

# FULL STABILITY OF LOCALLY OPTIMAL SOLUTIONS IN SECOND-ORDER CONE PROGRAMMING

BORIS S. MORDUKHOVICH<sup>1</sup>, JIŘÍ V. OUTFATA<sup>2</sup> and M. EBRAHIM SARABI<sup>3</sup>

**Abstract.** The paper presents complete characterizations of Lipschitzian full stability of locally optimal solutions to problems of second-order cone programming (SOCP) expressed entirely in terms of their initial data. These characterizations are obtained via appropriate versions of the quadratic growth and strong second-order sufficient conditions under the corresponding constraint qualifications. We also establish close relationships between full stability of local minimizers for SOCPs and strong regularity of the associated generalized equations at nondegenerate points. Our approach is mainly based on advanced tools of second-order variational analysis and generalized differentiation.

**Key words.** variational analysis, second-order cone programming, full stability of local minimizers, nondegeneracy, strong regularity, quadratic growth, second-order subdifferentials, coderivatives

**AMS subject classifications.** 49J52, 90C30, 90C31

## 1 Introduction

This paper is devoted to the study of full Lipschitzian stability of locally optimal solutions to problems of *second-order cone programming* (SOCP), which are written as follows:

$$(1.1) \quad \text{minimize } \varphi_0(x) \text{ subject to } \Phi(x) := (\Phi^1(x), \dots, \Phi^J(x)) \in \mathcal{Q},$$

where the data  $\varphi_0: \mathbb{R}^n \rightarrow \mathbb{R}$  and  $\Phi^j: \mathbb{R}^n \rightarrow \mathbb{R}^{m_j+1}$ ,  $j = 1, \dots, J$ , are twice continuously differentiable ( $\mathcal{C}^2$ -smooth) around the reference points. The underlying set  $\mathcal{Q}$  is given by

$$(1.2) \quad \mathcal{Q} := \prod_{j=1}^J \mathcal{Q}_{m_j+1} \subset \mathbb{R}^l \quad \text{with } l := \sum_{j=1}^J (m_j + 1)$$

as the  $J$ -product of the *second-order/Lorentz/ice-cream cones*

$$(1.3) \quad \mathcal{Q}_{m_j+1} = \{(s_0, s_r) \in \mathbb{R}^{m_j+1} \mid s_0 \geq \|s_r\|\}, \quad j = 1, \dots, J.$$

It has been well recognized that the SOCP model (1.1) describes various classes of problems important for optimization theory and applications; see [1, 3] and the references therein. Note

---

<sup>1</sup>Department of Mathematics, Wayne State University, Detroit, Michigan 48202, USA (boris@math.wayne.edu). Research of this author was partly supported by the USA National Science Foundation under grant DMS-1007132, by the Australian Research Council under grant DP-12092508, and by the Portuguese Foundation of Science and Technologies under grant MAT/11109.

<sup>2</sup>Institute of Information Theory and Automation, Academy of Sciences of the Czech Republic, 18208 Prague, Czech Republic (outrata@utia.cas.cz) and Centre for Informatics and Applied Optimization, University of Ballarat, P.O. Box 663, Ballarat, VIC 3353, Australia. Research of this author was partly supported by grant P402/12/1309 of the Grant Agency of the Czech Republic and the Australian Research Council under grant DP-110102011.

<sup>3</sup>Department of Mathematics, Wayne State University, Detroit, Michigan 48202, USA (ebrahim.sarabi@math.wayne.edu). Research of this author was partly supported by the USA National Science Foundation under grant DMS-1007132.

that, despite the  $\mathcal{C}^2$ -smoothness of the functions  $\varphi_0$  and  $\Phi$  in (1.1), this model belongs to nonsmooth optimization due to the nondifferentiability of the norm in (1.3) at the origin.

The concept of (Lipschitzian) *full stability* of local solutions to general optimization problems was introduced by Levy, Poliquin and Rockafellar [12] who were largely motivated by the far-going extension of the *tilt stability* notion from Poliquin and Rockafellar [30] and the importance of these stability notions for the justification of numerical algorithms; see [12, 30] and also Section 4 below for more details. In contrast to tilt stability for which significant progress has been achieved, especially during the recent years (see, e.g., [3, 7, 8, 9, 13, 20, 21, 24, 25, 26]), not much has been done for the study of full stability. The pioneering paper [12] contains a second-order subdifferential characterization of full stability in the unconstrained framework of finite-dimensional optimization with extended-real-valued objectives. The next step was done in [27], where the authors obtained (mainly based on the general approach of [12] and the second-order calculus rules established in [26]) several second-order characterizations of full stability for finite-dimensional problems of nonlinear programming (NLP), extended nonlinear programming, and mathematical programs with polyhedral constraints (MPPC) under certain nondegeneracy conditions. Quite recently, Mordukhovich and Nghia [22] have developed a new approach to both Lipschitzian and Hölderian (introduced therein) full stability in finite and infinite dimensions and applied it to deriving constructive characterization of full stability in NLPs, infinite-dimensional problems with polyhedral constraints, and optimal control problems governed by semilinear elliptic equations without any nondegeneracy assumption.

The classes of constrained optimization problems for which full stability has been constructively characterized in [22, 27] entirely in terms of the initial data possess a certain *polyhedral* structure that has been significantly used in the proofs. Such a polyhedrality is not the case for SOCPs, where no results of this type have been known even for tilt stability. Note to this end that related coderivative characterizations of tilt stability for general conic programs has been recently obtained in [25] while not in terms of the initial program data. The major goal of this paper is to establish complete characterizations of full stability for SOCPs (1.1) at nondegenerate local minimizers via the initial data, where no difference arises between Lipschitzian and Hölderian versions. This will be achieved by using second-order generalized differential tools of variational analysis and their constructive realizations in the SOCP framework.

The rest of the paper is organized as follows. Section 2 recalls basic tools of generalized differentiation employed in *deriving* (while not in formulations) of the main characterizations of full stability. Section 3 makes a bridge between general second-order constructions and constraint qualifications developed in the variational approach to full stability from one side, and their effective realizations via the initial data in the SOCP setting from the other. In particular, employing the coderivative calculations for the metric projection onto the Lorentz cone by Outrata and Sun [29] as well as new calculations of the second-order subdifferential of the indicator function for this cone allow us to establish the equivalence between the *second-order constraint qualification* (SOCQ) developed in second-order variational calculus and the *nondegeneracy condition* well recognized in constrained optimization.

Section 4 contains second-order characterizations of full stability of locally optimal solutions to SOCPs. First we discuss characterizations given via the *partial strong metric regularity* of a first-order subgradient mapping and via an SOCP version of the *uniform second-order/quadratic growth* under appropriate qualification conditions. Then we derive our main characterization of full stability of nondegenerate local solutions to SOCPs expressed via the *second-order strong sufficient condition* for SOCPs introduced in the nonparametric setting by Bonnans and Ramírez [2] from different perspectives. The proof of this result is based on the composite optimization approach to full stability with the usage of the aforementioned calculations of the second-order subdifferential together with recent second-order calculus rules developed in [28] and [19].

In Section 5 we establish close relationships between full stability of local minimizers for SOCPs and Robinson's notion of *strong regularity* [31] of the associated KKT systems involving Lagrange multipliers. In fact we show that these two notions are *equivalent* under the *SOCQ/nondegeneracy* condition. The given proof of this result works for general problems of conic programming described by *reducible* cones. As a by-product of the obtained equivalence and the SSOSC characterization of full stability from Section 4, we recover the characterization of strong regularity for SOCPs established by Bonnans and Ramírez [2] in a completely different way. Two illustrative examples are presented here showing, in particular, that full stability is a broader notion for SOCPs in the absence of nondegeneracy. The final Section 6 contains some concluding remarks and formulate several open questions of further research.

Throughout the paper we use standard notation of variational analysis and second-order cone programming; see, e.g., [1, 18, 33]. Everywhere  $\mathbb{R}^n$  stands for the  $n$ -dimensional Euclidean space with the norm  $\|\cdot\|$  and the inner product  $\langle \cdot, \cdot \rangle$ . By  $\mathcal{B}$  we denote the closed unit ball in the space in question and by  $B_r(x) = B(x, r) := x + r\mathcal{B}$  the closed ball centered at  $x$  with radius  $r > 0$ . For a set-valued mapping  $F: \mathbb{R}^n \rightrightarrows \mathbb{R}^m$  the symbol

$$(1.4) \quad \text{Lim sup}_{x \rightarrow \bar{x}} F(x) := \left\{ y \in \mathbb{R}^m \mid \begin{array}{l} \exists x_k \rightarrow \bar{x}, \exists y_k \rightarrow y \text{ as } k \rightarrow \infty \\ \text{with } y_k \in F(x_k) \text{ for all } k \in \mathbb{N} := \{1, 2, \dots\} \end{array} \right\}$$

signifies the *Painlevé-Kuratowski outer limit* of  $F$  as  $x \rightarrow \bar{x}$ . Given  $\Omega \subset \mathbb{R}^n$ , the symbol  $x \xrightarrow{\Omega} \bar{x}$  indicates that  $x \rightarrow \bar{x}$  with  $x \in \Omega$ . For a linear operator/matrix  $A$  the notation  $A^*$  stands for the adjoint operator/matrix transposition; we also use the symbol  $*$  to indicate the duality/polarity correspondence. For a vector column  $x \in \mathbb{R}^n$  the notation  $x^T$  stands for the corresponding vector row. Finally, by  $\text{cone } \Omega$  and  $\text{co } \Omega$  we denote the conic and convex hulls of  $\Omega$ , respectively.

## 2 Tools of Generalized Differentiation

Here we recall and briefly discuss, mostly following the books [18, 33], some basic generalized differential constructions of variational analysis needed in the paper. Unless otherwise stated, all the sets  $\Omega \subset \mathbb{R}^n$  under consideration are locally closed and the extended-real-valued functions  $\varphi: \mathbb{R}^n \rightarrow \overline{\mathbb{R}} := (-\infty, \infty]$  are lower semicontinuous around the reference points. Variational geometry is underlying in what follows, and so we first recall the original definition of the (limiting, Mordukhovich) *normal cone* to  $\Omega$  at  $\bar{x} \in \Omega$  given in [15] by

$$(2.1) \quad N_{\Omega}(\bar{x}) = \text{Lim sup}_{x \rightarrow \bar{x}} \left[ \text{cone}(x - \Pi_{\Omega}(x)) \right]$$

via the *projection operator*  $\Pi_{\Omega}: \mathbb{R}^n \rightrightarrows \mathbb{R}^n$ , which plays in crucial role in this paper. Observe that the normal cone (2.1) is often nonconvex while it can be represented via (1.4) as

$$(2.2) \quad N_{\Omega}(\bar{x}) = \text{Lim sup}_{x \xrightarrow{\Omega} \bar{x}} \widehat{N}_{\Omega}(x) \quad \text{with} \quad \widehat{N}_{\Omega}(x; \Omega) := \left\{ v \in \mathbb{R}^n \mid \limsup_{u \xrightarrow{\Omega} x} \frac{\langle v, u - x \rangle}{\|u - x\|} \leq 0 \right\},$$

where the convex cone  $\widehat{N}_{\Omega}(x)$  in (2.2) is known as the collection of Fréchet or *regular normals* to  $\Omega$  at  $x \in \Omega$ . There is the *duality/polarity* correspondence

$$(2.3) \quad \widehat{N}_{\Omega}(x) = T_{\Omega}(x)^* := \left\{ v \in \mathbb{R}^n \mid \langle v, w \rangle \leq 0 \text{ for all } w \in T_{\Omega}(x) \right\}$$

between  $\widehat{N}_{\Omega}(x)$  in (2.2) and the (Bouligand-Severi) *tangent cone* to  $\Omega$  at  $x$  defined by

$$(2.4) \quad T_{\Omega}(x) := \left\{ w \in \mathbb{R}^n \mid \exists x_k \xrightarrow{\Omega} x, \alpha_k \geq 0 \text{ with } \alpha_k(x_k - x) \rightarrow w \text{ as } k \rightarrow \infty \right\}.$$

Note that for convex sets  $\Omega$  the normal and tangent cone constructions in (2.1), (2.2), and (2.4) reduce to the corresponding constructions of convex analysis.

Given an extended-real-valued function  $\varphi: \mathbb{R}^n \rightarrow \overline{\mathbb{R}}$  finite at  $\bar{x}$ , the only (first-order) *subdifferential* of  $\varphi$  at  $\bar{x}$  we use in this paper is the one introduced in [15] by

$$(2.5) \quad \partial\varphi(\bar{x}) := \left\{ v \in \mathbb{R}^n \mid (v, -1) \in N_{\text{epi } \varphi}(\bar{x}, \varphi(\bar{x})) \right\}$$

via the normal cone (2.1) to the epigraph  $\text{epi } \varphi := \{(x, \alpha) \in \mathbb{R}^{n+1} \mid \alpha \geq \varphi(x)\}$ . There are various analytic descriptions of the subdifferential (2.5), which are not used in what follows; see [18, 33]. It is easy to observe the normal cone representation

$$(2.6) \quad N_{\Omega}(\bar{x}) = \partial\delta_{\Omega}(\bar{x}), \quad \bar{x} \in \Omega,$$

via the subdifferential of the set indicator function  $\delta_{\Omega}(x)$  equal to 0 for  $x \in \Omega$  and  $\infty$  otherwise. Note that, in spite of (or perhaps due to) the nonconvexity of the normal and subgradient sets (2.1) and (2.5), these constructions along with the associated coderivative of mappings enjoy comprehensive *calculus rules* based on *variational/extremal principles* of variational analysis.

Considering further a set-valued mapping  $F: \mathbb{R}^n \rightrightarrows \mathbb{R}^m$  with

$$\text{dom } F := \left\{ x \in \mathbb{R}^n \mid F(x) \neq \emptyset \right\} \quad \text{and} \quad \text{gph } F := \left\{ (x, y) \in \mathbb{R}^n \times \mathbb{R}^m \mid y \in F(x) \right\},$$

define its *coderivative* [16] at  $(\bar{x}, \bar{y}) \in \text{gph } F$  by

$$(2.7) \quad D^*F(\bar{x}, \bar{y})(v) := \left\{ u \in \mathbb{R}^n \mid (u, -v) \in N_{\text{gph } F}(\bar{x}, \bar{y}) \right\}, \quad v \in \mathbb{R}^m$$

via the normal cone (2.2) to the graph  $\text{gph } F := \{(x, y) \in \mathbb{R}^n \times \mathbb{R}^m \mid y \in F(x)\}$ . The set-valued mapping  $D^*F(\bar{x}, \bar{y}): \mathbb{R}^m \rightrightarrows \mathbb{R}^n$  is generally positive-homogeneous, while in the case of smooth single-valued mapping  $F: \mathbb{R}^n \rightarrow \mathbb{R}^m$  (when we omit  $\bar{y} = F(\bar{x})$  in the coderivative notation) it reduces to the *adjoint* derivative operator

$$D^*F(\bar{x})(v) = \{\nabla F(\bar{x})^*v\}, \quad v \in \mathbb{R}^m.$$

Coming back to extended-real-valued functions  $\varphi: \mathbb{R}^n \rightarrow \overline{\mathbb{R}}$  and following [17], define the *second-order subdifferential* (or generalized Hessian) of  $\varphi$  at  $\bar{x}$  relative to  $\bar{y} \in \partial\varphi(\bar{x})$  by

$$(2.8) \quad \partial^2\varphi(\bar{x}, \bar{y})(u) := (D^*\partial\varphi)(\bar{x}, \bar{y})(u), \quad u \in \mathbb{R}^n,$$

as the coderivative (2.7) of the first-order subdifferential mapping  $\partial\varphi$ . Observe that for  $\varphi \in \mathcal{C}^2$  with the (symmetric) Hessian matrix  $\nabla^2\varphi(\bar{x})$  we have

$$\partial^2\varphi(\bar{x})(u) = \{\nabla^2\varphi(\bar{x})u\} \quad \text{for all } u \in \mathbb{R}^n.$$

The second-order subdifferential construction (2.8) and its partial modification considered in Section 4 play a crucial role in deriving the main results of this paper.

### 3 Basic Calculations and Relationships for SOCPs

The main goal of this section is to establish the equivalence *in the case of SOCPs* between two major *qualification conditions* introduced and developed from completely different viewpoints in general frameworks of variational analysis and optimization. The first condition appeared in [11] and then was used under some modifications in [23, 26] for deriving second-order chain rules of generalized differentiation. It has been recently applied in [26, 27] to characterize tilt and full stability in particular classes of optimization problems with a polyhedral structure and in [4] to derive necessary conditions in problems of optimal control of the sweeping process.

**Definition 3.1 (second-order constraint qualification for SOCPs).** Let  $\bar{x}$  be a feasible solution to (1.1) with  $\mathcal{Q}$  given by (1.2), and  $\bar{z} := \Phi(\bar{x}) \in \mathcal{Q}$ . We say the SECOND-ORDER CONSTRAINT QUALIFICATION (SOCQ) holds at  $\bar{x}$  if

$$(3.1) \quad \partial^2 \delta_{\mathcal{Q}}(\bar{z}, \bar{y})(0) \cap \ker \nabla \Phi(\bar{x})^* = \{0\},$$

where  $\bar{y} \in N_{\mathcal{Q}}(\bar{z})$ , and where  $\ker A$  stands for the kernel of the linear continuous operator  $A$ .

Note that SOCQ (3.1) is automatic when the Jacobian matrix  $\nabla \Phi(\bar{x})$  has full rank, which is not required here. It is shown in [27] that in the case of MPPCs the SOCQ condition is equivalent to the *polyhedral constraint qualification* (PCQ) introduced therein while for NLPs it reduces to the classical *linear independence constraint qualification* (LICQ), which amounts to the full rank of  $\nabla \Phi(\bar{x})$  and is essentially stronger than the PCQ condition for MPPCs.

Next we formulate the *nondegeneracy condition* taken from Bonnans and Shapiro [3, Section 4.6] in the case of general conic programming that closely relates to the original one introduced by Robinson [32] under polyhedrality.

