

Parallel and Distributed Methods for Nonconvex Optimization—Part I: Theory

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Abstract—In this two-part paper, we propose a general algorithmic framework for the minimization of a nonconvex smooth function subject to *nonconvex* smooth constraints. The algorithm solves a sequence of (*separable*) *strongly convex* problems and maintains feasibility at each iteration. Convergence to a stationary solution of the original nonconvex optimization is established. Our framework is very general and flexible and unifies several existing Successive Convex Approximation (SCA)-based algorithms. More importantly, and differently from current SCA approaches, it naturally leads to *distributed and parallelizable* implementations for a large class of nonconvex problems.

This Part I is devoted to the description of the framework in its generality. In Part II we customize our general methods to several multi-agent optimization problems, mainly in communications and networking; the result is a new class of *centralized and distributed* algorithms that compare favorably to existing ad-hoc (centralized) schemes.

I. INTRODUCTION

THE minimization of a nonconvex (smooth) objective function $U : \mathcal{K} \rightarrow \mathbb{R}$ subject to convex constraints \mathcal{K} and nonconvex ones $g_j(\mathbf{x}) \leq 0$, with $g_j : \mathcal{K} \rightarrow \mathbb{R}$ smooth,

$$\begin{aligned} \min_{\mathbf{x}} \quad & U(\mathbf{x}) \\ \text{s.t.} \quad & \left. \begin{aligned} g_j(\mathbf{x}) \leq 0, \quad j = 1, \dots, m \\ \mathbf{x} \in \mathcal{K} \end{aligned} \right\} \triangleq \mathcal{X}, \end{aligned} \quad (\mathcal{P})$$

is an ubiquitous problem that arises in many fields, ranging from signal processing to communication, networking, machine learning, etc.

It is hardly possible here to even summarize the huge amount of solution methods that have been proposed for problem (\mathcal{P}) . Our focus in this paper is on *distributed* algorithms converging to stationary solutions of \mathcal{P} while *preserving the feasibility of the iterates*. While the former feature needs no further comment, the latter is motivated by several reasons. First, in many cases the objective function U is not even defined outside the feasible set; second, in some applications one may have to interrupt calculations before a solution has been reached and it is then important that the current iterate is feasible; and third, in on-line implementations it is mandatory that some constraints are satisfied by every iterate (e.g., think

of power budget or interference constraints). As far as we are aware of, there exists no method for the solution of \mathcal{P} in its full generality that is both feasible *and* distributed.

Existing efforts pursuing the above design criteria include: 1) Feasible Interior Point (FIP) methods (e.g., [4], [5]), 2) Feasible Sequential Quadratic Programming (FSQP) methods (e.g., [6]); 3) Parallel Variable Distribution (PVD) schemes (e.g., [7]–[9]); 4) SCA algorithms (in the spirit of [10]–[15]); and some specialized algorithms with roots in the structural optimization field (e.g., [16]–[18]). FIP and FSQP methods maintain feasibility throughout the iterations but are centralized and computationally expensive. PVD schemes are suitable for implementation over parallel architectures but they require an amount of information exchange/knowledge that is often not compatible with a distributed architecture (for example they cannot be applied to the case study discussed in Part II of the paper [19]). Furthermore, when applied to problem \mathcal{P} , they call for the solution of possibly difficult nonconvex (smaller) subproblems; and convergence has been established only for convex [7], [9] or nonconvex but block separable g_j s [8]. Standard SCA methods are centralized [10], [11], [15], with the exception of [13], [14] and some instances of [12] that lead instead to distributed schemes. However, convergence conditions have been established only in the case of *strongly convex* U [11] or *convex* and separable g_j s [12]–[14]. Finally, methods developed in the structural engineering field, including [16]–[18], share some similarities with our approach, but in most cases they lack reliable mathematical foundations or do not prove convergence to stationary points of the original problem \mathcal{P} . We refer to Sec. III-B for a more detailed discussion on existing works.

In this paper we propose a new framework for the general formulation \mathcal{P} which, on one hand, maintains feasibility and, on the other hand, leads, under very mild additional assumptions, to parallel and distributed solution methods. The essential, natural idea underlying the proposed approach is to compute a solution of \mathcal{P} by solving a sequence of (simpler) strongly convex subproblems whereby the nonconvex objective function and constraints are replaced by suitable convex approximations; the subproblems can be then solved (under some mild assumptions) in a distributed fashion using standard primal/dual decomposition techniques (e.g., [20], [21]). Additional key features of the proposed method are: i) it includes as special cases several classical SCA-based algorithms, such as (proximal) gradient or Newton type methods, block coordinate (parallel) descent schemes, Difference of Convex (DC) functions approaches, convex-concave approximation methods; ii) our convergence conditions unify and extend to the general class \mathcal{P} those of current (centralized) SCA methods; iii) it offers much flexibility in the choice of the convex approximation functions: for instance, as a major departure from current

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SCA-based methods [applicable to special cases of \mathcal{P}] [10], [12] and DC programs [15], the proposed approximation of the objective function U need not be a tight *global upper bound* of U , a fact that significantly enlarges the range of applicability of our framework; and iv) by allowing alternative choices for the convex approximants, it encompasses a gamut of novel algorithms, offering great flexibility to control iteration complexity, communication overhead and convergence speed, and all converging under the *same* conditions. Quite interestingly, the proposed scheme leads to new efficient algorithms even when customized to solve well-researched problems, including power control problems in cellular systems [22]–[25], MIMO relay optimization [26], dynamic spectrum management in DSL systems [27], [28], sum-rate maximization, proportional-fairness and max-min optimization of SISO/MISO/MIMO ad-hoc networks [13], [29]–[31], robust optimization of CR networks [32]–[34], transmit beamforming design for multiple co-channel multicast groups [35], [36], and cross-layer design of wireless networks [37], [38]. Part II of the paper [19] is devoted to the application of the proposed algorithmic framework to some of the aforementioned problems (and their generalizations). Numerical results show that our schemes compare favorably to existing ad-hoc ones (when they exist).

The rest of this two-part paper is organized as follows. Sec. II introduces the main assumptions underlying the study of the optimization problem \mathcal{P} and provides an informal description of our new algorithms. Sec. III presents our novel framework based on SCA, whereas Sec. IV focuses on its distributed implementation in the primal and dual domain. Finally, Sec. V draws some conclusions. In Part II of the paper [19] we apply our algorithmic framework to several resource allocation problems in wireless networks and provide extensive numerical results showing that the proposed algorithms compare favorably to state-of-the-art schemes.

II. TECHNICAL PRELIMINARIES AND MAIN IDEA

In this section we introduce the main assumptions underlying the study of the optimization problem \mathcal{P} along with some technical results that will be instrumental to describe our approach. We also provide an informal description of our new algorithms that sheds light on the core idea of the proposed decomposition technique. The formal description of the framework is given in Sec. III.

Consider problem \mathcal{P} , whose feasible set is denoted by \mathcal{X} .

Assumption 1. We make the blanket assumptions:

- A1) $\mathcal{K} \subseteq \mathbb{R}^n$ is closed and convex (and nonempty);
- A2) U and each g_j are continuously differentiable on \mathcal{K} ;
- A3) $\nabla_{\mathbf{x}}U$ is Lipschitz continuous on \mathcal{K} with constant $L_{\nabla U}$.
- A4) U is coercive on \mathcal{K} .

The assumptions above are quite standard and are satisfied by a large class of problems of practical interest. In particular, A4 guarantees that the problem has a solution, even when the feasible set \mathcal{X} is not bounded. Note that we do not assume convexity of U and g_1, \dots, g_m ; without loss of generality, convex constraints, if present, are accommodated in the set \mathcal{K} .

Our goal is to efficiently compute locally optimal solutions of \mathcal{P} , possibly in a distributed way, while preserving the feasibility of the iterates. Building on the idea of SCA methods,

our approach consists in solving a sequence of *strongly convex inner* approximations of \mathcal{P} in the form: given $\mathbf{x}^\nu \in \mathcal{X}$

$$\begin{aligned} \min_{\mathbf{x}} \quad & \tilde{U}(\mathbf{x}; \mathbf{x}^\nu) \\ \text{s.t.} \quad & \left. \begin{aligned} \tilde{g}_j(\mathbf{x}; \mathbf{x}^\nu) \leq 0, \quad j = 1, \dots, m \\ \mathbf{x} \in \mathcal{K} \end{aligned} \right\} \triangleq \mathcal{X}(\mathbf{x}^\nu), \quad (\mathcal{P}_{\mathbf{x}^\nu}) \end{aligned}$$

where $\tilde{U}(\mathbf{x}; \mathbf{x}^\nu)$ and $\tilde{g}_j(\mathbf{x}; \mathbf{x}^\nu)$ represent approximations of $U(\mathbf{x})$ and $g_j(\mathbf{x})$ at the current iterate \mathbf{x}^ν , respectively, and $\mathcal{X}(\mathbf{x}^\nu)$ denotes the feasible set of $\mathcal{P}_{\mathbf{x}^\nu}$.

We introduce next a number of assumptions that will be used throughout the paper.

Assumption 2 (On \tilde{U}). Let $\tilde{U} : \mathcal{K} \times \mathcal{X} \rightarrow \mathbb{R}$ be a function continuously differentiable with respect to the first argument and such that:

B1) $\tilde{U}(\bullet; \mathbf{y})$ is uniformly strongly convex on \mathcal{K} with constant $c_{\tilde{U}} > 0$, i.e. $\forall \mathbf{x}, \mathbf{z} \in \mathcal{K}, \forall \mathbf{y} \in \mathcal{X}$

$$(\mathbf{x} - \mathbf{z})^T \left(\nabla_{\mathbf{x}} \tilde{U}(\mathbf{x}; \mathbf{y}) - \nabla_{\mathbf{x}} \tilde{U}(\mathbf{z}; \mathbf{y}) \right) \geq c_{\tilde{U}} \|\mathbf{x} - \mathbf{z}\|^2;$$

B2) $\nabla_{\mathbf{x}} \tilde{U}(\mathbf{y}; \mathbf{y}) = \nabla_{\mathbf{x}} U(\mathbf{y})$, for all $\mathbf{y} \in \mathcal{X}$;

B3) $\nabla_{\mathbf{x}} \tilde{U}(\bullet; \bullet)$ is continuous on $\mathcal{K} \times \mathcal{X}$;

where $\nabla_{\mathbf{x}} \tilde{U}(\mathbf{u}; \mathbf{w})$ denotes the partial gradient of \tilde{U} with respect to the first argument evaluated at $(\mathbf{u}; \mathbf{w})$.

Assumption 3 (On \tilde{g}_j s). Let each $\tilde{g}_j : \mathcal{K} \times \mathcal{X} \rightarrow \mathbb{R}$ satisfy the following:

C1) $\tilde{g}_j(\bullet; \mathbf{y})$ is convex on \mathcal{K} for all $\mathbf{y} \in \mathcal{X}$;

C2) $\tilde{g}_j(\mathbf{y}; \mathbf{y}) = g_j(\mathbf{y})$, for all $\mathbf{y} \in \mathcal{X}$;

C3) $g_j(\mathbf{x}) \leq \tilde{g}_j(\mathbf{x}; \mathbf{y})$ for all $\mathbf{x} \in \mathcal{K}$ and $\mathbf{y} \in \mathcal{X}$;

C4) $\tilde{g}_j(\bullet; \bullet)$ is continuous on $\mathcal{K} \times \mathcal{X}$;

C5) $\nabla_{\mathbf{x}} g_j(\mathbf{y}) = \nabla_{\mathbf{x}} \tilde{g}_j(\mathbf{y}; \mathbf{y})$, for all $\mathbf{y} \in \mathcal{X}$;

C6) $\nabla_{\mathbf{x}} \tilde{g}_j(\bullet; \bullet)$ is continuous on $\mathcal{K} \times \mathcal{X}$;

where $\nabla_{\mathbf{x}} \tilde{g}_j(\mathbf{y}; \mathbf{y})$ denotes the (partial) gradient of \tilde{g}_j with respect to the first argument evaluated at \mathbf{y} (the second argument is kept fixed at \mathbf{y}).

For some results we need stronger continuity properties of the (gradient of the) approximation functions.

Assumption 4

B4) $\nabla_{\mathbf{x}} \tilde{U}(\mathbf{x}; \bullet)$ is uniformly Lipschitz continuous on \mathcal{X} with constant $\tilde{L}_{\nabla, 2}$;

B5) $\nabla_{\mathbf{x}} \tilde{U}(\bullet; \mathbf{y})$ is uniformly Lipschitz continuous on \mathcal{K} with constant $\tilde{L}_{\nabla, 1}$;

C7) Each $\tilde{g}_j(\bullet; \bullet)$ is Lipschitz continuous on $\mathcal{K} \times \mathcal{X}$.

The key assumptions are B1, C1, and C3: B1 and C1 make $\mathcal{P}_{\mathbf{x}^\nu}$ strongly convex, whereas C3 guarantees $\mathcal{X}(\mathbf{x}^\nu) \subseteq \mathcal{X}$ (iterate feasibility). The others are technical conditions (easy to be satisfied in practice) ensuring that the approximations have the same local first order behavior of the original functions. In the next section we provide some examples of approximate functions that automatically satisfy Assumptions 2-4. As a final remark, we point out that Assumptions 1-3 are in many ways similar *but generally weaker* than those used in the literature in order to solve special cases of problem \mathcal{P} [10]–[14]. For instance, [12]–[14] studied the simpler case of convex constraints; moreover, [12] requires the convex approximation $\tilde{U}(\bullet; \mathbf{x}^\nu)$ to be a *global upper bound* of the nonconvex objective function $U(\bullet)$, while we do not. The upper bound

condition C3 is assumed also in [10], [11] but, differently from those works, we are able to handle also nonconvex objective functions (rather than only strongly convex ones). Our weaker conditions on the approximations \tilde{U} and \tilde{g} along with a more general setting allow us to deal with a much larger class of problems than [10]–[14]; see Part II of the paper [19] for specific examples.

