Exact approaches for convex adjustable robust optimization

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Abstract. Adjustable Robust Optimization (ARO) is a paradigm for facing uncertainty in a decision problem, in case some recourse actions are allowed after the actual value of all input parameters is revealed. While several approaches have been introduced for the linear case, little is known regarding exact methods for the convex case. In this work, we introduce a new general framework for attacking ARO problems involving convex functions in the recourse problem. We first recall a semi-infinite reformulation of the problem and, provided that one can solve a non-convex separation problem, show how to solve it either by a generalized Benders decomposition or by a column-and-constraint generation approach. We show that, for the relevant case where the uncertainty set is a polytope, the separation problem can be reformulated as a convex Mixed-Integer Nonlinear Problem, thus allowing us to derive computationally sound exact methods. Finally, we apply the resulting algorithms to two different applications, namely a nonlinear facility location problem and a nonlinear resource allocation problem, to numerically assess their computational performance.

1. Introduction

Adjustable Robust Optimization (ARO) is a paradigm used to face uncertainty in case some recourse actions are allowed after the actual value of all input parameters is revealed. An ARO problem can be formulated as

$$\inf_{\boldsymbol{x}\in X} \quad \sup_{\boldsymbol{\xi}\in\Xi} \quad \inf_{\boldsymbol{y}\in Y(\boldsymbol{x},\boldsymbol{\xi})} \quad g_0(\boldsymbol{x},\boldsymbol{y}), \tag{P}$$

in which X denotes the feasible set of decisions to be taken here and now (first-stage decisions), Ξ is the uncertainty set, and $Y(\boldsymbol{x},\boldsymbol{\xi})$ is the set of all feasible recourse actions (second-stage decisions) for a given $\boldsymbol{x}\in X$ and $\boldsymbol{\xi}\in\Xi$. In this paper we consider a broad class of ARO problems, characterised by convex objective function g_0 and second stage feasible set. For this class of problems, we devise solution approaches based on separation of first-stage decisions via a cutting planes approach. We show that, for the relevant case where Ξ is a polytope, the separation problem can be formulated as a convex Mixed-Integer Nonlinear Problem (MINLP).

Notations. Matrices and vectors are written in bold case, e.g., $\boldsymbol{A}\in\mathbb{R}^{m\times n}$ and $\boldsymbol{b}\in\mathbb{R}^m$, while scalars are written in normal font, e.g., a_{ij} and b_i. We use $\leq$ to compare vectors of agreeable size, component-wise and let $\boldsymbol{0}$ be the zero-vector of appropriate size (which will be clear from the context). We denote by $\overline{\mathbb{R}}$ the extended real line $\mathbb{R}\cup\{-\infty,\infty\}$. For a given function $f:\mathbb{R}^n\to\overline{\mathbb{R}}$, f^* denotes its convex conjugate defined as

$$f^*(\boldsymbol{y}) := \sup_{\boldsymbol{x}\in\mathrm{dom}(f)} \left\{\boldsymbol{y}^\top\boldsymbol{x} - f(\boldsymbol{x})\right\}$$

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with $\text{dom}\,(f) := \{\boldsymbol{x} \in \mathbb{R}^n : f(\boldsymbol{x}) < +\infty\}$ its domain. Similarly, we let f_* denote its concave conjugate defined as

$$f_*(\boldsymbol{y}) = \inf_{x \in \text{dom}(-f)} \{\boldsymbol{y}^\top \boldsymbol{x} - f(\boldsymbol{x})\}.$$

Assuming that f is real-valued, its associated perspective function $h : \mathbb{R}^n \times \mathbb{R}_{\geq 0} \to \mathbb{R}$ is defined as $h(x,t) := tf(x/t)$ if $t > 0$, and $h(x,0) := \liminf_{(v',t')\to(v,0)} t'f(v'/t')$; see Rockafellar (1996), p. 67. For ease of exposition, we use $tf(x/t)$ to denote the perspective function $h(x,t)$ in the rest of this paper. For a given convex set S, we let vert (S) denote the set of extreme points of S, and we let relint(S) denote its relative interior. We recall that a 0-1 polytope is a polytope whose extreme points are binary vectors.

1.1. **Assumptions.** Let n_X, n_Ξ, n_Y and m be given natural numbers, we make the following assumptions.

Assumption 1. *For each $i = 1, \dots, m$ and $j = 1, \dots, n_\Xi$, we let $f_{ij} : \mathbb{R}^{n_X} \to \mathbb{R}$ be given real-valued convex functions; for a given $\boldsymbol{x} \in \mathbb{R}^{n_X}$, we denote by $\boldsymbol{F}(\boldsymbol{x})$ the $m \times n_\Xi$ matrix whose generic element is $f_{ij}(\boldsymbol{x})$. Similarly, for each $i = 1, \dots, m$, we let $g_i : \mathbb{R}^{n_X + n_Y} \to \mathbb{R}$ be a real-valued convex function; for a given $\boldsymbol{x} \in \mathbb{R}^{n_X}$ and $\boldsymbol{y} \in \mathbb{R}^{n_Y}$, we denote by $\boldsymbol{g}(\boldsymbol{x}, \boldsymbol{y})$ the m-dimensional vector whose generic element is $g_i(\boldsymbol{x}, \boldsymbol{y})$. For given $\boldsymbol{x} \in X$ and $\boldsymbol{\xi} \in \Xi$, the second-stage feasible space $Y(\boldsymbol{x}, \boldsymbol{\xi})$ is defined by*

$$Y(\boldsymbol{x}, \boldsymbol{\xi}) := \{\boldsymbol{y} \in \mathbb{R}^{n_Y} : \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} + \boldsymbol{g}(\boldsymbol{x}, \boldsymbol{y}) \leq \boldsymbol{0}\}.$$

Moreover, we assume that the objective function $g_0 : \mathbb{R}^{n_X + n_Y} \to \mathbb{R}$ is a real-valued convex function and that relint(dom $(g_i)) \neq \emptyset$ for all $i = 0, ..., m$.

This assumption simply states that (P) is an ARO problem with fixed recourse and convex second-stage feasible space. Additionally, we make the following technical assumption used to prove our main theorem.

Assumption 2. *For any $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$ and any $\boldsymbol{\xi} \in \Xi$, the set*

$$Z(x_0, \boldsymbol{x}, \boldsymbol{\xi}) := \left\{ \begin{pmatrix} \beta_0 \\ \boldsymbol{\beta} \end{pmatrix} \in \mathbb{R}^{m+1} : \exists \boldsymbol{y} \in Y(\boldsymbol{x}, \boldsymbol{\xi}), \begin{array}{ll} g_0(\boldsymbol{x}, \boldsymbol{y}) - x_0 & \leq \beta_0 \\ \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} + \boldsymbol{g}(\boldsymbol{x}, \boldsymbol{y}) & \leq \boldsymbol{\beta} \end{array} \right\}$$

is closed.

Finally, the next lemma, which directly derives from Geoffrion (1972), gives a sufficient condition for Assumption 2 to hold.

Lemma 1. *Assume that, for any $\boldsymbol{x} \in X$ and any $\boldsymbol{\xi} \in \Xi$, the set $Y(\boldsymbol{x}, \boldsymbol{\xi})$ is compact and that g_0 is continuous on $Y(\boldsymbol{x}, \boldsymbol{\xi})$. Then, Assumption 2 holds.*

1.2. **Literature review.**

1.2.1. *Linear case.* ARO problems are known to be intractable even in the simple case in which only linear functions appear in the constraints defining $Y(\boldsymbol{x}, \boldsymbol{\xi})$; see Ben-Tal et al. (2004). For this setting, several exact approaches have been introduced in the literature. A first line of research is based on an adaptation of Benders' decomposition algorithm, in which the second-stage problem is dualized and an epigraph reformulation of the remaining maximization problem is used. Then, "Benders' cuts" are dynamically generated in a dynamic way; see, e.g., Terry et al. (2009), Bertsimas et al. (2013), Jiang et al. (2014) and Gabrel et al. (2014). An alternative approach is the column-and-constraint generation algorithm proposed by Zeng and Zhao (2013). In this scheme, a restricted master problem is iteratively solved and augmented by introducing second-stage variables and constraints associated with harmful scenarios. The identification of such scenarios requires the solution of a bilevel problem. Later, Ayoub and Poss (2016) solve this bilevel problem by means of a Mixed-Integer Linear Program (MILP) obtained by exploiting a description of the uncertainty set in terms of its extreme points. Finally, the Fourier-Motzkin elimination technique is used in Zhen et al. (2018) to remove the second-stage decisions from the definition of (P) and solve the problem to optimality.

Given the complexity results for linear ARO problems, many approximation methods have been presented in the literature for this class of problems. For instance, Bertsimas and Caramanis (2010) introduce the *finite adaptability* approach (also known as K-adaptability), in which a fixed number of second-stage decisions must be taken in the first stage so that each of them is used to address a subset of the uncertainty set, the union of such subsets being the whole original uncertainty set. An MILP formulation was introduced by Hanasusanto et al. (2015) for problems with binary second-stage decisions and objective uncertainty only. For the general (still linear) case, a scenario-based branch-and-bound algorithm was later proposed by Subramanyam et al. (2019). The *Affine Decision Rule* (ADR) approach was introduced by Ben-Tal et al. (2004) in which second-stage decisions are replaced by affine functions of the uncertainty. Though this restriction may seem arbitrary and restrictive, experimental evidences show that the obtained approximation is typically of good quality; see Ben-Tal et al. (2004), Bertsimas and Goyal (2011) and Bertsimas and Bidkhori (2014), Thomä et al. (2024). Moreover, in Bertsimas and Goyal (2011), the authors show that an optimal affine policy always exists when the uncertainty set is a simplex and the uncertain parameters only appear in the right-hand-side of the second-stage linear problem. The work in Bertsimas and Bidkhori (2014) provides, for the same class of problems, a priori approximation bounds between the solution of (P) and its ADR approximation based on geometrical properties of the uncertainty set. In addition, the authors show that this gap is zero when the uncertainty set is the intersection of an ℓ_2-ball and the non-negative orthant. A bound on the adjustability gap between a static robust problem and its adjustable counterpart is given in Wei and Zhang (2024). In Bertsimas and Ruiter (2016), the authors derive a dualized formulation of linear ARO problems and show that its ADR approximation is typically faster to solve than its primal ADR counterpart. They also show that an optimal primal ADR can be derived from an optimal dual ADR.