**Definition 3.2 (nondegeneracy condition for SOCPs).** Let  $\bar{x}$  be a feasible solution to (1.1). We say that  $\bar{x}$  is a NONDEGENERATE POINT of  $\Phi$  with respect to  $\mathcal{Q}$  if

$$(3.2) \quad \nabla \Phi(\bar{x}) \mathbb{R}^n + \text{lin}\{T_{\mathcal{Q}}(\bar{z})\} = \prod_{j=1}^J \mathbb{R}^{m_j+1},$$

where  $T_{\mathcal{Q}}(\bar{z})$  is the tangent cone (2.4) to  $\mathcal{Q}$  at  $\bar{z} = \Phi(\bar{x})$ , and where  $\text{lin}\{T_{\mathcal{Q}}(\bar{z})\}$  stands the largest linear subspace contained in  $T_{\mathcal{Q}}(\bar{z})$ .

Taking the orthogonal complements on the both sides of (3.2) allows us to rewrite (3.2) as

$$(3.3) \quad \text{lin}\{T_{\mathcal{Q}}(\bar{z})\}^{\perp} \cap \ker \nabla \Phi(\bar{x})^* = 0.$$

Furthermore, since  $\mathcal{Q}$  is a closed and convex set, the result of [3, Proposition 4.37] and the duality correspondence (2.3) applied to (3.3) tell us that  $\text{lin}\{T_{\mathcal{Q}}(\bar{z})\}^{\perp} = \text{span}\{N_{\mathcal{Q}}(\bar{z})\}$ , and so the nondegeneracy condition (3.2) is equivalent to

$$(3.4) \quad \text{span}\{N_{\mathcal{Q}}(\bar{z})\} \cap \ker \nabla \Phi(\bar{x})^* = 0.$$

It follows from (3.1) and (3.4) that to show the equivalence between the second-order constraint qualification condition and the nondegeneracy condition for SOCPs we need to calculate the second-order subdifferential of the indicator function in (3.1) and relate it to the span of the normal cone to  $\Omega$  in (3.4). This will be done in what follows by a series of assertions all of which is of their own independent interest.

To proceed, let us first recall some notions and properties from *Jordan algebra* in connection with the second-order cone  $\mathcal{Q}_{m+1}$ ; see [10]. Given any  $u = (u_0, u_r)$  and  $v = (v_0, v_r)$  in  $\mathbb{R}^{m+1}$  with  $u_0, v_0 \in \mathbb{R}$  and  $u_r, v_r \in \mathbb{R}^m$  the *Jordan product* for  $\mathcal{Q}_{m+1}$  is defined by

$$u \circ v := \left( \sum_{i=0}^m u_i v_i, u_0 v_r + v_0 u_r \right) = (\langle v, u \rangle, u_0 v_r + v_0 u_r).$$

It is well known that for any  $u, v \in \mathcal{Q}_{m+1}$  we have  $u \circ v = 0$  if and only if  $\langle v, u \rangle = 0$ , which is also equivalent to the following conditions:

$$(3.5) \quad \begin{cases} \text{either } v = 0 \text{ or } u = 0, \\ \text{or there exists } \alpha \text{ such that } v_0 = \alpha u_0 \text{ and } v_r = -\alpha u_r. \end{cases}$$

Therefore for any  $u, v \in \mathcal{Q}_{m+1}$  it follows from  $\langle v, u \rangle = 0$  and  $u, v \neq 0$  that

$$(3.6) \quad v = (v_0, v_r) = t(u_0, -u_r),$$

where  $t := v_0/u_0$ . Given  $u \in \mathbb{R}^{m+1}$ , its *spectral decomposition* associated with  $\mathcal{Q}_{m+1}$  is

$$(3.7) \quad u = \lambda_1(u)c_1(u) + \lambda_2(u)c_2(u),$$

where  $\lambda_1(u)$  and  $\lambda_2(u)$  are the *spectral values* defined by

$$(3.8) \quad \lambda_i(u) := u_0 + (-1)^i \|u_r\| \quad \text{for } i = 1, 2,$$

and where  $c_1(u)$  and  $c_2(u)$  are the *spectral vectors* of  $u$  given by

$$(3.9) \quad c_i(u) := \begin{cases} \frac{1}{2} \left( 1, (-1)^i \frac{u_r}{\|u_r\|} \right) & \text{if } u_r \neq 0, \\ \frac{1}{2} \left( 1, (-1)^i v_r \right) & \text{if } u_r = 0, \quad i = 1, 2, \end{cases}$$

where  $v_r$  is a unit vector in  $\mathbb{R}^m$ . The decomposition in (3.8) is unique provided that  $u_r \neq 0$ .

Consider now the (single-valued) *metric projection* operator  $\Pi_{\mathcal{Q}_{m+1}}: \mathbb{R}^{m+1} \rightarrow \mathbb{R}^{m+1}$  onto the convex cone  $\mathcal{Q}_{m+1}$ . We know that  $\Pi_{\mathcal{Q}_{m+1}}$  is continuously differentiable at any point  $z \in \mathbb{R}^{m+1}$  with  $\det(z) := z_0^2 - \|z_r\|^2 \neq 0$  and

$$(3.10) \quad \nabla \Pi_{\mathcal{Q}_{m+1}}(z) = \begin{cases} 0 & \text{if } z_0 < -\|z_r\|, \\ I_{m+1} & \text{if } z_0 > \|z_r\|, \\ \frac{1}{2} \begin{pmatrix} 1 & w_r^T \\ w_r & H \end{pmatrix} & \text{if } -\|z_r\| < z_0 < \|z_r\|, \end{cases}$$

where  $w_r := \frac{z_r}{\|z_r\|}$  and  $H := (1 + \frac{z_0}{\|z_r\|})I_m - \frac{z_0}{\|z_r\|}w_r w_r^T$ . The following major result taken from Outrata and Sun [29, Theorem 3.4] gives us an explicit calculation of the coderivative (2.7) of the projection operator  $\Pi_{\mathcal{Q}_{m+1}}$  onto the Lorentz cone (1.3).

**Lemma 3.3 (coderivative of the metric projection onto the Lorentz cone).** *For an arbitrary vector  $z \in \mathbb{R}^{m+1}$  consider its the spectral decomposition (3.7) and take any  $u \in \mathbb{R}^{m+1}$ . Then the coderivative of the projection operator  $\Pi_{\mathcal{Q}_{m+1}}$  is calculated as follows:*

(i) *If  $\det(z) \neq 0$ , then  $D^* \Pi_{\mathcal{Q}_{m+1}}(z)(u) = \nabla \Pi_{\mathcal{Q}_{m+1}}(z)u$ .*

(ii) *If  $\det(z) = 0$  but  $\lambda_2(z) \neq 0$ , i.e.,  $z \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$ , then*

$$(3.11) \quad D^* \Pi_{\mathcal{Q}_{m+1}}(z)(u) = \begin{cases} \text{co } \{u, A(z)u\} & \text{if } \langle q, c_1(z) \rangle \geq 0, \\ \{u, A(z)u\} & \text{otherwise,} \end{cases}$$

where the matrix  $A(z)$  is defined by  $A(z) := I_{m+1} + \frac{1}{2} \begin{pmatrix} -1 & \frac{z_r^T}{\|z_r\|} \\ \frac{z_r}{\|z_r\|} & -\frac{z_r z_r^T}{\|z_r\|^2} \end{pmatrix}$ .

(iii) *If  $\det(z) = 0$  but  $\lambda_1(z) \neq 0$ , i.e.,  $z \in \text{bd } (-\mathcal{Q}_{m+1}) \setminus \{0\}$ , then*

$$(3.12) \quad D^* \Pi_{\mathcal{Q}_{m+1}}(z)(u) = \begin{cases} \text{co } \{0, B(z)u\} & \text{if } \langle u, c_1(z) \rangle \geq 0, \\ \{0, B(z)u\} & \text{otherwise,} \end{cases}$$

where the matrix  $B(z)$  is defined by  $B(z) := \frac{1}{2} \begin{pmatrix} 1 & \frac{z_r^T}{\|z_r\|} \\ \frac{z_r}{\|z_r\|} & \frac{z_r z_r^T}{\|z_r\|^2} \end{pmatrix}$ .

(iv) If  $z = 0$ , then we have

$$(3.13) \quad \begin{aligned} D^*\Pi_{\mathcal{Q}_{m+1}}(0)(u) &= \mathcal{D}u \cup \left( \mathcal{Q}_{m+1} \cap (u - \mathcal{Q}_{m+1}) \right) \\ &\cup \bigcup_{A \in \mathcal{A}} \text{co} \{u, Au\} \cup \bigcup_{B \in \mathcal{B}} \text{co} \{0, Bu\}, \end{aligned}$$

where the sets  $\mathcal{D}$ ,  $\mathcal{A}$ , and  $\mathcal{B}$  are defined, respectively, by

$$\begin{aligned} \mathcal{D} &:= \left\{ 0, I_{m+1} \right\} \cup \left\{ \frac{1}{2} \begin{pmatrix} 1 & w^T \\ w & 2\alpha I_m + (1 - 2\alpha)ww^T \end{pmatrix} \mid w \in \mathbb{R}^m, \|w\| = 1, \alpha \in [0, 1] \right\}, \\ \mathcal{A} &:= \left\{ I_{m+1} + \frac{1}{2} \begin{pmatrix} -1 & w^T \\ w & -ww^T \end{pmatrix} \mid w \in \mathbb{R}^m, \|w\| = 1, q_0 - \langle q_r, w \rangle \geq 0 \right\}, \\ \mathcal{B} &:= \left\{ \frac{1}{2} \begin{pmatrix} 1 & w^T \\ w & ww^T \end{pmatrix} \mid w \in \mathbb{R}^m, \|w\| = 1, q_0 + \langle q_r, w \rangle \geq 0 \right\}. \end{aligned}$$

The next lemma presents two coderivative properties for the projection operator onto the Lorentz cone that are important for deriving the full stability characterizations in Section 4.

**Lemma 3.4 (coderivative properties for the metric projection).** *Let  $\mathcal{C}$  be a convex subset of  $\mathbb{R}^n$ . Then for any  $z \in \mathcal{C}$ ,  $u \in \mathbb{R}^n$ , and  $q \in D^*\Pi_{\mathcal{C}}(z)(u)$  the following properties hold:*

- (i)  $\langle q, u \rangle \geq 0$  and
- (ii)  $\langle q, u - q \rangle \geq 0$ .

**Proof.** Fix  $q \in D^*\Pi_{\mathcal{C}}(z)(u)$  and recall the well-known relationship

$$\text{co} D^*\Pi_{\mathcal{C}}(z)(u) = \left\{ A^*u \mid A \in \mathcal{J}\Pi_{\mathcal{C}}(z) \right\}$$

between the coderivative and (Clarke's) *generalized Jacobian* of any single-valued locally Lipschitzian mapping; see, e.g., [16, 33]. Thus we find  $A \in \mathcal{J}\Pi_{\mathcal{C}}(z)$  with  $q = A^*u$ . It follows from [14, Proposition 1(i)] that  $A^* = A$ , and so we have  $q = Au$ . Employing finally the assertions from [14, Proposition 1(ii), (iii)] that ensure properties (i) and (ii) of this lemma for the generalized Jacobian of  $\Pi_{\mathcal{C}}$  completes the proof of the claimed coderivative properties.  $\triangle$

The next step is to calculate the normal cone  $N_{\mathcal{Q}_{m+1}}(z)$  at  $z \in \mathcal{Q}_{m+1}$ , which is the crucial ingredient of the nondegeneracy condition (3.4). We have the following result.

**Lemma 3.5 (calculating normals to the Lorentz cone).** *For any  $z := (z_0, z_r) \in \mathcal{Q}_{m+1}$  the normal cone to  $\mathcal{Q}_{m+1}$  at  $z$  is calculated by*

$$(3.14) \quad N_{\mathcal{Q}_{m+1}}(z) = \begin{cases} -\mathcal{Q}_{m+1} & \text{if } z = 0, \\ \{0\} & \text{if } z \in \text{int } \mathcal{Q}_{m+1}, \\ \left\{ (-tz_0, tz_r) \mid t \geq 0 \right\} & \text{if } z \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}. \end{cases}$$

**Proof.** It follows from the calculation of the tangent cone to  $\mathcal{Q}_{m+1}$  given in [2, Lemma 25] and the duality between the normal and tangent cones under consideration.  $\triangle$

In the sequel we often use the *self-dual property*  $\mathcal{Q}_{m+1} = -\mathcal{Q}_{m+1}^*$  of the Lorentz cone  $\mathcal{Q}_{m+1}$ , which implies the equivalence

$$(3.15) \quad q \in N_{\mathcal{Q}_{m+1}}(z) \iff \begin{cases} -q \in \mathcal{Q}_{m+1}, \\ \langle q, z \rangle = 0 \\ z \in \mathcal{Q}_{m+1}. \end{cases}$$

Furthermore, Lemma 3.5 immediately implies the span representation

$$(3.16) \quad \text{span} \{N_{\mathcal{Q}_{m+1}}(z)\} = \begin{cases} \text{span} \{-\mathcal{Q}_{m+1}\} = \mathbb{R}^{m+1} & \text{if } z = 0, \\ \{0\} & \text{if } z \in \text{int } \mathcal{Q}_{m+1}, \\ \{(-tz_0, tz_r) \mid t \in \mathbb{R}\} & \text{if } z \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}, \end{cases}$$

It is easy to extend Lemma 3.5 to the product cone  $\mathcal{Q} = \prod_{j=1}^J \mathcal{Q}_{m_j+1}$  by the well-known product formula for the normal cone:

$$(3.17) \quad N_{\mathcal{Q}}(z) = \prod_{j=1}^J N_{\mathcal{Q}_{m_j+1}}(z_j),$$

where  $z := (z_1, \dots, z_J) \in \mathcal{Q}$ . We can also observe that

$$\text{span} \left\{ \prod_{j=1}^J A_j \right\} = \prod_{j=1}^J \text{span} \{A_j\}$$

provided that the sets  $A_j$ ,  $j = 1, \dots, J$ , are cones. Thus plugging  $A_j = N_{\mathcal{Q}_{m_j+1}}(z_j)$  into this formula gives us the representation

$$(3.18) \quad \text{span} \{N_{\mathcal{Q}}(z)\} = \prod_{j=1}^J \text{span} \{N_{\mathcal{Q}_{m_j+1}}(z_j)\},$$

To proceed further, consider first the case of  $\mathcal{Q} = \mathcal{Q}_{m+1}$  in (1.1) when (3.1) reduces to

$$(3.19) \quad \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, \bar{y})(0) \cap \ker \nabla \Phi(\bar{x})^* = \{0\}, \quad \bar{y} \in N_{\mathcal{Q}_{m+1}}(\bar{z}).$$

It follows from [28, Lemma 19] that

$$(3.20) \quad q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, \bar{y})(p) \iff -p \in D^* \Pi_{\mathcal{Q}_{m+1}}(\bar{z} + \bar{y}, \bar{z})(-q - p)$$

when  $\bar{z} \in \mathcal{Q}_{m+1}$  and  $\bar{y} \in N_{\mathcal{Q}_{m+1}}(\bar{z})$ . Employing now the lemmas above and relationship (3.20) allow us to calculate the second-order subdifferential  $\delta_{\mathcal{Q}_{m+1}}$  at the origin  $p = 0$ , which leads consequently to establishing the equivalence between the SOCQ and nondegeneracy conditions.

**Theorem 3.6 (calculating the second-order subdifferential for the indicator function of the Lorentz cone).** *Let  $z := (z_0, z_r) \in \mathcal{Q}_{m+1}$ , and let  $-y \in N_{\mathcal{Q}_{m+1}}(z)$ . Then we have*

$$(3.21) \quad \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, -y)(0) = \text{span} \{N_{\mathcal{Q}_{m+1}}(z)\}.$$

**Proof.** It follows from the property (3.15) that that inclusion  $-y \in N_{\mathcal{Q}_{m+1}}(z)$  yields

$$(3.22) \quad y \in \mathcal{Q}_{m+1} \quad \text{and} \quad \langle z, y \rangle = 0.$$

We split the proof of (3.21) into the following six cases according to the position of  $z, y \in \mathcal{Q}_{m+1}$ .

**Case 1:**  $z = 0, y \in \text{int } \mathcal{Q}_{m+1}$ . Take  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, -y)(0)$ , which by (3.20) amounts to  $0 \in D^* \Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q)$ . Invoking Lemma 3.3(i) together with (3.10), we have

$$D^* \Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q) = \nabla \Pi_{\mathcal{Q}_{m+1}}(-y)(-q) = 0(-q) = 0$$



due to  $-y_0 < -\|y_r\|$ . This tells us that  $\partial^2\delta_{\mathcal{Q}_{m+1}}(0, -y)(0) = \mathbb{R}^{m+1}$ . Employing now Lemma 3.5 concludes the proof of (3.21) in this case.

**Case 2:**  $z \in \text{int } \mathcal{Q}_{m+1}$ . This gives us  $y = 0$ . Take  $q \in \partial^2\delta_{\mathcal{Q}_{m+1}}(z, 0)(0)$ , which by (3.20) is equivalent to  $0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(z, z)(-q)$ . Since  $z \in \text{int } \mathcal{Q}_{m+1}$ , it says that  $z_0 > \|z_r\|$ , and thus by Lemma 3.3(i) together with (3.10) we get

$$0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(z, z)(-q) = \nabla\Pi_{\mathcal{Q}_{m+1}}(z)(-q) = I_{m+1}(-q) = -q \iff q = 0.$$

This shows that  $\partial^2\delta_{\mathcal{Q}_{m+1}}(z, 0)(0) = \{0\}$ . Observing now that  $\text{span}\{N_{\mathcal{Q}_{m+1}}(z)\} = \{0\}$  due to  $z \in \text{int } \mathcal{Q}_{m+1}$  completes the proof of (3.21) in this case.