A. Regularity conditions

We conclude this section mentioning certain standard regularity conditions on the stationary points of constrained optimization problems. These conditions are needed in the study of the convergence properties of our method.

Definition 1 (Regularity): A point $\bar{\mathbf{x}} \in \mathcal{X}$ is called *regular* for \mathcal{P} if the Mangasarian-Fromovitz Constraint Qualification (MFCQ) holds at $\bar{\mathbf{x}}$, that is (see e.g. [39, Theorem 6.14]) if the following implication is satisfied:

$$\left. \begin{aligned} \mathbf{0} \in \sum_{j \in \bar{J}} \mu_j \nabla_{\mathbf{x}} g_j(\bar{\mathbf{x}}) + N_{\mathcal{K}}(\bar{\mathbf{x}}) \\ \mu_j \geq 0, \forall j \in \bar{J} \end{aligned} \right\} \Rightarrow \mu_j = 0, \forall j \in \bar{J}, \quad (1)$$

where $N_{\mathcal{K}}(\bar{\mathbf{x}}) \triangleq \{\mathbf{d} \in \mathcal{K} : \mathbf{d}^T(\mathbf{y} - \bar{\mathbf{x}}) \leq 0, \forall \mathbf{y} \in \mathcal{K}\}$ is the normal cone to \mathcal{K} at $\bar{\mathbf{x}}$, and $\bar{J} \triangleq \{j \in \{1, \dots, m\} : g_j(\bar{\mathbf{x}}) = 0\}$ is the index set of those (nonconvex) constraints that are active at $\bar{\mathbf{x}}$.

A similar definition holds for problem $\mathcal{P}_{\mathbf{x}^\nu}$: a point $\bar{\mathbf{x}} \in \mathcal{X}(\mathbf{x}^\nu)$ is called *regular* for $\mathcal{P}_{\mathbf{x}^\nu}$ if

$$\left. \begin{aligned} \mathbf{0} \in \sum_{j \in \bar{J}^\nu} \mu_j \nabla_{\mathbf{x}} \tilde{g}_j(\bar{\mathbf{x}}; \mathbf{x}^\nu) + N_{\mathcal{K}}(\bar{\mathbf{x}}) \\ \mu_j \geq 0, \forall j \in \bar{J}^\nu \end{aligned} \right\} \Rightarrow \mu_j = 0, \forall j \in \bar{J}^\nu, \quad (2)$$

where $\bar{J}^\nu \triangleq \{j \in \{1, \dots, m\} : \tilde{g}_j(\bar{\mathbf{x}}; \mathbf{x}^\nu) = 0\}$. \square

We point out that the regularity of $\bar{\mathbf{x}}$ is implied by stronger but easier to be checked CQs, such as the Linear Independence CQ, see [40, Sec. 3.2] for more details. Note that if the feasible set is convex, as it is in $\mathcal{P}_{\mathbf{x}^\nu}$, the MFCQ is equivalent to the Slater's CQ; for a set like $\mathcal{X}(\mathbf{x}^\nu)$, Slater's CQ reads

$$\text{ri}(\mathcal{K}) \cap \mathcal{X}_g^<(\mathbf{x}^\nu) \neq \emptyset,$$

where $\mathcal{X}_g^<(\mathbf{x}^\nu) \triangleq \{\mathbf{x} \in \mathcal{K} : \tilde{g}_j(\mathbf{x}; \mathbf{x}^\nu) < 0, j = 1, \dots, m\}$ and $\text{ri}(\mathcal{K})$ is the relative interior of \mathcal{K} (see, e.g., [41, Sec. 1.4]). In particular, this means that for problem $\mathcal{P}_{\mathbf{x}^\nu}$ either the MFCQ holds at all the feasible points or it does not hold at any point. Furthermore, because of C2 and C5, a point $\bar{\mathbf{x}}$ is regular for \mathcal{P} if and only if $\bar{\mathbf{x}}$ is regular for $\mathcal{P}_{\bar{\mathbf{x}}}$ (and, therefore, if any feasible point of $\mathcal{P}_{\bar{\mathbf{x}}}$ is regular).

We recall that $\bar{\mathbf{x}}$ is a stationary point of problem \mathcal{P} , if

$$\left. \begin{aligned} \mathbf{0} \in \nabla_{\mathbf{x}} U(\bar{\mathbf{x}}) + \sum_{j \in \bar{J}} \mu_j \nabla_{\mathbf{x}} g_j(\bar{\mathbf{x}}) + N_{\mathcal{K}}(\bar{\mathbf{x}}) \\ \mu_j \geq 0, \forall j \in \bar{J} \end{aligned} \right\}$$

for some suitable Lagrange multipliers μ_j s. It is well-known that a regular (local) minimum point of problem \mathcal{P} is also stationary. Finding stationary points is actually the classical goal of solution algorithms for nonconvex problems.

In order to simplify the presentation, in the rest of this paper we assume the following regularity condition.

Assumption 5 All feasible points of problem \mathcal{P} are regular.

One could relax this assumption and require regularity only at specific points, but at the cost of more convoluted statements; we leave this task to the reader. We remark, once again, that Assumption 5 implies that any feasible point of $\mathcal{P}_{\bar{\mathbf{x}}}$ is regular.

III. ALGORITHMIC FRAMEWORK

We are now ready to formally introduce the proposed solution method for \mathcal{P} . Note first that, because of B1 and C1, each subproblem $\mathcal{P}_{\mathbf{x}^\nu}$ is strongly convex and thus has a unique solution, which is denoted by $\hat{\mathbf{x}}(\mathbf{x}^\nu)$ (a function of \mathbf{x}^ν):

$$\hat{\mathbf{x}}(\mathbf{x}^\nu) \triangleq \underset{\mathbf{x} \in \mathcal{X}(\mathbf{x}^\nu)}{\text{argmin}} \tilde{U}(\mathbf{x}; \mathbf{x}^\nu). \quad (3)$$

The proposed convex approximation method consists in solving iteratively the optimization problems (3), possibly including a step-size in the iterates; we named it iNner cOnVex Approximation (NOVA) algorithm. The formal description of the NOVA algorithm along with its convergence properties are given in Algorithm 1 and Theorem 2, respectively.

Algorithm 1: NOVA Algorithm for \mathcal{P} .

Data: $\gamma^\nu \in (0, 1]$, $\mathbf{x}^0 \in \mathcal{X}$; set $\nu = 0$.

(S.1) If \mathbf{x}^ν is a stationary solution of \mathcal{P} : STOP.

(S.2) Compute $\hat{\mathbf{x}}(\mathbf{x}^\nu)$, the solution of $\mathcal{P}_{\mathbf{x}^\nu}$ [cf. (3)].

(S.3) Set $\mathbf{x}^{\nu+1} = \mathbf{x}^\nu + \gamma^\nu(\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu)$.

(S.4) $\nu \leftarrow \nu + 1$ and go to step (S.1).

Theorem 2: Given the nonconvex problem \mathcal{P} under Assumptions 1-3 and 5, let $\{\mathbf{x}^\nu\}$ be the sequence generated by Algorithm 1. The following hold.

(a) $\mathbf{x}^\nu \in \mathcal{X}(\mathbf{x}^\nu) \subseteq \mathcal{X}$ for all $\nu \geq 0$ (iterate feasibility);

(b) If the step-size γ^ν and $c_{\bar{U}}$ are chosen so that

$$0 < \inf_{\nu} \gamma^\nu \leq \sup_{\nu} \gamma^\nu \leq \gamma^{\max} \leq 1 \quad \text{and} \quad 2c_{\bar{U}} > \gamma^{\max} L_{\nabla}, \quad (4)$$

then $\{\mathbf{x}^\nu\}$ is bounded and each of its limit points is a stationary point of problem \mathcal{P} .

(c) If the step-size γ^ν is chosen so that

$$\gamma^\nu \in (0, 1], \quad \gamma^\nu \rightarrow 0, \quad \text{and} \quad \sum_{\nu} \gamma^\nu = +\infty, \quad (5)$$

then $\{\mathbf{x}^\nu\}$ is bounded and at least one of its limit points is stationary. If, in addition, Assumption 4 holds and \mathcal{X} is compact, every limit point of $\{\mathbf{x}^\nu\}$ is stationary.

Furthermore, if the algorithm does not stop after a finite number of steps, none of the stationary points above is a local maximum of U .

Proof: The proof is quite involved and is given in the appendix; rather classically, its crucial point is showing that $\lim_{\nu \rightarrow \infty} (\inf) \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\| = 0$. \blacksquare

A. Discussions on Algorithm 1

Algorithm 1 describes a novel family of inner convex approximation methods for problem \mathcal{P} . Roughly speaking, it consists in solving the sequence of strongly convex problems $\mathcal{P}_{\mathbf{x}^\nu}$ wherein the original objective function U is replaced by the strongly convex (simple) approximation \tilde{U} , and the nonconvex constraints g_j s with the convex upper estimates

\tilde{g}_j s; convex constraints, if any, are kept unaltered. A step-size in the update of the iterates \mathbf{x}^ν is also used, in the form of a convex combination via $\gamma^\nu \in (0, 1]$ (cf. Step 3). Note that the iterates $\{\mathbf{x}^\nu\}$ generated by the algorithm are all feasible for the original problem \mathcal{P} . Convergence is guaranteed under mild assumptions that offer a lot of flexibility in the choice of the approximation functions and free parameters [cf. Theorem 2(b) and (c)], making the proposed scheme appealing for many applications. We provide next some examples of candidate approximants, covering a variety of situations and problems of practical interest.

1) *On the approximations \tilde{g}_j s:* As already mentioned, while assumption C3 might look rather elusive, in many practical cases an upper approximate function for the nonconvex constraints g_j s is close at hand. Some examples of \tilde{g}_j satisfying Assumption 3 (and in particular C3) are given next; specific applications where such approximations are used are discussed in detail in Part II of the paper [19].

Example #1— Nonconvex constraints with Lipschitz gradients. If the nonconvex function g_j does not have a special structure but Lipschitz continuous gradient on \mathcal{K} with constant $L_{\nabla g_j}$, the following convex approximation function is a global upper bound of g_j : for all $\mathbf{x} \in \mathcal{K}$ and $\mathbf{y} \in \mathcal{X}$,

$$\tilde{g}_j(\mathbf{x}; \mathbf{y}) \triangleq g_j(\mathbf{y}) + \nabla_{\mathbf{x}} g_j(\mathbf{y})^T (\mathbf{x} - \mathbf{y}) + \frac{L_{\nabla g_j}}{2} \|\mathbf{x} - \mathbf{y}\|^2 \geq g_j(\mathbf{x}). \quad (6)$$

Example #2— Nonconvex constraints with (uniformly) bounded Hessian matrix. Suppose that g_j is (nonconvex) \mathcal{C}^2 with second order bounded derivatives on \mathcal{K} . Then, one can find a matrix $\mathbf{G} \succ \mathbf{0}$ such that $\nabla_{\mathbf{x}}^2 g_j(\mathbf{x}) + \mathbf{G} \succeq \mathbf{0}$ for all $\mathbf{x} \in \mathcal{K}$. For instance, one can set $\mathbf{G} = \lfloor \min_{\mathbf{x} \in \mathcal{K}} \lambda_{\min}(\nabla_{\mathbf{x}}^2 g_j(\mathbf{x})) \rfloor \cdot \mathbf{I}$, with $\lambda_{\min}(\nabla_{\mathbf{x}}^2 g_j(\mathbf{x}))$ denoting the minimum eigenvalue of $\nabla_{\mathbf{x}}^2 g_j(\mathbf{x})$ (which is a negative quantity if g_j is nonconvex). Then, the unstructured nonconvex constraint g_j can be equivalently written as a DC function:

$$g_j(\mathbf{x}) = \underbrace{g_j(\mathbf{x}) + \frac{1}{2} \mathbf{x}^T \mathbf{G} \mathbf{x}}_{\triangleq g_j^+(\mathbf{x})} - \underbrace{\frac{1}{2} \mathbf{x}^T \mathbf{G} \mathbf{x}}_{\triangleq g_j^-(\mathbf{x})}, \quad (7)$$

where g_j^+ and g_j^- are two *convex* continuously differentiable functions. An approximant \tilde{g}_j of g_j satisfying Assumption 3 can then readily be obtained by linearizing $g_j^-(\mathbf{x})$; see Example #3 below for details.

The two examples above cover successfully quite general *unstructured* functions g_j . However, in some cases, the function parameters involved in the approximations—the constants $L_{\nabla g_j}$ or $\lfloor \min_{\mathbf{x} \in \mathcal{K}} \lambda_{\min}(\nabla_{\mathbf{x}}^2 g_j(\mathbf{x})) \rfloor$ —are not known exactly but need to be estimated; if the estimates are not tight, the resulting \tilde{g}_j might be a loose overestimation of g_j , which may negatively affect the practical convergence of Algorithm 1. Other approximations can be obtained when g_j has further structure to exploit, as discussed in the next examples.

