



GALAHAD

LSRT

USER DOCUMENTATION

GALAHAD Optimization Library version 2.5

1 SUMMARY

Given a real m by n matrix \mathbf{A} , a real m vector \mathbf{b} and scalars $\sigma > 0$ and $p \geq 2$, this package finds an **approximate minimizer of the regularised linear-least-squares objective function** $\frac{1}{2}\|\mathbf{Ax} - \mathbf{b}\|_2^2 + \frac{1}{p}\sigma\|\mathbf{x}\|_2^p$. This problem commonly occurs as a subproblem in nonlinear optimization calculations involving cubic regularisation, and may be used to regularise the solution of under-determined or ill-conditioned linear least-squares problems. The method may be suitable for large m and/or n as no factorization involving \mathbf{A} is required. Reverse communication is used to obtain matrix-vector products of the form $\mathbf{u} + \mathbf{Av}$ and $\mathbf{v} + \mathbf{A}^T\mathbf{u}$.

ATTRIBUTES — **Versions:** GALAHAD_LSRT_single, GALAHAD_LSRT_double. **Uses:** GALAHAD_SYMBOLS, GALAHAD_SPACE, GALAHAD_NORMS, GALAHAD_ROOTS, GALAHAD_LSTR, GALAHAD_SPECFILE, *ROTG. **Date:** November 2007. **Origin:** N. I. M. Gould, Oxford University and Rutherford Appleton Laboratory. **Language:** Fortran 95 + TR 15581 or Fortran 2003.

2 HOW TO USE THE PACKAGE

Access to the package requires a USE statement such as

Single precision version

```
USE GALAHAD_LSRT_single
```

Double precision version

```
USE GALAHAD_LSRT_double
```

If it is required to use both modules at the same time, the derived types LSRT_control_type, LSRT_inform_type, LSRT_data_type, (Section 2.1) and the subroutines LSRT_initialize, LSRT_solve, LSRT_terminate (Section 2.2) and LSRT_read_specfile (Section 2.6) must be renamed on one of the USE statements.

2.1 The derived data types

Three derived data types are accessible from the package.

2.1.1 The derived data type for holding control parameters

The derived data type LSRT_control_type is used to hold controlling data. Default values may be obtained by calling LSRT_initialize (see Section 2.2.1). The components of LSRT_control_type are:

`error` is a scalar variable of type default INTEGER, that holds the stream number for error messages. Printing of error messages in LSRT_solve and LSRT_terminate is suppressed if `error` ≤ 0 . The default is `error` = 6.

`out` is a scalar variable of type default INTEGER, that holds the stream number for informational messages. Printing of informational messages in LSRT_solve is suppressed if `out` < 0 . The default is `out` = 6.

`print_level` is a scalar variable of type default INTEGER, that is used to control the amount of informational output which is required. No informational output will occur if `print_level` ≤ 0 . If `print_level` = 1 a single line of output will be produced for each iteration of the process. If `print_level` ≥ 2 this output will be increased to provide significant detail of each iteration. The default is `print_level` = 0.

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`itmin` is a scalar variable of type default `INTEGER`, that holds the minimum number of iterations which will be performed by `LSRT_solve`. The default is `itmin = -1`.

`itmax` is a scalar variable of type default `INTEGER`, that holds the maximum number of iterations which will be allowed in `LSRT_solve`. If `itmax` is set to a negative number, it will be reset by `LSRT_solve` to $\max(m, n) + 1$. The default is `itmax = -1`.

`bitmax` is a scalar variable of type default `INTEGER`, that holds the maximum number of Newton inner iterations which will be allowed for each main iteration in `LSRT_solve`. If `bitmax` is set to a negative number, it will be reset by `LSRT_solve` to 10. The default is `bitmax = -1`.

`extra_vectors` is a scalar variable of type default `INTEGER`, that specifies the number of additional vectors of length n that will be allocated to try to speed up the computation during the second pass. The default is `extra_vectors = 0`.

`space_critical` is a scalar variable of type default `LOGICAL`, that may be set `.TRUE.` if the user wishes the package to allocate as little internal storage as possible, and `.FALSE.` otherwise. The package may be more efficient if `space_critical` is set `.FALSE.`. The default is `space_critical = .FALSE.`.