**Case 3:**  $z, y \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$ . Denote  $c := z - y$  and then deduce from (3.6) and (3.22) that

$$(3.23) \quad c = (c_0, c_r) = (z_0 - y_0, z_r - y_r) = \left(z_0 - y_0, -\frac{z_0 + y_0}{y_0}y_r\right) = \left(z_0 - y_0, \frac{z_0 + y_0}{z_0}z_r\right),$$

which gives us therefore that

$$(3.24) \quad \|c_r\| = \left|\frac{z_0 + y_0}{y_0}\right| \cdot \|y_r\| = |z_0 + y_0| = z_0 + y_0.$$

Pick  $q \in \partial^2\delta_{\mathcal{Q}_{m+1}}(z, -y)(0)$  and write down by (3.20) that

$$(3.25) \quad 0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(z - y, z)(-q),$$

Taking into account that  $-\|c_r\| < c_0 < \|c_r\|$  and employing Lemma 3.3(i), we arrive at

$$D^*\Pi_{\mathcal{Q}_{m+1}}(z - y, z)(-q) = \frac{1}{2} \begin{pmatrix} 1 & \frac{c_r^T}{\|c_r\|} \\ \frac{c_r}{\|c_r\|} & H \end{pmatrix} \begin{pmatrix} -q_0 \\ -q_r \end{pmatrix} \quad \text{with } H := \left(1 + \frac{c_0}{\|c_r\|}\right)I_m - \frac{c_0}{\|c_r\|} \frac{c_r c_r^T}{\|c_r\|^2}.$$

This allows us to restate condition (3.25) in the form

$$\begin{pmatrix} 1 & \frac{c_r^T}{\|c_r\|} \\ \frac{c_r}{\|c_r\|} & H \end{pmatrix} \begin{pmatrix} -q_0 \\ -q_r \end{pmatrix} = 0$$

with  $q = (q_0, q_r)$ , which can be equivalently rewritten as

$$(3.26) \quad \begin{cases} q_0 + \frac{1}{\|c_r\|} \langle c_r, q_r \rangle = 0, \\ \frac{q_0}{\|c_r\|} c_r + \frac{2z_0}{z_0 + y_0} q_r - \frac{z_0 - y_0}{z_0 + y_0} \frac{c_r}{\|c_r\|^2} \langle c_r, q_r \rangle = 0. \end{cases}$$

Involving the last equality in (3.23), the first equation in (3.26) can be reformulated as

$$q_0 + \left\langle \frac{z_r}{z_0}, q_r \right\rangle = 0,$$

which, by taking into account that  $z_0 \neq 0$ , shows that

$$(3.27) \quad \langle q, z \rangle = q_0 z_0 + \langle z_r, q_r \rangle = 0.$$

Furthermore, it follows that  $\langle c_r, q_r \rangle = -q_0 \|c_r\|$  due to the first equation in (3.26), and thus

$$(3.28) \quad \begin{aligned} 0 &= \frac{q_0}{\|c_r\|} c_r + \frac{2z_0}{z_0 + y_0} q_r - \frac{z_0 - y_0}{z_0 + y_0} \frac{c_r}{\|c_r\|^2} \langle c_r, q_r \rangle \\ &= \frac{q_0}{\|c_r\|} c_r + \frac{2z_0}{z_0 + y_0} q_r - \frac{z_0 - y_0}{z_0 + y_0} \frac{c_r}{\|c_r\|^2} (-q_0 \|c_r\|) \\ &= \frac{2z_0}{z_0 + y_0} q_r + \frac{q_0}{\|c_r\|} \frac{2z_0}{z_0 + y_0} c_r, \end{aligned}$$

which yields  $\|c_r\|q_r = -q_0c_r$  and so  $\|q_r\| = \frac{|q_0|}{\|c_r\|}\|c_r\| = |q_0|$ . This tells us that either  $q \in \mathcal{Q}_{m+1}$  or  $-q \in \mathcal{Q}_{m+1}$ . Using it together with (3.27) and (3.15), observe that  $q = (-tz_0, tz_r)$  for some  $t \in \mathbb{R}$ , which verifies the inclusion  $\partial^2\delta_{\mathcal{Q}_{m+1}}(z, -y)(0) \subset \text{span}\{N_{\mathcal{Q}_{m+1}}(z)\}$  by Lemma 3.5.

To justify the converse inclusion in this case, take  $q := (-tz_0, tz_r) \in \text{span}\{N_{\mathcal{Q}_{m+1}}(z)\}$  for some  $t \in \mathbb{R}$ . It suffices to show that the relationships in (3.26) hold for the chosen vector  $q$ , which is surely equivalent to  $q \in \partial^2\delta_{\mathcal{Q}_{m+1}}(z, -y)(0)$ . Indeed, by  $z_0 = \|z_r\|$  we have

$$-tz_0 + \frac{1}{\|c_r\|}\langle c_r, tz_r \rangle = t\left(-z_0 + \frac{\|z_r\|^2}{z_0}\right) = 0$$

implying the first equation in (3.26). The other one therein means that, by the calculation in (3.28) with  $q = (-tz_0, tz_r)$  and  $c_r = \frac{z_0+y_0}{z_0}z_r$ , that

$$\frac{2z_0}{z_0+y_0}q_r + \frac{q_0}{\|c_r\|}\frac{2z_0}{z_0+y_0}c_r = 0,$$

which is definitely true and thus verifies (3.21) in this case.

**Case 4:**  $z = 0, y \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$ . As showed in (3.16), we have  $\text{span}\{N_{\mathcal{Q}_{m+1}}(z)\} = \mathbb{R}^{m+1}$ . take  $q \in \partial^2\delta_{\mathcal{Q}_{m+1}}(0, -y)(0)$ , which means by (3.20) that  $0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q)$ . Since  $-y \in \text{bd}(-\mathcal{Q}_{m+1}) \setminus \{0\}$ , it follows from Lemma 3.3(iii) that  $0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q)$  for all  $q \in \mathbb{R}^{m+1}$ . This verifies that  $\partial^2\delta_{\mathcal{Q}_{m+1}}(0, -y)(0) = \mathbb{R}^{m+1}$  and thus justifies (3.21) in this case.

**Case 5:**  $z \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}, y = 0$ . By (3.16) we have that

$$\text{span}\{N_{\mathcal{Q}_{m+1}}(z)\} = \left\{(-tz_0, tz_r) \mid t \in \mathbb{R}\right\}.$$

Take  $q := (q_0, q_r) \in \partial^2\delta_{\mathcal{Q}_{m+1}}(z, 0)(0)$ , which is equivalent by (3.21) to  $0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(z, z)(-q)$ . Employing Lemma 3.3(ii) with  $z \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$  tells us that the latter inclusion amounts to

$$(3.29) \quad G_s q = 0 \text{ for } G_s := (1-s)I_{m+1} + sA(z), s \in [0, 1],$$

where  $A(z)$  is defined in Lemma 3.3(ii). We claim that the solution set  $\Lambda(s)$  to (3.29) is

$$(3.30) \quad \Lambda(s) = \begin{cases} \{0\} & \text{if } s \in [0, 1), \\ \text{span}\{N_{\mathcal{Q}_{m+1}}(z)\} & \text{if } s = 1. \end{cases}$$

To verify (3.30), observe that for  $s = 0$  equation (3.29) reduces to  $I_{m+1}q = 0$ , which clearly has only the trivial solution  $q = 0$ . For  $s = 1$  equation (3.29) is equivalent to

$$A(z)q = q + \frac{1}{2} \begin{pmatrix} -1 & \frac{z_r^T}{\|z_r\|} \\ \frac{z_r}{\|z_r\|} & -\frac{z_r z_r^T}{\|z_r\|^2} \end{pmatrix} \begin{pmatrix} q_0 \\ q_r \end{pmatrix} = 0,$$

which reduces by  $\|z_r\| = z_0$  to the system of equations

$$(3.31) \quad \begin{cases} q_0 + \frac{1}{z_0}\langle z_r, q_r \rangle = 0, \\ q_r + \frac{q_0}{2z_0}z_r - \frac{\langle z_r, q_r \rangle}{2z_0^2}z_r = 0. \end{cases}$$

Take now  $q \in \text{span}\{N_{\mathcal{Q}_{m+1}}(z)\}$  meaning that  $q = (-tz_0, tz_r)$  for some  $t \in \mathbb{R}$ . Then  $q$  surely satisfies (3.31), and thus  $q \in \Lambda(0)$ . Conversely, let  $q \in \Lambda(0)$  and show that  $q \in \text{span}\{N_{\mathcal{Q}_{m+1}}(z)\}$ . Indeed, reformulating the first equation in (3.31) gives us

$$(3.32) \quad \langle q, z \rangle = q_0 z_0 + \langle z_r, q_r \rangle = 0,$$

and we get from the second equation in (3.31) that  $q_r = -\frac{q_0}{z_0}z_r$ ; hence  $\|q_r\| = |q_0|$ . It allows us to deduce that either  $q \in \mathcal{Q}_{m+1}$  or  $-q \in \mathcal{Q}_{m+1}$ . Using this together with (3.32) and self dual property (3.15), we observe that  $q = (-tz_0, tz_r)$  for some  $t \in \mathbb{R}$ , which verifies (3.30) for  $s = 0$ . Considering finally the case of  $s \in (0, 1)$ , we can show similarly to the previous calculation that the equation  $G_s q = 0$  is equivalent to the following system:

$$(3.33) \quad \begin{cases} \left(1 - \frac{s}{2}\right)q_0 + \frac{s}{2z_0}\langle z_r, q_r \rangle = 0, \\ q_r + \frac{sq_0}{2z_0}z_r - \frac{s\langle z_r, q_r \rangle}{2z_0^2}z_r = 0. \end{cases}$$

Let us verify that  $q := (q_0, q_r) = 0$ . Indeed, assuming the contrary tells us that  $q_0 \neq 0$ , since otherwise we get  $q_r = 0$  by the second equation in (3.33). Substituting now the expression  $\langle z_r, q_r \rangle = -(\frac{2}{s} - 1)z_0q_0$  from the first equation into the second equation in (3.33), we arrive at

$$0 = q_r + \frac{sq_0}{2z_0}z_r + \frac{s(\frac{2}{s} - 1)z_0q_0}{2z_0^2}z_r = q_r + \frac{q_0}{z_0}z_r.$$

Multiplying the latter by  $z_r$  and taking into account that  $\|z_r\| = z_0$  lead us to

$$\left(1 - \frac{2}{s}\right)z_0q_0 + q_0z_0 = 0,$$

which yields  $s = 1$  due to  $z_0q_0 \neq 0$ . This contradicts the assumption on  $s \in (0, 1)$  and hence shows that  $q = 0$ . Invoking (3.30) justifies the inclusion  $\partial^2\delta_{\mathcal{Q}_{m+1}}(0, -y)(0) \subset \text{span}\{N_{\mathcal{Q}_{m+1}}(z)\}$ .

To verify the converse inclusion, take  $q \in \text{span}\{N_{\mathcal{Q}_{m+1}}(z)\}$  and get from the above that it is a solution to (3.29) for  $s = 1$ . This means that  $0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(z, z)(-q)$ , which implies by (3.20) that  $q \in \partial^2\delta_{\mathcal{Q}_{m+1}}(z, 0)(0)$  and completes the proof of (3.21) in this case.

**Case 6:**  $y, z = 0$ . Since  $\text{span}\{N_{\mathcal{Q}_{m+1}}(z)\} = \mathbb{R}^{m+1}$  in this case and since  $0 \in D^*\Pi_{\mathcal{Q}_{m+1}}(0, 0)(q)$  for any  $q \in \mathbb{R}^{m+1}$  by Lemma 3.3(iv), we get similarly to Case 4 that  $\partial^2\delta_{\mathcal{Q}_{m+1}}(z, 0)(0) = \mathbb{R}^{m+1}$ , which completes the proof of theorem.  $\triangle$

This theorem immediately implies the equivalence between the second-order qualification and nondegeneracy conditions for SOCPs with only one Lorentz cone  $\mathcal{Q} = \mathcal{Q}_{m+1}$  in (1.1).

**Corollary 3.7 (equivalence between SOCQ and nondegeneracy for SOCPs with one Lorentz cone).** *Consider SOCP (1.1) with one Lorentz cone  $\mathcal{Q} = \mathcal{Q}_{m+1}$  therein. Then for any  $\bar{x} \in \mathbb{R}^n$  with  $\bar{z} = \Phi(\bar{x}) \in \mathcal{Q}_{m+1}$  and any  $\bar{y} \in -N_{\mathcal{Q}_{m+1}}(\bar{z})$  we have that SOCQ (3.19) amounts to saying that  $\bar{x}$  is an SOCP nondegenerate point (3.2) with  $\mathcal{Q} = \mathcal{Q}_{m+1}$  and  $J = 1$ .*

**Proof.** As mentioned above, the nondegeneracy condition (3.2) in this case can be rewritten in the dual form (3.4). The latter reduces to SOCQ (3.19) by Theorem 3.6.  $\triangle$

To extend the equivalence in Corollary 3.7 to the general case of the product cone  $\mathcal{Q}$  in (1.1), we need the following product lemma for the second-order subdifferential of set indicators. Although we present this result for products of two sets, it can be easily obtained by inductions for the case of finitely many sets in the product.

**Lemma 3.8 (second-order subdifferential of the indicator function for product sets).** *Let  $\Omega = \Omega_1 \times \Omega_2 \subset \mathbb{R}^n \times \mathbb{R}^m$ , let  $x = (x_1, x_2) \in \Omega$ , and let  $y = (y_1, y_2) \in N_{\Omega}(x)$ . Then for any  $u = (u_1, u_2) \in \mathbb{R}^n \times \mathbb{R}^m$  we have the equality*

$$(3.34) \quad \partial^2\delta_{\Omega}(x, y)(u) = \partial^2\delta_{\Omega_1}(x_1, y_1)(u_1) \times \partial^2\delta_{\Omega_2}(x_2, y_2)(u_2).$$

**Proof.** The well-known product formula for the normal cone (2.1) tells us that

$$(3.35) \quad N_{\Omega_1 \times \Omega_2}(x_1, x_2) = N_{\Omega_1}(x_1) \times N_{\Omega_2}(x_2),$$

and thus  $y_i \in N_{\Omega_i}(x_i)$  for  $i = 1, 2$  in the notation above. By definition (2.8) of the second-order subdifferential in the case of  $\varphi = \delta_\Omega$  and by formula (2.6) we have

$$\partial^2 \delta_\Omega(x, y)(u) = (D^* \partial \delta_{\Omega_1 \times \Omega_2})(x, y)(u) = (D^* N_{\Omega_1 \times \Omega_2})(x, y)(u).$$

Furthermore, it is easy to deduce from the coderivative definition (2.7) and formula (3.35) that

$$(D^* N_{\Omega_1 \times \Omega_2})(x, y)(u) = (D^* N_{\Omega_1})(x_1, y_1)(u_1) \times (D^* N_{\Omega_2})(x_2, y_2)(u_2).$$

Combining all the above verifies the claimed result (3.34).  $\triangle$

Now we are ready to establish the main result of this section.

**Theorem 3.9 (equivalence between SOCQ and nondegeneracy conditions for general SOCPs).** *Consider the general SOCP (1.1) with the product cone (1.2) and take any  $\bar{x} \in \mathbb{R}^n$  with  $\bar{z} = (\bar{z}^1, \dots, \bar{z}^J) = \Phi(\bar{x}) \in \mathcal{Q}$  and  $\bar{y} = (\bar{y}^1, \dots, \bar{y}^J) \in -N_{\mathcal{Q}}(\bar{z})$ . Then SOCQ (3.1) is equivalent to the nondegeneracy condition (3.2).*

**Proof.** Letting  $u = 0$  in Lemma 3.8 in the case of  $\Omega = \mathcal{Q}$  therein, we get that

$$v := (v^1, \dots, v^J) \in \partial^2 \delta_{\mathcal{Q}}(\bar{z}, -\bar{y})(0) \iff v^j \in \partial^2 \delta_{\mathcal{Q}_{m_j+1}}(\bar{z}^j, -\bar{y}^j)(0), \quad j = 1, \dots, J.$$

This gives us by Corollary 3.7 that

$$\partial^2 \delta_{\mathcal{Q}}(\bar{z}, -\bar{y})(0) = \prod_{j=1}^J \partial^2 \delta_{\mathcal{Q}_{m_j+1}}(\bar{z}^j, -\bar{y}^j)(0) = \prod_{j=1}^J \text{span} \left\{ N_{\mathcal{Q}_{m_j+1}}(\bar{z}^j) \right\}.$$

Now using the product relationship (3.18), we arrive at

$$(3.36) \quad \partial^2 \delta_{\mathcal{Q}}(\bar{z}, -\bar{y})(0) = \text{span} \left\{ \prod_{j=1}^J N_{\mathcal{Q}_{m_j+1}}(z_j) \right\} = \text{span} \{ N_{\mathcal{Q}}(z) \},$$

which completes the proof of the theorem due to the equivalence between forms (3.2) and (3.4) of the nondegeneracy condition for SOCPs.  $\triangle$

## 4 Characterizations of Full Stability for SOCPs

In this section we derive complete second-order characterizations of full stability of local optimal solutions to SOCPs (1.1) entirely in terms of their initial data. As mentioned in Section 1, the notion of full stability was introduced in [12] in the unconstrained framework of optimization with extended-real-valued objectives. To adopt this approach for the case of SOCPs under consideration, we consider the two-parametric version  $\mathcal{P}(w, v)$  of (1.1) written as

$$(4.1) \quad \text{minimize } \varphi_0(x, w) + \delta_{\mathcal{Q}}(\Phi(x, w)) - \langle v, x \rangle \quad \text{over } x \in \mathbb{R}^n$$

with  $\Phi(x) = (\Phi^1(x), \dots, \Phi^J(x))$  and the product cone  $\mathcal{Q}$  taken from (1.2). In accordance with [12], the vector  $w \in \mathbb{R}^d$  signifies *basic* perturbations while the linear parametric shift of the objective with  $v \in \mathbb{R}^n$  represents *tilt* perturbations. Define the function  $\varphi: \mathbb{R}^n \times \mathbb{R}^d \rightarrow \overline{\mathbb{R}}$  by

$$(4.2) \quad \varphi(x, w) := \varphi_0(x, w) + \delta_{\mathcal{Q}}(\Phi(x, w)) \quad \text{with } x \in \mathbb{R}^n, w \in \mathbb{R}^d$$

and fix in what follows the triple  $(\bar{x}, \bar{w}, \bar{v})$  such that  $\Phi(\bar{x}, \bar{w}) \in \mathcal{Q}$  and  $\bar{v} \in \partial_x \varphi(\bar{x}, \bar{w})$ . Given a number  $\gamma > 0$ , consider the (local) optimal value function

$$(4.3) \quad m_\gamma(w, v) := \inf_{\|x - \bar{x}\| \leq \gamma} \left\{ \varphi(x, w) - \langle v, x \rangle \right\}, \quad (w, v) \in \mathbb{R}^d \times \mathbb{R}^n,$$

and the corresponding parametric family of optimal solution sets in (4.1) defined by

$$(4.4) \quad M_\gamma(w, v) := \operatorname{argmin}_{\|x - \bar{x}\| \leq \gamma} \left\{ \varphi(x, w) - \langle v, x \rangle \right\}, \quad (w, v) \in \mathbb{R}^d \times \mathbb{R}^n,$$

with the convention that  $\operatorname{argmin} := \emptyset$  when the expression under minimization is  $\infty$ . In this terms,  $\bar{x}$  is a *locally optimal solution* to  $\mathcal{P}(\bar{w}, \bar{v})$  if  $\bar{x} \in M_\gamma(\bar{w}, \bar{v})$  for some  $\gamma > 0$  sufficiently small.