Example #3— Nonconvex constraints with DC structure. Suppose that g_j has a DC structure, that is,

$$g_j(\mathbf{x}) = g_j^+(\mathbf{x}) - g_j^-(\mathbf{x})$$

is the difference of two convex and continuously differentiable functions g_j^+ and g_j^- . By linearizing the concave part $-g_j^-$ and keeping the convex part g_j^+ unchanged, we obtain the

following convex upper approximation of g_j : for all $\mathbf{x} \in \mathcal{K}$ and $\mathbf{y} \in \mathcal{X}$,

$$\tilde{g}_j(\mathbf{x}; \mathbf{y}) \triangleq g_j^+(\mathbf{x}) - g_j^-(\mathbf{y}) - \nabla_{\mathbf{x}} g_j^-(\mathbf{y})^T (\mathbf{x} - \mathbf{y}) \geq g_j(\mathbf{x}). \quad (8)$$

Example #4— Bi-linear constraints. Suppose that g_j has a bi-linear structure, that is,

$$g_j(x_1, x_2) = x_1 \cdot x_2. \quad (9)$$

Observe preliminarily that $g_j(x_1, x_2)$ can be rewritten as a DC function:

$$g_j(x_1, x_2) = \frac{1}{2} (x_1 + x_2)^2 - \frac{1}{2} (x_1^2 + x_2^2). \quad (10)$$

A valid \tilde{g}_j can be then obtained linearizing the concave part in (10): for any given $(y_1, y_2) \in \mathbb{R}^2$,

$$\begin{aligned} \tilde{g}_j(x_1, x_2; y_1, y_2) &\triangleq \frac{1}{2} (x_1 + x_2)^2 - \frac{1}{2} (y_1^2 + y_2^2) \\ &\quad - y_1 \cdot (x_1 - y_1) - y_2 \cdot (x_2 - y_2). \end{aligned}$$

In Part II of the paper [19] we show that the constraint functions of many resource allocation problems in wireless systems and networking fit naturally in Examples 1-4 above.

2) *On the approximation \tilde{U} :* The function \tilde{U} should be regarded as a (possibly simple) convex approximation that preserves the first order properties of U . Some instances of valid \tilde{U} s for a specific U occurring in practical applications are discussed next.

Example #5— Block-wise convex $U(\mathbf{x}_1, \dots, \mathbf{x}_n)$. In many applications, the vector of variables \mathbf{x} is partitioned in blocks $\mathbf{x} = (\mathbf{x}_i)_{i=1}^I$ and the function U is convex in each block \mathbf{x}_i separately, but not jointly. A natural approximation for such a U exploring its “partial” convexity is

$$\tilde{U}(\mathbf{x}; \mathbf{y}) = \sum_{i=1}^I \tilde{U}_i(\mathbf{x}_i; \mathbf{y}), \quad (11)$$

with each $\tilde{U}_i(\mathbf{x}_i; \mathbf{y})$ defined as

$$\tilde{U}_i(\mathbf{x}_i; \mathbf{y}) \triangleq U(\mathbf{x}_i, \mathbf{y}_{-i}) + \frac{\tau_i}{2} (\mathbf{x}_i - \mathbf{y}_i)^T \mathbf{H}_i(\mathbf{y})(\mathbf{x}_i - \mathbf{y}_i), \quad (12)$$

where $\mathbf{y} \triangleq (\mathbf{y}_i)_{i=1}^I$, $\mathbf{y}_{-i} \triangleq (\mathbf{y}_j)_{j \neq i}$, and $\mathbf{H}_i(\mathbf{y})$ is any uniformly positive definite matrix (possibly depending on \mathbf{y}). Note that the quadratic term in (12) can be set to zero if $U(\mathbf{x}_i, \mathbf{y}_{-i})$ is strongly convex in \mathbf{x}_i , uniformly for all feasible \mathbf{y}_{-i} . An alternative choice for $\tilde{U}_i(\mathbf{x}_i; \mathbf{y})$ is

$$\begin{aligned} \tilde{U}_i(\mathbf{x}_i; \mathbf{y}) &\triangleq \nabla_{\mathbf{x}_i} U(\mathbf{y})^T (\mathbf{x}_i - \mathbf{y}_i) \\ &\quad + \frac{1}{2} (\mathbf{x}_i - \mathbf{y}_i)^T \nabla_{\mathbf{x}_i}^2 U(\mathbf{y})(\mathbf{x}_i - \mathbf{y}_i) + \frac{\tau_i}{2} \|\mathbf{x}_i - \mathbf{y}_i\|^2, \end{aligned}$$

where $\nabla_{\mathbf{x}_i}^2 U(\mathbf{y})$ is the Hessian of U w.r.t. \mathbf{x}_i evaluated in \mathbf{y} . One can also use any positive definite “approximation” of $\nabla_{\mathbf{x}_i}^2 U(\mathbf{y})$. Needless to say, if $U(\mathbf{x}_1, \dots, \mathbf{x}_n)$ is *jointly* convex in all the variables’ blocks, then $\tilde{U}(\mathbf{x}; \mathbf{y})$ can be chosen so that

$$\tilde{U}(\mathbf{x}; \mathbf{y}) \triangleq U(\mathbf{x}) + \sum_i \frac{\tau_i}{2} \|\mathbf{x}_i - \mathbf{y}_i\|^2, \quad (13)$$

where $\frac{\tau_i}{2} \|\mathbf{x}_i - \mathbf{y}_i\|^2$ is not needed if $U(\mathbf{x}_i, \mathbf{x}_{-i})$ is strongly convex in \mathbf{x}_i , uniformly for all feasible \mathbf{x}_{-i} .

Example #6—(Proximal) gradient-like approximations. If no convexity whatsoever is present in U , mimicking proximal-gradient methods, a valid choice of \tilde{U} is the first order approximation of U , that is, $\tilde{U}(\mathbf{x}; \mathbf{y}) = \sum_{i=1}^I \tilde{U}_i(\mathbf{x}_i; \mathbf{y})$, with each

$$\tilde{U}_i(\mathbf{x}_i; \mathbf{y}) \triangleq \nabla_{\mathbf{x}_i} U(\mathbf{y})^T (\mathbf{x}_i - \mathbf{y}_i) + \frac{\tau_i}{2} \|\mathbf{x}_i - \mathbf{y}_i\|^2.$$

Note that even though classical (proximal) gradient descent methods (see, e.g., [21]) share the same approximation function, they are not applicable to problem \mathcal{P} , due to the nonconvexity of the feasible set.

Example #7— Sum-utility function. In multi-agent scenarios, the objective function U is generally written as $U(\mathbf{x}) \triangleq \sum_{i=1}^I f_i(\mathbf{x}_1, \dots, \mathbf{x}_I)$, that is, the sum of the utilities $f_i(\mathbf{x}_1, \dots, \mathbf{x}_I)$ of I agents, each controlling the variables \mathbf{x}_i . A typical situation is when the f_i s are convex in some agents' variables. To capture this property, let us define by

$$\mathcal{S}_i \triangleq \{j : f_j(\bullet, \mathbf{x}_{-i}) \text{ is convex in } \mathbf{x}_i, \forall (\mathbf{x}_i, \mathbf{x}_{-i}) \in \mathcal{K}\}$$

the set of indices of all the functions $f_j(\mathbf{x}_i, \mathbf{x}_{-i})$ that are convex in \mathbf{x}_i , for any feasible \mathbf{x}_{-i} , and let $\mathcal{C}_i \subseteq \mathcal{S}_i$ be any subset of \mathcal{S}_i . Then, the following approximation function $\tilde{U}(\mathbf{x}; \mathbf{y})$ satisfies Assumption 2 while exploiting the partial convexity of U (if any): $\tilde{U}(\mathbf{x}; \mathbf{y}) = \sum_{i=1}^I \tilde{U}_{\mathcal{C}_i}(\mathbf{x}_i; \mathbf{y})$, with each $\tilde{U}_{\mathcal{C}_i}$ defined as

$$\begin{aligned} \tilde{U}_{\mathcal{C}_i}(\mathbf{x}_i; \mathbf{y}) &\triangleq \sum_{j \in \mathcal{C}_i} f_j(\mathbf{x}_i, \mathbf{y}_{-i}) + \sum_{k \notin \mathcal{C}_i} \nabla_{\mathbf{x}_i} f_k(\mathbf{y})^T (\mathbf{x}_i - \mathbf{y}_i) \\ &\quad + \frac{\tau_i}{2} (\mathbf{x}_i - \mathbf{y}_i)^T \mathbf{H}_i(\mathbf{y}) (\mathbf{x}_i - \mathbf{y}_i), \end{aligned}$$

where $\mathbf{H}_i(\mathbf{y})$ is any uniformly positive definite matrix. Roughly speaking, for each agent i we built an approximation function such that the convex part of U w.r.t. \mathbf{x}_i may be preserved while the nonconvex part is linearized.

Example #8— Product of functions. The function U is often the product of functions (see Part II [19] for some examples); we consider here the product of two functions, but the proposed approach can be readily extended to the case of three or more functions or to the sum of such product terms. Suppose that $U(\mathbf{x}) = f_1(\mathbf{x})f_2(\mathbf{x})$, with f_1 and f_2 convex and positive. In view of the expression of the gradient of U , $\nabla_{\mathbf{x}} U = f_2 \nabla_{\mathbf{x}} f_1 + f_1 \nabla_{\mathbf{x}} f_2$, it seems natural to consider the approximation

$$\tilde{U}(\mathbf{x}; \mathbf{y}) = f_1(\mathbf{x})f_2(\mathbf{y}) + f_1(\mathbf{y})f_2(\mathbf{x}) + \frac{\tau_i}{2} (\mathbf{x} - \mathbf{y})^T \mathbf{H}(\mathbf{y}) (\mathbf{x} - \mathbf{y}),$$

where, as usual, $\mathbf{H}(\mathbf{y})$ is a uniformly positive definite matrix; this term can be omitted if f_1 and f_2 are bounded away from zero on the feasible set and $f_1 + f_2$ is strongly convex (for example if one of the two functions is strongly convex). It is clear that this \tilde{U} satisfies Assumption 2. In case f_1 and f_2 are still positive but not necessarily convex, we can use the expression

$$\tilde{U}(\mathbf{x}; \mathbf{y}) = \tilde{f}_1(\mathbf{x}; \mathbf{y})f_2(\mathbf{y}) + f_1(\mathbf{y})\tilde{f}_2(\mathbf{x}; \mathbf{y}),$$

where \tilde{f}_1 and \tilde{f}_2 are any legitimate approximations for f_1 and f_2 , for example those considered in Examples 5-7 above. Finally, if f_1 and f_2 can take non-positive values, we can write

$$\tilde{U}(\mathbf{x}; \mathbf{y}) = \tilde{h}_1(\mathbf{x}, \mathbf{y}) + \tilde{h}_2(\mathbf{x}, \mathbf{y}),$$

where $h_1(\mathbf{x}, \mathbf{y}) \triangleq \tilde{f}_1(\mathbf{x}; \mathbf{y})f_2(\mathbf{y})$, $h_2(\mathbf{x}, \mathbf{y}) \triangleq f_1(\mathbf{y})\tilde{f}_2(\mathbf{x}; \mathbf{y})$, and \tilde{h}_1 and \tilde{h}_2 are legitimate approximations for h_1 and h_2 , for example, again, those considered in Examples 5-7. Note that in the last cases we no longer need the quadratic term because it is already included in the approximations \tilde{f}_1 and \tilde{f}_2 , and \tilde{h}_1 and \tilde{h}_2 , respectively. As a final remark, it is important to point out that the the U s discussed above belong to a class of nonconvex functions for which it does not seem possible to find a global convex upper bound; therefore, all current SCA techniques (see, e.g., [10], [12], [15]) are not applicable.

We conclude the discussion on the approximation functions observing that, in Examples 5-7, the proposed $\tilde{U}(\mathbf{x}; \mathbf{y})$ s are all separable in the blocks \mathbf{x}_i for any given \mathbf{y} ; in Example 8, instead, the separability is problem dependent and should be examined on a case-by-case basis. The separability of the \tilde{U} s paves the way to parallelizable and distributed versions of Algorithm 1; we discuss this topic more in detail in Sec. IV.

3) *On the choice of the step-size rule γ^ν :* Theorem 2 states that Algorithm 1 converges either employing a constant step-size rule [cf. (4)] or a diminishing step-size rule [cf. (5)].

If a constant step-size is used, one can set in (4) $\gamma^\nu = \gamma \leq \gamma^{\max}$ for every ν , and choose any $\gamma^{\max} \in (0, 1]$ and $c_{\tilde{U}}$ so that $2c_{\tilde{U}} > \gamma^{\max} L_{\nabla U}$ (recall that $c_{\tilde{U}}$ is the constant of strong convexity of the approximation \tilde{U} and, thus, is a degree of freedom). This can be done in several ways. For instance, if the chosen \tilde{U} contains a proximal term with gain $\tau > 0$, i.e., a term of the type $(\tau/2)\|\mathbf{x} - \mathbf{y}\|^2$, then the inequality $2c_{\tilde{U}} > \gamma^{\max} L_{\nabla U}$ is readily satisfied setting $2\tau/\gamma^{\max} > L_{\nabla U}$ (we used $c_{\tilde{U}} \geq \tau$). Note that this simple (but conservative) condition imposes a constraint only on the ratio τ/γ^{\max} , leaving free the choice of one of the two parameters. An interesting special case worth mentioning is when $\gamma^{\max} = 1$ and $2\tau > L_{\nabla U}$: the choice $\gamma^\nu = 1$ leads to an instance of Algorithm 1 with no memory, i.e., $\mathbf{x}^{\nu+1} = \hat{\mathbf{x}}(\mathbf{x}^\nu)$, for all ν .

When the Lipschitz constant $L_{\nabla U}$ cannot be estimated, one can use a diminishing step-size rule, satisfying the standard conditions (5). A rule that we found to work well in practice is, see [13]:

$$\gamma^\nu = \gamma^{\nu-1}(1 - \varepsilon\gamma^{\nu-1}), \quad \nu \geq 1, \quad (14)$$

with $\gamma^0 \in (0, 1]$ and $\varepsilon \in (0, 1)$. Other effective rules can be found in [13]. Notice that, while this rule may still require some tuning for optimal behavior, it is quite reliable, since in general we are not using a (sub)gradient direction, so that many of the well-known practical drawbacks associated with a (sub)gradient method with diminishing step-size are mitigated in our setting. Furthermore, this choice of step-size does not require any form of centralized coordination and, thus, provides a favorable feature in distributed environments.