1.2.2. *Convex case.* Regarding the convex case, occurring when $Y(\boldsymbol{x}, \boldsymbol{\xi})$ is defined by convex functions of the first- and second- stage variables, the techniques introduced for the linear case are not directly applicable; the scientific literature is much more sparse and existing approaches focus on specific settings.

In Marandi and Hertog (2017), conditions are given under which an ARO problem is equivalent to its static robust version in which all decisions are taken before uncertainty realizes. We refer to Leyffer et al. (2020) for a survey on static nonlinear robust optimisation. In Takeda et al. (2007) the authors consider ARO problems in which the uncertainty set is expressed as the convex hull of a finite set of points, and report conditions under which such problems can be reduced to a single-stage problem. In Boni and Ben-Tal (2008), the authors consider ARO problems with ellipsoidal uncertainty set and conic quadratic second-stage constraints. They show that an optimal ADR can be obtained by means of a semidefinite problem. In Ruiter et al. (2023), the authors extend the approach proposed by Bertsimas and Ruiter (2016) and derive a dualized problem for a class of convex ARO problems. Linearity of the dualized problem with respect to the uncertain parameters allows then to obtain a tight approximation by using ADRs. Moreover, the authors show that a primal *feasible* ADR can be derived from an optimal dual ADR. This is in contrast with the result of Bertsimas and Ruiter (2016) in which an *optimal* primal

ADR could be derived from the dual. Moreover, we enlight that their approach considers a smaller class of problems compared to that studied in this work as they require g_i to be separable in $\boldsymbol{x}$ and $\boldsymbol{y}$ for all $i = 1, ..., m$ (i.e., there exists g_i^X and g_i^Y such that $g_i(\boldsymbol{x}, \boldsymbol{y}) = g_i^X(\boldsymbol{x}) + g_i^Y(\boldsymbol{y})$). Recently, problem (P) has been addressed in Khademi et al. (2024), where a dual reformulation is derived and an alternating method is used within a cutting plane algorithm producing locally robust solutions.

1.3. **Contributions.** As discussed in the literature review, few exact methods for convex ARO have been proposed so far, mostly relying on strong assumptions. In this work, we first recall a quite general reformulation for ARO problems, involving an exponential number of constraints. We start filling the literature gap and provide the following contributions:

- We show that the separation of the exponentially-many constraints of the reformulation can be performed via the solution of a non-convex program. This result, obtained through the use of convex conjugates and Fenchel duality, can be applied to any convex ARO, including cases in which the second stage is a second order cone program, a semidefinite program, or a (conic) linear program (this last case generalizing a previous result from Ayoub and Poss (2016)).
- We introduce two solution approaches based on a generalized Benders decomposition (GBD) scheme (Geoffrion 1972) and a Column-and-Constraint-Generation (CCG) scheme (Zeng and Zhao 2013), respectively, for which we show finite convergence under the mild hypothesis of our setting.
- We consider the relevant case in which the uncertainty set is a polytope. We show that, even in this case, the resulting problem is Σ_2^P-hard and the separation problem admits a convex MINLP reformulation, allowing to exploit the full power of modern MINLP solvers for effectively tackling the problem. For this setting, which includes budgeted uncertainty, we introduce two alternative approaches, that are based on the existence of an affine mapping to a 0-1 polytope and on KKT conditions, respectively.
- Finally, we give the computational evidence of the applicability of our solution methods to two applications arising from practical fields. The first one is a nonlinear version of the Capacitated Facility Location Problem, involving both binary and continuous decisions, while the second one is a nonlinear variant of a Resource Allocation Problem from the literature.

The paper is organized as follows: Section 2 gives the main theoretical contributions, namely the definition of the separation problem for a reformulation of (P). This allows us to introduce in Section 3 alternative solution approaches based on generalized Benders decomposition and on column-and-constraint generation, respectively, for which we study the finite termination and correctness. Section 4.1 discusses the special case in which the uncertainty set allows an affine mapping to a 0-1 polytope. Finally, Section 5 presents computational experiments and Section 6 draws some conclusions.

2. Theoretical development: a non-convex separation problem

Problem (P) can be reformulated as (see e.g., Takeda et al. 2007)

$$\inf_{x_0, \boldsymbol{x}} \quad x_0 \tag{1a}$$

$$\text{s.t.} \quad \boldsymbol{x} \in X, x_0 \in \mathbb{R}, \tag{1b}$$

$$\forall \boldsymbol{\xi} \in \Xi, \exists \boldsymbol{y} \in Y(\boldsymbol{x}, \boldsymbol{\xi}), x_0 \geq g_0(\boldsymbol{x}, \boldsymbol{y}). \tag{1c}$$

Since explicitly adding all constraints (1c) to the formulation is not viable in practice, we follow a separation approach in which, given pair $(x_0, \boldsymbol{x})$, we check whether a violated constraint exists. Solving the *separation problem* asks to answer the following question:

Question 1. *Given* $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$*, can we show that for any* $\boldsymbol{\xi} \in \Xi$ *there exists a* $\hat{\boldsymbol{y}} \in Y(\boldsymbol{x}, \boldsymbol{\xi})$ *such that* $x_0 \geq g_0(\boldsymbol{x}, \hat{\boldsymbol{y}})$ *? If not, can we identify* $\hat{\boldsymbol{\xi}} \in \Xi$ *such that either* $Y(\boldsymbol{x}, \hat{\boldsymbol{\xi}}) = \emptyset$ *or* $\forall \boldsymbol{y} \in Y(\boldsymbol{x}, \hat{\boldsymbol{\xi}}), x_0 < g_0(\boldsymbol{x}, \boldsymbol{y})$ *?*

In the following Lemma, we give a sufficient and necessary condition for answering an easier question:

Question 2. *Given* $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$ *and* $\boldsymbol{\xi} \in \Xi$*, is there a feasible second-stage decision* $\hat{\boldsymbol{y}} \in Y(\boldsymbol{x}, \boldsymbol{\xi})$ *such that* $x_0 \geq g_0(\boldsymbol{x}, \hat{\boldsymbol{y}})$*?*

Lemma 2. *Let* $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$ *and* $\boldsymbol{\xi} \in \Xi$*. Then, if Assumptions 1-2 hold, there exists* $\hat{\boldsymbol{y}} \in Y(\boldsymbol{x}, \boldsymbol{\xi})$ *such that* $x_0 \geq g_0(\boldsymbol{x}, \hat{\boldsymbol{y}})$ *if and only if, the following condition holds*

$$\forall (\lambda_0, \boldsymbol{\lambda}) \in \mathbb{R}^{m_Y+1}_{\geq 0}, \quad \inf_{\boldsymbol{y} \in \mathbb{R}^{n_Y}} \left\{ \boldsymbol{\lambda}^\top (\boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} + \boldsymbol{g}(\boldsymbol{x}, \boldsymbol{y})) + \lambda_0 (g_0(\boldsymbol{x}, \boldsymbol{y}) - x_0) \right\} \leq 0. \tag{2}$$

Proof. First, it is straightforward to verify that $\hat{\boldsymbol{y}} \in Y(\boldsymbol{x}, \boldsymbol{\xi})$ implies (2). Assume now that condition (2) holds, in which case we have

$$\sup_{(\lambda_0, \boldsymbol{\lambda}) \in \mathbb{R}^{m_Y+1}_{\geq 0}} \inf_{\boldsymbol{y} \in \mathbb{R}^{n_Y}} \left\{ \boldsymbol{\lambda}^\top (\boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} + \boldsymbol{g}(\boldsymbol{x}, \boldsymbol{y})) + \lambda_0 (g_0(\boldsymbol{x}, \boldsymbol{y}) - x_0) \right\} \leq 0. \tag{3}$$

Since $(\boldsymbol{0}, 0)$ is a possible choice for $(\lambda_0, \boldsymbol{\lambda})$ in (3), we have that

$$\sup_{(\lambda_0, \boldsymbol{\lambda}) \in \mathbb{R}^{m_Y+1}_{\geq 0}} \inf_{\boldsymbol{y} \in \mathbb{R}^{n_Y}} \left\{ \boldsymbol{\lambda}^\top (\boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} + \boldsymbol{g}(\boldsymbol{x}, \boldsymbol{y})) + \lambda_0 (g_0(\boldsymbol{x}, \boldsymbol{y}) - x_0) \right\} = 0. \tag{4}$$

As the left-hand side of (4) is the dual of

$$\inf_{\boldsymbol{y} \in \mathbb{R}^{n_Y}} \left\{ 0 : x_0 \geq g_0(\boldsymbol{x}, \boldsymbol{y}), \boldsymbol{y} \in Y(\boldsymbol{x}, \boldsymbol{\xi}) \right\} \tag{5}$$

and has finite value, by Assumption 2 and Theorem 5.1 in Geoffrion (1972), (5) must be feasible, i.e., there indeed exists $\boldsymbol{y} \in Y(\boldsymbol{x}, \boldsymbol{\xi})$ such that $x_0 \geq g_0(\boldsymbol{x}, \boldsymbol{y})$. ☐

Remark 1. *The condition (2) from Lemma 2 remains valid when adding the restriction* $||(\lambda_0, \boldsymbol{\lambda})|| \leq 1$*, where* $||\cdot||$ *is any norm of* $\mathbb{R}^{m+1}$*. Indeed, scaling does not impact the sign of the optimization problem in (3).*

Thanks to Lemma 2, we now introduce a non-convex optimization problem which solves the separation problem.