**Definition 4.1 (full stability).** *A point  $\bar{x}$  is a FULLY STABLE locally optimal solution to problem  $\mathcal{P}(\bar{w}, \bar{v})$  if there exist a number  $\gamma > 0$  and neighborhoods  $W$  of  $\bar{w}$  and  $V$  of  $\bar{v}$  such that the mapping  $(w, v) \mapsto M_\gamma(w, v)$  is single-valued and Lipschitz continuous with  $M_\gamma(\bar{w}, \bar{v}) = \bar{x}$  and the function  $(w, v) \mapsto m_\gamma(w, v)$  is likewise Lipschitz continuous on  $W \times V$ .*

When the basic perturbation vector  $w$  is absent, Definition 4.1 corresponds to *tilt stability* of local minimizers introduced in [30] in the general extended-real-valued framework of unconstrained optimization. In this case the value function (4.3) is automatically locally Lipschitzian.

We proceed with characterizing full stability (as well as tilt stability as a particular case) for SOCPs under appropriate constraint qualifications. Recall (cf. [31] and [3, Definition 2.86]) that the *Robinson constraint qualification* (RCQ) with respect to  $x$  holds for (1.1) at  $(\bar{x}, \bar{w})$  if

$$(4.5) \quad 0 \in \operatorname{int} \left\{ \Phi(\bar{x}, \bar{w}) + \nabla_x \Phi(\bar{x}, \bar{w}) \mathbb{R}^n - \mathcal{Q} \right\}.$$

It is well known that this condition can be equivalently described as

$$(4.6) \quad N_{\mathcal{Q}}(\Phi(\bar{x}, \bar{w})) \cap \ker \nabla_x \Phi(\bar{x}, \bar{w})^* = \{0\},$$

which obviously reduces to the classical *Mangasarian-Fromovitz constraint qualification* (MFCQ) with respect to  $x$  in the case of NLPs.

Let us first present a characterization of full stability of locally optimal solutions to SOCPs under RCQ (4.5). Consider the partial first-order subdifferential mapping  $\partial_x \varphi: \mathbb{R}^n \times \mathbb{R}^d \rightrightarrows \mathbb{R}^n$  of the function  $\varphi$  from (4.2) and define the *partial inverse* of  $\partial_x \varphi$  by

$$(4.7) \quad S_\varphi(w, v) := \left\{ x \in \mathbb{R}^n \mid v \in \partial_x \varphi(x, w) \right\}.$$

Observe that under the validity of RCQ at  $(\bar{x}, \bar{w})$ , and hence around this point, we have the partial subdifferential representation

$$(4.8) \quad \partial_x \varphi(x, w) = \nabla_x \varphi_0(x, w) + \nabla_x \Phi(x, w)^* N_{\mathcal{Q}}(\Phi(x, w)) \quad \text{near } (\bar{x}, \bar{w}).$$

It follows by employing the elementary subdifferential sum rule in (4.2) and then the chain rule from [33, Exercise 10.26(b)] for the amenable composition  $\delta_{\mathcal{Q}}(\Phi(x, w))$  valid under RCQ in the equivalent form (4.6) due to the convexity of the second-order product cone  $\mathcal{Q}$ . This implies the local representation of the partial inverse (4.7) in terms of the initial data of (1.1) by

$$(4.9) \quad S_\varphi(w, v) = \left\{ x \in \mathbb{R}^n \mid v \in \nabla_x \varphi_0(x, w) + \nabla_x \Phi(x, w)^* N_{\mathcal{Q}}(\Phi(x, w)) \right\}.$$

Following [27, Definition 3.3], we say that the mapping  $\partial_x \varphi: \mathbb{R}^n \times \mathbb{R}^d \rightrightarrows \mathbb{R}^n$  is *partially strongly metrically regular* (PSMR) at  $(\bar{x}, \bar{w}, \bar{v})$  if its partial inverse (4.7) admits a Lipschitzian single-valued localization around this point. In the parameter-independent case of  $\varphi(x, w) = \varphi(x)$  this notion reduces to strong metric regularity [6] of the subgradient mapping  $\partial \varphi$  defined as an abstract version of Robinson’s strong regularity [31] for generalized equations; see Section 5.

The next result is actually a constructive implementation of the general full stability characterization from [27, Theorem 3.4] to the case of SOCPs. Its tilt stability versions in various optimization settings were given in [7, 13, 24, 27].

**Theorem 4.2 (PSMR characterization of full stability in SOCPs under RCQ).** *Let  $\Phi(\bar{x}, \bar{w}) \in \mathcal{Q}$  for SOCP (1.1), and let RCQ (4.5) hold at  $(\bar{x}, \bar{w})$ . Then  $\bar{x}$  is a fully stable locally optimal solution to  $\mathcal{P}(\bar{w}, \bar{v})$  in (4.1) with  $\bar{v}$  satisfying the condition*

$$(4.10) \quad \bar{v} \in \nabla_x \varphi_0(\bar{x}, \bar{w}) + \nabla_x \Phi(\bar{x}, \bar{w})^* N_{\mathcal{Q}}(\Phi(\bar{x}, \bar{w}))$$

*if and only if  $\bar{x} \in M_\gamma(\bar{w}, \bar{v})$  for some  $\gamma > 0$  and the mapping  $\partial_x \varphi$  from (4.8) is PSMR at  $(\bar{x}, \bar{w}, \bar{v})$ .*

**Proof.** We apply [27, Theorem 3.4] to problem  $\mathcal{P}(\bar{w}, \bar{v})$  in (4.1). It follows from the subdifferential formula (4.8) verified above that the partial inverse mapping (4.7) is locally represented by (4.9) and that the stationary condition  $0 \in \partial_x \varphi(\bar{x}, \bar{w})$  reduces to (4.10). Furthermore, we deduce from [12, Proposition 2.2] that the assumed RCQ implies the validity of the basic constraint qualification as well as the parametric continuous prox-regularity of the function  $\varphi$  at  $(\bar{x}, \bar{w}, \bar{v})$  imposed in [27, Theorem 3.4]. Then the “only if” part of this theorem follows from [27, Theorem 3.4(ii)]. Likewise, the “if” part of the theorem is a direct consequence of [27, Theorem 3.4(i)] due to the aforementioned calculus rules.  $\triangle$

To proceed further, consider the *KKT system*

$$(4.11) \quad \bar{v} = \nabla_x L(\bar{x}, \bar{w}, \bar{\lambda}), \quad -\bar{\lambda} \in N_{\mathcal{Q}}(\Phi(\bar{x}, \bar{w})) \subset \mathbb{R}^l \quad \text{with } l = \sum_{j=1}^J (m_j + 1),$$

associated with the local minimizer  $\bar{x}$  in  $\mathcal{P}(\bar{w}, \bar{v})$ , where  $L$  is the *Lagrangian* for (1.1) given by

$$(4.12) \quad L(x, w, \lambda) := \varphi_0(x, w) - \sum_{j=1}^J \langle \lambda^j, \Phi^j(x, w) \rangle, \quad \lambda^j \in \mathbb{R}^{m_j+1}.$$

It is well known in conic programming (see, e.g., [3, Theorem 3.9]) that RCQ (4.5) ensures the existence a Lagrange multiplier vector  $\bar{\lambda} = (\bar{\lambda}^1, \dots, \bar{\lambda}^J)$  satisfying the KKT system (4.11). On the other hand, it is easy to see that the *uniqueness* of the Lagrange multiplier  $\bar{\lambda} \in \mathbb{R}^l$  in (4.11) is guaranteed by the *partial in  $x$  second-order constraint qualification*

$$(4.13) \quad \partial^2 \delta_{\mathcal{Q}}(\bar{z}, \bar{y})(0) \cap \ker \nabla_x \Phi(\bar{x}, \bar{w})^* = \{0\} \quad \text{with } \bar{z} := \Phi(\bar{x}, \bar{w}), \bar{y} \in N_{\mathcal{Q}}(\bar{z})$$

as well as by the *partial in  $x$  nondegeneracy condition*

$$(4.14) \quad \nabla_x \Phi(\bar{x}, \bar{w}) \mathbb{R}^n + \text{lin}\{T_{\mathcal{Q}}(\bar{z})\} = \prod_{j=1}^J \mathbb{R}^{m_j+1}$$

equivalent to (4.13) by Theorem 3.9. In what follows we use only these versions of SOCQ and nondegeneracy conditions and thus omit the adjective “partial” when no confusion arises.

In the rest of this section we derive two second-order characterizations of full stability in SOCPs under the *equivalent SOCQ/nondegeneracy conditions* (4.13) and (4.14). The proofs

of both of them strongly involve the recent chain rule from [19, Theorem 4.3] for the partial second-order subdifferential for functions of two variables defined by scheme (2.8) as follows; see [12]. Given a function  $\psi: \mathbb{R}^n \times \mathbb{R}^d \rightarrow \overline{\mathbb{R}}$  of the variables  $(x, w) \in \mathbb{R}^n \times \mathbb{R}^d$ , its *partial second-order subdifferential* at  $(\bar{x}, \bar{w})$  relative to some  $\bar{y} \in \partial_x \psi(\bar{x}, \bar{w})$  is

$$(4.15) \quad \partial_x^2 \psi(\bar{x}, \bar{w}, \bar{y})(u) := (D^* \partial_x \psi)(\bar{x}, \bar{w}, \bar{y})(u), \quad u \in \mathbb{R}^n.$$

To avoid confusion, note that in [26, 27] the second-order construction (4.15) is labeled as the “extended partial second-order subdifferential” with using the symbol  $\tilde{\partial}_x^2 \psi$ .

The following second-order chain rule is a particular case of [19, Theorem 4.3] while its nonparametric counterpart with  $\Phi = \Phi(x)$  was first obtained in [28, Theorem 7]. Both results were proved under the nondegeneracy condition. Their SOCQ versions hold due to Theorem 3.9.

**Lemma 4.3 (second-order chain rule for parametric compositions in SOCPs).** *Let  $\bar{v} \in \partial_x(\delta_{\mathcal{Q}} \circ \Phi)(\bar{x}, \bar{w})$  in the SOCP setting (1.1) with  $\bar{z} := \Phi(\bar{x}, \bar{w}) \in \mathcal{Q}$  under the validity of the SOCQ/nondegeneracy condition at  $(\bar{x}, \bar{w})$ , and let  $\bar{y} \in \mathbb{R}^J$  be the (unique) vector in  $\partial \delta_{\mathcal{Q}}(\bar{z})$  satisfying  $\bar{v} = \nabla_x \Phi(\bar{x}, \bar{w})^* \bar{y}$ . Then for all  $u \in \mathbb{R}^J$  we have the equality*

$$(4.16) \quad \begin{aligned} \partial^2(\delta_{\mathcal{Q}} \circ \Phi)(\bar{x}, \bar{w}, \bar{v})(u) &= \left( \nabla_{xx}^2 \langle \bar{y}, \Phi \rangle(\bar{x}, \bar{w})u, \nabla_{xw}^2 \langle \bar{y}, \Phi \rangle(\bar{x}, \bar{w})u \right) \\ &+ \left( \nabla_x \Phi(\bar{x}, \bar{w}), \nabla_w \Phi(\bar{x}, \bar{w}) \right)^* \partial^2 \delta_{\mathcal{Q}}(\bar{z}, \bar{y})(\nabla_x \Phi(\bar{x}, \bar{w})u). \end{aligned}$$

**Proof.** It follows from [19, Theorem 4.3] by the convexity and pointedness of the cone  $\mathcal{Q}$  and by the automatic validity in finite dimensions of the SNC assumptions imposed therein.  $\triangle$

Our next goal is to characterize full stability of local minimizers for SOCPs via the following SOCP version [2] of the uniform second-order growth condition from [3, Definition 5.16]. Given  $\varphi: \mathbb{R}^n \times \mathbb{R}^d \rightarrow \overline{\mathbb{R}}$  in (4.2) with  $\Phi(\bar{x}, \bar{w}) \in \mathcal{Q}$  and given  $\bar{v} \in \partial_x \varphi(\bar{x}, \bar{w})$ , we say that the *SOCP uniform second-order growth condition (USOGC)* holds at  $(\bar{x}, \bar{w}, \bar{v})$  if there exist  $\eta > 0$  as well as neighborhoods  $U$  of  $\bar{x}$ ,  $W$  of  $\bar{w}$ , and  $V$  of  $\bar{v}$  such that for any  $(w, v) \in W \times V$  and any stationary point  $x_{wv} \in U$  satisfying  $v \in \partial_x \varphi(x_{wv}, w)$  we have

$$(4.17) \quad \varphi_0(x, w) \geq \varphi_0(x_{wv}, w) + \langle v, x - x_{wv} \rangle + \eta \|x - x_{wv}\|^2 \quad \text{for } x \in U, \Phi(x, w) \in \mathcal{Q}.$$

**Theorem 4.4 (characterizing full stability in SOCPs via USOGC).** *Let  $(\bar{x}, \bar{w})$  be such that  $\Phi(\bar{x}, \bar{w}) \in \mathcal{Q}$  in the SOCP framework (1.1) under the SOCQ/nondegeneracy condition at  $(\bar{x}, \bar{w})$ , and let  $\bar{v}$  be taken from (4.10). Then  $\bar{x}$  is a fully stable local minimizer of  $\mathcal{P}(\bar{w}, \bar{v})$  in (4.1) if and only if  $\bar{x} \in M_\gamma(\bar{x}, \bar{w})$  for some  $\gamma > 0$  and USOGC (4.17) is satisfied at  $(\bar{x}, \bar{w}, \bar{v})$ .*

**Proof.** The necessity part of the theorem follows from [27, Theorem 3.7(i)] specified in the SOCP setting. To justify the sufficiency part, find numbers  $\gamma, \sigma > 0$  such that USOGC (4.17) holds with  $U := \text{int } \mathcal{B}_\gamma(\bar{x})$ ,  $W := \text{int } \mathcal{B}_\gamma(\bar{w})$ ,  $V := \text{int } \mathcal{B}_\gamma(\bar{v})$ , and  $\eta := \frac{1}{2\sigma}$ . It easily follows from (4.17) that for all  $(w, v) \in W \times V$  there is the unique minimizer  $x_{wv}$  for (4.1). Moreover, by [33, Proposition 3.5] we can suppose without loss of generality that  $x_{wv} \in \text{int } \mathcal{B}_{\frac{\gamma}{2}}(\bar{x})$ . Let us now prove that the mapping  $(w, v) \mapsto x_{wv}$  is a Lipschitzian single-valued localization of (4.9) around  $(\bar{w}, \bar{v})$  and thus Theorem 4.2 ensures that  $\bar{x}$  is a fully stable local minimizer of  $\mathcal{P}(\bar{w}, \bar{v})$ .

To proceed, define the set-valued mapping  $\Theta: \mathbb{R}^d \rightrightarrows \mathbb{R}^n \times \mathbb{R}^n$  by

$$(4.18) \quad \Theta(w) := \text{gph } \partial_x \varphi(\cdot, w) = \left\{ (x, \nabla_x \varphi_0(x, w) - \nabla_x \Phi(x, w)^* \lambda) \mid -\lambda \in N_{\mathcal{Q}}(\Phi(x, w)) \right\}$$

with  $\varphi$  taken from (4.2). We claim  $\Theta$  has the Lipschitz-like/Aubin property around  $(\bar{w}, \bar{x}, \bar{v})$ , which means that there exists a number  $\ell > 0$  such that

$$(4.19) \quad \Theta(w) \cap (U \times V) \subset \Theta(w') + \ell \|w - w'\| \mathcal{B}_1(0) \quad \text{for all } w, w' \in W.$$

Indeed, it follows from [12, Propositions 3.2 and 4.3] via the Mordukhovich criterion of [33, Theorem 9.40] that the latter property holds for (4.18) if and only if

$$(4.20) \quad (0, q) \in \partial_x^2 \varphi(\bar{x}, \bar{w}, \bar{v})(0) \implies q = 0.$$

Employing now in  $\varphi$  the second-order sum rule from [18, Proposition 1.121] and then the second-order chain rule from Lemma 4.3 above, we get that (4.20) is equivalent to the implication

$$\left[ \nabla_x \Phi(\bar{x}, \bar{w})^* p = 0, \nabla_w \Phi(\bar{x}, \bar{w})^* p = q, p \in \partial^2 \delta_{\mathcal{Q}}(\bar{z}, -\bar{\lambda})(0) \right] \implies q = 0,$$

where  $-\bar{\lambda}$  is the unique vector in  $N_{\mathcal{Q}}(\Phi(\bar{x}, \bar{w}))$  satisfying (4.11). But this is automatic under the imposed SOCQ (4.13), which thus verifies (4.19).