We remark that it is possible to prove the convergence of Algorithm 1 also using other step-size rules, such as a standard Armijo-like line-search procedure. We omit the discussion of line-search based approaches because such options are not in line with our goal of developing distributed algorithms, see Sec. IV. In [11] it is shown that, in the specific case of a *strongly convex* U and, in our terminology, $\tilde{U} = U$ and $\mathcal{K} = \mathbb{R}^n$, by choosing $\gamma^\nu = 1$ at every iteration, one can prove the stationarity of every limit point of the sequence generated

by Algorithm 1 (assuming regularity). We can easily derive this particular result from our general analysis, see Remark 12 in the Appendix. Here we only mention that, attractive as this result may be, the strong convexity of U is a very restrictive assumption, and forcing $\tilde{U} = U$ does not permit the development of distributed versions of Algorithm 1.

Finally, as a technical note, it is interesting to contrast the different kinds of convergence that one can obtain by choosing a constant or a diminishing step-size rule. In the former case, every limit point of the sequence generated by Algorithm 1 is guaranteed to be a stationary solution of the original nonconvex problem \mathcal{P} , whereas, in the latter case, there exists at least a limit point being stationary, which thus is a weaker condition. On the other hand, a diminishing step-size has been observed to be numerically more efficient than a constant one. In order to obtain, also with a diminishing step-size rule, the strong convergence behavior that can be guaranteed when a constant step-size is employed, one needs extra conditions on the approximation functions \tilde{U} and \tilde{g} (cf. Assumptions 4); these conditions are quite standard and easy to be satisfied in most practical applications (as those studied in Part II [19]).

B. Related works

Our approach draws on the SCA paradigm, which has been widely explored in the literature, see [10]–[15]. However, our framework and convergence conditions unify and extend current SCA methods in several directions, as outlined next.

–*On the approximation functions:* Conditions on the approximation function \tilde{U} as in Assumption 2 are relatively weak: this feature allows us to enlarge significantly the class of utility functions U s that can be successfully handled by Algorithm 1. A key difference with current SCA methods [applicable to special cases of \mathcal{P}] [10], [12] and DC programs [15] is that the approximation $\tilde{U}(\mathbf{x}; \mathbf{y})$ need not be a tight *global upper bound* of the objective function $U(\mathbf{x})$ for every $\mathbf{x} \in \mathcal{K}$ and $\mathbf{y} \in \mathcal{X}$ [cf. Assumption 2]. This fact represents a big step forward in the literature of SCA methods; Part II of the paper [19] provides a solid evidence of the wide range of applicability of the proposed framework.

–*Convergence conditions:* There are only a few SCA-based methods in the literature handling nonconvex constraints, namely [10], [11], [15], and the existing convergence results are quite weak. In particular, [10, Th. 1] states that if *the whole sequence converges*, then the algorithm converges to a stationary point; however, in general, it is hardly possible to show that the sequence generated by the algorithms does converge. In [11], (subsequence) convergence to regular points is proved, but only for nonconvex problems with *strongly convex* objective functions; this fact restricts considerably the range of applicability of this result (for instance, none of the problems that we study in Part II [19] have strongly convex objective functions). Finally, [15] can handle only (possibly nonsmooth) nonconvex problems whose objective functions and constraints have a DC form. To the best of our knowledge, this work is the first attempt towards the generalization of SCA methods to nonconvex problems having general nonconvex objective functions and constraints.

–*Distributed implementation:* A second key and unique feature of Algorithm 1, missing in current SCA schemes [10], [11], [15], is that it easily leads to distributed implementations, as we will discuss in Sec. IV. This feature, along with the feasibility of the iterates, represents a key difference also with classical techniques [6]–[9] that have been proposed in the literature to deal with nonconvex optimization problems.

IV. DISTRIBUTED IMPLEMENTATION

In many applications, e.g., multi-agent optimization or distributed networking, it is desirable to keep users coordination and communication overhead at minimum level. In this section we discuss distributed versions of Algorithm 1. Of course, we need to assume that problem \mathcal{P} has some suitable structure, and that consistent choices on \tilde{U} and \tilde{g} are made. Therefore, in this section we consider the following additional assumptions.

Assumption 6 (Decomposability). Given \mathcal{P} , suppose that:

D1) the set \mathcal{K} has a Cartesian structure, i.e., $\mathcal{K} = \mathcal{K}_1 \times \cdots \times \mathcal{K}_I$, with each $\mathcal{K}_i \subset \mathbb{R}^{n_i}$, and $\sum_i n_i = n$; $\mathbf{x} \triangleq (\mathbf{x}_i)_{i=1}^I$ is partitioned accordingly, with each $\mathbf{x}_i \in \mathcal{K}_i$;

D2) the approximate function $\tilde{U}(\mathbf{x}; \mathbf{y})$ satisfying Assumption 2 is chosen so that $\tilde{U}(\mathbf{x}; \mathbf{y}) = \sum_i \tilde{U}_i(\mathbf{x}_i; \mathbf{y})$;

D3) each approximate function $\tilde{g}_j(\mathbf{x}; \mathbf{y})$ satisfying Assumption 3 is (block) separable in the \mathbf{x} -variables, for any given \mathbf{y} , that is, $\tilde{g}_j(\mathbf{x}; \mathbf{y}) = \sum_i \tilde{g}_j^i(\mathbf{x}_i; \mathbf{y})$, for some $\tilde{g}_j^i : \mathcal{K}_i \times \mathcal{X} \rightarrow \mathbb{R}$.

Condition D1 is a very natural assumption on problem \mathcal{P} and is usually satisfied when a distributed implementation is called for. If problem \mathcal{P} does not satisfy this assumption, it is not realistic to expect that efficient distributed solution methods can be devised; D2 and D3, instead, are assumptions on our algorithmic choices. In particular, condition D2 permits many choices for \tilde{U} . For instance, as already discussed at the end of the subsection "On the approximation \tilde{U} ", essentially all \tilde{U} s introduced in Examples 5-7 (and possibly some of the \tilde{U} s in Example 8) satisfy D2. The critical condition in Assumption 6 is D3. Some examples of constraints functions g_j for which one can find a $\tilde{g}_j(\mathbf{x}; \mathbf{y})$ satisfying D3 are:

–*Individual nonconvex constraints:* Each g_j (still nonconvex) depends only on one of the block variables $\mathbf{x}_1, \dots, \mathbf{x}_I$, i.e., $g_j(\mathbf{x}) = g_j^i(\mathbf{x}_i)$, for some $g_j^i : \mathcal{K}_i \rightarrow \mathbb{R}$ and i ;

–*Separable nonconvex constraints:* Each g_j has the form $g_j(\mathbf{x}) = \sum_i g_j^i(\mathbf{x}_i)$, with $g_j^i : \mathcal{K}_i \rightarrow \mathbb{R}$;

–*Nonconvex constraints with Lipschitz gradients:* Each g_j is not necessarily separable but has Lipschitz gradient on \mathcal{K} . In this case one can choose, e.g., the approximation \tilde{g}_j as in (6).

It is important to remark that, even for problems \mathcal{P} [or $\mathcal{P}_{\mathbf{x}^\nu}$] for which it looks hard to satisfy D3, the introduction of proper slack variables can help to decouple the constraint functions, making thus possible to find a \tilde{g}_j that satisfies D3; we refer the reader to Part II of the paper [19] for some non trivial examples where this technique is applied.

For notational simplicity, let us introduce the vector function $\tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \triangleq (\tilde{g}_j^i(\mathbf{x}_i; \mathbf{x}^\nu))_{j=1}^m$, for $i = 1, \dots, I$. Under Assumption 6, each subproblem $\mathcal{P}_{\mathbf{x}^\nu}$ becomes

$$\begin{aligned} \min_{\mathbf{x}} \quad & \sum_{i=1}^I \tilde{U}_i(\mathbf{x}_i; \mathbf{x}^\nu) \\ \text{s.t.} \quad & \tilde{\mathbf{g}}(\mathbf{x}; \mathbf{x}^\nu) \triangleq \sum_i \tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \leq \mathbf{0}, \quad (\tilde{\mathcal{P}}_{\mathbf{x}^\nu}) \\ & \mathbf{x}_i \in \mathcal{K}_i, \quad i = 1, \dots, I. \end{aligned}$$

With a slight abuse of notation, we will still denote the feasible set of $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$ by $\mathcal{X}(\mathbf{x}^\nu)$.

The block separable structure of both the objective function and the constraints lends itself to a parallel decomposition of the subproblems $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$ in the primal or dual domain: hence, it allows the distributed implementation of Step 2 of Algorithm 1. In the next section we briefly show how to customize standard primal/dual decomposition techniques (see, e.g., [20], [21]) in order to solve subproblem $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$. We conclude this section observing that, if there are only individual constraints in \mathcal{P} , given \mathbf{x}^ν , each $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$ can be split in I independent subproblems in the variables \mathbf{x}_i , even if the original nonconvex U is *not separable*. To the best of our knowledge, this is the first attempt to obtain distributed algorithms for a nonconvex problem in the general form \mathcal{P} .

A. Dual decomposition methods

Subproblem $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$ is convex and can be solved in a distributed way if the constraints $\tilde{\mathbf{g}}(\mathbf{x}; \mathbf{x}^\nu) \leq \mathbf{0}$ are dualized. The dual problem associated with each $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$ is: given $\mathbf{x}^\nu \in \mathcal{X}(\mathbf{x}^\nu)$,

$$\max_{\boldsymbol{\lambda} \geq \mathbf{0}} d(\boldsymbol{\lambda}; \mathbf{x}^\nu) \quad (15)$$

with

$$d(\boldsymbol{\lambda}; \mathbf{x}^\nu) \triangleq \min_{\mathbf{x} \in \mathcal{K}} \left\{ \sum_{i=1}^I \left(\tilde{U}_i(\mathbf{x}_i; \mathbf{x}^\nu) + \boldsymbol{\lambda}^T \tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \right) \right\} \quad (16)$$

Note that, for $\boldsymbol{\lambda} \geq \mathbf{0}$, by Assumptions 2 and 3, the minimization in (16) has a unique solution, which will be denoted by $\hat{\mathbf{x}}(\boldsymbol{\lambda}; \mathbf{x}^\nu) \triangleq (\hat{\mathbf{x}}_i(\boldsymbol{\lambda}; \mathbf{x}^\nu))_{i=1}^I$, with

$$\hat{\mathbf{x}}_i(\boldsymbol{\lambda}; \mathbf{x}^\nu) \triangleq \operatorname{argmin}_{\mathbf{x}_i \in \mathcal{K}_i} \left\{ \tilde{U}_i(\mathbf{x}_i; \mathbf{x}^\nu) + \boldsymbol{\lambda}^T \tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \right\}. \quad (17)$$

Before proceeding, let us mention the following standard condition.

D4) $\tilde{\mathbf{g}}(\bullet; \mathbf{x}^\nu)$ is uniformly Lipschitz continuous on \mathcal{K} with constant $L_{\tilde{\mathbf{g}}}$;

We remind that D4 is implied by condition C7 of Assumption 4; therefore we do not need to assume it if Assumption 4 is invoked. But in order to connect our results below to classical ones, it is good to highlight it as a separate assumption.

The next lemma summarizes some desirable properties of the dual function $d(\boldsymbol{\lambda}; \mathbf{x}^\nu)$, which are instrumental to prove the convergence of dual schemes.

Lemma 3: Given $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$, under Assumptions 1-3, 5, and 6, the following hold.

(a) $d(\boldsymbol{\lambda}; \mathbf{x}^\nu)$ is differentiable with respect to $\boldsymbol{\lambda}$ on \mathbb{R}_+^m , with gradient

$$\nabla_{\boldsymbol{\lambda}} d(\boldsymbol{\lambda}; \mathbf{x}^\nu) = \sum_i \tilde{\mathbf{g}}^i(\hat{\mathbf{x}}_i(\boldsymbol{\lambda}; \mathbf{x}^\nu); \mathbf{x}^\nu). \quad (18)$$

(b) If in addition D4 holds, then $\nabla_{\boldsymbol{\lambda}} d(\boldsymbol{\lambda}; \mathbf{x}^\nu)$ is Lipschitz continuous on \mathbb{R}_+^m with constant $L_{\nabla d} \triangleq L_{\tilde{\mathbf{g}}}^2 \sqrt{m}/c_{\tilde{U}}$.

Proof: See Appendix C. ■

The dual-problem can be solved, e.g., using well-known gradient algorithms [41]; an instance is given in Algorithm 2, whose convergence is stated in Theorem 4. The proof of the theorem follows from Lemma 3 and standard convergence results for gradient projection algorithms (e.g., see [42, Th. 3.2] and [41, Prop. 8.2.6] for the theorem statement under assumptions (a) and (b), respectively). We remark that an assumption made in the aforementioned references is that subproblem $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$ has a zero-duality gap and the dual problem (15) has a non-empty solution set. In our setting, this is guaranteed by Assumption 5, that ensures that $\mathcal{X}(\mathbf{x}^\nu)$ satisfies Slater's CQ (see the discussion around Assumption 5).

In (19) $[\bullet]_+$ denotes the Euclidean projection onto \mathbb{R}_+ , i.e., $[x]_+ \triangleq \max(0, x)$.

Algorithm 2: Dual-based Distributed Implementation of Step 2 of NOVA Algorithm (Algorithm 1).

Data: $\boldsymbol{\lambda}^0 \geq \mathbf{0}$, \mathbf{x}^ν , $\{\alpha^n\} > 0$; set $n = 0$.

(S. 2a) If $\boldsymbol{\lambda}^n$ satisfies a suitable termination criterion: STOP.

(S. 2b) Solve in parallel (17): for all $i = 1, \dots, I$, compute $\hat{\mathbf{x}}_i(\boldsymbol{\lambda}^n; \mathbf{x}^\nu)$.

(S. 2c) Update $\boldsymbol{\lambda}$ according to

$$\boldsymbol{\lambda}^{n+1} \triangleq \left[\boldsymbol{\lambda}^n + \alpha^n \sum_{i=1}^I \tilde{\mathbf{g}}^i(\hat{\mathbf{x}}_i(\boldsymbol{\lambda}^n; \mathbf{x}^\nu); \mathbf{x}^\nu) \right]_+. \quad (19)$$

(S. 2d) $n \leftarrow n + 1$ and go back to (S. 2a).