`deallocate_error_fatal` is a scalar variable of type default `LOGICAL`, that may be set `.TRUE.` if the user wishes the package to return to the user in the unlikely event that an internal array deallocation fails, and `.FALSE.` if the package should be allowed to try to continue. The default is `deallocate_error_fatal = .FALSE.`.

`stop_relative` and `stop_absolute` are scalar variables of type `REAL` (double precision in `GALAHAD_LSRT_double`), that holds the relative and absolute convergence tolerances (see Section 4). The computed solution \mathbf{x} is accepted by `LSRT_solve` if the computed value of $\|\mathbf{A}^T(\mathbf{Ax} - \mathbf{b}) + \lambda\mathbf{x}\|_2$ is less than or equal to $\max(\|\mathbf{A}^T\mathbf{b}\|_2 * \text{stop_relative}, \text{stop_absolute})$, where the multiplier $\lambda = \sigma\|\mathbf{x}\|_2^{p-2}$. The defaults are `stop_relative = \sqrt{u}` and `stop_absolute = 0.0`, where u is `EPSILON(1.0)` (`EPSILON(1.0D0)` in `GALAHAD_LSRT_double`).

`fraction_opt` is a scalar variable of type default `REAL` (double precision in `GALAHAD_LSRT_double`), that specifies the fraction of the optimal value which is to be considered acceptable by the algorithm. A negative value is considered to be zero, and a value of larger than one is considered to be one. Reducing `fraction_opt` below one will result in a reduction of the computation performed at the expense of an inferior optimal value. The default is `fraction_opt = 1.0`.

`prefix` is a scalar variable of type default `CHARACTER` and length 30, that may be used to provide a user-selected character string to preface every line of printed output. Specifically, each line of output will be prefaced by the string `prefix(2:LEN(TRIM(prefix))-1)`, thus ignoring the first and last non-null components of the supplied string. If the user does not want to preface lines by such a string, they may use the default `prefix = ""`.

2.1.2 The derived data type for holding informational parameters

The derived data type `LSRT_inform_type` is used to hold parameters that give information about the progress and needs of the algorithm. The components of `LSRT_inform_type` are:

`status` is a scalar variable of type default `INTEGER`, that gives the current status of the algorithm. See Sections 2.3 and 2.4 for details.

`alloc_status` is a scalar variable of type default `INTEGER`, that gives the status of the last internal array allocation or deallocation. This will be 0 if `status = 0`.

`bad_alloc` is a scalar variable of type default `CHARACTER` and length 80, that gives the name of the last internal array for which there were allocation or deallocation errors. This will be the null string if `status = 0`.

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`obj` is a scalar variable of type default REAL (double precision in GALAHAD_LSRT_double), that holds the value of the objective function $\frac{1}{2}\|\mathbf{Ax} - \mathbf{b}\|_2^2 + \frac{1}{p}\sigma\|\mathbf{x}\|_2^p$.

`multiplier` is a scalar variable of type default REAL (double precision in GALAHAD_LSRT_double), that holds the value of the multiplier $\lambda = \sigma\|\mathbf{x}\|_2^{p-2}$.

`x_norm` is a scalar variable of type default REAL (double precision in GALAHAD_LSRT_double), that holds the current value of $\|\mathbf{x}\|_2$.

`r_norm` is a scalar variable of type default REAL (double precision in GALAHAD_LSRT_double), that holds the current value of $\|\mathbf{Ax} - \mathbf{b}\|_2$.

`Atr_norm` is a scalar variable of type default REAL (double precision in GALAHAD_LSRT_double), that holds the current value of $\|\mathbf{A}^T(\mathbf{Ax} - \mathbf{b}) + \lambda\mathbf{x}\|_2$.

`iter` is a scalar variable of type default INTEGER, that holds the current number of Lanczos vectors used.

`iter_pass2` is a scalar variable of type default INTEGER, that holds the current number of Lanczos vectors used in the second pass.