Let us finally show that the mapping  $(w, v) \mapsto x_{wv}$  is Lipschitz continuous around  $(\bar{w}, \bar{v})$ . To furnish this, take  $w_1, w_2 \in W$  and  $v_1, v_2 \in V$  and observe that USOGC (4.17) implies the existence and uniqueness of minimizers  $x_{w_1 v_1}, x_{w_2 v_2}$  for  $\mathcal{P}(\bar{w}, \bar{v})$  on  $\text{int } \mathbb{B}_{\frac{\gamma}{2}}(\bar{x})$ . This yields by (4.18) that  $(x_{w_1 v_1}, v_1) \in \Theta(w_1)$  and  $(x_{w_2 v_2}, v_2) \in \Theta(w_2)$ . Since  $(x_{w_2 v_2}, v_2) \in U \times V$ , we get from the Lipschitzian condition (4.19) that

$$(4.21) \quad \|x_{w_2 v_2} - \tilde{x}\| + \|v_2 - \tilde{v}\| \leq \ell \|w_1 - w_2\| \quad \text{for some } (\tilde{x}, \tilde{v}) \in \Theta(w_1).$$

Suppose without loss of generality that  $(x_{w_2 v_2}, v_2) \in U \times V$  and employing USOGC (4.17) shows that  $M_\gamma(w_1, \tilde{v}) = \{\tilde{x}\}$ . Implementing (4.17) again with the chosen number  $\eta := \frac{1}{2\sigma}$  tells us that

$$\begin{aligned} \varphi_0(x_{w_1 v_1}, w_1) &\geq \varphi_0(\tilde{x}, w_1) + \langle \tilde{v}, x_{w_1 v_1} - \tilde{x} \rangle + \frac{1}{2\sigma} \|x_{w_1 v_1} - \tilde{x}\|^2, \\ \varphi_0(\tilde{x}, w_1) &\geq \varphi_0(x_{w_1 v_1}, w_1) + \langle v_1, \tilde{x} - x_{w_1 v_1} \rangle + \frac{1}{2\sigma} \|x_{w_1 v_1} - \tilde{x}\|^2 \end{aligned}$$

from which we readily deduce the estimates

$$\begin{aligned} \|x_{w_1 v_1} - \tilde{x}\| &\leq \sigma \|\tilde{v} - v_1\| \leq \sigma \|\tilde{v} - v_2\| + \sigma \|v_2 - v_1\| \\ &\leq \sigma \ell \|w_1 - w_2\| + \sigma \|v_2 - v_1\|. \end{aligned}$$

Combining this together with (4.21) shows that

$$\begin{aligned} \|x_{w_1 v_1} - x_{w_2 v_2}\| &\leq \|\tilde{x} - x_{w_2 v_2}\| + \|x_{w_1 v_1} - \tilde{x}\| \\ &\leq \ell(\sigma + 1)(\|w_1 - w_2\| + \|v_1 - v_2\|), \end{aligned}$$

which verifies the claimed local Lipschitz continuity and thus completes the proof.  $\triangle$

The last and most important topic of this section is deriving second-order subdifferential descriptions of full stability of locally optimal solutions to SOCPs, which eventually leads us to complete characterizations of this notion entirely in terms of the initial data of (1.1). The next lemma revisits the result of [27, Theorem 5.1] on the second-order subdifferential characterization of full stability replacing for the case of SOCPs the full rank assumption on  $\nabla_x \Phi(\bar{x}, \bar{w})$  by the milder SOCQ/nondegeneracy condition in (4.13) and (4.14).

**Lemma 4.5 (second-order subdifferential characterization of fully stable local minimizers for SOCPs at nondegenerate solutions).** *Let  $\bar{x}$  be a feasible solution to the unperturbed problem  $\mathcal{P}(\bar{w}, \bar{v})$  in (4.1) with some  $\bar{w} \in \mathbb{R}^d$  and  $\bar{v} \in \mathbb{R}^n$  taken from (4.10) under the SOCQ/nondegeneracy condition at  $(\bar{x}, \bar{w})$ , and let  $\bar{\lambda}$  be the unique vector satisfying*

$$(4.22) \quad \nabla_x \varphi_0(\bar{x}, \bar{w}) - \nabla_x \Phi(\bar{x}, \bar{w})^* \bar{\lambda} = \bar{v} \quad \text{and} \quad -\bar{\lambda} \in N_{\mathcal{Q}}(\bar{z}).$$



Then  $\bar{x}$  is a fully stable local minimizer of  $\mathcal{P}(\bar{w}, \bar{v})$  if and only if we have the implication

$$(4.23) \quad [(p, q) \in \mathcal{T}(\bar{x}, \bar{w}, \bar{v})(u), u \neq 0] \implies \langle p, u \rangle > 0$$

for the set-valued mapping  $\mathcal{T}(\bar{x}, \bar{w}, \bar{v}): \mathbb{R}^n \rightrightarrows \mathbb{R}^n \times \mathbb{R}^d$  defined by

$$\begin{aligned} \mathcal{T}(\bar{x}, \bar{w}, \bar{v})(u) : &= \left( \nabla_{xx}^2 \varphi_0(\bar{x}, \bar{w})u, \nabla_{xw}^2 \varphi_0(\bar{x}, \bar{w})u \right) - \left( \nabla_{xx}^2 \langle \bar{\lambda}, \Phi \rangle(\bar{x}, \bar{w})u, \nabla_{xw}^2 \langle \bar{\lambda}, \Phi \rangle(\bar{x}, \bar{w})u \right) \\ &+ \left( \nabla_x \Phi(\bar{x}, \bar{w}), \nabla_w \Phi(\bar{x}, \bar{w}) \right)^* \partial^2 \delta_{\mathcal{Q}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u), \quad u \in \mathbb{R}^n. \end{aligned}$$

**Proof.** It follows the lines in the proof of [27, Theorem 5.1] with replacing the second-order chain rule for (4.15) from [26, Theorem 3.1] obtained under the full rank assumption by that of Lemma 4.3 established under the more subtle SOCQ (4.13).  $\triangle$

It is worth mentioning that Lemma 4.5 can *not* be derived from [27, Theorem 5.2] under the SOCQ/nondegeneracy condition, since the outer function  $\delta_{\mathcal{Q}}$  for SOCPs is neither piecewise linear nor piecewise linear-quadratic of the type considered therein.

Now we proceed with expressing the second-order subdifferential characterization of full stability in Lemma 4.5 *entirely in terms of the initial data* of the SOCP (1.1) under consideration. To accomplish it, we need to *calculate the second-order subdifferential*  $\partial^2 \delta_{\mathcal{Q}}$  in condition (4.23) at *nonzero* points, which is of its own interest. This calculation is partly similar to by generally different from that at zero derived in Theorem 3.6 while it also strongly involves the results of Lemma 3.3 on the coderivative description for the metric projection onto the Lorentz cone  $\mathcal{Q}_{m+1}$ . The key ingredients are given in the following lemma.

**Lemma 4.6 (domain of the second-order subdifferential for the indicator function of the Lorentz cone).** *Let  $z = (z_0, z_r) \in \mathcal{Q}_{m+1}$ , and let  $-y \in N_{\mathcal{Q}_{m+1}}(z)$  for the Lorentz cone  $\mathcal{Q}_{m+1}$  in (1.3). Then we have the representation*

$$(4.24) \quad \text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, -y) = \left\{ u \in \mathbb{R}^n \left| \begin{array}{ll} u = 0 & \text{if } y \in \text{int } \mathcal{Q}_{m+1}, \\ u \in \mathbb{R}(y_0, -y_r) & \text{if } y \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}, z = 0, \\ \langle u, y \rangle = 0 & \text{if } y, z \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\} \end{array} \right. \right\}.$$

**Proof.** We split the proof into the following six cases according to the position of  $z, y \in \mathcal{Q}_{m+1}$ .

**Case 1:**  $z = 0, y \in \text{int } \mathcal{Q}_{m+1}$ . Take  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, -y)(u)$ , which by (3.20) amounts to  $-u \in D^* \Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q - u)$ . Arguing as in Case 1 from the proof of Theorem 3.6 gives us  $D^* \Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q - u) = 0$ , which yields  $u = 0$  and thus  $\text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, -y)(0) = \{0\}$ .

**Case 2:**  $z \in \text{int } \mathcal{Q}_{m+1}$ . This implies that  $y = 0$ . Take  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, 0)(u)$ , which is equivalent by (3.20) to  $-u \in D^* \Pi_{\mathcal{Q}_{m+1}}(z, z)(-q - u)$ . Since  $z \in \text{int } \mathcal{Q}_{m+1}$ , it says that  $z_0 > \|z_r\|$  and thus Lemma 3.3(i) together with (3.10) tells us that

$$-u \in D^* \Pi_{\mathcal{Q}_{m+1}}(z, z)(-q - u) = \nabla \Pi_{\mathcal{Q}_{m+1}}(z)(-q - u) = I_{m+1}(-q - u) = -q - u \iff q = 0.$$

Therefore we have  $\text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, 0) = \mathbb{R}^{m+1}$  in this case.

**Case 3:**  $z, y \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$ . Taking  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, -y)(u)$  and using (3.20) give us

$$(4.25) \quad -u \in D^* \Pi_{\mathcal{Q}_{m+1}}(\bar{z} - \bar{\lambda}, \bar{z})(-q - u).$$

First we claim that  $\langle u, y \rangle = 0$ . To furnish this, observe that  $-y \in N_{\mathcal{Q}_{m+1}}(z)$  yields  $\langle y, z \rangle = 0$  due to the property (3.15). Put  $c = (c_0, c_r) := z - y$  and deduce from (3.6) that the validity of

equalities (3.23) and (3.24) for these vectors. Similarly to Case 3 in the proof of Theorem 3.6 with  $q = (q_0, q_r)$  and  $u = (u_0, u_r)$  we arrive at the coderivative representation

$$D^*\Pi_{\mathcal{Q}_{m+1}}(\bar{z} - \bar{\lambda}, \bar{z})(-q - u) = \frac{1}{2} \begin{pmatrix} 1 & \frac{c_r^T}{\|c_r\|} \\ \frac{c_r}{\|c_r\|} & H \end{pmatrix} \begin{pmatrix} -q_0 - u_0 \\ -q_r - u_r \end{pmatrix},$$

where  $H$  is defined in the proof of Theorem 3.6. This allows us reducing (4.25) to the system

$$(4.26) \quad \begin{cases} \frac{1}{2}(q_0 + u_0) + \frac{1}{2\|c_r\|} \langle c_r, q_r + u_r \rangle = u_0, \\ \frac{1}{2}(q_0 + u_0) \frac{c_r}{\|c_r\|} + \frac{z_0}{z_0 + y_0} (q_r + u_r) - \frac{z_0 - y_0}{2(z_0 + y_0)} \frac{c_r}{\|c_r\|^2} \langle c_r, q_r + u_r \rangle = u_r. \end{cases}$$

Arguing similarly to Theorem 3.6 in this case, we deduce from (4.26) that

$$u_0 \|c_r\| = \langle c_r, u_r \rangle = \left\langle -\frac{\|c_r\|}{y_0} y_r, u_r \right\rangle$$

and thus verify that  $\langle u, y \rangle = 0$ . Hence for  $\langle u, y \rangle \neq 0$  we have  $\partial^2 \delta_{\mathcal{Q}_{m+1}}(z, -y)(u) = \emptyset$ .

It remains to consider the situation when  $\langle u, y \rangle = 0$  and show that  $\text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, -y) \neq \emptyset$ . To proceed, take  $\bar{q} := -\frac{y_0}{z_0}(u_0, -u_r)$  and verify that  $\bar{q} \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, -y)(u)$ , which amounts to saying that  $\bar{q}$  satisfies the system of equations in (4.26). Indeed, it follows from (3.23) that

$$\langle c_r, u_r \rangle = -\frac{y_0 + z_0}{y_0} \langle y_r, u_r \rangle = \frac{y_0 + z_0}{y_0} y_0 u_0 = u_0(z_0 + y_0) = u_0 \|c_r\|$$

due to  $\langle y, u \rangle = 0$ . This implies the equalities

$$(4.27) \quad \begin{aligned} \frac{1}{2}(\bar{q}_0 + u_0) + \frac{1}{2\|c_r\|} \langle c_r, \bar{q}_r + u_r \rangle &= \frac{1}{2} \left( -\frac{y_0}{z_0} + 1 \right) u_0 + \frac{1}{2\|c_r\|} \left\langle c_r, \left( \frac{y_0}{z_0} + 1 \right) u_r \right\rangle \\ &= \frac{1}{2} \left[ \frac{(z_0 - y_0)u_0}{z_0} + \frac{(y_0 + z_0)u_0}{z_0} \right] = u_0, \end{aligned}$$

and thus the first equation in (4.26) holds. Also it follows from by (4.27) that

$$\begin{aligned} &\frac{1}{2}(\bar{q}_0 + u_0) \frac{c_r}{\|c_r\|} + \frac{z_0}{z_0 + y_0} (\bar{q}_r + u_r) - \frac{z_0 - y_0}{2(z_0 + y_0)} \frac{c_r}{\|c_r\|^2} \langle c_r, \bar{q}_r + u_r \rangle \\ &= \frac{1}{2} \left( -\frac{y_0}{z_0} + 1 \right) \frac{c_r}{\|c_r\|} u_0 + \frac{z_0}{z_0 + y_0} \left( \frac{y_0}{z_0} + 1 \right) u_r - \frac{z_0 - y_0}{2(z_0 + y_0)} \frac{c_r}{\|c_r\|^2} \frac{\|c_r\|^2}{z_0} u_0 \\ &= \frac{1}{2} \frac{c_r}{\|c_r\|} u_0 \left( \frac{y_0 - z_0}{z_0} - \frac{y_0 - z_0}{z_0} \right) + \frac{z_0}{z_0 + y_0} \left( \frac{y_0 + z_0}{z_0} \right) u_r = u_r, \end{aligned}$$

and therefore the second equation in (4.26) is satisfied as well. This verifies that  $\bar{q} \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, -y)(u)$  and hence completes the proof in this case.

**Case 4:**  $z = 0, y \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$ . Take  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, -y)(u)$  and get by (3.20) that

$$(4.28) \quad -u \in D^*\Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q - u).$$

Let us first check that  $u \in \{t(y_0, -y_r) \mid t \in \mathbb{R}\}$ . Indeed, it follows from Lemma 3.3(iii) that

$$D^*\Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q - u) \in \left\{ \frac{t}{2} B(-y)(-q - u) \mid B(-y) = \begin{pmatrix} 1 & -\frac{y_r^T}{\|y_r\|} \\ -\frac{y_r}{\|y_r\|} & \frac{y_r y_r^T}{\|y_r\|^2} \end{pmatrix}, t \in [0, 1] \right\}.$$

This together with (4.28) ensures the existence of  $t_0 \in [0, 1]$  such that

$$(4.29) \quad \begin{pmatrix} u_0 \\ u_r \end{pmatrix} = \frac{t_0}{2} \begin{pmatrix} 1 & -\frac{y_r^T}{\|y_r\|} \\ -\frac{y_r}{\|y_r\|} & \frac{y_r y_r^T}{\|y_r\|^2} \end{pmatrix} \begin{pmatrix} q_0 + u_0 \\ q_r + u_r \end{pmatrix}.$$

For  $t_0 = 0$  we have  $u = 0$  and so  $u \in \{t(y_0, -y_r) \mid t \in \mathbb{R}\}$ . If  $t_0 \neq 0$ , we rephrase (4.29) as

$$(4.30) \quad \begin{cases} \frac{t_0}{2} \left[ q_0 + u_0 - \frac{\langle y_r, q_r + u_r \rangle}{\|y_r\|} \right] = u_0, \\ \frac{t_0}{2} \left[ \frac{-(q_0 + u_0)}{\|y_r\|} y_r + \frac{\langle y_r, q_r + u_r \rangle}{\|y_r\|^2} y_r \right] = u_r. \end{cases}$$

The first equation in (4.30) gives us the relationship

$$(4.31) \quad \langle y_r, q_r + u_r \rangle = \|y_r\| \left( -\frac{2}{t_0} u_0 + u_0 + q_0 \right).$$

Multiplying both sides of the second equation in (4.30) by  $y_r$  and using (4.31) yield

$$\begin{aligned} \langle y_r, u_r \rangle &= \frac{t_0}{2} \left[ -(q_0 + u_0) \|y_r\| + \langle y_r, q_r + u_r \rangle \right] \\ &= \frac{t_0}{2} \left[ -(q_0 + u_0) \|y_r\| + \|y_r\| \left( -\frac{2}{t_0} u_0 - u_0 - q_0 \right) \right] \\ &= -u_0 \|y_r\| = -u_0 y_0, \end{aligned}$$

which implies that  $\langle y, u \rangle = 0$ . Furthermore, substituting (4.31) into the second equation in (4.30) brings us to the expression

$$u_r = \frac{t_0}{2} \left[ \frac{-(q_0 + u_0)}{\|y_r\|} y_r + \frac{-\frac{2}{t_0} u_0 + u_0 + q_0}{\|y_r\|} y_r \right] = \frac{-u_0}{\|y_r\|} y_r,$$

and thus  $\|u_r\| = |u_0|$ . If  $u_0 = 0$ , we have  $u = 0$  and therefore  $u \in \{t(y_0, -y_r) \mid t \in \mathbb{R}\}$ . Otherwise, it follows that either  $u \in \mathcal{Q}_{m+1}$  or  $-u \in \mathcal{Q}_{m+1}$ . Using this together with  $\langle y, u \rangle = 0$  and property (3.5), we observe that  $u = (-ty_0, ty_r)$  for some  $t \in \mathbb{R}$  and so verify  $u \in \mathbb{R}(y_0, -y_r)$ . To finish the proof in this case, it remains to show that if  $(u_0, u_r) = t_0(y_0, -y_r)$  for some  $t_0 \in \mathbb{R}$ , then  $\text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, -y) \neq \emptyset$ . Indeed, note that the vector  $q = (q_0, q_r) = (0, 0)$  satisfies the system

$$(4.32) \quad \begin{pmatrix} u_0 \\ u_r \end{pmatrix} = \frac{1}{2} \begin{pmatrix} 1 & -\frac{y_r^T}{\|y_r\|} \\ -\frac{y_r}{\|y_r\|} & \frac{y_r y_r^T}{\|y_r\|^2} \end{pmatrix} \begin{pmatrix} q_0 + u_0 \\ q_r + u_r \end{pmatrix}.$$

and that by Lemma 3.3(iii) we have the inclusion

$$\frac{1}{2} \begin{pmatrix} 1 & -\frac{y_r^T}{\|y_r\|} \\ -\frac{y_r}{\|y_r\|} & \frac{y_r y_r^T}{\|y_r\|^2} \end{pmatrix} (-q - u) \in D^* \Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q - u).$$

This together with (4.32) leads us to

$$-u \in D^* \Pi_{\mathcal{Q}_{m+1}}(-y, 0)(-q - u) \text{ and hence } 0 = q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, -y)(u),$$

which completes the proof of (4.24) in this case.

**Case 5:**  $z \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$ ,  $y = 0$ . Employing Lemma 3.3(ii), we have

$$-u \in D^* \Pi_{\mathcal{Q}_{m+1}}(z, z)(-u), \quad u \in \mathbb{R}^{m+1},$$

which amounts to  $0 \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, 0)(u)$  by the equivalence in (3.20). This tells us  $\text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(z, 0) = \mathbb{R}^{m+1}$  and ends the proof of (4.24) in this case.