Theorem 1. *Let* $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$*. Then, if Assumptions 1-2 hold, the following propositions are equivalent:*

1. $\forall \boldsymbol{\xi} \in \Xi, \exists \hat{\boldsymbol{y}} \in Y(\boldsymbol{x}, \boldsymbol{\xi}), x_0 \geq g_0(\boldsymbol{x}, \hat{\boldsymbol{y}})$*, i.e., Question 1 has a positive answer;*
2. *The following non-convex optimization problem has an optimal objective value which is non-positive*

$$\sup_{\boldsymbol{\xi}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \ldots, \boldsymbol{u}^m} \quad -\sum_{i=0}^m \lambda_i g_i|^*_{\boldsymbol{x}} \left(\frac{\boldsymbol{u}^i}{\lambda_i} \right) + \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} - \lambda_0 x_0 \tag{6a}$$

$$\text{s.t.} \quad \sum_{i=0}^m \boldsymbol{u}^i = \boldsymbol{0}, \tag{6b}$$

$$(\lambda_0, \boldsymbol{\lambda}) \in \Lambda, \tag{6c}$$

$$\boldsymbol{\xi} \in \Xi, \tag{6d}$$

$$\boldsymbol{u}^i \in \mathbb{R}^{n_Y} \qquad i = 0, 1, \ldots, m, \tag{6e}$$

with $g_i|_{\boldsymbol{x}}(\bullet) := g_i(\boldsymbol{x}, \bullet)$*, and* $\Lambda = \{(\lambda_0, \boldsymbol{\lambda}) \in \mathbb{R}^m_+ \times \mathbb{R}_+ : ||(\lambda_0, \boldsymbol{\lambda})|| \leq 1\}$.

We recall that in (6a), $\lambda_i g_i|^*_{\boldsymbol{x}}(\boldsymbol{u}^i/\lambda_i)$ denotes the perspective function of $g_i|^*_{\boldsymbol{x}}$ as defined in Rockafellar (1996), page 67.

Proof. Let $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$. By Lemma 2, for any $\boldsymbol{\xi} \in \Xi$, there exists $\hat{\boldsymbol{y}} \in Y(\boldsymbol{x}, \boldsymbol{\xi})$ such that $x_0 \geq g_0(\boldsymbol{x}, \hat{\boldsymbol{y}})$ if, and only if, condition (2) is satisfied. Let $(\lambda_0, \boldsymbol{\lambda})$ be any element of Λ. We start by re-arranging the terms of (2) for $(\lambda_0, \boldsymbol{\lambda})$ as follows

$$\inf_{\boldsymbol{y}\in\mathbb{R}^{n_Y}} \left\{ \boldsymbol{\lambda}^\top \boldsymbol{g}|_{\boldsymbol{x}}(\boldsymbol{y}) + \lambda_0 g_0|_{\boldsymbol{x}}(\boldsymbol{y}) \right\} + \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} - \lambda_0 x_0 \leq 0, \tag{7}$$

in which terms which do not depend on $\boldsymbol{y}$ are moved out from the optimization problem. Now, letting $\phi(\boldsymbol{y}) = \boldsymbol{\lambda}^\top \boldsymbol{g}|_{\boldsymbol{x}}(\boldsymbol{y}) + \lambda_0 g_0|_{\boldsymbol{x}}(\boldsymbol{y})$, by definition of concave conjugates, the inf problem in (7) is $(-\phi)_*(\mathbf{0}) = \inf\{\phi(\boldsymbol{y}) : \boldsymbol{y} \in \mathbb{R}^{n_Y}\}$. By exploiting the fact that $(-\phi)_*(\mathbf{0}) = -\phi^*(\mathbf{0})$ (see Rockafellar 1996, p. 308), we have that (7) is equivalent to

$$-\phi^*(\mathbf{0}) + \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} - \lambda_0 x_0 \leq 0.$$

Using standard conjugate rules (see Rockafellar 1996, p. 145), one obtains the following expression of $\phi^*(\mathbf{0})$

$$\begin{aligned}
\phi^*(\mathbf{0}) = \inf_{\lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m} \quad & \sum_{i=1}^m (\lambda_i g_i|_{\boldsymbol{x}})^*(\boldsymbol{u}^i) + (\lambda_0 g_0|_{\boldsymbol{x}})^*(\boldsymbol{u}^0) \\
\text{s.t.} \quad & \sum_{i=0}^m \boldsymbol{u}^i = \mathbf{0}, \\
& \boldsymbol{u}^i \in \mathbb{R}^{n_Y} \qquad i = 0, 1, ..., m.
\end{aligned}$$

Then, we have $(\lambda_i g_i|_{\boldsymbol{x}})^*(\boldsymbol{u}^i) = \lambda_i g_i|^*_{\boldsymbol{x}}(\boldsymbol{u}^i/\lambda_i)$ (see Rockafellar 1996, p. 140). The proof is achieved by requiring that (7) be enforced for all $\boldsymbol{\xi} \in \Xi$. □

The result from Theorem 1 addresses generic convex functions. In the following two examples, we apply this general result to two prominent special cases. In particular, we show that Theorem 1 reduces to the results of Ayoub and Poss (2016) if all involved functions are linear. In the second example, we take interest in problems with convex functions defined using ℓ_p-norms.

Example 1 (Linear case)**.** *Assume that, for each $i = 0, \dots, m$, it holds $g_i(\boldsymbol{x}, \boldsymbol{y}) = \boldsymbol{t}^i \boldsymbol{x} + \boldsymbol{w}^i \boldsymbol{y} - b_i$ for given $\boldsymbol{t}^i \in \mathbb{R}^{n_X}, \boldsymbol{w}^i \in \mathbb{R}^{n_Y}$ and $b_i \in \mathbb{R}$, and define $r_i(\boldsymbol{x}) = \boldsymbol{t}^i \boldsymbol{x} - b_i$. By observing that*

$$g_i|^*_{\boldsymbol{x}} \left(\frac{\boldsymbol{u}^i}{\lambda_i} \right) = \begin{cases} -r_i(\boldsymbol{x}) & \text{if } \frac{\boldsymbol{u}^i}{\lambda_i} = \boldsymbol{w}^i, \\ +\infty & \text{otherwise,} \end{cases}$$

we conclude that the first case must be enforced and Theorem 1 yields the following separation problem:

$$\begin{aligned}
\max_{\boldsymbol{\xi}, \lambda_0, \boldsymbol{\lambda}} \quad & (\boldsymbol{r}(\boldsymbol{x}) + \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi})^\top \boldsymbol{\lambda} + (r^0(\boldsymbol{x}) - x_0)\lambda_0 \\
\text{s.t.} \quad & \boldsymbol{W}^\top \boldsymbol{\lambda} + \boldsymbol{w}_{(0)}^\top \lambda_0 = \mathbf{0}, \\
& (\lambda_0, \boldsymbol{\lambda}) \in \Lambda, \\
& \boldsymbol{\xi} \in \Xi,
\end{aligned}$$

where $\boldsymbol{r}(\boldsymbol{x})$ denotes the vector with components $r_i(\boldsymbol{x})$ for $i = 1, \dots, m$.
We enlight that the derivation requires linearity with respect to $\boldsymbol{y}$ only, and hence the result remains valid when replacing $\boldsymbol{t}^i \boldsymbol{x}$ with $t^i(\boldsymbol{x})$ for a generic function $t^i : \mathbb{R}^{n_X} \to \mathbb{R}$. Finally, our result includes the specific case, addressed in Theorem 1 in Ayoub and Poss (2016), in which $\boldsymbol{F}$ is affine in $\boldsymbol{x}$, $\boldsymbol{t}^i = 0$ for all $i = 1, \dots, m$ and $\boldsymbol{w}^0 = \mathbf{0}$.

Example 2 (ℓ_p-norm objective and constraints)**.** *Assume that, for each $i = 0$, 1, ..., m, it holds $g_i(\boldsymbol{x},\boldsymbol{y}) = \left|\left|\boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{K}_Y^i\boldsymbol{y} + \boldsymbol{\chi}^i\right|\right|_{p_i} + \boldsymbol{t}^i\boldsymbol{x} + \boldsymbol{w}^i\boldsymbol{y} - b_i$ for given matrices $\boldsymbol{K}_X^i$, $\boldsymbol{K}_Y^i$, $\boldsymbol{\chi}^i$, vectors $\boldsymbol{t}^i$, $\boldsymbol{w}^i$ and scalar b_i. Let us denote, for each $i = 0,\dots,m$, $\boldsymbol{a}^i(\boldsymbol{x}) = \boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{\chi}^i$ and $r_i(\boldsymbol{x}) = \boldsymbol{t}^i\boldsymbol{x} - b_i$. Finally, let $\boldsymbol{W}$ be the matrix composed by vectors $\boldsymbol{w}^i$ ($i = 1\dots,m$), and $\boldsymbol{r}(\boldsymbol{x})$ be the vector with components $r_i(\boldsymbol{x})$ ($i = 1,\dots,m$). Then, the separation problem from Theorem 1 reads*[1]

$$
\begin{aligned}
\sup_{\boldsymbol{\xi},\lambda_0,\boldsymbol{\lambda},\boldsymbol{z}^0,\dots,\boldsymbol{z}^m} \quad & \sum_{i=0}^{m} \boldsymbol{a}^i(\boldsymbol{x})^\top \boldsymbol{z}^i + \left(\boldsymbol{r}(\boldsymbol{x}) + \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi}\right)^\top \boldsymbol{\lambda} + (r_0(\boldsymbol{x}) - x_0)\lambda_0 \\
\text{s.t.} \quad & \sum_{i=0}^{m} \boldsymbol{K}_Y^{i^\top} \boldsymbol{z}^i + \boldsymbol{W}^\top \boldsymbol{\lambda} + \boldsymbol{w}^{0^\top}\lambda_0 = \boldsymbol{0}, \\
& \left|\left|\boldsymbol{z}^i\right|\right|_{p_i'} \le \lambda_i \qquad i = 0,1,\dots,m, \\
& \boldsymbol{z}^i \in \mathbb{R}^{n_Y} \qquad i = 0,1,\dots,m, \\
& (\lambda_0, \boldsymbol{\lambda}) \in \Lambda, \\
& \boldsymbol{\xi} \in \Xi.
\end{aligned}
$$

Here, p_i' is such that $1/p_i + 1/p_i' = 1$ so that $\|\cdot\|_{p_i'}$ is the dual norm of $\|\cdot\|_{p_i}$.