2.1.3 The derived data type for holding problem data

The derived data type `LSRT_data_type` is used to hold all the data for a particular problem between calls of LSRT procedures. This data should be preserved, untouched, from the initial call to `LSRT_initialize` to the final call to `LSRT_terminate`.

2.2 Argument lists and calling sequences

There are three procedures for user calls (see Section 2.6 for further features):

1. The subroutine `LSRT_initialize` is used to set default values, and initialize private data.
2. The subroutine `LSRT_solve` is called repeatedly to solve the problem. On each exit, the user may be expected to provide additional information and, if necessary, re-enter the subroutine.
3. The subroutine `LSRT_terminate` is provided to allow the user to automatically deallocate array components of the private data, allocated by `LSRT_solve`, at the end of the solution process. It is important to do this if the data object is re-used for another problem since `LSRT_initialize` cannot test for this situation, and any existing associated targets will subsequently become unreachable.

2.2.1 The initialization subroutine

Default values are provided as follows:

```
CALL LSRT_initialize( data, control, inform )
```

`data` is a scalar INTENT(INOUT) argument of type `LSRT_data_type` (see Section 2.1.3). It is used to hold data about the problem being solved.

`control` is a scalar INTENT(OUT) argument of type `LSRT_control_type` (see Section 2.1.1). On exit, `control` contains default values for the components as described in Section 2.1.1. These values should only be changed after calling `LSRT_initialize`.

`inform` is a scalar INTENT(OUT) argument of type `LSRT_inform_type` (see Section 2.1.2). A successful call to `LSRT_initialize` is indicated when the component status has the value 0. For other return values of status, see Section 2.4.

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2.2.2 The optimization problem solution subroutine

The optimization problem solution algorithm is called as follows:

```
CALL LSRT_solve( m, n, p, sigma, X, U, V, data, control, inform )
```

- m is a scalar INTENT(IN) argument of type default INTEGER, that must be set to the number of equations, m .
Restriction: $m > 0$.
- n is a scalar INTENT(IN) argument of type default INTEGER, that must be set to the number of unknowns, n .
Restriction: $n > 0$.
- p is a scalar INTENT(IN) variable of type default REAL (double precision in GALAHAD_LSRT_double), that must be set on initial entry to the desired order p of regularisation. **Restriction:** $p \geq 2$.
- sigma is a scalar INTENT(IN) variable of type default REAL (double precision in GALAHAD_LSRT_double), that must be set on initial entry to the value of the weight σ associated with the regularisation term. **Restriction:** $\sigma > 0$.
- X is an array INTENT(INOUT) argument of dimension n and type default REAL (double precision in GALAHAD_LSRT_double), that holds an estimate of the solution \mathbf{x} of the linear system. On initial entry, X need not be set. It must not be changed between entries. On exit, X contains the current best estimate of the solution.
- U is an array INTENT(INOUT) argument of dimension m and type default REAL (double precision in GALAHAD_LSRT_double), that is used to hold left-Lanczos vectors used during the iteration. On initial entry, U must contain the vector \mathbf{b} . If `inform%status = 2` or `4` on exit, U must be reset as directed by `inform%status`; otherwise it must be left unchanged.
- V is an array INTENT(INOUT) argument of dimension n and type default REAL (double precision in GALAHAD_LSRT_double), that is used to hold left-Lanczos vectors used during the iteration. It need not be set on initial entry. If `inform%status = 3` on exit, V must be reset as directed by `inform%status`; otherwise it must be left unchanged.
- data is a scalar INTENT(INOUT) argument of type LSRT_data_type (see Section 2.1.3). It is used to hold data about the problem being solved. It must not have been altered **by the user** since the last call to LSRT_initialize.
- control is a scalar INTENT(IN) argument of type LSRT_control_type. (see Section 2.1.1). Default values may be assigned by calling LSRT_initialize prior to the first call to LSRT_solve.
- inform is a scalar INTENT(INOUT) argument of type LSRT_inform_type (see Section 2.1.2). On initial entry, the component status must be set to 1. The remaining components need not be set. A successful call to LSRT_solve is indicated when the component status has the value 0. For other return values of status, see Sections 2.3 and 2.4.