**Case 6:**  $z = 0, y = 0$ . Similarly to Case 5 we have by employing Lemma 3.3(iv) that

$$-u \in D^* \Pi_{\mathcal{Q}_{m+1}}(0, 0)(-u), \quad u \in \mathbb{R}^{m+1},$$

which amounts to  $0 \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, 0)(u)$  by (3.20). This shows that  $\text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(0, 0) = \mathbb{R}^{m+1}$  in this case and thus ends the proof of the lemma.  $\triangle$

To derive our main characterization of full stability of locally optimal solutions to SOCP (1.1) in terms of the initial data, we need one more result about properties of the second-order subdifferential  $\partial^2 \delta_{\mathcal{Q}_{m+1}}$ . For formulating this result and for the subsequent developments below, let us fix a pair  $(\bar{x}, \bar{w})$  with  $\Phi(\bar{x}, \bar{w}) \in \mathcal{Q}$  and a Lagrange multiplier with  $-\bar{\lambda} \in N_{\mathcal{Q}}(\Phi(\bar{x}, \bar{w}))$ . Following [2], introduce the function

$$(4.33) \quad \mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda}) := \sum_{j=1}^J \mathcal{H}^j(\bar{x}, \bar{w}, \bar{\lambda}),$$

where each  $n \times n$  matrix  $\mathcal{H}^j(\bar{x}, \bar{w}, \bar{\lambda})$  is defined by

$$(4.34) \quad \mathcal{H}^j(\bar{x}, \bar{w}, \bar{\lambda}) := \begin{cases} -\frac{\bar{\lambda}_0^j}{\bar{z}_0^j} \nabla_x \Phi^j(\bar{x}, \bar{w})^* \begin{pmatrix} 1 & 0^T \\ 0 & -I_{m_j} \end{pmatrix} \nabla_x \Phi^j(\bar{x}, \bar{w}) & \text{if } \bar{z}^j \in \text{bd } \mathcal{Q}_{m_j+1} \setminus \{0\} \\ 0 & \text{otherwise} \end{cases}$$

with  $\bar{\lambda}^j = (\bar{\lambda}_0^j, \bar{\lambda}_r^j)$  and  $\bar{z}^j = \Phi^j(\bar{x}, \bar{w}) = (\bar{z}_0^j, \bar{z}_r^j)$  for  $j = 1, \dots, J$ . In the case of one Lorentz cone  $\mathcal{Q} = \mathcal{Q}_{m+1}$  in (4.33), i.e., when  $J = 1$ , we drop the index  $j$  in (4.33) and (4.34) for convenience. To unify consideration of similar cases regarding the position of the vectors  $\bar{\lambda}$  and  $\bar{z} = \Phi(\bar{x}, \bar{w})$  in  $\mathcal{Q}_{m+1}$ , we write  $(\bar{z}, \bar{\lambda}) \in I_1$  if  $\bar{z}, \bar{\lambda} \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}$  and  $(\bar{z}, \bar{\lambda}) \in I_2$  otherwise.

**Lemma 4.7 (properties of the second-order subdifferential of  $\delta_{\mathcal{Q}_{m+1}}$ ).** *Given the vectors  $\bar{z} := (\bar{z}_0, \bar{z}_r) \in \mathcal{Q}_{m+1}$  and  $-\bar{\lambda} \in N_{\mathcal{Q}_{m+1}}(\bar{z})$ , the following assertions hold.*

(i) *If  $(\bar{z}, \bar{\lambda}) \in I_1$  and  $\nabla_x \Phi(\bar{x}, \bar{w})u \in \text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})$  with  $u \in \mathbb{R}^n$ , then for any vector  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u)$  we have*

$$(4.35) \quad \langle \mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda})u, u \rangle = \langle q, \nabla_x \Phi(\bar{x}, \bar{w})u \rangle.$$

(ii) *If  $(\bar{z}, \bar{\lambda}) \in I_2$  and  $u \in \text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})$ , then*

$$(4.36) \quad 0 \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u).$$

**Proof.** To verify (i) first, we see that if  $\nabla_x \Phi(\bar{x}, \bar{w})u = 0$ , then (4.35) clearly holds. Suppose that  $\beta := (\beta_0, \beta_r) = \nabla_x \Phi(\bar{x}, \bar{w})u \neq 0$ . Taking into account  $(\beta_0, \beta_r) \in \text{dom } \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})$  together with Lemma 4.5 gives that  $\langle \bar{\lambda}, \beta \rangle = 0$ , which implies in turn that  $\beta_r \neq 0$ . Fix now  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\beta)$  and get by (3.20) that

$$-\beta \in D^* \Pi_{\mathcal{Q}_{m+1}}(\bar{z} - \bar{\lambda}, \bar{z})(-q - \beta).$$

It follows from the inclusion  $-\bar{\lambda} \in N_{\mathcal{Q}_{m+1}}(\bar{z})$  due to the property (3.15) that  $\langle \bar{\lambda}, \bar{z} \rangle = 0$ . Denote  $c = (c_0, c_r) := \bar{z} - \bar{\lambda}$  and derive similarly to Case 3 in the proof of Lemma 4.6 that these elements with  $q = (q_0, q_r)$  and  $\beta = (\beta_0, \beta_r)$  satisfy system (4.26) therein and thus the relationship

$$(4.37) \quad \langle c_r, \beta_r \rangle = \beta_0 \|c_r\|, \quad \langle c_r, q_r \rangle = -q_0 \|c_r\|.$$

Multiplying both sides of the second equation in (4.26) by  $u_r$  and unifying it with (4.37) yield

$$\begin{aligned}\|\beta_r\|^2 &= \frac{1}{2}(q_0 + \beta_0) \frac{\langle c_r, \beta_r \rangle}{\|c_r\|} + \frac{\bar{z}_0}{\bar{z}_0 + \bar{\lambda}_0} \langle q_r + \beta_r, \beta_r \rangle - \frac{\bar{z}_0 - \bar{\lambda}_0}{2(\bar{z}_0 + \bar{\lambda}_0)} \frac{\langle c_r, \beta_r \rangle}{\|c_r\|^2} \langle c_r, q_r + \beta_r \rangle \\ &= \frac{1}{2}(q_0 + \beta_0)\beta_0 + \frac{\bar{z}_0}{\bar{z}_0 + \bar{\lambda}_0} (\langle q_r, \beta_r \rangle + \|\beta_r\|^2) - \frac{\bar{z}_0 - \bar{\lambda}_0}{2(\bar{z}_0 + \bar{\lambda}_0)} \beta_0(\beta_0 - q_0),\end{aligned}$$

which implies in turn the equality

$$\langle q_r, \beta_r \rangle = \frac{\bar{\lambda}_0}{\bar{z}_0} \|\beta_r\|^2 + \frac{\bar{z}_0 - \bar{\lambda}_0}{2\bar{z}_0} \beta_0(\beta_0 - q_0) - \frac{\bar{z}_0 + \bar{\lambda}_0}{2\bar{z}_0} (q_0 + \beta_0)\beta_0.$$

Using this and the definition of  $\mathcal{H}$  in (4.34), we arrive at the expression

$$\begin{aligned}\langle q, \beta \rangle &= \beta_0 q_0 + \langle q_r, \beta_r \rangle = \beta_0 q_0 + \frac{\bar{\lambda}_0}{\bar{z}_0} \|\beta_r\|^2 + \frac{\bar{z}_0 - \bar{\lambda}_0}{2\bar{z}_0} \beta_0(\beta_0 - q_0) - \frac{\bar{z}_0 + \bar{\lambda}_0}{2\bar{z}_0} (q_0 + \beta_0)\beta_0 \\ &= -\frac{\bar{\lambda}_0}{\bar{z}_0} (\beta_0^2 - \|\beta_r\|^2) = \langle \mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda})u, u \rangle,\end{aligned}$$

which verifies (4.35) and thus completes the proof of assertion (i).

To justify assertion (ii), we proceed as in the corresponding proof of Lemma 4.6 and show that in the case of  $(\bar{z}, \bar{\lambda}) \in I_2$  inclusion (4.36) is satisfied.  $\triangle$

Considering now the general SOCP setting (1.1), define the *critical cone*

$$(4.38) \quad \mathcal{C}(\bar{x}, \bar{w}) := \left\{ u \in \mathbb{R}^n \mid \nabla_x \varphi_0(\bar{x}, \bar{w})u \leq 0, \nabla_x \Phi(\bar{x}, \bar{w})u \in T_{\mathcal{Q}}(\Phi(\bar{x}, \bar{w})) \right\}$$

at  $(\bar{x}, \bar{w})$  with  $\Phi(\bar{x}, \bar{w}) \in \mathcal{Q}$ . It is well known [3, Proposition 3.10] that that under the nondegeneracy condition (4.14) the critical cone (4.38) admits the representation

$$(4.39) \quad \mathcal{C}(\bar{x}, \bar{w}) = \left\{ u \in \mathbb{R}^n \mid \nabla_x \Phi(\bar{x}, \bar{w})u \in T_{\mathcal{Q}}(\Phi(\bar{x}, \bar{w})) \cap \bar{\lambda}^\perp \right\},$$

where  $\bar{\lambda}$  is a unique solution of the KKT system (4.11) with  $\bar{v}$  taken from (4.10). Furthermore, it is proved in [2, Theorem 30] that the nondegeneracy condition (4.14) ensures that

$$\text{span} \{ \mathcal{C}(\bar{x}, \bar{w}) \} = \left\{ u \in \mathbb{R}^n \mid \begin{array}{ll} \nabla_x \Phi^j(\bar{x}, \bar{w})u = 0 & \text{if } \bar{\lambda}^j \in \text{int } \mathcal{Q}_{m_j+1}, \\ \nabla_x \Phi^j(\bar{x}, \bar{w})u \in \mathbb{R}(\bar{\lambda}_0^j, -\bar{\lambda}_r^j) & \text{if } \bar{\lambda}^j \in \text{bd } \mathcal{Q}_{m_j+1} \setminus \{0\}, \bar{z}^j = 0, \\ \langle \nabla_x \Phi^j(\bar{x}, \bar{w})u, \bar{\lambda}^j \rangle = 0 & \text{if } \bar{\lambda}^j, \bar{z}^j \in \text{bd } \mathcal{Q}_{m_j+1} \setminus \{0\} \end{array} \right\}.$$

Assuming further the validity of the nondegeneracy condition (4.14) and following Bonnans and Ramírez [2] who considered the case when the basic perturbation parameter  $\bar{w}$  is absent, we say that the *strong second-order sufficient optimality condition* (SSOSC) holds at  $(\bar{x}, \bar{w})$  if

$$(4.40) \quad \langle u, \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u \rangle + \langle \mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda})u, u \rangle > 0 \text{ for all } u \in \text{span} \{ \mathcal{C}(\bar{x}, \bar{w}) \} \setminus \{0\}$$

with  $\mathcal{H}$  defined in (4.33). Note that condition (4.40) is an SOCP counterpart of the SSOSC condition first introduced by Robinson [31] for problems of nonlinear programming.

Now we are ready to establish the main result of this paper characterizing full stability of locally optimal solutions to SOCPs in terms of their initial data.

**Theorem 4.8 (SSOSC characterization of full stability for SOCPs).** *Let  $\bar{x}$  be a feasible solution to problem  $\mathcal{P}(\bar{w}, \bar{v})$  in (4.1) for some  $\bar{w} \in \mathbb{R}^d$  and  $\bar{v}$  satisfying (4.10) under the validity of the SOCQ/nondegeneracy condition at  $(\bar{x}, \bar{w})$ , and let  $\bar{\lambda} \in \mathbb{R}^l$  be the corresponding unique Lagrange multiplier satisfying the KKT system (4.11). Then  $\bar{x}$  is a fully stable locally optimal solution to (4.1) if and only if SSOSC (4.40) holds at  $(\bar{x}, \bar{w})$ .*

**Proof.** First we consider the case of just one Lorentz cone  $\mathcal{Q} = \mathcal{Q}_{m+1}$  in (1.1) and define the set-valued mapping  $\mathcal{T}(\bar{x}, \bar{w}, \bar{v}) = (\mathcal{T}_1(\bar{x}, \bar{w}, \bar{v}), \mathcal{T}_2(\bar{x}, \bar{w}, \bar{v})): \mathbb{R}^n \rightrightarrows \mathbb{R}^n \times \mathbb{R}^d$  by

$$(4.41) \quad \begin{cases} \mathcal{T}_1(\bar{x}, \bar{w}, \bar{v})(u) : &= \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u + \nabla_x \Phi(\bar{x}, \bar{w})^* \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u), \\ \mathcal{T}_2(\bar{x}, \bar{w}, \bar{v})(u) : &= \nabla_{xw}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u + \nabla_w \Phi(\bar{x}, \bar{w})^* \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u) \end{cases}$$

for all  $u \in \mathbb{R}^n$ , where  $\bar{z} = \Phi(\bar{x}, \bar{w})$  as usual. Let us start with justifying the “if” part of the theorem and suppose that SSOSC (4.40) holds. According to Lemma 4.5 we need to verify implication (4.23) for the mapping  $\mathcal{T}(\bar{x}, \bar{w}, \bar{v})$  in (4.41). This amounts to saying that

$$\langle p, u \rangle > 0 \quad \text{whenever} \quad p \in \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u + \nabla_x \Phi(\bar{x}, \bar{w})^* \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u), \quad u \neq 0,$$

which can be rewritten as follows:

$$(4.42) \quad \langle u, \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u \rangle + \langle q, \nabla_x \Phi(\bar{x}, \bar{w})u \rangle > 0$$

for all  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u)$  with  $u \neq 0$ .

To proceed, take any  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\beta_0, \beta_r)$  with  $u \neq 0$ , where we use the notation  $\beta = (\beta_0, \beta_r) =: \nabla_x \Phi(\bar{x}, \bar{w})u$ . This implies  $\beta \in \text{dom} \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})$ , and thus Lemma 4.6 and the above description of  $\text{span}\{\mathcal{C}(\bar{x}, \bar{w})\}$  tell us that  $u \in \text{span}\{\mathcal{C}(\bar{x}, \bar{w})\} \setminus \{0\}$ . Using the notation of that lemma, consider first the case of  $(\bar{z}, \bar{\lambda}) \in I_2$ , which gives us  $\mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda}) = 0$ . Thus the assumed SSOSC (4.40) reduces to  $\langle u, \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u \rangle > 0$  in this case. Using now Lemma 3.4(ii) and the second-order subdifferential representation (3.20) bring us to

$$\langle u, \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u \rangle + \langle q, \nabla_x \Phi(\bar{x}, \bar{w})u \rangle \geq \langle u, \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u \rangle + 0 > 0,$$

which shows that condition (4.42) is satisfied and thus  $\bar{x}$  is a fully stable local minimizer of  $\mathcal{P}(\bar{w}, \bar{v})$  by Lemma 4.5. Considering further the remaining case of  $(\bar{z}, \bar{\lambda}) \in I_1$  in Lemma 4.7, we deduce from it that  $\langle \mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda})u, u \rangle = \langle q, \nabla_x \Phi(\bar{x}, \bar{w})u \rangle$ , and so

$$\langle u, \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u \rangle + \langle q, \nabla_x \Phi(\bar{x}, \bar{w})u \rangle = \langle u, \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})u \rangle + \langle \mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda})u, u \rangle > 0$$

due to SSOSC (4.40), which brings us to (4.42) and hence justifies the “if” part of the theorem.

To prove the “only if” part, suppose that  $\bar{x}$  is a fully stable locally optimal solution to  $\mathcal{P}(\bar{w}, \bar{v})$ , which is obviously a usual local minimizer for this problem. Thus the well-known first-order necessary optimality conditions for  $\mathcal{P}(\bar{w}, \bar{v})$  under the assumed SOCQ/nondegeneracy condition (4.13) tells us that there is a unique vector  $-\bar{\lambda} \in N_{\mathcal{Q}_{m+1}}(\Phi(\bar{x}, \bar{w}))$  satisfying (4.11). It follows from Lemma 4.5 that condition (4.42) is satisfied for all  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u)$  with  $u \neq 0$ . Let us show that it implies the validity of SSOSC (4.40). To proceed, fix any  $u \in \text{span}\{\mathcal{C}(\bar{x}, \bar{w})\} \setminus \{0\}$  and observe that  $\beta = (\beta_0, \beta_r) \in \text{dom} \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda}) \neq \emptyset$  in the notation above. Considering the case of  $(\bar{z}, \bar{\lambda}) \in I_2$ , we deduce from Lemma 4.7(ii) that  $0 \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\nabla_x \Phi(\bar{x}, \bar{w})u)$ . Letting  $q = 0$  in (4.42) and taking into account that  $\mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda}) = 0$  allow us to conclude that (4.40) holds in this case. In the other case of  $(\bar{z}, \bar{\lambda}) \in I_1$ , consider the vector  $q := -\frac{\bar{\lambda}_0}{\bar{z}_0}(\beta_0, -\beta_r)$  and deduce from Lemma 4.7(i) that

$$\langle q, \beta \rangle = -\frac{\bar{\lambda}_0}{\bar{z}_0}(\beta_0^2 - \|\beta_r\|^2) = \langle \mathcal{H}(\bar{x}, \bar{w}, \bar{\lambda})u, u \rangle.$$

Similar to the proof of Case 3 in Lemma 4.6, we get that  $q \in \partial^2 \delta_{\mathcal{Q}_{m+1}}(\bar{z}, -\bar{\lambda})(\beta_0, \beta_r)$  and, substituting this vector into (4.42), arrive at SSOSC (4.40). This completes the proof of the theorem in the case of the single Lorentz cone  $\mathcal{Q} = \mathcal{Q}_{m+1}$  in (1.1).