Theorem 4: Given \mathcal{P} , under Assumptions 1-3, 5, and 6, suppose that one of the two following conditions is satisfied: (a) D4 holds true and $\{\alpha^n\}$ is chosen such that $0 < \inf_n \alpha^n \leq \sup_n \alpha^n < 2/L_{\nabla d}$, for all $n \geq 0$;

(b) $\nabla_{\boldsymbol{\lambda}} d(\bullet; \mathbf{x}^\nu)$ is uniformly bounded on \mathbb{R}_+^m , and α^n is chosen such that $\alpha^n > 0$, $\alpha^n \rightarrow 0$, $\sum_n \alpha^n = \infty$, and $\sum_n (\alpha^n)^2 < \infty$.

Then, the sequence $\{\boldsymbol{\lambda}^n\}$ generated by Algorithm 2 converges to a solution of (15), and the sequence $\{\hat{\mathbf{x}}(\boldsymbol{\lambda}^n; \mathbf{x}^\nu)\}$ converges to the unique solution of $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$.

Remark 5 (On the distributed implementation):

The implementation of Algorithm 1 based on Algorithm 2 leads to a double-loop scheme: given the current value of the multipliers $\boldsymbol{\lambda}^n$, the subproblems (17) can be solved in parallel across the blocks; once the new values $\hat{\mathbf{x}}_i(\boldsymbol{\lambda}^n; \mathbf{x}^\nu)$ are available, the multipliers are updated according to (19). Note that when $m = 1$ (i.e., there is only one shared constraint), the update in (19) can be replaced by a bisection search, which generally converges quite fast. When $m > 1$, the potential slow convergence of gradient updates (19) can be alleviated using accelerated gradient-based (proximal) schemes; see, e.g., [43], [44].

As far as the communication overhead is concerned, the required signaling is in the form of message passing and of course is problem dependent; see Part II of the paper [19] for specific examples. For instance, in networking applications where there is a cluster-head, the update of the multipliers can be performed at the cluster, and, then, it can be broadcasted to the users. In fully decentralized networks instead, the update of $\boldsymbol{\lambda}$ can be done by the users themselves,

by running consensus based algorithms to locally estimate $\sum_{i=1}^I \tilde{\mathbf{g}}^i(\hat{\mathbf{x}}_i(\boldsymbol{\lambda}^n; \mathbf{x}^\nu); \mathbf{x}^\nu)$. This, in general, requires a limited signaling exchange among neighboring nodes only. Note also that the size of the dual problem (the dimension of $\boldsymbol{\lambda}$) is equal to m (the number of shared constraints), which makes Algorithm 2 scalable in the number of blocks (users).

B. Primal decomposition methods

Algorithm 2 is based on the relaxation of the shared constraints into the Lagrangian, resulting, in general, in a violation of these constraints during the intermediate iterates. In some applications this fact may prevent the on-line implementation of the algorithm. In this section we propose a distributed scheme that does not suffer from this issue: we cope with the shared constraints using a primal decomposition technique.

Introducing the slack variables $\mathbf{t} \triangleq (\mathbf{t}_i)_{i=1}^I$, with each $\mathbf{t}_i \in \mathbb{R}^m$, $\tilde{\mathcal{P}}_{\mathbf{x}^\nu}$ can be rewritten as

$$\begin{aligned} \min_{(\mathbf{x}_i, \mathbf{t}_i)_{i=1}^I} \quad & \sum_{i=1}^I \tilde{U}_i(\mathbf{x}_i; \mathbf{x}^\nu), \\ \text{s.t.} \quad & \mathbf{x}_i \in \mathcal{K}_i, \quad \forall i = 1, \dots, I, \\ & \tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \leq \mathbf{t}_i, \quad \forall i = 1, \dots, I, \\ & \sum_{i=1}^I \mathbf{t}_i \leq \mathbf{0}. \end{aligned} \quad (20)$$

When $\mathbf{t} = (\mathbf{t}_i)_{i=1}^I$ is fixed, (20) can be decoupled across the users: for each $i = 1, \dots, I$, solve

$$\begin{aligned} \min_{\mathbf{x}_i} \quad & \tilde{U}_i(\mathbf{x}_i; \mathbf{x}^\nu), \\ \text{s.t.} \quad & \mathbf{x}_i \in \mathcal{K}_i, \\ & \tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \stackrel{\mu_i(\mathbf{t}_i; \mathbf{x}^\nu)}{\leq} \mathbf{t}_i, \end{aligned} \quad (21)$$

where $\mu_i(\mathbf{t}_i; \mathbf{x}^\nu)$ is the optimal Lagrange multiplier associated with the inequality constraint $\tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \leq \mathbf{t}_i$. Note that the existence of $\mu_i(\mathbf{t}_i; \mathbf{x}^\nu)$ is guaranteed if (21) has zero-duality gap [45, Prop. 6.5.8] (e.g., when some CQ hold), but $\mu_i(\mathbf{t}_i; \mathbf{x}^\nu)$ may not be unique. Let us denote by $\mathbf{x}_i^*(\mathbf{t}_i; \mathbf{x}^\nu)$ the unique solution of (21), given $\mathbf{t} = (\mathbf{t}_i)_{i=1}^I$. The optimal partition $\mathbf{t}^* \triangleq (\mathbf{t}_i^*)_{i=1}^I$ of the shared constraints can be found solving the so-called *master* (convex) problem (see, e.g., [20]):

$$\begin{aligned} \min_{\mathbf{t}} \quad & P(\mathbf{t}; \mathbf{x}^\nu) \triangleq \sum_{i=1}^I \tilde{U}_i(\mathbf{x}_i^*(\mathbf{t}_i; \mathbf{x}^\nu); \mathbf{x}^\nu) \\ \text{s.t.} \quad & \sum_{i=1}^I \mathbf{t}_i \leq \mathbf{0}. \end{aligned} \quad (22)$$

Due to the non-uniqueness of $\mu_i(\mathbf{t}_i; \mathbf{x}^\nu)$, the objective function in (22) is nondifferentiable; problem (22) can be solved by subgradient methods. The partial subgradient of $P(\mathbf{t}; \mathbf{x}^\nu)$ with respect to the first argument evaluated at $(\mathbf{t}; \mathbf{x}^\nu)$ is

$$\partial_{\mathbf{t}_i} P(\mathbf{t}; \mathbf{x}^\nu) = -\mu_i(\mathbf{t}_i; \mathbf{x}^\nu), \quad i = 1, \dots, I.$$

We refer to [41, Prop. 8.2.6] for standard convergence results for subgradient projection algorithms.

V. CONCLUSIONS

In this Part I of the two-part paper, we proposed a novel general algorithmic framework based on convex approximation techniques for the solution of nonconvex smooth optimization problems: we point out that the nonconvexity may occur both in the objective function and in the constraints. Some key novel features of our scheme are: i) it maintains feasibility

and leads to *parallel and distributed* solution methods for a very general class of nonconvex problems; ii) it offers a lot of flexibility in choosing the approximation functions, enlarging significantly the class of problems that can be solved with provable convergence; iii) by choosing different approximation functions, different (distributed) schemes can be obtained: they are all convergent, but differ for (practical) convergence speed, complexity, communication overhead, and a priori knowledge of the system parameters; iv) it includes as special cases several classical SCA-based algorithms and improves on their convergence properties; and v) it provides new efficient algorithms also for old problems. In Part II [19] we customize the developed algorithmic framework to a variety of new (and old) multi-agent optimization problems in signal processing, communications and networking, providing a solid evidence of its good performance. Quite interestingly, even when compared with existing schemes that have been designed for very specific problems, our algorithms are shown to outperform them.

APPENDIX

We first introduce some intermediate technical results that are instrumental to prove Theorem 2. The proof of Theorem 2 is given in Appendix B.

A. Intermediate results

We first prove Lemma 6-Lemma 10, providing some key properties of the sequence $\{\mathbf{x}^\nu\}$ generated by Algorithm 1 and of the best-response function $\hat{\mathbf{x}}(\bullet)$ defined in (3). Finally, with Theorem 11 we establish some technical conditions under which a (at least one) regular limit point of the sequence generated by Algorithm 1 is a stationary solution of the original nonconvex problem \mathcal{P} ; the proof of Theorem 2 will rely on such conditions. We recall that, for the sake of simplicity, throughout this section we tacitly assume that Assumptions 1-3 and 5 are satisfied.

Lemma 6. The first lemma shows, among other things, that Algorithm 1 produces a sequence of points that are feasible for the original problem \mathcal{P} .

Lemma 6: The following properties hold.

- (i) $\mathbf{y} \in \mathcal{X}(\mathbf{y}) \subseteq \mathcal{X}$ for all $\mathbf{y} \in \mathcal{X}$;
- (ii) $\hat{\mathbf{x}}(\mathbf{y}) \in \mathcal{X}(\mathbf{y}) \subseteq \mathcal{X}$ for all $\mathbf{y} \in \mathcal{X}$.

Moreover, the sequence $\{\mathbf{x}^\nu\}$ generated by Algorithm 1 is such that:

- (iii) $\mathbf{x}^\nu \in \mathcal{X}$;
- (iv) $\mathbf{x}^{\nu+1} \in \mathcal{X}(\mathbf{x}^\nu) \cap \mathcal{X}(\mathbf{x}^{\nu+1})$.

Proof: (i) the first implication $\mathbf{y} \in \mathcal{X}(\mathbf{y})$ follows from $\tilde{g}_j(\mathbf{y}; \mathbf{y}) = g_j(\mathbf{y}) \leq 0$, for all $j = 1, \dots, m$ [due to C2]. For the inclusion $\mathcal{X}(\mathbf{y}) \subseteq \mathcal{X}$, it suffices to recall that, by C3, we have $g_j(\mathbf{x}) \leq \tilde{g}_j(\mathbf{x}; \mathbf{y})$ for all $\mathbf{x} \in \mathcal{K}$, $\mathbf{y} \in \mathcal{X}$, and $j = 1, \dots, m$, implying that, if $\mathbf{x} \in \mathcal{X}(\mathbf{y})$, then $\mathbf{x} \in \mathcal{X}$.

(ii) $\hat{\mathbf{x}}(\mathbf{y}) \in \mathcal{X}(\mathbf{y})$ since it is the optimal solution of $\mathcal{P}_{\mathbf{y}}$ (and thus also feasible).

(iii) In view of (i) and (ii), it follows by induction and the fact that $\mathbf{x}^{\nu+1}$ is a convex combination of $\mathbf{x}^\nu \in \mathcal{X}(\mathbf{x}^\nu)$ and $\hat{\mathbf{x}}(\mathbf{x}^\nu) \in \mathcal{X}(\mathbf{x}^\nu)$, which is a convex subset of \mathcal{X} .

(iv) By (iii), $\mathbf{x}^{\nu+1} \in \mathcal{X}(\mathbf{x}^\nu)$. Furthermore, we have $\tilde{g}_j(\mathbf{x}^{\nu+1}; \mathbf{x}^{\nu+1}) = g_j(\mathbf{x}^{\nu+1}) \leq 0$, for all $j = 1, \dots, m$, where

the equality follows from C2 and the inequality is due to $\mathbf{x}^{\nu+1} \in \mathcal{X}$; thus, $\mathbf{x}^{\nu+1} \in \mathcal{X}(\mathbf{x}^{\nu+1})$. ■

Lemma 7. With Lemma 7, we establish some key properties of the best-response function $\hat{\mathbf{x}}(\bullet)$. We will use the following definitions. Given $\mathbf{y}, \mathbf{z} \in \mathcal{X}$ and $\rho > 0$, let

$$\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{z}) \triangleq \hat{\mathbf{x}}(\mathbf{y}) - \rho \nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{y}); \mathbf{z}); \quad (23)$$

and let $P_{\mathcal{X}(\mathbf{y})}(\mathbf{u})$ denote the Euclidean projection of $\mathbf{u} \in \mathbb{R}^n$ onto the closed convex set $\mathcal{X}(\mathbf{y})$:

$$P_{\mathcal{X}(\mathbf{y})}(\mathbf{u}) = \operatorname{argmin}_{\mathbf{x} \in \mathcal{X}(\mathbf{y})} \|\mathbf{x} - \mathbf{u}\|. \quad (24)$$

Lemma 7: The best-response function $\mathcal{X} \ni \mathbf{y} \mapsto \hat{\mathbf{x}}(\mathbf{y})$ satisfies the following:

(i) For every $\mathbf{y} \in \mathcal{X}$, $\hat{\mathbf{x}}(\mathbf{y}) - \mathbf{y}$ is a descent direction for U at \mathbf{y} such that

$$\nabla U(\mathbf{y})^T (\hat{\mathbf{x}}(\mathbf{y}) - \mathbf{y}) \leq -c_{\tilde{U}} \|\hat{\mathbf{x}}(\mathbf{y}) - \mathbf{y}\|^2, \quad (25)$$

where $c_{\tilde{U}} > 0$ is the constant of uniform strong convexity of \tilde{U} (cf. B1);

(ii) For every $\mathbf{y} \in \mathcal{X}$, it holds that

$$\hat{\mathbf{x}}(\mathbf{y}) = P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{y})), \quad (26)$$

for every fixed $\rho > 0$.

(iii) Suppose that also B5 holds true. Then, $\hat{\mathbf{x}}(\bullet)$ is continuous at every $\bar{\mathbf{x}} \in \mathcal{X}$ such that $\hat{\mathbf{x}}(\bar{\mathbf{x}}) \in \mathcal{X}(\bar{\mathbf{x}})$ is regular.