2.2.3 The termination subroutine

All previously allocated arrays are deallocated as follows:

```
CALL LSRT_terminate( data, control, inform )
```

- data is a scalar INTENT(INOUT) argument of type LSRT_data_type exactly as for LSRT_solve that must not have been altered **by the user** since the last call to LSRT_initialize. On exit, array components will have been deallocated.
- control is a scalar INTENT(IN) argument of type LSRT_control_type exactly as for LSRT_solve.
- inform is a scalar INTENT(OUT) argument of type LSRT_type exactly as for LSRT_solve. Only the component status will be set on exit, and a successful call to LSRT_terminate is indicated when this component status has the value 0. For other return values of status, see Section 2.4.

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2.3 Reverse communication

A positive value of `inform%status` on exit from `LSRT_solve` indicates that the user needs to take appropriate action before re-entering the subroutine. Possible values are:

2. The user must perform the operation

$$\mathbf{u} := \mathbf{u} + \mathbf{A}\mathbf{v},$$

and recall `LSRT_solve`. The vectors \mathbf{u} and \mathbf{v} are available in the arrays `U` and `V` respectively, and the result \mathbf{u} must overwrite the content of `U`. No argument except `U` should be altered before recalling `LSRT_solve`.

3. The user must perform the operation

$$\mathbf{v} := \mathbf{v} + \mathbf{A}^T\mathbf{u},$$

and recall `LSRT_solve`. The vectors \mathbf{u} and \mathbf{v} are available in the arrays `U` and `V` respectively, and the result \mathbf{v} must overwrite the content of `V`. No argument except `V` should be altered before recalling `LSRT_solve`.

4. The user should reset `U` to \mathbf{b} and recall `LSRT_solve`. No argument except `U` should be altered before recalling `LSRT_solve`.

2.4 Warning and error messages

A negative value of `inform%status` on exit from `LSRT_solve` or `LSRT_terminate` indicates that an error has occurred. No further calls should be made until the error has been corrected. Possible values are:

- 1. An allocation error occurred. A message indicating the offending array is written on unit `control%error`, and the returned allocation status and a string containing the name of the offending array are held in `inform%alloc_status` and `inform%bad_alloc` respectively.
- 2. A deallocation error occurred. A message indicating the offending array is written on unit `control%error` and the returned allocation status and a string containing the name of the offending array are held in `inform%alloc_status` and `inform%bad_alloc` respectively.
- 3. (`LSRT_solve` only) At least one of the restrictions $m > 0$, $n > 0$, $\sigma > 0$ or $p \geq 2$ has been violated.
- 18. (`LSRT_solve` only) More than `control%imax` iterations have been performed without obtaining convergence.
- 25. (`LSRT_solve` only) `inform%status` is not > 0 on entry.

2.5 Weighted least-squares, scaled regularisation and preconditioning

The package may also be used to solve a weighted regularisation least-squares problem

$$\min \frac{1}{2} \|\mathbf{W}(\mathbf{Ax} - \mathbf{b})\|_2^2 + \frac{1}{p} \sigma \|\mathbf{Sx}\|_2^p$$

simply by solving instead the problem

$$\min \frac{1}{2} \|\bar{\mathbf{A}}\bar{\mathbf{x}} - \bar{\mathbf{b}}\|_2^2 + \frac{1}{p} \sigma \|\bar{\mathbf{x}}\|_2^p$$

where $\bar{\mathbf{A}} = \mathbf{WAS}^{-1}$ and $\bar{\mathbf{b}} = \mathbf{Wb}$ and then recovering $\mathbf{x} = \mathbf{S}^{-1}\bar{\mathbf{x}}$. Note the implication here that \mathbf{S} must be non-singular.

Thus on initial entry (`inform%status = 1`) and re-entry (`inform%status = 4`), `U` should contain \mathbf{Wb} , while for `inform%status = 2` and `3` entries, the operations

$$\mathbf{u} := \mathbf{u} + \mathbf{WAS}^{-1}\mathbf{v} \quad \text{and} \quad \mathbf{v} := \mathbf{v} + \mathbf{S}^{-T}\mathbf{A}^T\mathbf{W}^T\mathbf{u}$$

respectively, should be performed.