We conclude this section by discussing the differences of Theorem 1 and a related result (Theorem 1), independently derived in Khademi et al. (2024). The two results are based on different assumption and, therefore, allow to derive different reformulations of (P). In particular, while we do not make the complete recourse assumption, the results in Khademi et al. (2024) assume Slater conditions, which is an even stronger requirement than complete recourse. The stronger assumptions in Khademi et al. (2024) allow to exploit strong duality in the derivation, but may limit the applicability of such method to more general settings.

3. Algorithms

We now exploit the theoretical results of the previous section to derive two alternative solution approaches for problem (P), for which we prove finite termination when the following assumption holds.

Assumption 3. *The first-stage feasible set $X \subset \mathbb{R}^{n_X}$ is bounded.*

3.1. Generalized Benders decomposition.

In this section, we introduce a new GBD algorithm able to solve (P) by means of successive separation of infeasible $(x_0, \boldsymbol{x})$ points.

For notational convenience, we denote by $\boldsymbol{s}$ a generic tuple $(\boldsymbol{\xi}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m)$, and by S the set of all such tuples satisfying constraints (6b)-(6e). In addition, we introduce function σ defined for each $x_0 \in \mathbb{R}$, $\boldsymbol{x} \in X$ and $\boldsymbol{s} \in S$ as the objective function (6a), i.e.,

$$
\sigma(x_0, \boldsymbol{x}; \boldsymbol{s}) := -\sum_{i=0}^{m} \lambda_i g_i|_{\boldsymbol{x}}^{*} \left(\frac{\boldsymbol{u}}{\lambda_i}\right) + \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} - \lambda_0 x_0.
$$

In the following theorem, we use the result from Theorem 1 to introduce an alternative projected formulation of (P).

[1] Full details of the derivation can be found in Appendix A.

Theorem 2. *If Assumption 1-2 hold, problem (P) is equivalently solved by the following infinite-dimensional problem*

$$\inf_{x_0, \boldsymbol{x}} \quad x_0 \tag{8a}$$

$$\text{s.t.} \quad \boldsymbol{x} \in X, x_0 \in \mathbb{R}, \tag{8b}$$

$$\sigma(x_0, \boldsymbol{x}; \boldsymbol{s}) \le 0 \qquad \forall \boldsymbol{s} \in S. \tag{8c}$$

If, moreover, X is a convex MINLP set, then this problem is a convex MINLP.

Proof. The reformulation holds by Theorem 1. Assume that X is a convex MINLP set. To show that the continuous relaxation of (8) is convex, we have to show that, for any $\boldsymbol{s} \in S$, function $(x_0, \boldsymbol{x}) \mapsto \sigma(x_0, \boldsymbol{x}; \boldsymbol{s})$ is convex. Note that since $\boldsymbol{\lambda}, \boldsymbol{\xi} \ge \boldsymbol{0}$ are fixed and, for each $i = 1, \dots, m$ and $j = 1, \dots, n_\Xi$, function f_{ij} is convex, we have that $\boldsymbol{x} \mapsto \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} - \lambda_0 x_0$ is a non-negative sum of convex functions. Thus, it is convex. We therefore focus on the remaining part and show that $\boldsymbol{x} \mapsto g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi})$ is a concave function for any fixed $\boldsymbol{\pi} \in \mathbb{R}^{n_Y}$. To this end, let $\boldsymbol{\pi} \in \mathbb{R}^{n_Y}$ be fixed with $i = 0, ..., m$. By definition, we have

$$g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi}) = \sup_{\boldsymbol{y} \in \text{dom}(g_i|_{\boldsymbol{x}})} \{ \boldsymbol{\pi}^\top \boldsymbol{y} - g_i|_{\boldsymbol{x}}(\boldsymbol{y}) \} = \sup_{\boldsymbol{y} \in \text{dom}(g_i|_{\boldsymbol{x}})} \{ \boldsymbol{\pi}^\top \boldsymbol{y} - g_i(\boldsymbol{x}, \boldsymbol{y}) \}.$$

Let us introduce new variables $\boldsymbol{z} \in \mathbb{R}^{n_X}$ such that $\boldsymbol{z} = \boldsymbol{x}$. Then, the following holds by Lagrangian duality (note that we have relint(dom $(g_i)) \neq \emptyset$; see Assumption 1):

$$\begin{aligned}
g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi}) &= \sup_{(\boldsymbol{z}, \boldsymbol{y}) \in \text{dom}(g_i), \boldsymbol{z} = \boldsymbol{x}} \{ \boldsymbol{\pi}^\top \boldsymbol{y} - g_i(\boldsymbol{z}, \boldsymbol{y}) \} \\
&= \inf_{\boldsymbol{\lambda} \in \mathbb{R}^{n_X}} \sup_{(\boldsymbol{z}, \boldsymbol{y}) \in \text{dom}(g_i)} \{ \boldsymbol{\lambda}^\top (\boldsymbol{z} - \boldsymbol{x}) + \boldsymbol{\pi}^\top \boldsymbol{y} - g_i(\boldsymbol{z}, \boldsymbol{y}) \} \\
&= \inf_{\boldsymbol{\lambda} \in \mathbb{R}^{n_X}} \sup_{(\boldsymbol{z}, \boldsymbol{y}) \in \text{dom}(g_i)} \left\{ -\boldsymbol{\lambda}^\top \boldsymbol{x} + \begin{pmatrix} \boldsymbol{\lambda} \\ \boldsymbol{\pi} \end{pmatrix}^\top \begin{pmatrix} \boldsymbol{z} \\ \boldsymbol{y} \end{pmatrix} - g_i(\boldsymbol{z}, \boldsymbol{y}) \right\} \\
&= \inf_{\boldsymbol{\lambda} \in \mathbb{R}^{n_X}} \{ -\boldsymbol{\lambda}^\top \boldsymbol{x} + g_i^*(\boldsymbol{\lambda}, \boldsymbol{\pi}) \}.
\end{aligned}$$

Thus, $g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi})$ can be expressed as the infimum of infinitely many affine functions of $\boldsymbol{x}$. As a result, it is concave in $\boldsymbol{x}$. □

Algorithm 1 Generalized Benders decomposition

Given an instance of problem (P), a tolerance $\varepsilon > 0$, and an initial set $S^0 \subseteq S$ such that (MP$_t$) is bounded with $t = 0$.
Let $t \leftarrow 0$ be an iteration counter.
repeat
  Solve

$$\inf\{x_0 : (x_0, \boldsymbol{x}) \in \mathbb{R} \times X, \quad \sigma(x_0, \boldsymbol{x}; \boldsymbol{s}) \le 0 \ \forall \boldsymbol{s} \in S^t\} \tag{MP$_t$}$$

  with a feasibility tolerance ε.
  if (MP$_t$) is infeasible **then** problem (P) is infeasible, **stop**.
  Let $(x_0^t, \boldsymbol{x}^t)$ be an optimal point of (MP$_t$).
  Solve the separation problem (6) with $(x_0, \boldsymbol{x}) = (x_0^t, \boldsymbol{x}^t)$ and denote by $\boldsymbol{s}^t := (\boldsymbol{\xi}^t, \lambda_0^t, \boldsymbol{\lambda}^t, \boldsymbol{u}^{0t}, ..., \boldsymbol{u}^{mt})$ an optimal point.
  Let $S^{t+1} \leftarrow S^t \cup \{\boldsymbol{s}^t\}$ and $t \leftarrow t + 1$.
until $\sigma(x_0^t, \boldsymbol{x}^t; \boldsymbol{s}^t) \le \varepsilon$

Based on Theorem 2, we can derive a cutting-plane algorithm in which cuts (8c) are dynamically generated. The complete procedure is reported in Algorithm 1, with a tolerance $\varepsilon > 0$ used for checking violation of constraints (8c). In our scheme, the restricted master problem is solved to optimality before performing separation. In case X includes integrality requirements on some variables, and some enumeration has to be performed, one could instead solve the separation problem at branch-and-bound nodes. However, this option depends on the features of the solver used for enumeration.

We now give sufficient conditions for Algorithm 1 to terminate after a finite number of iterations. In the following theorem, we show that assuming Lipschitz continuity of σ on variables $(x_0, \boldsymbol{x})$ is sufficient for finite termination. Later, we show that finite termination is ensured as well in case set X is discrete.

Theorem 3 (Finite termination - Lipschitz)**.** *Let Assumptions 1-3 hold and assume that $(x_0, \boldsymbol{x}) \mapsto \sigma(x_0, \boldsymbol{x}, \hat{s})$ is Lipschitz continuous for any $\hat{s} \in S$. Then, Algorithm 1 finitely terminates.*

Proof. Assume that the algorithm does not finitely terminate. It must be that (MP_t) is feasible for all $t \geq 0$, otherwise the algorithm would have stopped at Line 5. Moreover, we must have

$$\sigma(x_0^t, \boldsymbol{x}^t; \boldsymbol{s}^t) > \varepsilon \quad \forall t > 0, \tag{9}$$

since, otherwise, the algorithm would have stopped at Line 9. Now, consider any iteration $k \in \mathbb{N}$: it must be that

$$\sigma(x_0^t, \boldsymbol{x}^t; \boldsymbol{s}^k) \leq 0 \quad \forall t > k, \tag{10}$$

since constraints "$\sigma(x_0, \boldsymbol{x}; \boldsymbol{s}^k) \leq 0$" is then part of ($\text{MP}_t$) for $t > k$. Combining (9) and (10), we have

$$\varepsilon < \sigma(x_0^k, \boldsymbol{x}^k; \boldsymbol{s}^k) - \sigma(x_0^t, \boldsymbol{x}^t; \boldsymbol{s}^k) \quad \forall t > k.$$

By Lipschitz continuity of σ, there exists $K > 0$ such that

$$\varepsilon < K \| (x_0^k, \boldsymbol{x}^k) - (x_0^t, \boldsymbol{x}^t) \| \quad \forall t > k.$$

Thus, at each iteration t, a ball B^t of center $(x_0^t, \boldsymbol{x}^t)$ with radius ε / K is prevented from being reached in any future iteration. However, by Assumption 3, X is bounded and, thus, the total volume of all the balls that are cut must be bounded, which contradicts that $t \to \infty$ and that the algorithm does not terminate. □

We now show two cases in which the Lipschitz continuity assumption is verified.