Proof: (i) By Assumption 2, for any given $\mathbf{y} \in \mathcal{X}$, $\hat{\mathbf{x}}(\mathbf{y})$ is the solution of the strongly convex optimization problem $\mathcal{P}_{\mathbf{x}^\nu}$; therefore,

$$(\mathbf{z} - \hat{\mathbf{x}}(\mathbf{y}))^T \nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{y}); \mathbf{y}) \geq 0, \quad \forall \mathbf{z} \in \mathcal{X}(\mathbf{y}). \quad (27)$$

By choosing $\mathbf{z} = \mathbf{y}$ [recall by Lemma 6(i) that $\mathbf{y} \in \mathcal{X}(\mathbf{y})$], we get

$$(\mathbf{y} - \hat{\mathbf{x}}(\mathbf{y}))^T \left(\nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{y}); \mathbf{y}) - \nabla_{\mathbf{x}} \tilde{U}(\mathbf{y}; \mathbf{y}) + \nabla_{\mathbf{x}} \tilde{U}(\mathbf{y}; \mathbf{y}) \right) \geq 0,$$

which, using B1 and B2, leads to

$$(\mathbf{y} - \hat{\mathbf{x}}(\mathbf{y}))^T \nabla_{\mathbf{x}} U(\mathbf{y}) \geq c_{\tilde{U}} \|\hat{\mathbf{x}}(\mathbf{y}) - \mathbf{y}\|^2.$$

(ii) It follows readily from the fixed-point characterization of the solution $\hat{\mathbf{x}}(\mathbf{y})$ of the strongly convex subproblem $\mathcal{P}_{\mathbf{y}}$: see, e.g., [46, Prop. 1.5.8].

(iii) We first observe that, under the assumed regularity of all the points in $\mathcal{X}(\bar{\mathbf{x}})$, $\mathcal{X}(\bullet)$ is continuous at $\bar{\mathbf{x}}$ [39, Example 5.10]. It follows from [39, Proposition 4.9] (see also [39, Example 5.57]) that, for every fixed $\mathbf{u} \in \mathbb{R}^n$, the map $\mathbf{x} \mapsto P_{\mathcal{X}(\mathbf{x})}(\mathbf{u})$ is continuous at $\mathbf{x} = \bar{\mathbf{x}}$. This, together with B1, B3 and B5 is sufficient for $\hat{\mathbf{x}}(\bullet)$ to be continuous at $\bar{\mathbf{x}}$ [47, Theorem 2.1]. ■

Lemma 8. Under the extra conditions B4-B5, with the following lemma, which is reminiscent of similar results in [47] and [48], we can establish a suitable sensitivity property of the best-response function $\hat{\mathbf{x}}(\bullet)$; Lemma 8 will play a key role in the proof of statement (c) of Theorem 2.

Lemma 8: Suppose that B4-B5 hold and there exist $\bar{\rho} > 0$ and $\beta > 0$ such that

$$\|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z})) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z}))\| \leq \beta \|\mathbf{y} - \mathbf{z}\|^{\frac{1}{2}}, \quad (28)$$

for all $\rho \in (0, \bar{\rho}]$ and $\mathbf{y}, \mathbf{z} \in \mathcal{X}$. Then there exists $\tilde{\rho} \in (0, \bar{\rho}]$ such that

$$\|\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z})\| \leq \eta_\rho \|\mathbf{y} - \mathbf{z}\| + \theta_\rho \|\mathbf{y} - \mathbf{z}\|^{\frac{1}{2}}, \quad (29)$$

for all $\mathbf{y}, \mathbf{z} \in \mathcal{X}$ and $\rho \in (0, \tilde{\rho}]$, with

$$\eta_\rho \triangleq \frac{\rho \tilde{L}_{\nabla, 2}}{1 - \sqrt{1 + \rho^2 \tilde{L}_{\nabla, 1}^2 - 2\rho c_{\tilde{U}}}} \quad (30)$$

$$\theta_\rho \triangleq \frac{\beta}{1 - \sqrt{1 + \rho^2 \tilde{L}_{\nabla, 1}^2 - 2\rho c_{\tilde{U}}}},$$

where $\tilde{L}_{\nabla, 1}$ and $\tilde{L}_{\nabla, 2}$ are the Lipschitz constants of $\nabla_{\mathbf{x}} \tilde{U}(\bullet; \mathbf{y})$ and $\nabla_{\mathbf{x}} \tilde{U}(\mathbf{x}; \bullet)$, respectively (cf. B4 and B5); $\tilde{L}_{\nabla, 1}$ is assumed to be such that $\tilde{L}_{\nabla, 1} \geq c_{\tilde{U}}$ without loss of generality.

Proof: Using (26) we have, for every $\rho > 0$,

$$\begin{aligned} \|\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z})\| &= \|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{y})) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z}))\| \\ &\leq \|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{y})) - P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y}))\| \\ &\quad + \|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y})) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z}))\|. \end{aligned} \quad (31)$$

We bound next the two terms on the RHS of (31).

For every $\rho > 0$, it holds

$$\begin{aligned} &\|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{y})) - P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y}))\|^2 \\ &\stackrel{(a)}{\leq} \|\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{y}) - \mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y})\|^2 \\ &= \|\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z})\|^2 \\ &\quad + \rho^2 \|\nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y}) - \nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{y})\|^2 \\ &\quad - 2\rho (\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z}))^T \left(\nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{y}), \mathbf{y}) - \nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y}) \right) \\ &\stackrel{(b)}{\leq} \|\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z})\|^2 + \rho^2 \tilde{L}_{\nabla, 1}^2 \|\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z})\|^2 \\ &\quad - 2\rho c_{\tilde{U}} \|\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z})\|^2 \\ &= (1 + \rho^2 \tilde{L}_{\nabla, 1}^2 - 2\rho c_{\tilde{U}}) \|\hat{\mathbf{x}}(\mathbf{y}) - \hat{\mathbf{x}}(\mathbf{z})\|^2, \end{aligned} \quad (32)$$

where (a) is due to the non-expansive property of the projection operator $P_{\mathcal{X}(\mathbf{y})}(\bullet)$ and (b) follows from B1 and B5. Note that $1 + \rho^2 \tilde{L}_{\nabla, 1}^2 - 2\rho c_{\tilde{U}} > 0$ since we assumed $\tilde{L}_{\nabla, 1} \geq c_{\tilde{U}}$.

Let us bound now the second term on the RHS of (31). For every $\rho \in (0, \bar{\rho}]$, we have

$$\begin{aligned} &\|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y})) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z}))\| \\ &\leq \|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y})) - P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z}))\| \\ &\quad + \|P_{\mathcal{X}(\mathbf{y})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z})) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z}))\| \\ &\stackrel{(a)}{\leq} \|\mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{y}) - \mathbf{w}_\rho(\hat{\mathbf{x}}(\mathbf{z}), \mathbf{z})\| + \beta \|\mathbf{y} - \mathbf{z}\|^{\frac{1}{2}} \\ &\stackrel{(b)}{\leq} \rho \tilde{L}_{\nabla, 2} \|\mathbf{y} - \mathbf{z}\| + \beta \|\mathbf{y} - \mathbf{z}\|^{\frac{1}{2}}, \end{aligned} \quad (33)$$

where (a) is due to the non-expansive property of the projection $P_{\mathcal{X}(\mathbf{y})}(\bullet)$ and (28), and (b) follows from B4.

Combining (31), (32) and (33) we obtain the desired result (29) with $\tilde{\rho} = \min\{2c_{\tilde{U}}/\tilde{L}_{\nabla,1}^2, \tilde{\rho}\}$ (so that $0 < 1 + \rho^2\tilde{L}_{\nabla,1}^2 - 2\rho c_{\tilde{U}} < 1$ for every $\rho \in (0, \tilde{\rho})$). ■

Lemmas 9 and 10. While Assumptions 1-3 and B4-B5 in Lemma 8 are quite standard, condition (28) is less trivial and not easy to be checked. The following Lemma 10 provides some easier to be checked sufficient conditions that imply (28). To prove Lemma 10 we need first Lemma 9, as stated next.

Lemma 9: Consider $\bar{\mathbf{x}} \in \mathcal{X}$. By assuming C7, the following hold:

(i) If $\tilde{\mathbf{x}} \in \mathcal{X}(\bar{\mathbf{x}})$ is regular, then $\mathcal{X}(\bullet)$ enjoys the Aubin property at $(\bar{\mathbf{x}}, \tilde{\mathbf{x}})$;¹

(ii) If in addition \mathcal{X} is compact, then a neighborhood $\mathcal{V}_{\bar{\mathbf{x}}}$ of $\bar{\mathbf{x}}$, a neighborhood $\mathcal{W}_{\tilde{\mathbf{x}}}$ of $\tilde{\mathbf{x}}$, and a constant $\hat{\beta} > 0$ exist such that

$$\|P_{\mathcal{X}(\mathbf{y})}(\mathbf{u}) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{u})\| \leq \hat{\beta}\|\mathbf{y} - \mathbf{z}\|^{\frac{1}{2}} \quad (34)$$

for all $\mathbf{y}, \mathbf{z} \in \mathcal{X} \cap \mathcal{V}_{\bar{\mathbf{x}}}$, and $\mathbf{u} \in \mathcal{W}_{\tilde{\mathbf{x}}}$.

Proof: (i) Under Assumptions 1-3 and C7, the statement follows readily from [49, Theorem 3.2] in view of the regularity of $\tilde{\mathbf{x}}$.

(ii) Since $\mathcal{X}(\bullet)$ has the Aubin property at $(\bar{\mathbf{x}}, \tilde{\mathbf{x}})$, there exist a neighborhood $\mathcal{V}_{\bar{\mathbf{x}}}$ of $\bar{\mathbf{x}}$, a neighborhood $\mathcal{W}_{\tilde{\mathbf{x}}}$ of $\tilde{\mathbf{x}}$, and a constant $\hat{\beta} > 0$ such that [48, Lemma 1.1]:

$$\|P_{\mathcal{X}(\mathbf{y}) \cap \mathcal{B}_{\tilde{\mathbf{x}}}(\mathbf{u})} - P_{\mathcal{X}(\mathbf{z}) \cap \mathcal{B}_{\tilde{\mathbf{x}}}(\mathbf{u})}\| \leq \hat{\beta}\|\mathbf{y} - \mathbf{z}\|^{\frac{1}{2}}, \quad (35)$$

for all $\mathbf{y}, \mathbf{z} \in \mathcal{X} \cap \mathcal{V}_{\bar{\mathbf{x}}}$, and $\mathbf{u} \in \mathcal{W}_{\tilde{\mathbf{x}}}$, where $\mathcal{B}_{\tilde{\mathbf{x}}}$ denotes a closed convex neighborhood of $\tilde{\mathbf{x}}$. Since \mathcal{X} is compact, one can always choose $\mathcal{B}_{\tilde{\mathbf{x}}}$ such that $\mathcal{X}(\bar{\mathbf{x}}) \subset \mathcal{B}_{\tilde{\mathbf{x}}}$ for every $\bar{\mathbf{x}} \in \mathcal{X}$ and, thus,

$$\|P_{\mathcal{X}(\mathbf{y}) \cap \mathcal{B}_{\tilde{\mathbf{x}}}(\mathbf{u})} - P_{\mathcal{X}(\mathbf{z}) \cap \mathcal{B}_{\tilde{\mathbf{x}}}(\mathbf{u})}\| = \|P_{\mathcal{X}(\mathbf{y})}(\mathbf{u}) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{u})\|,$$

which proves the desired result. ■

We can now derive sufficient conditions for (28) to hold.

Lemma 10: Suppose that C7 holds true, \mathcal{X} is compact and $\hat{\mathbf{x}}(\bar{\mathbf{x}}) \in \mathcal{X}(\bar{\mathbf{x}})$ is regular for every $\bar{\mathbf{x}} \in \mathcal{X}$. Then, property (28) holds.

Proof: It follows from Lemma 9(ii) that, for every $\bar{\mathbf{x}} \in \mathcal{X}$, there exist a neighborhood $\mathcal{V}_{\bar{\mathbf{x}}}$ of $\bar{\mathbf{x}}$, a neighborhood $\mathcal{W}_{\hat{\mathbf{x}}(\bar{\mathbf{x}})}$ of $\hat{\mathbf{x}}(\bar{\mathbf{x}})$, and a constant $\hat{\beta} > 0$ such that:

$$\|P_{\mathcal{X}(\mathbf{y})}(\mathbf{u}) - P_{\mathcal{X}(\mathbf{z})}(\mathbf{u})\| \leq \hat{\beta}\|\mathbf{y} - \mathbf{z}\|^{\frac{1}{2}} \quad (36)$$

for every $\mathbf{y}, \mathbf{z} \in \mathcal{X} \cap \mathcal{V}_{\bar{\mathbf{x}}}$, $\mathbf{u} \in \mathcal{W}_{\hat{\mathbf{x}}(\bar{\mathbf{x}})}$.

Suppose now by contradiction that (28) does not hold. Then, for all $\bar{\rho} > 0$ and $\beta > 0$ there exist $\rho \in (0, \bar{\rho}]$, $\bar{\mathbf{x}}^\nu$, and $\bar{\mathbf{y}}^\nu \in \mathcal{X}$ such that:

$$\begin{aligned} & \|P_{\mathcal{X}(\bar{\mathbf{y}}^\nu)}(\mathbf{w}_{\rho^\nu}(\hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu), \bar{\mathbf{x}}^\nu)) - P_{\mathcal{X}(\bar{\mathbf{x}}^\nu)}(\mathbf{w}_{\rho^\nu}(\hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu), \bar{\mathbf{x}}^\nu))\| \\ & > \beta^\nu \|\bar{\mathbf{y}}^\nu - \bar{\mathbf{x}}^\nu\|^{\frac{1}{2}}. \end{aligned} \quad (37)$$

¹See [39, Def. 9.36] for the definition of the Aubin property. Note also that we use some results from [48] where a point-to-set map that has the Aubin property is called pseudo-Lipschitz [48, Def. 1.1].

