d). The level lines multiple of 10 are superimposed on the plots.

7