Example 3 (Separable functions)**.** *Let us assume that, for each $i = 0, \ldots, m$, there exists functions g_i^X and g_i^Y such that $g_i(\boldsymbol{x}, \boldsymbol{y}) = g_i^X(\boldsymbol{x}) + g_i^Y(\boldsymbol{y})$ and that g_i^X are Lipschitz continuous functions and that f_{ij} is Lipschitz continuous for any $i = 1, \ldots, m$ and $j = 1, \ldots, n_\Xi$. Then, $(x_0, \boldsymbol{x}) \mapsto \sigma(x_0, \boldsymbol{x}, \hat{\boldsymbol{s}})$ is Lipschitz continuous for all $\hat{\boldsymbol{s}} \in S$.*

Proof. We first show that $-g_i|_{\boldsymbol{x}}^*$ is Lipschitz continuous in $\boldsymbol{x}$. Let $\boldsymbol{\pi} \in \mathbb{R}^{n_Y}$ be fixed. By definition, it holds

$$\begin{aligned} -g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi}) &= - \sup_{y \in \text{dom}(-g_i|_{\boldsymbol{x}}^*)} \{ \boldsymbol{\pi}^\top \boldsymbol{y} - g_i(\boldsymbol{x}, \boldsymbol{y}) \} \\ &= - \sup_{y \in \text{dom}(-g_i|_{\boldsymbol{x}}^*)} \{ \boldsymbol{\pi}^\top \boldsymbol{y} - g_i^X(\boldsymbol{x}) - g_i^Y(\boldsymbol{y}) \} \\ &= g_i^X(\boldsymbol{x}) - g_i^{Y*}(\boldsymbol{\pi}). \end{aligned}$$

Thus, $\boldsymbol{x} \mapsto -g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi})$ is Lipschitz continuous for any $\boldsymbol{\pi}$. The rest follows by nonnegative sums of Lipschitz continuous functions and scaling. □

Example 4 (ℓ_p-norms objective and constraints)**.** *Consider the setting of Example 2 in which all constraints as well as the objective function are defined using ℓ_p-norms. In this case, σ is given by*

$$\sigma(x_0, \boldsymbol{x}, \boldsymbol{s}) = \sum_{i=0}^{m} \boldsymbol{a}^i(\boldsymbol{x})^\top \boldsymbol{z}^i + (\boldsymbol{r}(\boldsymbol{x}) + \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi})^\top \boldsymbol{\lambda} + (r^0(\boldsymbol{x}) - x_0)\lambda_0,$$

which is Lipschitz continuous in $(x_0, \boldsymbol{x})$ if $\boldsymbol{F}$ have all its components Lipschitz continuous.

In the next theorem we show that, when X is a finite discrete set, finite termination is obtained without further assumptions on function σ.

Theorem 4 (Finite termination - discrete)**.** *Let Assumptions 1-3 hold and assume that X is a discrete set. Then, Algorithm 1 finitely terminates.*

Proof. Assume that the algorithm does not terminate. Then (MP$_t$) must be feasible for all $t \geq 0$ and (9) must hold; see proof of Theorem 3. Because X is finite, there must exist a point $(\hat{x}_0, \hat{\boldsymbol{x}})$ that is repeated during the algorithm, i.e., there exist natural numbers i and j with $i < j$ such that $(\hat{x}_0, \hat{\boldsymbol{x}}) = (x_0^i, \boldsymbol{x}^i) = (x_0^j, \boldsymbol{x}^j)$. However, we show that this is impossible. By Equation (9), the following holds

$$\sigma(x_0^i, \boldsymbol{x}^i, \boldsymbol{s}^i) = \sigma(\hat{x}_0, \hat{\boldsymbol{x}}, \boldsymbol{s}^i) > \varepsilon.$$

Yet, by Equation (10) and since $i < j$, we have

$$\sigma(x_0^j, \boldsymbol{x}^j, \boldsymbol{s}^i) = \sigma(\hat{x}_0, \hat{\boldsymbol{x}}, \boldsymbol{s}^i) \leq 0.$$

We therefore get a contradiction showing that the algorithm must terminate after a finite number of iterations. □

The previous results show that Algorithm 1 terminates in a finite number of iterations. We now discuss the approximation of the solution returned by the algorithm with respect to the tolerance ε. For the sake of generality, we consider the case in which the separation problem is solved by means of an oracle having accuracy $\delta \geq 0$, i.e., a procedure which, for a given pair $(x_0, \boldsymbol{x})$, returns an $\overline{\boldsymbol{s}} \in S$ such that

$$\sup_{\boldsymbol{s} \in S} \sigma(x_0, \boldsymbol{x}; \boldsymbol{s}) - \sigma(x_0, \boldsymbol{x}, \overline{\boldsymbol{s}}) \leq \delta.$$

In addition, for a given $\alpha \geq 0$, we introduce the set-valued map $Y^\alpha(\boldsymbol{x}, \boldsymbol{\xi})$ which, for any $\boldsymbol{x} \in X$ and any $\boldsymbol{\xi} \in \Xi$, is a super-set of $Y(\boldsymbol{x}, \boldsymbol{\xi})$ in which all constraints are relaxed by a term α, i.e.,

$$Y^\alpha(\boldsymbol{x}, \boldsymbol{\xi}) = \left\{ \boldsymbol{y} \in \mathbb{R}^{n_Y} : \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} + \boldsymbol{g}(\boldsymbol{x}, \boldsymbol{y}) \leq \alpha \boldsymbol{e} \right\}.$$

Theorem 5 (Correctness)**.** *Let Assumptions 1-3 hold and assume that the separation problem is solved by means of an oracle having accuracy $\delta \geq 0$. If Algorithm 1 terminates, it correctly identifies problem (P) as infeasible, or returns a solution $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$ such that $\forall \boldsymbol{\xi} \in \Xi, \exists \boldsymbol{y} \in Y^{\varepsilon+\delta}(\boldsymbol{x}, \boldsymbol{\xi}), x_0 \geq g_0(\boldsymbol{x}, \boldsymbol{y}) - \varepsilon - \delta$.*

Proof. Assume that the algorithm terminates in Line 9, i.e., at some iteration T, the separation problem returns a solution $\boldsymbol{s}^T$ such that $\sigma(x_0^T, \boldsymbol{x}^T; \boldsymbol{s}^T) \leq \varepsilon$. Since the separation problem is solved with a precision up to δ, it holds

$$\sup_{\boldsymbol{s} \in S} \sigma(x_0^T, \boldsymbol{x}^T; \boldsymbol{s}) - \sigma(x_0^T, \boldsymbol{x}^T, \boldsymbol{s}^T) \leq \delta.$$

Thus, it must be that $\sup_{\boldsymbol{s}\in S}\sigma(x_0^T,\boldsymbol{x}^T;\boldsymbol{s})\leq\varepsilon+\delta$. In turn, this implies

$$\begin{aligned}
&\sup_{\boldsymbol{s}\in S}\sigma(x_0^T,\boldsymbol{x}^T;\boldsymbol{s})\\
&=\sup_{\boldsymbol{\xi}\in\Xi,(\lambda_0,\boldsymbol{\lambda})\in\Lambda}\ \inf_{\boldsymbol{y}\in\mathbb{R}^{n_Y}}\left\{\boldsymbol{\lambda}^\top(\boldsymbol{F}(\boldsymbol{x}^T)\boldsymbol{\xi}+\boldsymbol{g}(\boldsymbol{x}^T,\boldsymbol{y}))+\lambda_0(g_0(\boldsymbol{x}^T,\boldsymbol{y})-x_0^T)\right\}\\
&=\sup_{\boldsymbol{\xi}\in\Xi}\ \inf_{\boldsymbol{y}\in\mathbb{R}^{n_Y}}\ \sup_{(\lambda_0,\boldsymbol{\lambda})\in\Lambda}\left\{\boldsymbol{\lambda}^\top(\boldsymbol{F}(\boldsymbol{x}^T)\boldsymbol{\xi}+\boldsymbol{g}(\boldsymbol{x}^T,\boldsymbol{y}))+\lambda_0(g_0(\boldsymbol{x}^T,\boldsymbol{y})-x_0^T)\right\}\\
&=\sup_{\boldsymbol{\xi}\in\Xi}\ \inf_{\boldsymbol{y}\in\mathbb{R}^{n_Y}}\ \max\left\{\max_{i=1,\ldots,m}\left\{\boldsymbol{f}_{(i)}(\boldsymbol{x}^T)\boldsymbol{\xi}+g_i(\boldsymbol{x}^T,\boldsymbol{y})\right\};g_0(\boldsymbol{x}^T,\boldsymbol{y})-x_0^T;0\right\}\\
&\leq\varepsilon+\delta.
\end{aligned}$$

Here, the minimax theorem from Perchet and Vigeral (2015) was used to swap the sup and inf operators. This shows that $(x_0^T,\boldsymbol{x}^T)$ is such that $\forall\boldsymbol{\xi}\in\Xi,\exists\boldsymbol{y}\in Y^{\varepsilon+\delta}(\boldsymbol{x},\boldsymbol{\xi}),x_0\geq g_0(\boldsymbol{x},\boldsymbol{y})-\varepsilon-\delta$.

Otherwise, assume that the algorithm stops at Line 5, i.e., at some iteration problem (MP_t) is infeasible. As problem (MP_t) is a relaxation of (8), this implies infeasibility of (P). □

3.2. **Column-and-constraint generation.** As a second solution approach, we propose a CCG algorithm for our convex setting. We refer to Zeng and Zhao (2013) for an introduction to this class of algorithms in the linear case. We first focus on the prominent case in which Ξ is polytope. To this end, we introduce the following assumption.

Assumption 4. *The uncertainty set is a polytope (i.e., a non-empty bounded polyhedron) which can be written as* $\Xi:=\{\boldsymbol{\xi}\in\mathbb{R}^{n_\Xi}:\boldsymbol{U}\boldsymbol{\xi}\leq\boldsymbol{d}\}$.