Note that the choice of \mathbf{W} and \mathbf{S} will affect the convergence of the method, and thus good choices may be used to accelerate its convergence. This is often known as preconditioning, but be aware that preconditioning changes the norms that define the problem. Good preconditioners will cluster the singular values of $\bar{\mathbf{A}}$ around a few distinct values, and ideally (but usually unrealistically) all the singular values will be mapped to 1.

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2.6 Further features

In this section, we describe an alternative means of setting control parameters, that is components of the variable control of type `LSRT_control_type` (see Section 2.1.1), by reading an appropriate data specification file using the subroutine `LSRT_read_specfile`. This facility is useful as it allows a user to change LSRT control parameters without editing and recompiling programs that call LSRT.

A specification file, or specfile, is a data file containing a number of "specification commands". Each command occurs on a separate line, and comprises a "keyword", which is a string (in a close-to-natural language) used to identify a control parameter, and an (optional) "value", which defines the value to be assigned to the given control parameter. All keywords and values are case insensitive, keywords may be preceded by one or more blanks but values must not contain blanks, and each value must be separated from its keyword by at least one blank. Values must not contain more than 30 characters, and each line of the specfile is limited to 80 characters, including the blanks separating keyword and value.

The portion of the specification file used by `LSRT_read_specfile` must start with a "BEGIN LSRT" command and end with an "END" command. The syntax of the specfile is thus defined as follows:

```
( .. lines ignored by LSRT_read_specfile .. )
  BEGIN LSRT
    keyword    value
    .....
    keyword    value
  END
( .. lines ignored by LSRT_read_specfile .. )
```

where keyword and value are two strings separated by (at least) one blank. The "BEGIN LSRT" and "END" delimiter command lines may contain additional (trailing) strings so long as such strings are separated by one or more blanks, so that lines such as

```
BEGIN LSRT SPECIFICATION
```

and

```
END LSRT SPECIFICATION
```

are acceptable. Furthermore, between the "BEGIN LSRT" and "END" delimiters, specification commands may occur in any order. Blank lines and lines whose first non-blank character is ! or * are ignored. The content of a line after a ! or * character is also ignored (as is the ! or * character itself). This provides an easy manner to "comment out" some specification commands, or to comment specific values of certain control parameters.

The value of a control parameters may be of three different types, namely integer, logical or real. Integer and real values may be expressed in any relevant Fortran integer and floating-point formats (respectively). Permitted values for logical parameters are "ON", "TRUE", ".TRUE.", "T", "YES", "Y", or "OFF", "NO", "N", "FALSE", ".FALSE." and "F". Empty values are also allowed for logical control parameters, and are interpreted as "TRUE".

The specification file must be open for input when `LSRT_read_specfile` is called, and the associated device number passed to the routine in `device` (see below). Note that the corresponding file is `REWINDed`, which makes it possible to combine the specifications for more than one program/routine. For the same reason, the file is not closed by `LSRT_read_specfile`.

2.6.1 To read control parameters from a specification file

Control parameters may be read from a file as follows:

```
CALL LSRT_read_specfile( control, device )
```

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`control` is a scalar `INTENT(INOUT)` argument of type `LSRT_control_type` (see Section 2.1.1). Default values should have already been set, perhaps by calling `LSRT_initialize`. On exit, individual components of `control` may have been changed according to the commands found in the specfile. Specfile commands and the component (see Section 2.1.1) of `control` that each affects are given in Table 2.1.

command	component of control	value type
<code>error-printout-device</code>	<code>%error</code>	integer
<code>printout-device</code>	<code>%out</code>	integer
<code>print-level</code>	<code>%print_level</code>	integer
<code>minimum-number-of-iterations</code>	<code>%itmin</code>	integer
<code>maximum-number-of-iterations</code>	<code>%itmax</code>	integer
<code>maximum-number-of-inner-iterations</code>	<code>%bitmax</code>	integer
<code>number-extra-n-vectors-used</code>	<code>%extra_vectors</code>	integer
<code>relative-accuracy-required</code>	<code>%stop_relative</code>	real
<code>absolute-accuracy-required</code>	<code>%stop_absolute</code>	real
<code>fraction-optimality-required</code>	<code>%fraction_opt</code>	real
<code>space-critical</code>	<code>%space_critical</code>	logical
<code>deallocate-error-fatal</code>	<code>%deallocate_error_fatal</code>	logical

Table 2.1: Specfile commands and associated components of `control`.