It remains to consider the general case of the product cone (1.2) in (1.1). Define the mapping  $\mathcal{T}(\bar{x}, \bar{w}, \bar{v}) = (\mathcal{T}_1(\bar{x}, \bar{w}, \bar{v}), \mathcal{T}_2(\bar{x}, \bar{w}, \bar{v})): \mathbb{R}^n \rightrightarrows \mathbb{R}^n \times \mathbb{R}^d$  by (4.41) with replacing  $\mathcal{Q}_{m+1}$  by  $\mathcal{Q}$  therein. Then using the results above for one cone  $\mathcal{Q}_{m+1}$  in (1.1) and the product formula for the second-order subdifferential in Lemma 3.8. This completes the proof of the theorem.  $\triangle$

To conclude this section, observe that the calculations and results presented above are new also in the study of *tilt stability* for SOCPs when the basic perturbation parameter  $w$  is absent in (4.1) and thus its nominal value  $\bar{w}$  does not appear in the obtained characterizations. In this case the partial versions of SOQC (4.13) and (4.14) reduce to their full counterparts in (3.1) and (3.2), respectively, and the partial SSOSC (4.40) agrees with its nonparametric version from [2]. Thus the latter provides a characterization of tilt stability for SOCPs in accordance with Theorem 4.8 when the basic perturbation parameter is dropped.

## 5 Relationships with Strong Stability of Generalized Equations

In this section we address the relationship between full stability of local minimizers for  $\mathcal{P}(\bar{w}, \bar{v})$  in (4.1) and Robinson's notion of strong regularity for the associated parametric *KKT system* (4.11). We show that these notions are in fact *equivalent* under the imposed SOCQ/nondegeneracy condition. As a by-product of this result, we recover the SSOSC characterization of strong regularity obtained, via a completely different approach, by Bonnans and Ramírez [2].

Considering two closed and convex sets  $Z \subset \mathbb{R}^n$  and  $C \subset \mathbb{R}^p$ , recall [3, Definition 3.135] that  $Z \subset \mathbb{R}^n$  is  $\mathcal{C}^2$ -reducible at  $\bar{z} \in Z$  to  $C$  if there is a neighborhood  $U$  of  $\bar{z}$  and a  $\mathcal{C}^2$ -smooth mapping  $h: \mathbb{R}^n \rightarrow \mathbb{R}^p$  such that  $\delta_Z(z) = \delta_C(h(z))$  for all  $z \in U \cap Z$ , and the derivative operator  $\nabla h(\bar{z}): \mathbb{R}^n \rightarrow \mathbb{R}^p$  is surjective. If this holds for all  $z \in Z$ , then we say that  $Z$  is  $\mathcal{C}^2$ -reducible to  $C$ . It is proved in [2, Lemma 15] that the Lorentz cone  $\mathcal{Q}_{m+1}$  is  $\mathcal{C}^2$ -reducible at  $\bar{z} \in \mathcal{Q}_{m+1}$  to

$$K_m := \begin{cases} \mathcal{Q}_{m+1} & \text{if } \bar{z} = 0, \\ \{0\} & \text{if } \bar{z} \in \text{int } \mathcal{Q}_{m+1} \setminus \{0\}, \\ \mathbb{R}_- & \text{if } \bar{z} \in \text{bd } \mathcal{Q}_{m+1} \setminus \{0\}. \end{cases}$$

It readily implies that the product cone (1.2) is also  $\mathcal{C}^2$ -reducible at  $\bar{z} \in \mathcal{Q}$  to some closed and convex cone  $K \subset \mathbb{R}^s$ . This allows us to find a neighborhood  $U$  of  $\bar{z}$  and a  $\mathcal{C}^2$ -smooth mapping  $h: \prod_{j=1}^J \mathbb{R}^{j+1} \rightarrow \mathbb{R}^s$  with  $0 \leq s \leq \sum_{j=1}^J (m_j + 1)$ , such that

$$(5.1) \quad \begin{cases} \delta_{\mathcal{Q}}(z) = \delta_K(h(z)) \text{ for all } z \in U \cap \mathcal{Q} \text{ and} \\ \nabla h(\bar{z}): \prod_{j=1}^J \mathbb{R}^{j+1} \rightarrow \mathbb{R}^s \text{ is surjective.} \end{cases}$$

The following theorem is of its own interest while playing a crucial role in establishing the subsequent equivalence between full stability of SOCP (1.1) and Robinson's strong regularity of the associated KKT system with respect to canonical perturbations.

**Theorem 5.1 (equivalence between full stability of SOCP and Lipschitz continuity of the single-valued solution map to the associated KKT system).** *Let  $\bar{x}$  be a constraint nondegenerate point of SOCP (1.1). Then it is a fully stable locally optimal solution to problem  $\mathcal{P}(\bar{w}, \bar{v})$  in (4.1) with  $\bar{v}$  from (4.10) if and only if we have  $\bar{x} \in M_\gamma(\bar{w}, \bar{v})$  for some  $\gamma > 0$  and the solution map  $S_{KKT}: (w, v) \mapsto (x, \lambda)$  for the KKT system (4.11) is single-valued and Lipschitz continuous around  $(\bar{w}, \bar{v}, \bar{x}, \bar{\lambda})$ .*

**Proof.** To justify the “if” part of theorem, observe first that the nondegeneracy condition (4.14), and hence its SOCQ counterpart (4.13), follows for the local minimizer  $\bar{x} \in M_\gamma(\bar{v}, \bar{w})$  from the strong regularity of (4.11) due to [3, Theorem 5.24]. Since RCQ (4.5) is obviously fulfilled in this

setting, Theorem 4.2 tells us that  $\bar{x}$  is a fully stable local minimizer of  $\mathcal{P}(\bar{w}, \bar{v})$  provided that the subgradient mapping  $\partial_x \varphi$  from (4.8) is PSMR at  $(\bar{x}, \bar{w}, \bar{v})$  for  $\bar{v}$  from (4.10). To verify the latter property, it is easy to see that the local single-valuedness and Lipschitz continuity of the KKT solution map  $S_{KKT}$  around  $(\bar{w}, \bar{v}, \bar{x}, \lambda)$  implies, by using the calculus rules in (4.11) similarly to deriving (4.8), that the partial inverse mapping (4.9) admits a single-valued Lipschitzian localization around  $(\bar{x}, \bar{w}, \bar{v})$ . But this exactly means the claimed PSMR of  $\partial_x \varphi$ .

To prove the “only if” part of the theorem, suppose that  $\bar{x}$  is a fully stable local minimizer of  $\mathcal{P}(\bar{w}, \bar{v})$ . Then we have  $\bar{x} \in M_\gamma(\bar{v}, \bar{w})$  and it follows from the nondegeneracy condition that the mapping  $S_{KKT}$  is single-valued on some neighborhood  $W \times V$  of  $(\bar{w}, \bar{v})$ , i.e.,  $S_{KKT}(w, v) = \{(x_{wv}, \lambda_{wv})\}$  therein. Note further that the Lipschitz continuity of the mapping  $(w, v) \mapsto x_{wv}$  around  $(\bar{x}, \bar{w})$  follows directly from the full stability of  $\bar{x}$  in (4.1). Thus it remains to verify that the mapping  $(w, v) \mapsto \lambda_{wv}$  is Lipschitz continuous around  $(\bar{w}, \bar{v})$  as well.

To proceed, observe that due the validity of RCQ (4.5) in this setting there is a positive number  $\rho < \infty$  such that  $\|\lambda_{wv}\| \leq \rho$  for all  $(w, v) \in W \times V$ . Let  $\ell > 0$  be a common Lipschitz constant for the mappings  $\nabla_x \varphi_0$ ,  $\nabla_x \Phi$ , and  $(w, v) \mapsto x_{wv}$  on  $W \times V$ . Due to reducibility (5.1) of the cone  $\mathcal{Q}$  at  $\bar{z} = \Phi(\bar{x}, \bar{w})$  we have

$$(5.2) \quad N_{\mathcal{Q}}(z) = \nabla h(z)^* N_K(h(z)) \quad \text{whenever } z \in U \cap \mathcal{Q}$$

with  $\text{rank } \nabla h(\bar{z}) = s$ . This easily implies (see [3, p. 315]) that the Jacobian matrix  $\nabla_x \psi(\bar{x}, \bar{w})$  for the composition  $\psi := h \circ \Phi$  is of full rank  $s$ .

Pick now any  $w_1, w_2 \in W$  and  $v_1, v_2 \in V$  and denote  $z_i := \Phi(x_{w_i v_i}, w_i)$  for  $i = 1, 2$ . It follows from (5.2) and the composite representation  $\delta_{\mathcal{Q}} \circ \Phi = \delta_K \circ \psi$  that there are unique normals  $\mu_{w_i v_i} \in N_K(h(z_i))$  for  $i = 1, 2$  satisfying the conditions

$$(5.3) \quad \lambda_{w_i v_i} = \nabla h(z_i)^* \mu_{w_i v_i} \quad \text{and} \quad \nabla_x \Phi(x_{w_i v_i}, w_i)^* \lambda_{w_i v_i} = \nabla_x \psi(x_{w_i v_i}, w_i)^* \mu_{w_i v_i}, \quad i = 1, 2,$$

which readily ensure the equations

$$\begin{cases} v_2 = \nabla_x \varphi_0(x_{w_2 v_2}, w_2) + \nabla_x \Phi(x_{w_2 v_2}, w_2)^* \lambda_{w_2 v_2} = \nabla_x \varphi_0(x_{w_2 v_2}, w_2) + \nabla_x \psi(x_{w_2 v_2}, w_2)^* \mu_{w_2 v_2} \\ v_1 = \nabla_x \varphi_0(x_{w_1 v_1}, w_1) + \nabla_x \Phi(x_{w_1 v_1}, w_1)^* \lambda_{w_1 v_1} = \nabla_x \varphi_0(x_{w_1 v_1}, w_1) + \nabla_x \psi(x_{w_1 v_1}, w_1)^* \mu_{w_1 v_1}. \end{cases}$$

Combining the above relationships, we arrive at

$$(5.4) \quad \begin{aligned} \nabla_x \psi(x_{w_2 v_2}, w_2)^* (\mu_{w_2 v_2} - \mu_{w_1 v_1}) &= \left( \nabla_x \psi(x_{w_1 v_1}, w_1) - \nabla_x \psi(x_{w_2 v_2}, w_2) \right)^* \mu_{w_1 v_1} \\ &+ \nabla_x \varphi_0(x_{w_1 v_1}, w_1) - \nabla_x \varphi_0(x_{w_2 v_2}, w_2) + v_2 - v_1. \end{aligned}$$

Having  $\text{rank } \nabla_x \psi(\bar{x}, \bar{w}) = s \leq n$ , we can always reduce the situation to the square case of  $s = n$ . Indeed, when  $s < n$  construct a linear mapping  $\tilde{\psi}: \mathbb{R}^n \times \mathbb{R}^d \rightarrow \mathbb{R}^{n-s}$  such that the matrix

$$(5.5) \quad \bar{\psi}(x, w) := (\psi(x, w), \tilde{\psi}(x, w)): \mathbb{R}^n \times \mathbb{R}^d \longrightarrow \mathbb{R}^n$$

has full rank for any fixed  $(x, w)$  close to  $(\bar{x}, \bar{w})$ . We do it by taking an orthogonal basis  $\{b_1, \dots, b_{n-s}\}$  in the  $(n-s)$ -dimensional space  $\{u \in \mathbb{R}^n \mid \nabla_x \psi(\bar{x}, \bar{w})u = 0\}$  and then defining  $\tilde{\psi}(x, w) := (\langle b_1, x \rangle, \dots, \langle b_{n-s}, x \rangle)$ . Denote further  $\bar{\delta}_K(z, q) := \delta_K(z)$  for all  $z \in \mathbb{R}^s$  and  $q \in \mathbb{R}^{n-s}$ . Employ now an elementary first-order chain rule for “full rank” compositions yields

$$\begin{aligned} \partial_x (\bar{\delta}_K \circ \bar{\psi})(x, w) &= \nabla_x \bar{\psi}(x, w)^* \partial \bar{\delta}_K(\bar{\psi}(x, w)) \\ &= \left( \nabla_x \psi(x, w)^*, b_1, \dots, b_{n-s} \right) \begin{pmatrix} \partial \delta_K(z) \\ 0^{n-s} \end{pmatrix} \\ &= \nabla_x \psi(x, w)^* N_K(z) \end{aligned}$$



with  $z = \psi(x, w)$ . This ensures the existence of the unique subgradients  $\zeta_1 \in \partial\bar{\delta}_K(z'_1)$  and  $\zeta_2 \in \partial\bar{\delta}_K(z'_2)$  such that  $z'_1 = \bar{\psi}(x_{w_1v_1}, w_1)$ ,  $z'_2 = \bar{\psi}(x_{w_2v_2}, w_2)$ , and

$$(5.6) \quad \nabla_x \psi(x_{w_i v_i}, w_i)^* \mu_{w_i v_i} = \nabla_x \bar{\psi}(x_{w_i v_i}, w_i)^* \zeta_i \quad \text{with } \zeta_i = (\mu_{w_i v_i}, 0^{n-s}), \quad i = 1, 2.$$

Combining the above relationships with (5.4), we deduce that

$$(5.7) \quad \begin{aligned} \nabla_x \bar{\psi}(x_{w_2 v_2}, w_2)^* (\zeta_2 - \zeta_1) &= \left( \nabla_x \bar{\psi}(x_{w_1 v_1}, w_1) - \nabla_x \bar{\psi}(x_{w_2 v_2}, w_2) \right)^* \zeta_1 \\ &+ \nabla_x \varphi_0(x_{w_1 v_1}, w_1) - \nabla_x \varphi_0(x_{w_2 v_2}, w_2) + v_2 - v_1. \end{aligned}$$

Since the mapping  $\bar{\psi}$  in (5.5) is invertible in  $x$ , we apply to it the standard inverse function theorem and arrive at

$$(5.8) \quad \begin{aligned} \|\zeta_2 - \zeta_1\| &\leq \left\| \left( \nabla_x \bar{\psi}(x_{w_2 v_2}, w_2)^* \right)^{-1} \right\| \left( \left\| \nabla_x \bar{\psi}(x_{w_1 v_1}, w_1) - \nabla_x \bar{\psi}(x_{w_2 v_2}, w_2) \right\| \cdot \|\mu_{w_1 v_1}\| \right. \\ &+ \left. \left\| \nabla_x \varphi_0(x_{w_1 v_1}, w_1) - \nabla_x \varphi_0(x_{w_2 v_2}, w_2) \right\| + \|v_2 - v_1\| \right) \\ &\leq \gamma \left[ \|\mu_{w_1 v_1}\| \ell \left( \|x_{w_2 v_2} - x_{w_1 v_1}\| + \|w_2 - w_1\| \right) \right. \\ &+ \left. \ell \left( \|x_{w_2 v_2} - x_{w_1 v_1}\| + \|w_2 - w_1\| \right) + \|v_2 - v_1\| \right] \end{aligned}$$

by substituting (5.6) into (5.4), where  $\gamma > 0$  is an upper bound of  $\|(\nabla_x \bar{\psi}(x, w)^*)^{-1}\|$  over  $(x, w)$  near  $(\bar{x}, \bar{w})$ . Since  $\|\lambda_{wv}\| \leq \rho$  for  $(w, v) \in W \times V$ ,  $\lambda_{w_i v_i} = \nabla h(z_i)^* \mu_{w_i v_i}$  for  $i = 1, 2$ , and  $\nabla h(\bar{z})$  is of full rank, we find arguing as above that there is  $\check{h}: \prod_{j=1}^J \mathbb{R}^{j+1} \rightarrow \prod_{j=1}^J \mathbb{R}^{j+1}$  such that

$$(5.9) \quad \partial(\check{\delta}_K \circ \check{h})(z) = \nabla \check{h}(z)^* \partial \check{\delta}_K(\check{h}(z)) = \nabla h(z)^* N_K(h(z))$$

with  $\check{\delta}_K(z, q) := \delta_K(z)$  for all  $z \in \mathbb{R}^s$  and  $q \in \mathbb{R}^{\sum_{j=1}^J (m_j+1)-s}$ . This gives us

$$(5.10) \quad \lambda_{w_i v_i} = \nabla h(z_i)^* \mu_{w_i v_i} = \nabla \check{h}(z_i)^* \check{\mu}_{w_i v_i}$$

with  $\check{\mu}_{w_i v_i} \in \partial \check{\delta}_K(\check{h}(z)) = (N_K(h(z)), 0^{\sum_{j=1}^J (m_j+1)-s})$ , which ensures in turn that

$$(5.11) \quad \check{\mu}_{w_i v_i} = (\mu_{w_i v_i}, 0^{\sum_{j=1}^J (m_j+1)-s}).$$

Using now (5.10) and (5.11) together with the classical inverse function theorem for the mapping  $\check{h}$  invertible in  $x$  tells us that the family of  $\{\mu_{wv}\}$  is uniformly bounded when the pairs  $(w, v)$  are close enough to  $(\bar{w}, \bar{v})$ . Without loss of generality, suppose that

$$(5.12) \quad \|\mu_{wv}\| \leq \rho, \quad \text{for all } (w, v) \in W \times V.$$

Also the equalities in (5.3) imply the relationships

$$(5.13) \quad \begin{aligned} \|\lambda_{w_2 v_2} - \lambda_{w_1 v_1}\| &= \|\nabla h(z_2)^* \mu_{w_2 v_2} - \nabla h(z_1)^* \mu_{w_1 v_1}\| \\ &\leq \|\nabla h(z_2)^*\| \cdot \|\mu_{w_2 v_2} - \mu_{w_1 v_1}\| + \|\nabla h(z_2) - \nabla h(z_1)\| \cdot \|\mu_{w_1 v_1}\| \\ &\leq \tau \|\mu_{w_2 v_2} - \mu_{w_1 v_1}\| + \rho \ell' \left( \|x_{w_2 v_2} - x_{w_1 v_1}\| + \|w_2 - w_1\| \right) \\ &\leq \tau \|\zeta_2 - \zeta_1\| + \rho \ell' \left( \|x_{w_2 v_2} - x_{w_1 v_1}\| + \|w_2 - w_1\| \right), \end{aligned}$$

where  $\tau > 0$  is an upper bound of  $\|\nabla h(z)^*\|$  for all  $z$  sufficiently close to  $\bar{z}$ , and where  $\ell' > 0$  is a Lipschitz constant for the mapping  $\nabla h$  around  $\bar{z}$ .

Combining finally the estimates in (5.8), (5.12), and (5.13) with the local Lipschitz continuity of the mapping  $(w, v) \mapsto x_{wv}$  allows us to conclude that  $(w, v) \mapsto \lambda_{wv}$  is Lipschitz continuous around  $(\bar{w}, \bar{v})$ , which thus completes the proof of the theorem.  $\triangle$

It is easy to see that the given proof of Theorem 5.1 does not exploit specific features of SOCPs in (1.1) and holds true for any  $\mathcal{C}^2$ -reducible cones generating problems of conic programming.