Lemma 3. *Let Assumptions 1 and 4 hold. Then, Problem* (P) *is equivalently solved by the following finite-dimensional problem*

$$\begin{aligned}
\inf_{x_0,\boldsymbol{x},\boldsymbol{y}_{\boldsymbol{\xi}}}\quad & x_0 && && \text{(11a)}\\
\text{s.t.}\quad & \boldsymbol{x}\in X, && && \text{(11b)}\\
& x_0\geq g_0(\boldsymbol{x},\boldsymbol{y}_{\boldsymbol{\xi}}) && \forall\boldsymbol{\xi}\in\operatorname{vert}(\Xi), && \text{(11c)}\\
& \boldsymbol{y}_{\boldsymbol{\xi}}\in Y(\boldsymbol{x},\boldsymbol{\xi}) && \forall\boldsymbol{\xi}\in\operatorname{vert}(\Xi). && \text{(11d)}
\end{aligned}$$

Proof. Consider the inf-sup-inf formulation of (P) and let, for a fixed $\bar{\boldsymbol{x}}\in X$, $\zeta_{\bar{\boldsymbol{x}}}$ be defined as $\zeta_{\bar{\boldsymbol{x}}}(\boldsymbol{\xi})=\inf_{\boldsymbol{y}\in Y(\bar{\boldsymbol{x}},\boldsymbol{\xi})}g_0(\bar{\boldsymbol{x}},\boldsymbol{y})$. From Proposition 2.1 in Fiacco and Kyparisis (1986), it holds that $\zeta_{\bar{\boldsymbol{x}}}$ is a convex function. Thus, we have that

$$\forall\bar{\boldsymbol{x}}\in X,\qquad\sup_{\boldsymbol{\xi}\in\Xi}\ \zeta_{\bar{\boldsymbol{x}}}(\boldsymbol{\xi})\ =\ \sup_{\boldsymbol{\xi}\in\operatorname{vert}(\Xi)}\ \zeta_{\bar{\boldsymbol{x}}}(\boldsymbol{\xi})$$

The rest follows; see e.g. Takeda et al. (2007). □

The core idea of CCG (see, Zhen et al. 2018) is to solve model (11) initially with a (nonempty) subset of scenarios $\hat{\Xi}\subseteq\operatorname{vert}(\Xi)$ in constraints (11c)-(11d). Then, given an optimal solution $(x_0^*,\boldsymbol{x}^*)$ to this relaxed problem, the separation problem is solved to check the feasibility of $(x_0^*,\boldsymbol{x}^*)$. If it is feasible, then it is also optimal for (P). Otherwise, there exists a value for the uncertain parameters, say $\hat{\boldsymbol{\xi}}$, which disproves the feasibility of $(x_0^*,\boldsymbol{x}^*)$. Thus, constraints of type (11c)-(11d) are added to the relaxation, introducing new variables $\boldsymbol{y}_{\hat{\boldsymbol{\xi}}}$. This step is repeated until no such $\hat{\boldsymbol{\xi}}$ can be identified by solving the separation problem. A complete description of the algorithm is given in Algorithm 2.

We now show, without introducing further assumptions, finite convergence of Algorithm 2.

Algorithm 2 Column-and-Constraint Generation

Given an instance of (P) and an initial set $\Xi^0 \subseteq \Xi$ such that ($\widetilde{\text{MP}}_t$) is bounded with $t = 0$.
Let $t \leftarrow 0$ be an iteration counter.
repeat
  Solve

$$\inf\{x_0 : (x_0, \boldsymbol{x}) \in \mathbb{R} \times X, \quad \boldsymbol{y}_{\hat{\boldsymbol{\xi}}} \in Y(\boldsymbol{x}, \hat{\boldsymbol{\xi}}) \wedge x_0 \geq g_0(\boldsymbol{x}, \boldsymbol{y}_{\hat{\boldsymbol{\xi}}}) \; \forall \hat{\boldsymbol{\xi}} \in \Xi^t\}. \qquad (\widetilde{\text{MP}}_t)$$

  if ($\widetilde{\text{MP}}_t$) is infeasible **then** (P) is infeasible, **stop**.
  Let $(x_0^t, \boldsymbol{x}^t)$ be an optimal point of ($\widetilde{\text{MP}}_t$).
  Solve the separation problem (6) with $(x_0, \boldsymbol{x}) = (x_0^t, \boldsymbol{x}^t)$ and denote by $\boldsymbol{s}^t := (\boldsymbol{\xi}^t, \lambda_0^t, \boldsymbol{\lambda}^t, {\boldsymbol{u}^0}^t, ..., {\boldsymbol{u}^m}^t)$ an optimal point.
  Let $\Xi^{t+1} \leftarrow \Xi^t \cup \{\boldsymbol{\xi}^t\}$ and $t \leftarrow t + 1$.
until $\sigma(x_0^t, \boldsymbol{x}^t; \boldsymbol{s}^t) \leq \varepsilon$

Theorem 6 (Finite termination)**.** *Let Assumptions 1, 2 and 4 hold. Then, Algorithm 2 terminates after a finite number of operations.*

Proof. To prove the result it is enough to observe that the number of constraints (11c)– (11d) is bounded by the number of vertices of Ξ, and that one different vertex is identified at each iteration. □

We conclude this section by comparing the cuts generated by the two algorithms. Specifically, we show that each cut that would be generated at some iteration of Algorithm 1 is implied by a single cut that is generated at an iteration of Algorithm 2. Thus, the finite termination of Algorithm 1 established in Theorem 3 and 4 naturally extends to Algorithm 2 in case Assumption 4 does not hold. Indeed, let $\hat{\boldsymbol{\xi}}$ be a given scenario and consider the case in which Algorithm 2 imposes feasibility of a given first-stage solution, say $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$, with respect to that scenario. To this aim, Algorithm 2 would add a pair of constraints (11c)– (11d) which ensure that $\exists \boldsymbol{y} \in Y(\boldsymbol{x}, \hat{\boldsymbol{\xi}})$ so that $x_0 \geq g_0(\boldsymbol{x}, \boldsymbol{y})$. According to Theorem 1, this is true if and only if

$$\sup_{(\hat{\boldsymbol{\xi}}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m) \in S} \sigma(x_0, \boldsymbol{x}; (\hat{\boldsymbol{\xi}}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m)) \leq 0 \tag{12}$$

Let us consider any point $s := (\boldsymbol{\xi}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m) \in S$. Clearly, (12) implies

$$\sigma(x_0, \boldsymbol{x}; s) \leq 0 \quad \forall s := (\boldsymbol{\xi}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m) \text{ such that } \boldsymbol{\xi} = \hat{\boldsymbol{\xi}},$$

i.e., a whole family of constraints that would be generated by Algorithm 1.

4. Separation problem for polyhedral uncertainty sets

The practical use of Algorithms 1 and 2 depends on the possibility to solve the separation problem. In this section, we focus on the relevant class of problems where Ξ is a polytope. We show that in this setting, problem (P) belongs to the Σ_2^P complexity class and provide a refomulation of the separation problem as a convex mixed-integer nonlinear problem.

The following result states that Problem (P) is Σ_2^P-hard even in the special case where Assumption 4 holds.

Theorem 7. *Let Assumptions 1, 2 and 4 hold. Then, Problem (P) is Σ_2^P-hard.*

Proof. In Appendix A.1 we show that the bilevel knapsack with interdiction constraints, which is known to be Σ_2^P-hard (see Caprara et al. (2016)), can be cast into problem (P) with polyhedral uncertainty set. □

We now discuss two alternative approaches for solving the separation problem when Assumption 4 is satisfied.

4.1. **Separation by affine mapping to a 0-1 polytope.** In this section, we exploit the fact that an arbitrary polytope, and therefore Ξ (by Assumption 4), admits an affine mapping to a 0-1 polytope. The following theorem exploits this mapping to reformulate the separation problem as a convex MINLP.

Theorem 8. *Let Assumptions 1, 2 and 4 hold and let $\Omega \subseteq \mathbb{R}^{n_\Omega}$ be a 0-1 polytope and $\boldsymbol{\rho}^0, \boldsymbol{\rho}^1, \dots, \boldsymbol{\rho}^{n_\Omega} \in \mathbb{R}^{n_\Xi}$ be n_Ω vectors such that $\Xi = \tilde{\boldsymbol{\rho}}(\Omega)$ where $\tilde{\boldsymbol{\rho}} : \boldsymbol{\omega} \mapsto \boldsymbol{\rho}^0 + \sum_{k=1}^{n_\Omega} \boldsymbol{\rho}^k \omega_k$. Then, given a pair $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$, the separation model introduced in Theorem 1 can be reformulated as the convex MINLP*

$$\sup_{\substack{\boldsymbol{\omega},\lambda_0,\boldsymbol{\lambda},\boldsymbol{u}^0,\dots,\boldsymbol{u}^m,\\ \boldsymbol{\theta}^1,\dots,\boldsymbol{\theta}^{n_\Omega}}} \quad -\sum_{i=0}^{m} \lambda_i g_i|_{\boldsymbol{x}}^* \left(\frac{\boldsymbol{u}}{\lambda_i}\right) + \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\rho}^0 + \sum_{k=1}^{n_\Omega} {\boldsymbol{\theta}^k}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\rho}^k - \lambda_0 x_0 \tag{13a}$$

$$\text{s.t.} \quad \sum_{i=0}^{m} \boldsymbol{u}^i = \boldsymbol{0}, \tag{13b}$$

$$(\lambda_0, \boldsymbol{\lambda}) \in \Lambda, \tag{13c}$$

$$\boldsymbol{\theta}^k \leq \boldsymbol{\lambda} \qquad k = 1, ..., n_\Omega, \tag{13d}$$

$$\boldsymbol{\theta}^k \leq \omega_k \boldsymbol{e} \qquad k = 1, ..., n_\Omega, \tag{13e}$$

$$\boldsymbol{\theta}^k \geq \boldsymbol{\lambda} + \omega_k \boldsymbol{e} - \boldsymbol{e} \qquad k = 1, ..., n_\Omega, \tag{13f}$$

$$\boldsymbol{\theta}^k \in \mathbb{R}^m_{\geq 0} \qquad k = 1, ..., n_\Omega, \tag{13g}$$

$$\boldsymbol{\omega} \in \Omega \cap \{0, 1\}^{n_\Omega}, \tag{13h}$$

$$\boldsymbol{u}^i \in \mathbb{R}^{n_Y} \qquad i = 0, 1, ..., m, \tag{13i}$$

where $\boldsymbol{e}$ denotes the unitary vector in $\mathbb{R}^m$.