Furthermore, in view of the compactness of \mathcal{X} , denoting by $D_{\mathcal{X}}$ the (finite) diameter of \mathcal{X} , the LHS of (37) can be bounded by

$$D_{\mathcal{X}} \geq \|P_{\mathcal{X}(\bar{\mathbf{y}}^\nu)}(\mathbf{w}_{\rho^\nu}(\hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu), \bar{\mathbf{x}}^\nu)) - P_{\mathcal{X}(\bar{\mathbf{x}}^\nu)}(\mathbf{w}_{\rho^\nu}(\hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu), \bar{\mathbf{x}}^\nu))\|. \quad (38)$$

Suppose without loss of generality that $\beta^\nu \rightarrow +\infty$, $\bar{\rho}^\nu \downarrow 0$, and $\bar{\mathbf{x}}^\nu \xrightarrow{\mathcal{N}} \bar{\mathbf{x}} \in \mathcal{X}(\bar{\mathbf{x}}) \subseteq \mathcal{X}$ and $\bar{\mathbf{y}}^\nu \xrightarrow{\mathcal{N}} \bar{\mathbf{y}} \in \mathcal{X}(\bar{\mathbf{y}}) \subseteq \mathcal{X}$, possibly on a suitable subsequence \mathcal{N} [recall that $\bar{\mathbf{x}}^\nu \in \mathcal{X}(\bar{\mathbf{x}}^\nu)$ and $\bar{\mathbf{y}}^\nu \in \mathcal{X}(\bar{\mathbf{y}}^\nu)$]. From (37) and (38), we obtain

$$D_{\mathcal{X}} \geq \limsup_{\nu \rightarrow +\infty} \beta^\nu \|\bar{\mathbf{y}}^\nu - \bar{\mathbf{x}}^\nu\|^{\frac{1}{2}},$$

which, in turn, considering that $\beta^\nu \rightarrow \infty$ and $\|\bar{\mathbf{y}}^\nu - \bar{\mathbf{x}}^\nu\|^{\frac{1}{2}} \geq 0$, implies

$$\lim_{\nu \rightarrow +\infty} \|\bar{\mathbf{y}}^\nu - \bar{\mathbf{x}}^\nu\|^{\frac{1}{2}} = 0. \quad (39)$$

Then, it must be $\bar{\mathbf{x}} = \bar{\mathbf{y}}$.

Invoking now the continuity of $\hat{\mathbf{x}}(\bullet)$ at $\bar{\mathbf{x}}$ [cf. Lemma 7(iii)] and $\nabla_{\bar{\mathbf{x}}}\tilde{U}(\bullet, \bullet)$ on $\mathcal{K} \times \mathcal{X}$ [cf. B3], we have

$$\mathbf{w}_{\rho^\nu}(\hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu), \bar{\mathbf{x}}^\nu) = \hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu) - \rho^\nu \nabla_{\bar{\mathbf{x}}}\tilde{U}(\hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu), \bar{\mathbf{x}}^\nu) \xrightarrow{\mathcal{N}} \hat{\mathbf{x}}(\bar{\mathbf{x}}). \quad (40)$$

Therefore, for every $\hat{\beta} > 0$ and neighborhoods $\mathcal{V}_{\bar{\mathbf{x}}}$ and $\mathcal{W}_{\hat{\mathbf{x}}(\bar{\mathbf{x}})}$, there exists a sufficiently large ν such that (37) holds with $\beta^\nu > \hat{\beta}$ (recall that $\beta^\nu \rightarrow +\infty$), $\bar{\mathbf{x}}^\nu, \bar{\mathbf{y}}^\nu \in \mathcal{V}_{\bar{\mathbf{x}}} \cap \mathcal{X}$ [due to (39)], and $\mathbf{w}_{\rho^\nu}(\hat{\mathbf{x}}(\bar{\mathbf{x}}^\nu), \bar{\mathbf{x}}^\nu) \in \mathcal{W}_{\hat{\mathbf{x}}(\bar{\mathbf{x}})}$ [due to (40)]; this is in contradiction with (36). ■

We recall that the assumption on the regularity of $\hat{\mathbf{x}}(\bar{\mathbf{x}}) \in \mathcal{X}(\bar{\mathbf{x}})$ for every $\bar{\mathbf{x}} \in \mathcal{X}$, as required in Lemma 10, is implied by Assumption 5.

Theorem 11. The last theorem of this section provides technical conditions under which a (at least one) regular limit point of the sequence generated by Algorithm 1 is a stationary solution of the original nonconvex problem \mathcal{P} .

Theorem 11: Let $\{\mathbf{x}^\nu\}$ be the sequence generated by Algorithm 1 under Assumptions 1-3 and 5. The the following hold.

(a) Suppose

$$\liminf_{\nu \rightarrow \infty} \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\| = 0. \quad (41)$$

Then, at least one regular limit point of $\{\mathbf{x}^\nu\}$ is a stationary solution of \mathcal{P} .

(b) Suppose

$$\lim_{\nu \rightarrow \infty} \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\| = 0. \quad (42)$$

Then, every regular limit point of $\{\mathbf{x}^\nu\}$ is a stationary solution of \mathcal{P} .

Proof: We prove only (a); (b) follows applying the result in (a) to every convergent subsequence of $\{\mathbf{x}^\nu\}$.

Let $\bar{\mathbf{x}}$ be a regular accumulation point of the subsequence $\{\mathbf{x}^\nu\}_{\mathcal{N}}$ of $\{\mathbf{x}^\nu\}$ satisfying (41); thus, there exists $\mathcal{N}' \subseteq \mathcal{N}$ such that $\lim_{\mathcal{N}' \ni \nu \rightarrow \infty} \mathbf{x}^\nu = \bar{\mathbf{x}}$. We show next that $\bar{\mathbf{x}}$ is a KKT point of the original problem. Let \bar{J} and J^ν be the following sets:

$$\bar{J} \triangleq \{j \in [1, \dots, m] : g_j(\bar{\mathbf{x}}) = 0\},$$

$$J^\nu \triangleq \{j \in [1, \dots, m] : \tilde{g}_j(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) = 0\}$$

with $\nu \in \mathcal{N}'$. Using $\lim_{\mathcal{N}' \ni \nu \rightarrow \infty} \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\| = 0$ [cf. (41)] along with the continuity of \tilde{g}_j , by C2, we have

$$\lim_{\mathcal{N}' \ni \nu \rightarrow \infty} \tilde{g}_j(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) = \tilde{g}_j(\bar{\mathbf{x}}; \bar{\mathbf{x}}) = g_j(\bar{\mathbf{x}}), \quad j = 1, \dots, m. \quad (43)$$

The limit above implies that there exists a positive integer $\tilde{\nu} \in \mathcal{N}'$ such that

$$J^\nu \subseteq \bar{J}, \quad \forall \nu \geq \tilde{\nu} \text{ and } \nu \in \mathcal{N}'. \quad (44)$$

Since the functions $\nabla_{\mathbf{x}} \tilde{U}$ and $\nabla_{\mathbf{x}} \tilde{g}_j$ are continuous, we get, by B2,

$$\lim_{\mathcal{N}' \ni \nu \rightarrow \infty} \nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) = \nabla_{\mathbf{x}} \tilde{U}(\bar{\mathbf{x}}; \bar{\mathbf{x}}) = \nabla U(\bar{\mathbf{x}}), \quad (45)$$

and, for $j = 1, \dots, m$, by C5,

$$\lim_{\mathcal{N}' \ni \nu \rightarrow \infty} \nabla_{\mathbf{x}} \tilde{g}_j(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) = \nabla_{\mathbf{x}} \tilde{g}_j(\bar{\mathbf{x}}; \bar{\mathbf{x}}) = \nabla g_j(\bar{\mathbf{x}}). \quad (46)$$

We claim now that for sufficiently large $\nu \in \mathcal{N}'$, the MFCQ holds at $\hat{\mathbf{x}}(\mathbf{x}^\nu) \in \mathcal{X}(\mathbf{x}^\nu)$. Assume by contradiction that the following implication does not hold for infinitely many $\nu \in \mathcal{N}'$:

$$\underbrace{\begin{aligned} & - \sum_{j \in J^\nu} \mu_j^\nu \nabla_{\mathbf{x}} \tilde{g}_j(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) \in N_{\mathcal{K}}(\hat{\mathbf{x}}(\mathbf{x}^\nu)) \\ & \mu_j^\nu \geq 0, \quad \forall j \in J^\nu, \end{aligned}}_{\downarrow} \\ \mu_j^\nu = 0, \quad \forall j \in J^\nu. \quad (47)$$

It follows that a nonempty index set $\bar{J} \subseteq \bar{J}$ exists such that, after a suitable renumeration, for every $\nu \in \mathcal{N}'$, we must have

$$\begin{aligned} & - \sum_{j \in \bar{J}} \mu_j^\nu \nabla_{\mathbf{x}} \tilde{g}_j(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) \in N_{\mathcal{K}}(\hat{\mathbf{x}}(\mathbf{x}^\nu)) \\ & \mu_j^\nu \geq 0, \quad \forall j \in \bar{J} \\ & \sum_{j \in \bar{J}} \mu_j^\nu = 1. \end{aligned} \quad (48)$$

We may assume without loss of generality that, for each $j \in \bar{J}$, the sequence $\{\mu_j^\nu\}$ converges to a limit $\bar{\mu}_j$ such that $\sum_{j \in \bar{J}} \bar{\mu}_j = 1$. In view of the inclusion $\bar{J} \subseteq \bar{J}$, by taking the limit $\mathcal{N}' \ni \nu \rightarrow \infty$ in (48), and invoking (46) along with the outer semicontinuity of the mapping $N_{\mathcal{K}}(\bullet)$ [39, Prop. 6.6], we get

$$\begin{aligned} & - \sum_{j \in \bar{J}} \bar{\mu}_j \nabla_{\mathbf{x}} g_j(\bar{\mathbf{x}}) \in N_{\mathcal{K}}(\bar{\mathbf{x}}) \\ & \bar{\mu}_j \geq 0, \quad \forall j \in \bar{J} \\ & \sum_{j \in \bar{J}} \bar{\mu}_j = 1, \end{aligned} \quad (49)$$

in contradiction with the regularity of $\bar{\mathbf{x}}$ [the MFCQ holds at $\bar{\mathbf{x}}$, see (2)]. Therefore, (47) must hold for sufficiently large $\nu \in \mathcal{N}'$, implying that the KKT system of problem $\mathcal{P}_{\mathbf{x}^\nu}$ has a solution for every sufficiently large $\nu \in \mathcal{N}'$: thus, there exist $(\mu_j^\nu)_{j=1}^m$ such that

$$\begin{aligned} & - \left[\nabla_{\mathbf{x}} \tilde{U}(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) + \sum_{j=1}^m \mu_j^\nu \nabla_{\mathbf{x}} \tilde{g}_j(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) \right] \in N_{\mathcal{K}}(\hat{\mathbf{x}}(\mathbf{x}^\nu)) \\ & 0 \leq \mu_j^\nu \perp \tilde{g}_j(\hat{\mathbf{x}}(\mathbf{x}^\nu); \mathbf{x}^\nu) \leq 0, \quad j = 1, \dots, m. \end{aligned} \quad (50)$$

Note that by (44) and the complementarity slackness in (50), $\mu_j^\nu = 0$ for all $j \notin \bar{J}$ and large $\nu \in \mathcal{N}'$. Moreover, the sequence of nonnegative multipliers $\{\boldsymbol{\mu}^\nu \triangleq (\mu_j^\nu)_{j \in \bar{J}}\}_{\nu \in \mathcal{N}'}$ must be bounded, as shown next. Suppose by contradiction

that $\lim_{\mathcal{N}' \ni \nu \rightarrow \infty} \|\boldsymbol{\mu}^\nu\| = +\infty$ for some $\{\hat{\mathbf{x}}(\mathbf{x}^\nu)\}_{\nu \in \mathcal{N}'}$ (possibly over a subsequence). Dividing both sides of (50) by $\|\boldsymbol{\mu}^\nu\|$ and taking the limit $\mathcal{N}' \ni \nu \rightarrow \infty$, one would get

$$\begin{aligned} & - \sum_{j \in \bar{J}} \bar{\mu}_j \nabla g_j(\bar{\mathbf{x}}) \in N_{\mathcal{K}}(\bar{\mathbf{x}}) \\ & 0 \leq \bar{\mu}_j \perp g_j(\bar{\mathbf{x}}) \leq 0, \quad j \in \bar{J}, \end{aligned} \quad (51)$$

for some $\bar{\boldsymbol{\mu}} \triangleq (\bar{\mu}_j)_{j \in \bar{J}} \neq \mathbf{0}$, in contradiction with (2).

Therefore, $\{\boldsymbol{\mu}^\nu \triangleq (\mu_j^\nu)_{j \in \bar{J}}\}_{\nu \in \mathcal{N}'}$ must have a limit; let us denote by $(\bar{\mu}_j)_{j \in \bar{J}}$ such a limit (after a suitable renumeration). Taking the limit $\mathcal{N}' \ni \nu \rightarrow \infty$ in (50), and using (45) and (46) along with the outer semicontinuity of the mapping $N_{\mathcal{K}}(\bullet)$, we get

$$\begin{aligned} & - \left[\nabla U(\bar{\mathbf{x}}) + \sum_{j \in \bar{J}} \bar{\mu}_j \nabla g_j(\bar{\mathbf{x}}) \right] \in N_{\mathcal{K}}(\bar{\mathbf{x}}) \\ & 0 \leq \bar{\mu}_j \perp g_j(\bar{\mathbf{x}}) \leq 0, \quad j \in \bar{J}. \end{aligned} \quad (52)$$

It follows from (52) that $\bar{\mathbf{x}}$ is a stationary solution of the original problem \mathcal{P} . ■

B. Proof of Theorem 2

Proof of statement (a). It follows from Lemma 6.

Proof of statement (b). Invoking Theorem 11(b), it is sufficient to show that (42) in Theorem 11 is satisfied.