`device` is a scalar `INTENT(IN)` argument of type `default INTEGER`, that must be set to the unit number on which the specfile has been opened. If `device` is not open, `control` will not be altered and execution will continue, but an error message will be printed on unit `control%error`.

2.7 Information printed

If `control%print_level` is positive, information about the progress of the algorithm will be printed on unit `control%out`. If `control%print_level = 1`, a single line of output will be produced for each iteration of the process. So long as the current estimate lies within the constraint boundary, this will include the iteration number, the norm of the residual $\mathbf{Ax} - \mathbf{b}$, the norm of the gradient, and the norm of \mathbf{x} . A further message will be printed if the constraint boundary is encountered during the current iteration. Thereafter, the one-line summary will also record the value of the Lagrange multiplier $\lambda = \sigma \|\mathbf{x}\|_2^{p-2}$ and the number of Newton steps required to find λ . If `control%print_level` ≥ 2 , this output will be increased to provide significant detail of each iteration. This extra output includes a complete history of the inner iteration required to solve the “bi-diagonal” least-squares subproblem.

3 GENERAL INFORMATION

Use of common: None.

Workspace: Provided automatically by the module.

Other routines called directly: `LSRT_solve` calls the BLAS function `*ROTG`, where `*` is `S` for the default real version and `D` for the double precision version.

Other modules used directly: `LSRT_solve` calls the GALAHAD packages `GALAHAD_SYMBOLS`, `GALAHAD_SPACE`, `GALAHAD_NORMS`, `GALAHAD_ROOTS`, `GALAHAD_LSTR` and `GALAHAD_SPECFILE`.

Input/output: Output is under control of the arguments `control%error`, `control%out` and `control%print_level`.

Restrictions: $m > 0$, $n > 0$, $\sigma > 0$, $p \geq 2$.

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Portability: ISO Fortran 95 + TR 15581 or Fortran 2003. The package is thread-safe.

4 METHOD

The required solution \mathbf{x} necessarily satisfies the optimality condition $\mathbf{A}^T(\mathbf{A}\mathbf{x} - \mathbf{b}) + \lambda\mathbf{x} = \mathbf{0}$, where $\lambda = \sigma\|\mathbf{x}\|_2^{p-2}$.

The method is iterative. Starting with the vector $\mathbf{u}_1 = \mathbf{b}$, a bi-diagonalisation process is used to generate the vectors \mathbf{v}_k and $\mathbf{u}_k + 1$ so that the n by k matrix $\mathbf{V}_k = (\mathbf{v}_1 \dots \mathbf{v}_k)$ and the m by $(k + 1)$ matrix $\mathbf{U}_k = (\mathbf{u}_1 \dots \mathbf{u}_{k+1})$ together satisfy

$$\mathbf{A}\mathbf{V}_k = \mathbf{U}_{k+1}\mathbf{B}_k \text{ and } \mathbf{b} = \|\mathbf{b}\|_2\mathbf{U}_{k+1}\mathbf{e}_1$$

where \mathbf{B}_k is $(k + 1)$ by k and lower bi-diagonal, \mathbf{U}_k and \mathbf{V}_k have orthonormal columns and \mathbf{e}_1 is the first unit vector. The solution sought is of the form $\mathbf{x}_k = \mathbf{V}_k\mathbf{y}_k$, where \mathbf{y}_k solves the bi-diagonal regularised least-squares problem

$$\min \|\mathbf{B}_k\mathbf{y} - \|\mathbf{b}\|\mathbf{e}_1\|_2 + \frac{1}{p}\sigma\|\mathbf{y}\|_2^p. \quad (4.1)$$