Proof. Let $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$ be fixed. Given a 0-1 polytope $\Omega \subseteq \mathbb{R}^{n_\Omega}$ and vectors $\boldsymbol{\rho}^0, \boldsymbol{\rho}^1, ..., \boldsymbol{\rho}^{n_\Omega} \in \mathbb{R}^{n_\Xi}$, such that each $\boldsymbol{\xi} \in \Xi$ can be expressed as $\boldsymbol{\xi} = \boldsymbol{\rho}^0 + \sum_{k=1}^{n_\Omega} \boldsymbol{\rho}^k \omega_k$ with $\boldsymbol{\omega} \in \Omega$, the objective function (6a) can be rewritten as

$$-\sum_{i=0}^{m} \lambda_i g_i|_{\boldsymbol{x}}^* \left(\frac{\boldsymbol{u}^i}{\lambda_i}\right) + \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\rho}^0 + \sum_{k=1}^{n_\Omega} \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\rho}^k w_k - \lambda_0 x_0$$

Note that, for a fixed $(\lambda_0, \boldsymbol{\lambda})$, this is a linear function of $\boldsymbol{w}$ and that $(\lambda_0, \boldsymbol{\lambda})$ and $\boldsymbol{w}$ do not appear together in any of the constraints (6b)–(6e). Thus, when optimizing the reformulated objective function, there always exists an optimal point $(\boldsymbol{w}, \lambda_0, \boldsymbol{\lambda})$ such that $\boldsymbol{w}$ is a vertex of Ω. Therefore, we can restrict our attention to $\omega \in \operatorname{vert}(\Omega) \subseteq \{0, 1\}^{n_\Omega}$. By introducing variables $\theta_i^k = \lambda_i \omega_k$ ($i = 1, ..., m$ and $k = 1, ..., n_\Omega$), the bilinear term can be linearized as follows

$$\sum_{k=1}^{n_\Omega} \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\rho}^k w_k = \sum_{k=1}^{n_\Omega} \sum_{i=1}^{m} \sum_{j=1}^{n_\Xi} f_{ij}(\boldsymbol{x}) \rho_j^k \underbrace{\lambda_i \omega_k}_{=\theta_i^k} = \sum_{k=1}^{n_\Omega} {\boldsymbol{\theta}^k}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\rho}^k.$$

The result follows as (13d)–(13f) are linearization constraints and $0 \leq \lambda_i \leq 1$ by assumption. □

We now discuss how to determine a proper mapping for a given uncertainty set Ξ. When Ξ is a generic polytope, one can always express each of its elements $\boldsymbol{\xi}$ as a convex combination of its vertices $\bar{\boldsymbol{\xi}}^1, \dots, \bar{\boldsymbol{\xi}}^{n_\Omega}$, i.e.,

$$\Xi = \left\{ \sum_{k=1}^{n_\Omega} \omega_k \bar{\boldsymbol{\xi}}^k \quad : \quad \sum_{k=1}^{n_\Omega} \omega_k = 1, \quad 0 \le \omega_k \le 1, \, k = 1, \dots, n_\Omega \right\},$$

where n_Ω denotes the number of vertices of Ξ. In this case, $\boldsymbol{\rho}^0$ is the null vector and $\bar{\boldsymbol{\xi}}^1, \dots, \bar{\boldsymbol{\xi}}^{n_\Omega}$ play the role of vectors $\boldsymbol{\rho}^1, \dots, \boldsymbol{\rho}^{n_\Omega}$. Although this mapping is always possible, the number of vertices of Ξ can be very large in practice, resulting in an unpractical reformulation.

In the special case where set $\Xi := \{\boldsymbol{\xi} \in [0,1]^{n_\Xi} : \boldsymbol{U}\boldsymbol{\xi} \le \boldsymbol{d}\}$, in which $\boldsymbol{U}$ is a totally unimodular matrix and $\boldsymbol{d}$ is integral, then the identity mapping can be used, i.e., $n_\Omega = n_\Xi$ and $\Omega = \Xi$. This is notably the case for the budgeted uncertainty set, introduced in Bertsimas and Sim (2004), with an integer budget parameter. For the case with fractional budget parameter, Ayoub and Poss (2016) shows that an affine mapping with a 0-1 polytope of size $2n_\Xi$ exists.

4.2. **Separation by KKT conditions.** In this section we introduce an alternative approach, exploiting KKT conditions, to reformulate the separation problem as a (different) convex MINLP.

Theorem 9. *Let Assumptions 1, 2 and 4 hold. Then, given a pair $(x_0, \boldsymbol{x}) \in \mathbb{R} \times X$, the separation model introduced in Theorem 1 can be reformulated as the following convex MINLP*

$$\begin{aligned}
\sup_{\boldsymbol{\xi}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m, \boldsymbol{\mu}} \quad & -\sum_{i=0}^m \lambda_i g_i|_{\boldsymbol{x}}^* \left(\frac{\boldsymbol{u}^i}{\lambda_i} \right) - \lambda_0 x_0 + \boldsymbol{d}^\top \boldsymbol{\mu} \\
\text{s.t.} \quad & \sum_{i=0}^m \boldsymbol{u}^i = \boldsymbol{0}, \\
& (\lambda_0, \boldsymbol{\lambda}) \in \Lambda, \\
& \boldsymbol{U}^\top \boldsymbol{\mu} = \boldsymbol{F}(\boldsymbol{x})^\top \boldsymbol{\lambda}, \\
& \boldsymbol{0} \le \boldsymbol{\mu} \le \boldsymbol{z} M, \\
& \boldsymbol{0} \le \boldsymbol{d} - \boldsymbol{U}\boldsymbol{\xi} \le (\boldsymbol{e} - \boldsymbol{z}) M, \\
& \boldsymbol{u}^i \in \mathbb{R}^{n_Y} \quad i = 0, 1, \dots, m, \\
& \boldsymbol{z} \in \{0,1\}^{m_\Xi}.
\end{aligned}$$

Here, M is a sufficiently large value that can be computed in polynomial time with respect to the input size and m_Ξ denotes the number of rows in $\boldsymbol{U}$.

Proof. First, let us introduce the function

$$\varphi(\boldsymbol{\lambda}, \boldsymbol{x}) := \max_{\xi \in \Xi} \; \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x}) \boldsymbol{\xi},$$

so that the separation model (6) from Theorem 1 can be written as

$$\begin{aligned}
\sup_{\lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \dots, \boldsymbol{u}^m} \quad & -\sum_{i=0}^m \lambda_i g_i|_{\boldsymbol{x}}^* \left(\frac{\boldsymbol{u}^i}{\lambda_i} \right) - \lambda_0 x_0 + \varphi(\boldsymbol{x}, \boldsymbol{\lambda}) \\
\text{s.t.} \quad & \sum_{i=0}^m \boldsymbol{u}^i = \boldsymbol{0}, \quad (\lambda_0, \boldsymbol{\lambda}) \in \Lambda, \quad \boldsymbol{u}^i \in \mathbb{R}^{n_Y} \quad i = 0, 1, \dots, m.
\end{aligned}$$

Now, φ is the value function of a linear optimization problem which is feasible and bounded for any $\boldsymbol{\lambda}$ and $\boldsymbol{x}$; see Assumption 4. Hence, the Karush–Kuhn–Tucker (KKT) optimality conditions are both necessary and sufficient and it holds

$\varphi(\boldsymbol{\lambda}, \boldsymbol{x}) = \boldsymbol{\lambda}^\top \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi}$ with $\boldsymbol{\xi}$ such that there exists a dual point $\boldsymbol{\mu}$ satisfying

$$\boldsymbol{U}\boldsymbol{\xi} \leq \boldsymbol{d}, \quad \boldsymbol{U}^\top \boldsymbol{\mu} = \boldsymbol{F}(\boldsymbol{x})^\top \boldsymbol{\lambda}, \quad \boldsymbol{\mu} \geq \boldsymbol{0}, \quad \boldsymbol{\mu}^\top (\boldsymbol{U}\boldsymbol{\xi} - \boldsymbol{d}) = 0. \tag{14}$$

Moreover, strong duality implies that $\boldsymbol{\lambda}^\top \boldsymbol{F}(x)\boldsymbol{\xi} = \boldsymbol{d}^\top \boldsymbol{\mu}$. Hence, the separation problem can be written as

$$\begin{aligned} \sup_{\boldsymbol{\xi}, \lambda_0, \boldsymbol{\lambda}, \boldsymbol{u}^0, \ldots, \boldsymbol{u}^m, \boldsymbol{\mu}} \quad & -\sum_{i=0}^m \lambda_i g_i|_{\boldsymbol{x}}^* \left(\frac{\boldsymbol{u}^i}{\lambda_i} \right) - \lambda_0 x_0 + \boldsymbol{d}^\top \boldsymbol{\mu} \\ \text{s.t.} \quad & \sum_{i=0}^m \boldsymbol{u}^i = \boldsymbol{0}, \quad (\lambda_0, \boldsymbol{\lambda}) \in \Lambda, \quad (14), \quad \boldsymbol{u}^i \in \mathbb{R}^{n_Y} \quad i = 0, 1, \ldots, m. \end{aligned}$$

Finally, the only nonlinear terms in (14) are the complementary conditions that can be linearized using standard techniques; see, e.g., Fortuny-Amat and McCarl (1981). The fact that the M values can be computed in polynomial time is due to Buchheim (2023). □

5. Applications

We tested our methods on variants of two relevant problems arising from logistic and planning applications, taking into account robustness with respect to uncertain input parameters.

Our algorithms are implemented in C++17 using Mosek 10.0 to solve the underlying optimization sub-problems and the open-source library idol, see Lefebvre (2025). All experiments were executed on an Intel Xeon Gold 6126 at 2.6 GHz, with a time limit equal to 7,200 CPU seconds per run. Code and instances are freely available at https://github.com/hlefebvr/AD-convex-adjustable-robust-optimization.