By the descent lemma [21, Propo. A.24] and Step 3 of Algorithm 1, we get:

$$\begin{aligned} U(\mathbf{x}^{\nu+1}) & \leq U(\mathbf{x}^\nu) + \gamma^\nu \nabla U(\mathbf{x}^\nu)^T (\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu) \\ & \quad + \frac{(\gamma^\nu)^2 L_{\nabla U}}{2} \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\|^2. \end{aligned}$$

Invoking (25) in Lemma 7, we obtain

$$U(\mathbf{x}^{\nu+1}) \leq U(\mathbf{x}^\nu) - \gamma^\nu \left(c_{\bar{U}} - \frac{\gamma^\nu L_{\nabla U}}{2} \right) \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\|^2. \quad (53)$$

Since $0 < \inf_{\nu} \gamma^\nu \leq \sup_{\nu} \gamma^\nu \leq \gamma^{\max} \leq 1$ and $2c_{\bar{U}} > \gamma^{\max} L_{\nabla U}$, we deduce from (53) that either $U(\mathbf{x}^\nu) \rightarrow -\infty$ or $\{U(\mathbf{x}^\nu)\}$ converges to a finite value and

$$\lim_{\nu \rightarrow \infty} \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\| = 0. \quad (54)$$

By assumption A4, $\{U(\mathbf{x}^\nu)\}$ is convergent and the sequence $\{\mathbf{x}^\nu\} \subseteq \mathcal{X}$ [Lemma 6(iii)] is bounded. Therefore, (54) holds true and $\{\mathbf{x}^\nu\}$ has a limit point in \mathcal{X} . By Theorem 11(b) and (54), statement (b) of the theorem follows readily. Finally, by (53), $U(\mathbf{x}^\nu)$ is a decreasing sequence: hence, no limit point of $\{\mathbf{x}^\nu\}$ can be a local maximum of U .

Proof of statement (c). Invoking Theorem 11(a), it is sufficient to show that (41) in Theorem 11 is satisfied. Following the same steps as in the proof of statement (b), by (53) and $\gamma^\nu \rightarrow 0$, for $\nu \geq \bar{\nu}$ sufficiently large, there exists a positive constant ζ such that:

$$U(\mathbf{x}^{\nu+1}) \leq U(\mathbf{x}^\nu) - \gamma^\nu \zeta \|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu\|^2, \quad (55)$$

which, again, by A4, leads to

$$\lim_{\nu \rightarrow \infty} \sum_{t=\bar{\nu}}^{\nu} \gamma^t \|\hat{\mathbf{x}}(\mathbf{x}^t) - \mathbf{x}^t\|^2 < +\infty. \quad (56)$$

The desired result (41) follows from (56) and $\sum_{\nu=0}^{\infty} \gamma^\nu = +\infty$. Similarly to the previous case, by (56), eventually $U(\mathbf{x}^\nu)$

is a decreasing sequence: thus, no limit point of $\{\mathbf{x}^\nu\}$ can be a local maximum of U .

Suppose now that Assumption 4 holds. By Theorem 11(b) it is sufficient to prove that (42) holds true. For notational simplicity, we set $\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu) \triangleq \hat{\mathbf{x}}(\mathbf{x}^\nu) - \mathbf{x}^\nu$. We already proved that $\liminf_\nu \|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| = 0$; therefore, (42) holds if $\limsup_\nu \|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| = 0$, as stated next.

First of all, note that, by Assumption 4, Lemma 10 and, by consequence, Lemma 8 hold true; therefore, there exists $\tilde{\rho} > 0$ such that (cf. Lemma 8)

$$\|\hat{\mathbf{x}}(\mathbf{x}^\nu) - \hat{\mathbf{x}}(\mathbf{x}^t)\| \leq \eta_\rho \|\mathbf{x}^\nu - \mathbf{x}^t\| + \theta_\rho \|\mathbf{x}^\nu - \mathbf{x}^t\|^{\frac{1}{2}}, \quad (57)$$

for any $\nu, t \geq 1$ and $\rho \in (0, \tilde{\rho}]$, with η_ρ and θ_ρ defined in (30) (cf. Lemma 8).

Suppose by contradiction that $\limsup_\nu \|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| > 0$. Then, there exists $\delta > 0$ such that $\|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| > 2\delta + \sqrt{\delta/2}$ for infinitely many ν , and also $\|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| < \delta + \sqrt{\delta/2}$ for infinitely many ν . Thus, there exists an infinite subset of indices \mathcal{N} such that, for each $\nu \in \mathcal{N}$ and some $i_\nu > \nu$, the following hold:

$$\|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| < \delta + \sqrt{\delta/2}, \quad \|\Delta\hat{\mathbf{x}}(\mathbf{x}^{i_\nu})\| > 2\delta + \sqrt{\delta/2} \quad (58)$$

and, in case $i_\nu > \nu + 1$,

$$\delta + \sqrt{\delta/2} \leq \|\Delta\hat{\mathbf{x}}(\mathbf{x}^j)\| \leq 2\delta + \sqrt{\delta/2}, \quad \nu < j < i_\nu. \quad (59)$$

Hence, for all $\nu \in \mathcal{N}$, we can write

$$\begin{aligned} \delta &< \|\Delta\hat{\mathbf{x}}(\mathbf{x}^{i_\nu})\| - \|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| \\ &\leq \|\hat{\mathbf{x}}(\mathbf{x}^{i_\nu}) - \hat{\mathbf{x}}(\mathbf{x}^\nu)\| + \|\mathbf{x}^{i_\nu} - \mathbf{x}^\nu\| \\ &\stackrel{(a)}{\leq} (1 + \eta_\rho) \|\mathbf{x}^{i_\nu} - \mathbf{x}^\nu\| + \theta_\rho \|\mathbf{x}^{i_\nu} - \mathbf{x}^\nu\|^{\frac{1}{2}} \\ &\stackrel{(b)}{\leq} (1 + \eta_\rho) \left(2\delta + \sqrt{\delta/2} \right) \sum_{t=\nu}^{i_\nu-1} \gamma^t \\ &\quad + \theta_\rho \left(2\delta + \sqrt{\delta/2} \right)^{\frac{1}{2}} \left(\sum_{t=\nu}^{i_\nu-1} \gamma^t \right)^{\frac{1}{2}}, \end{aligned} \quad (60)$$

where (a) is due to (57) and (b) comes from the triangle inequality and the updating rule of the algorithm. It follows from (58) and (60) that

$$\liminf_\nu \left[(1 + \eta_\rho) \left(2\delta + \sqrt{\delta/2} \right) \sum_{t=\nu}^{i_\nu-1} \gamma^t + \theta_\rho \left(2\delta + \sqrt{\delta/2} \right)^{\frac{1}{2}} \left(\sum_{t=\nu}^{i_\nu-1} \gamma^t \right)^{\frac{1}{2}} \right] > 0. \quad (61)$$

We now prove that $\|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| \geq \delta/2$ for sufficiently large $\nu \in \mathcal{N}$. Reasoning as in (60), we have

$$\begin{aligned} \|\Delta\hat{\mathbf{x}}(\mathbf{x}^{\nu+1})\| - \|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| &\leq \\ &(1 + \eta_\rho) \|\mathbf{x}^{\nu+1} - \mathbf{x}^\nu\| + \theta_\rho \|\mathbf{x}^{\nu+1} - \mathbf{x}^\nu\|^{\frac{1}{2}} \\ &\leq (1 + \eta_\rho) \gamma^\nu \|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| + \theta_\rho (\gamma^\nu)^{1/2} \|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\|^{\frac{1}{2}}, \end{aligned} \quad (62)$$

for any given ν . For large $\nu \in \mathcal{N}$, so that $(1 + \eta_\rho) \gamma^\nu \delta/2 + \theta_\rho (\gamma^\nu \delta/2)^{\frac{1}{2}} < \delta/2 + \sqrt{\delta/2}$, suppose by contradiction that $\|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| < \delta/2$; this would give $\|\Delta\hat{\mathbf{x}}(\mathbf{x}^{\nu+1})\| < \delta + \sqrt{\delta/2}$ and condition (59) (or, in case, (58)) would be violated. Then, it must be

$$\|\Delta\hat{\mathbf{x}}(\mathbf{x}^\nu)\| \geq \delta/2. \quad (63)$$

Using (63), we can show now that (61) is in contradiction with the convergence of $\{U(\mathbf{x}^\nu)\}$. By (55), (possibly over a subsequence) for sufficiently large $\nu \in \mathcal{N}$, we have

$$\begin{aligned} U(\mathbf{x}^{i_\nu}) &\leq U(\mathbf{x}^\nu) - \zeta \sum_{t=\nu}^{i_\nu-1} \gamma^t \|\Delta\hat{\mathbf{x}}(\mathbf{x}^t)\|^2 \\ &< U(\mathbf{x}^\nu) - \zeta \frac{\delta^2}{4} \sum_{t=\nu}^{i_\nu-1} \gamma^t, \end{aligned} \quad (64)$$

where, in the last inequality, we have used (59) (or, in case, (58)) and (63). Thus, since $U(\mathbf{x}^\nu)$ converges, (64) implies $\lim_{\nu \in \mathcal{N}} \sum_{t=\nu}^{i_\nu-1} \gamma^t = 0$, in contradiction with (61).

Remark 12: As we already mentioned in subsection III-A3, in [11] it is shown that, in the specific case of a *strongly convex* U , $\tilde{U} = U$, and $\mathcal{K} = \mathbb{R}^n$, one can choose $\gamma^\nu = 1$ at every iteration and prove the stationarity of every limit point of the sequence generated by Algorithm 1 (assuming regularity). For completeness we sketch how this result can be readily obtained using our framework (and actually slightly improved on by also considering the case in which \mathcal{K} is not necessarily \mathbb{R}^n). The proof is based on Theorem 11(b) and a result in [11]. By Theorem 11(b), it is enough to show that (42) holds. But (42) does indeed hold because of the strong convexity of U , as shown at the beginning of Proposition 3.2 in [11]. Note that the strong convexity of U plays here a fundamental role and that, once we remove this restrictive assumption, things get considerably more difficult, as clearly shown by the complexity of the proof of Theorem 2.

C. Proof of Lemma 3

(a) It is a consequence of Danskin's theorem [21, Prop. A.43]. (b) The statement follows from the uniform Lipschitz continuity of $\hat{\mathbf{x}}(\bullet; \mathbf{x}^\nu)$ on \mathbb{R}_+^m with constant $L_{\nabla d}$, which is proved next. For notational simplicity, let us write $\hat{\mathbf{x}}_\lambda \triangleq \hat{\mathbf{x}}(\lambda; \mathbf{x}^\nu)$ and $\hat{\mathbf{x}}_{\lambda'} \triangleq \hat{\mathbf{x}}(\lambda'; \mathbf{x}^\nu)$. Defining $\mathcal{L}(\mathbf{x}, \lambda) \triangleq \sum_{i=1}^I \left(\tilde{U}_i(\mathbf{x}_i; \mathbf{x}^\nu) + \lambda^T \tilde{\mathbf{g}}^i(\mathbf{x}_i; \mathbf{x}^\nu) \right)$, we have, by the minimality principle,

$$\begin{aligned} (\hat{\mathbf{x}}_{\lambda'} - \hat{\mathbf{x}}_\lambda)^T \nabla_{\mathbf{x}} \mathcal{L}(\hat{\mathbf{x}}_\lambda, \lambda) &\geq 0 \\ (\hat{\mathbf{x}}_\lambda - \hat{\mathbf{x}}_{\lambda'})^T \nabla_{\mathbf{x}} \mathcal{L}(\hat{\mathbf{x}}_{\lambda'}, \lambda') &\geq 0. \end{aligned}$$

Adding the two inequalities above and summing and subtracting $\nabla_{\mathbf{x}} \mathcal{L}(\hat{\mathbf{x}}_\lambda, \lambda')$, we obtain

$$\begin{aligned} c_{\tilde{U}} \cdot \|\hat{\mathbf{x}}_\lambda - \hat{\mathbf{x}}_{\lambda'}\|^2 &\leq (\hat{\mathbf{x}}_{\lambda'} - \hat{\mathbf{x}}_\lambda)^T \left[\nabla_{\mathbf{x}} \mathcal{L}(\hat{\mathbf{x}}_\lambda, \lambda) - \nabla_{\mathbf{x}} \mathcal{L}(\hat{\mathbf{x}}_\lambda, \lambda') \right] \\ &= (\hat{\mathbf{x}}_\lambda - \hat{\mathbf{x}}_{\lambda'})^T \left[\nabla_{\mathbf{x}} \mathcal{L}(\hat{\mathbf{x}}_\lambda, \lambda') - \nabla_{\mathbf{x}} \mathcal{L}(\hat{\mathbf{x}}_\lambda, \lambda) \right], \end{aligned} \quad (65)$$

where, in the first inequality, we used the uniform strong convexity of $\mathcal{L}(\bullet, \lambda')$. Hence, we have

$$\begin{aligned} c_{\tilde{U}} \cdot \|\hat{\mathbf{x}}_\lambda - \hat{\mathbf{x}}_{\lambda'}\| &\leq \sum_{j=1}^m \left| \lambda'_j - \lambda_j \right| \|\nabla_{\mathbf{x}} \tilde{g}_j(\hat{\mathbf{x}}_\lambda; \mathbf{x}^\nu)\| \\ &\stackrel{(a)}{\leq} \sum_{j=1}^m \left| \lambda'_j - \lambda_j \right| L_{\tilde{g}} = \|\lambda' - \lambda\|_1 \cdot L_{\tilde{g}} \\ &\leq L_{\tilde{g}} \sqrt{m} \|\lambda' - \lambda\|_2, \end{aligned} \quad (66)$$

where (a) follows from the uniform Lipschitz continuity of $\tilde{\mathbf{g}}$. The inequality above proves the Lipschitz property of $\hat{\mathbf{x}}(\bullet; \mathbf{x}^\nu)$.

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