Following Robinson [31], we say that the pair  $(\bar{x}, \bar{\lambda})$  is *strongly regular* for the KKT system (4.11) if the solution map to the *linearized* generalized equation

$$(5.14) \quad \begin{bmatrix} v_1 \\ v_2 \end{bmatrix} \in \begin{bmatrix} \nabla_{xx}^2 L(\bar{x}, \bar{w}, \bar{\lambda})(x - \bar{x}) - \nabla_x \Phi(\bar{x}, \bar{w})^*(\lambda - \bar{\lambda}) \\ -\Phi(\bar{x}, \bar{w}) - \nabla_x \Phi(\bar{x}, \bar{w})(x - \bar{x}) \end{bmatrix} + \begin{bmatrix} 0 \\ N_{\mathcal{Q}}(\lambda) \end{bmatrix}$$

has a Lipschitz continuous single-valued localization around  $(0, 0) \in \mathbb{R}^n \times \mathbb{R}^s$ .

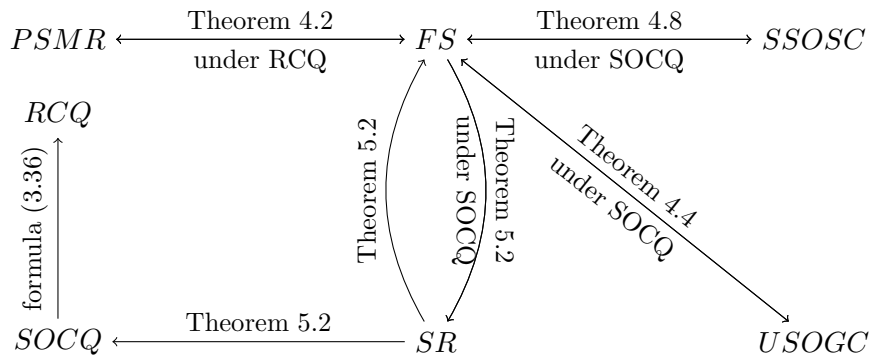
**Theorem 5.2 (equivalence between full stability and strong regularity for SOCPs under the nondegeneracy condition).** *Let  $(\bar{x}, \bar{w})$  be a feasible solution to  $\mathcal{P}(\bar{w}, \bar{v})$  with  $\bar{v}$  satisfying (4.10), and let  $\bar{\lambda} \in \mathbb{R}^s$  be a unique Lagrange multiplier of the KKT system (4.11). Imposing the nondegeneracy condition (4.14), or the SOCQ condition (4.13), we have that  $\bar{x}$  is a fully stable locally optimal solution to  $\mathcal{P}(\bar{w}, \bar{v})$  if and only if  $\bar{x} \in M_\gamma(\bar{w}, \bar{v})$  for some  $\gamma > 0$  and  $(\bar{x}, \bar{\lambda})$  is a strongly regular solution to (4.11). Furthermore, this strong regularity implies the validity of the SOCQ/nondegeneracy condition for SOCPs.*

**Proof.** Note that the generalized equation (5.14) can be considered as a linearization of the *canonically perturbed* KKT system (4.11) as follows:

$$(5.15) \quad \begin{bmatrix} v_1 \\ v_2 \end{bmatrix} \in \begin{bmatrix} \nabla_x L(x, \bar{w}, \lambda) \\ -\Phi(x, \bar{w}) \end{bmatrix} + \begin{bmatrix} 0 \\ N_{\mathcal{Q}}(\lambda) \end{bmatrix}$$

with the perturbation pair  $(v_1, v_2)$  varied around  $(\bar{v}, 0) \in \mathbb{R}^n \times \mathbb{R}^s$ . It has been well recognized in optimization theory (see, e.g., [6, Theorem 2B.10]) that the single-valuedness and Lipschitz continuity of the canonically perturbed GE/KKT system is equivalent to these properties of its linearization (5.14). Taking into account this result regarding systems (5.15) and (5.14) and applying Theorem 5.1 to the solution map  $S_{KKT}(v_1, v_2) \mapsto (x, \lambda)$  of the canonically perturbed KKT system (5.15), we arrive at the claimed equivalence. It is a general fact of conic programming (see, e.g., [3, Theorem 5.24]) that strong regularity implies nondegeneracy, which also ensures the validity of SOCQ in the SOCP setting by Theorem 3.9.  $\triangle$

For the reader's convenience we present now the diagram on relationships between the main properties considered in this paper. Here the symbols FS and SR stand for full stability and strong regularity, respectively, while the other abbreviations have been defined earlier.



Finally in this section, we give two examples illustrating some important features of full stability for SOCPs and its relationships with strong regularity. The first example shows that, for the same SOCP, one local minimizer is fully stable while another is not under the validity of the nondegeneracy condition for both of them.

**Example 5.3 (full stability for different local minimizers under nondegeneracy).** For the three-dimensional SOCP (1.1) consider the corresponding problem  $\mathcal{P}(w, v)$  in (4.1) given by

$$\mathcal{P}(w, v) \begin{cases} \text{minimize} & \frac{1}{2}\|u - a(w)\|^2 + \frac{1}{2}\|z - b(w)\|^2 + wu_1z_1 - \langle v, (u, z) \rangle \\ \text{subject to} & \\ & u \in \mathcal{Q}_3, z \in \mathcal{Q}_3, \end{cases}$$

where  $x := (u, z) \in \mathbb{R}^3 \times \mathbb{R}^3$ ,  $w \in \mathbb{R}$ , and

$$a(w) := \begin{bmatrix} w \\ \frac{w}{1+w} \\ 0 \end{bmatrix}, \quad b(w) := \begin{bmatrix} w \\ 0 \\ \frac{w}{1+w} \end{bmatrix}.$$

Taking the reference perturbation pair  $(\bar{w}, \bar{v}) = (0.5, 0^{\mathbb{R}^6})$ , it is easy to verify that  $\bar{x} = (\bar{u}, \bar{z}) = (\frac{1}{3}, \frac{1}{3}, 0, \frac{1}{3}, 0, \frac{1}{3})$  is a nondegenerate local minimizer of  $\mathcal{P}(\bar{w}, \bar{v})$  and that  $\bar{\lambda} = 0$  is the corresponding (unique) Lagrange multiplier of the KKT system (4.11). As shown in [28, Table 4.1], the given point  $(\bar{x}, \bar{\lambda})$  is strongly regular for (4.11). Thus it follows from Theorem 5.2 that  $\bar{x}$  is a fully stable locally optimal solution to the problem  $\mathcal{P}(\bar{w}, \bar{v})$  under consideration.

Consider now the perturbation pair  $(\tilde{w}, \tilde{v}) = (1, 0^{\mathbb{R}^6})$ . In this case we check that  $\tilde{x} = (\tilde{u}, \tilde{z}) = (0.5, 0.5, 0, 0.5, 0, 0.5)$  is a nondegenerate minimizer of  $\mathcal{P}(\tilde{w}, \tilde{v})$  and, again,  $\bar{\lambda} = 0$  is the corresponding (unique) Lagrange multiplier of the associated KKT system (4.11). Applying [2, Theorem 30] allows us to conclude that the pair  $(\tilde{x}, \bar{\lambda})$  is not strongly regular for (4.11), and thus Theorem 5.2 shows that  $\tilde{x}$  is not a fully stable locally optimal solution to  $\mathcal{P}(\tilde{w}, \tilde{v})$ .

The second example demonstrates that full stability is indeed a broader concept than strong regularity for SOCPs in the *absence of nondegeneracy*.

**Example 5.4 (full stability without strong regularity).** In the full stability framework, consider the following problem  $\mathcal{P}(w, v)$  for the two-dimensional SOCP:

$$\mathcal{P}(w, v) \begin{cases} \text{minimize} & -x - vx \\ \text{subject to} & \\ & \begin{bmatrix} 1 - x \\ 1 - w \end{bmatrix} \in \mathcal{Q}_2 \end{cases}$$

with  $x, w, v \in \mathbb{R}$ . Picking the reference perturbation pair  $(\bar{w}, \bar{v}) = (1, 0)$ , it is easy to see that  $\bar{x} = 1$  is the unique minimizer for  $\mathcal{P}(\bar{w}, \bar{v})$ , which is not nondegenerate but satisfies RCQ (4.5). To examine the full stability in this case, we invoke Theorem 4.2 and check the PSMR property of the corresponding partial subgradient mapping

$$(5.16) \quad \partial_x \varphi(x, w) := -1 - [-1, 0]N_{\mathcal{Q}_2} \left( \begin{bmatrix} 1 - x \\ 1 - w \end{bmatrix} \right).$$

Denote by  $G: \mathbb{R} \times \mathbb{R} \rightrightarrows \mathbb{R}$  the partial inverse (4.7) of the mapping  $\partial_x \varphi$  in (5.16). It readily follows from (5.16) that there are neighborhoods  $\mathcal{W}$  of  $\bar{w}$  and  $\mathcal{V}$  of  $\bar{v}$  on which the mapping  $G$  is single-valued and admits the representation

$$G(w, v) = \begin{cases} w & \text{for } w \leq 1, \\ 1 - w & \text{for } w > 1, \end{cases}$$

which shows that the mapping  $\partial_x \varphi$  is PSMR at  $(\bar{x}, \bar{w}, \bar{v})$ . Thus we deduce from Theorem 4.2 that  $\bar{x} = 1$  is a fully stable locally optimal solution to the problem  $\mathcal{P}(\bar{w}, \bar{v})$  under consideration. Observe further that the corresponding KKT system (4.11) attains the form

$$(5.17) \quad v = -1 - [-1, 0]\lambda, \quad -\lambda \in N_{\mathcal{Q}_2} \left( \begin{bmatrix} 1 - x \\ 1 - w \end{bmatrix} \right).$$

It is easy to see that the triple  $(\bar{x}, \bar{w}, \bar{v})$  satisfies (5.17) along with *any* vector  $\lambda \in \mathcal{Q}_2$  whose first component amounts to 1, and thus the solution map to the linearized system (5.14) is not single-valued. This shows that strong regularity is violated in this case, and thus full stability is a broader concept than strong regularity for SOCPs in the absence of nondegeneracy.

## 6 Concluding Remarks

This paper presents several second-order characterizations of the important notion of full stability for locally optimal solutions to the general problems of second-order cone programming. The main result, Theorem 4.8, describes necessary and sufficient conditions for full stability entirely in terms of the initial data of SOCPs under the constraint nondegeneracy, which happens to be equivalent to the second-order constrained qualification appeared in the core theory of second-order variational calculus. The interplay between general forms of second-order variational analysis and generalized differentiation from one side and their specific implementations in the SOCP framework is one of the major themes of this paper. It is worth mentioning that most of the results obtained in this paper including the main Theorem 4.8 are also new for tilt stability of locally optimal solutions to SOCPs, which is a more narrow notion than full stability.

Among the most challenging issues of further research is to study full and tilt stability for SOCPs without the *nondegeneracy* assumption, which reduces to the classical (and rather restrictive) LICQ condition for NLPs. In the latter framework the LICQ condition has been recently essentially relaxed in the study of tilt and full stability by exploiting some specific features of nonlinear programs; see [21, 22, 24]. It seems to be highly important to relax the SOCQ/nondegeneracy assumption for tilt and full stability of SOCPs and other remarkable classes of problems in conic programming.

On the other hand, the established equivalence between full/tilt stability and strong regularity under the nondegeneracy condition opens the gate to the broad usage of the former in numerical applications. Furthermore, it has been well recognized in optimization that nondegeneracy is in fact *necessary* for strong regularity while is not the case for tilt and full stability. Thus the latter stability notions promise to be an efficient tool of qualitative and numerical analysis of optimization problems even in the absence of nondegeneracy and strong regularity.

**Acknowledgement.** The authors are gratefully indebted to Tran Nghia for helpful discussions on the topics and results of this paper, particularly those related to Theorem 5.2.

## References

- [1] F. ALIZADEH and D. GOLDFARB, *Second-order cone programming*, Math. Program., 95 (2003), pp. 3–51.
- [2] J. F. BONNANS and H. RAMÍREZ C., *Perturbation analysis of second-order cone programming problems*, Math. Program., 104 (2005), pp. 205–227.
- [3] J. F. BONNANS and A. SHAPIRO, *Perturbation Analysis of Optimization Problems*, Springer, New York, 2000.

- [4] H. COLOMBO, R. HENRION, N. D. HOANG and B. S. MORDUKHOVICH, *Optimal control of the sweeping process over polyhedral controlled sets*, preprint (2013).
- [5] A. L. DONTCHEV and R. T. ROCKAFELLAR, *Characterizations of strong regularity for variational inequalities over polyhedral convex sets*, SIAM J. Optim., 6 (1996), pp. 1087–1105.
- [6] A. L. DONTCHEV and R. T. ROCKAFELLAR, *Implicit Functions and Solution Mappings: A View from Variational Analysis*, Springer, Dordrecht, 2009.
- [7] D. DRUSVYATSKIY and A. S. LEWIS, *Tilt stability, uniform quadratic growth, and strong metric regularity of the subdifferential*, SIAM J. Optim., 23 (2013), pp. 256–267.
- [8] D. DRUSVYATSKIY, B. S. MORDUKHOVICH and T. T. A. NGHIA, *Second-order growth, tilt stability, and metric regularity of the subdifferential*, preprint (2013); [http://www.optimization-online.org/DB\\_HTML/2013/04/3848.html](http://www.optimization-online.org/DB_HTML/2013/04/3848.html)
- [9] A. C. EBERHARD and R. WENCZEL, *A study of tilt-stable optimality and sufficient conditions*, Nonlinear Anal., 75 (2012), pp. 1260–1281.
- [10] J. FARAUT and A. KORANYI, *Analysis on Symmetric Cones*, Oxford University Press, New York, 1994.
- [11] A. B. LEVY and B. D. MORDUKHOVICH, *Coderivatives in parametric optimization*, Math. Program., 99 (2004), pp. 311–327.
- [12] A. B. LEVY, R. A. POLIQUIN and R. T. ROCKAFELLAR, *Stability of locally optimal solutions*, SIAM J. Optim., 10 (2000), pp. 580–604.
- [13] A. S. LEWIS and S. ZHANG, *Partial smoothness, tilt stability, and generalized Hessians*, SIAM J. Optim., 23 (2013), pp. 74–94.
- [14] F. MENG, D. SUN and G. ZHAO, *Semismoothness of solutions to generalized equations and the Moreau-Yosida regularization*, Math. Program., 104 (2005), pp. 561–581.
- [15] B. S. MORDUKHOVICH, *Maximum principle in problems of time optimal control with nonsmooth constraints*, J. Appl. Math. Mech., 40 (1976), pp. 960–969.
- [16] B. S. MORDUKHOVICH, *Metric approximations and necessary optimality conditions for general classes of extremal problems*, Soviet Math. Dokl., 22 (1980), pp. 526–530.
- [17] B. S. MORDUKHOVICH, *Sensitivity analysis in nonsmooth optimization*, in Theoretical Aspects of Industrial Design, D. A. Field and V. Komkov (eds.), Proceedings in Applied Mathematics, Vol. 58, SIAM, Philadelphia, 1992, pp. 32–46.
- [18] B. S. MORDUKHOVICH, *Variational Analysis and Generalized Differentiation, I: Basic Theory; II: Applications*, Springer, Berlin, 2006.
- [19] B. S. MORDUKHOVICH and N. M. NAM and N. T. Y. NHI, *Partial second-order subdifferentials in variational analysis and optimization*, Numer. Func. Anal. Optim., to appear.
- [20] B. S. MORDUKHOVICH and T. T. A. NGHIA, *Second-order variational analysis and characterizations of tilt-stable optimal solutions in infinite-dimensional spaces*, Nonlinear Anal., 86 (2013), pp. 159–180.
- [21] B. S. MORDUKHOVICH and T. T. A. NGHIA, *Second-order characterizations of tilt stability with applications to nonlinear programmings*, preprint (2013).
- [22] B. S. MORDUKHOVICH and T. T. A. NGHIA, *Full Lipschitzian and Hölderian stability in optimization with applications to mathematical programming and optimal control*, preprint (2013).
- [23] B. S. MORDUKHOVICH and J. V. OUTRATA, *Coderivative analysis of quasi-variational inequalities with applications to stability and optimization*, SIAM J. Optim., 18 (2007), pp. 380–412.
- [24] B. S. MORDUKHOVICH and J. V. OUTRATA, *Tilt stability in nonlinear programming under Mangasarian-Fromovitz constraint qualification*, Kybernetika, 49 (2013), pp. 446–464.

- [25] B. S. MORDUKHOVICH, J. V. OUTRATA and H. RAMÍREZ C., Second-order variational analysis in conic programming with applications to optimality and stability, preprint (2012); [http://www.optimization-online.org/DB\\_HTML/2013/01/3723.html](http://www.optimization-online.org/DB_HTML/2013/01/3723.html)
- [26] B. S. MORDUKHOVICH and R. T. ROCKAFELLAR, *Second-order subdifferential calculus with application to tilt stability in optimization*, SIAM J. Optim., 22 (2012), pp. 953–986.
- [27] B. S. MORDUKHOVICH, R. T. ROCKAFELLAR and M. E. SARABI, *Characterizations of full stability in constrained optimization*, SIAM J. Optim., to appear.
- [28] J. V. OUTRATA and H. RAMÍREZ C., *On the Aubin property of critical points to perturbed second-order cone programs*, SIAM J. Optim., 21 (2011), pp. 798–823.
- [29] J. V. OUTRATA and D. SUN, *On the coderivative of the projection operator onto the second-order cone*, Set-Valued Anal., 17 (2009), pp. 999–1014.
- [30] R. A. POLIQUIN and R. T. ROCKAFELLAR, *Tilt stability of a local minimum*, SIAM J. Optim., 8 (1998), pp. 287–299.
- [31] S. M. ROBINSON, *Strongly regular generalized equations*, Math. Oper. Res., 5 (1980), pp. 43–62.
- [32] S. M. ROBINSON, *Local structure of feasible sets in nonlinear programming, part II: Nondegeneracy*, Math. Program. Study, 22 (1984), pp. 217–230.
- [33] R. T. ROCKAFELLAR and R. J-B. WETS, *Variational Analysis*, Springer, Berlin, 2006.