To minimize (4.1), the optimality conditions

$$(\mathbf{B}_k^T(\mathbf{B}_k\mathbf{y}(\lambda) - \|\mathbf{b}\|\mathbf{e}_1) + \lambda\mathbf{y}(\lambda) = \mathbf{0}, \quad (4.2)$$

where $\lambda = \sigma\|\mathbf{y}(\lambda)\|_2^{p-2}$, are used as the basis of an iteration. The vector $\mathbf{y}(\lambda)$ is equivalently the solution to the regularised least-squares problem

$$\min \left\| \begin{pmatrix} \mathbf{B}_k \\ \lambda^{\frac{1}{2}}\mathbf{I} \end{pmatrix} \mathbf{y} - \|\mathbf{b}\|\mathbf{e}_1 \right\|_2. \quad (4.3)$$

Thus, given an estimate $\lambda \geq 0$, (4.3) may be efficiently solved to give $\mathbf{y}(\lambda)$. It is then simply a matter of adjusting λ (for example by a Newton-like process) to solve the scalar nonlinear equation

$$\theta(\lambda) \equiv \|\mathbf{y}(\lambda)\|_2^{p-2} - \frac{\lambda}{\sigma} = 0. \quad (4.4)$$

In practice (4.4) is reformulated, and a more rapidly converging iteration is used. Having found \mathbf{y}_k , a second pass in which $\mathbf{x}_k = \mathbf{V}_k\mathbf{y}_k$ is regenerated is needed—this need only be done once \mathbf{x}_k has implicitly deemed to be sufficiently close to optimality. As this second pass is an additional expense, a record is kept of the optimal objective function values for each value of k , and the second pass is only performed so far as to ensure a given fraction of the final optimal objective value. Large savings may be made in the second pass by choosing the required fraction to be significantly smaller than one.

Special code is used in the special case $p = 2$, as in this case a single pass suffices.

References: A complete description of the un- and quadratically-regularised cases is given by

C. C. Paige and M. A. Saunders, LSQR: an algorithm for sparse linear equations and sparse least squares. *ACM Transactions on Mathematical Software*, 8(1):43–71, 1982

and

C. C. Paige and M. A. Saunders, ALGORITHM 583: LSQR: an algorithm for sparse linear equations and sparse least squares. *ACM Transactions on Mathematical Software*, 8(2):195–209, 1982.

Additional details on the Newton-like process needed to determine λ and other details are described in

C. Cartis, N. I. M. Gould and Ph. L. Toint, Trust-region and other regularisation of linear least-squares problems. Technical Report RAL-TR-2008-005, Rutherford Appleton Laboratory, 2008.

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```

END DO
WRITE( 6, "( 1X, I0, ' 1st pass and ', I0, ' 2nd pass iterations' )" ) &
  inform%iter, inform%iter_pass2
WRITE( 6, "( ' objective recurred and calculated = ', 2ES16.8 )" ) &
  inform%obj, 0.5_working * DOT_PRODUCT( RES, RES ) + ( sigma / p ) * &
  ( SQRT( DOT_PRODUCT( X, X ) ) ) ** p
WRITE( 6, "( ' ||x|| recurred and calculated = ', 2ES16.8 )" ) &
  inform%x_norm, SQRT( DOT_PRODUCT( X, X ) )
WRITE( 6, "( ' ||Ax-b|| recurred and calculated = ', 2ES16.8 )" ) &
  inform%r_norm, SQRT( DOT_PRODUCT( RES, RES ) )
CALL LSRT_terminate( data, control, inform ) ! delete internal workspace
EXIT
CASE DEFAULT
      ! Error returns
WRITE( 6, "( ' LSRT_solve exit status = ', I6 )" ) inform%status
CALL LSRT_terminate( data, control, inform ) ! delete internal workspace
EXIT
END SELECT
END DO
END PROGRAM GALAHAD_LSRT_EXAMPLE

```

This produces the following output:

```

59 1st pass and 26 2nd pass iterations
objective recurred and calculated = 2.19903278E+01 2.19903278E+01
||x|| recurred and calculated = 9.04718377E-01 9.04718377E-01
||Ax-b|| recurred and calculated = 6.59446524E+00 6.59446524E+00

```

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