5.1. Facility location problem with convex production cost.

In the standard Capacitated Facility Location Problem (CFLP), we are given a set V_1 of potential facilities that can be opened and a set V_2 of customers to be served. Each facility $i \in V_1$ has a capacity q_i and an opening cost f_i, while each customer $j \in V_2$ is associated with a demand d_j. In addition, for each facility $i \in V_1$ and customer $j \in V_2$, a unitary transportation cost $t_{ij} > 0$ is given. The problem asks to decide which facilities to open so as to serve all customers while minimizing the sum of opening and transportation costs. We assume that the demand of a customer can be split among multiple facilities.

We study here a variant of the CFLP in which diseconomies of scale occur at each facility and the unitary production cost increases with the amount of demand served by the facility. In the deterministic version of this problem, studied by Christensen and Klose (2021), the production cost of a facility $i \in V_1$ is

$$F_i(v_i) = a_i \frac{v_i}{q_i - v_i}, \tag{15}$$

where v_i is the amount of good allocated to the facility and a_i is a given parameter.

By introducing, for each facility $i \in V_1$, a decision variable x_i taking value one if and only if facility i is activated and, for each connection $(i, j) \in V_1 \times V_2$, a non-negative variable y_{ij} representing the amount of good transported from i to j, the deterministic version of the problem can be formulated as

$$\min_{\boldsymbol{x},\boldsymbol{y},\boldsymbol{v}} \quad \sum_{i\in V_1}\left(f_i x_i + F_i(v_i) + \sum_{j\in V_2} t_{ij} y_{ij}\right) \tag{16a}$$

$$\text{s.t.} \quad \sum_{j\in V_2} y_{ij} = v_i \qquad \forall i \in V_1, \tag{16b}$$

$$\sum_{i\in V_1} y_{ij} = d_j \qquad \forall j \in V_2, \tag{16c}$$

$$v_i \le q_i x_i \qquad \forall i \in V_1, \tag{16d}$$

$$y_{ij} \ge 0 \qquad \forall (i,j) \in V_1 \times V_2, \tag{16e}$$

$$x_i \in \{0,1\} \qquad \forall i \in V_1, \tag{16f}$$

$$v_i \ge 0 \qquad \forall i \in V_1. \tag{16g}$$

The objective function (16a) minimizes the sum of opening, production and transportation costs. Constraints (16b) define the amount of good leaving each facility, whereas constraints (16c) ensure that every demand is satisfied. Finally, constraints (16d) enforce capacity constraints of each facility.

We consider here a robust version of this problem in which demands are uncertain: while opening decisions are taken here and now, transportation decisions are taken in a second stage, when the uncertain demands can be observed. More formally, we assume that, for each customer j, the actual demand is $d_j = \bar{d}_j + \tilde{d}_j\xi_j$, where $\bar{d}_j$ and $\tilde{d}_j$ denote the minimum demand and maximum demand increase, respectively. Vector $\boldsymbol{\xi}$ modelling the overall uncertainty of the problem belongs to the budgeted uncertainty set

$$\Xi^{\text{bu}} = \left\{ \boldsymbol{\xi} \in [0,1]^{|V_2|} : \sum_{j\in V_2} \xi_j \le \Gamma \right\}. \tag{17}$$

Here, $\Gamma > 0$ is a parameter used to control the conservatism of the obtained solution; see Bertsimas and Sim (2004).

Thus, in this application, the set X is defined as $X = \{0,1\}^{|V_1|}$ while, for given $\boldsymbol{x} \in X$ and $\boldsymbol{\xi} \in \Xi$, set $Y(\boldsymbol{x},\boldsymbol{\xi})$ includes all pairs $(\boldsymbol{y},\boldsymbol{v})$, such that $\boldsymbol{y} \in \mathbb{R}_{\ge 0}^{|V_1|\times|V_2|}$, $\boldsymbol{v} \in \mathbb{R}_{\ge 0}^{|V_1|}$, and fulfilling constraints (16b)-(16g) with $d_j = \bar{d}_j + \tilde{d}_j\xi_j$. Thus, our model reads

$$\min_{\boldsymbol{x}\in X}\left\{ \sum_{i\in V_1} f_i x_i + \max_{\boldsymbol{\xi}\in\Xi^{\text{bu}}} \min_{(\boldsymbol{y},\boldsymbol{v})\in Y(\boldsymbol{x},\boldsymbol{\xi})} \sum_{i\in V_1}\left(F_i(v_i) + \sum_{j\in V_2} t_{ij} y_{ij}\right)\right\}.$$

5.1.1. *Instance generation.* We consider a benchmark of instances that are randomly generated according to Cornuejols et al. (1991). First, potential facilities and customers are randomly placed in a unit square and transportation cost between a facility i and a customer j is defined as their Euclidean distance multiplied by 10. The capacity of each facility $i \in V_1$ is $q_i = \mathcal{U}(10,160)$, while its activation cost is $f_i = \mathcal{U}(0,90) + \mathcal{U}(100,110)\sqrt{q_i}$, with $\mathcal{U}(a,b)$ a uniformly generated random number between a and b. Minimum demands of customers are randomly generated in the interval $[0,1]$ and scaled so that $\sum_{i\in V_1} q_i / \sum_{j\in V_2} \bar{d}_j = \mu$, with $\mu > 1$ a parameter. Finally, the coefficient a_i defining F_i is computed as in Christensen and Klose (2021), i.e., we first compute the "base" value $\bar{a}$ defined as

$$\bar{a} = 0.2\bar{f}\frac{\bar{q} - \bar{u}}{\bar{u}},$$

where $\bar{f}$ and $\bar{q}$ are the average opening cost and capacity, respectively, whereas $\bar{u}$ is the estimated average demand allocated to a facility, computed as $\bar{u} = D/\lceil 1.2D/\bar{q} \rfloor$ and $D = \sum_{j \in V_2} d_j$. Then, for each facility $i \in V_1$, we set

$$a_i = \bar{a} \frac{f^{\max}}{f_i + f^{\max}} \mathcal{U}(1.8, 2.2),$$

with $f^{\max} = \max\{f_i : i \in V_1\}$.
Finally, to avoid the discontinuity of $F_i(v_i)$ occurring at $v_i = q_i$, we replace F_i by

$$\tilde{F}_i(v_i) = a_i \frac{v_i}{q_i - v_i + \varepsilon},$$

with $\varepsilon = 10^{-3}$, which ensures $q_i - v_i + \varepsilon$ be always strictly positive.

The test set includes instances obtained by varying sizes and parameters. In particular, $(|V_1|, |V_2|)$ takes values $(10, 15)$, $(10, 20)$, $(15, 30)$; μ takes values 1.5 and 2.0; As to uncertainty, the ratio $\tilde{d}_j/\bar{d}_j$ between maximum demand increase and minimum demand is set to 0.25 and 0.50. The budget uncertainty Γ is set to $\lfloor p|V_2| \rfloor$ with $p \in \{0.1, 0.2, 0.3\}$, i.e., up to a fraction p of the customers maximally change their demands. For each combination of these parameters, 10 instances are generated, thus producing a total of 360 instances.

5.1.2. *Results.* Table 1 reports the outcome of our experiments for algorithms implementing generalized Benders decomposition (GBD) and column-and-constraint generation (CCG) on CFLP instances. Given that the uncertainty set is defined by a totally unimodular matrix, in both algorithms separation is carried out by exploiting Theorem 8 where the affine mapping is the identity. For each algorithm we report the number of instances solved to optimality (out of 20) and the average values of the computing time (t_{TOT}), which is then split in the time spent for solving the master and the separation problems (t_M and t_S, respectively). In addition, we report the average number of iterations before convergence. All figures refer to instances that are solved to proven optimality only.

				Algorithm GBD					Algorithm CCG				
$\lvert V_1\rvert$	$\lvert V_2\rvert$	p	$\tilde{d}/\bar{d}$	# opt.	t_{TOT}	t_M	t_S	# Iter	# opt.	t_{TOT}	t_M	t_S	# Iter
10	15	0.1	0.25	20	9.63	0.59	9.00	31.95	20	1.25	0.52	0.68	2.25
10	15	0.1	0.50	20	9.41	0.56	8.81	31.15	20	1.22	0.50	0.67	2.20
10	15	0.2	0.25	20	43.64	0.55	43.04	29.95	20	3.94	0.55	3.34	2.25
10	15	0.2	0.50	20	43.41	0.47	42.89	27.55	20	4.76	0.64	4.06	2.45
10	15	0.3	0.25	20	71.43	0.52	70.86	29.65	20	7.91	0.86	6.99	2.75
10	15	0.3	0.50	20	63.00	0.44	62.52	25.15	20	7.71	0.69	6.96	2.65
10	20	0.1	0.25	20	48.39	0.66	47.67	31.90	20	4.98	0.94	3.98	2.50
10	20	0.1	0.50	20	47.93	0.64	47.24	30.95	20	5.03	0.94	4.03	2.55
10	20	0.2	0.25	20	294.82	0.65	294.12	31.35	20	26.35	1.01	25.29	2.65
10	20	0.2	0.50	20	277.99	0.61	277.33	29.15	20	26.58	0.97	25.54	2.70
10	20	0.3	0.25	20	894.53	0.56	893.92	29.45	20	83.87	0.95	82.85	2.70
10	20	0.3	0.50	20	856.88	0.57	856.26	27.85	20	88.27	0.83	87.38	2.70
15	30	0.1	0.25	18	2401.50	4.62	2396.76	66.17	20	129.85	4.12	125.60	2.90
15	30	0.1	0.50	19	2765.66	5.43	2760.10	71.95	20	131.51	4.23	127.16	2.95
15	30	0.2	0.25	-	-	-	-	-	20	2969.99	4.79	2965.07	3.10
15	30	0.2	0.50	-	-	-	-	-	20	3027.15	4.61	3022.41	3.10
15	30	0.3	0.25	-	-	-	-	-	5	4303.16	2.27	4300.79	2.60
15	30	0.3	0.50	-	-	-	-	-	5	4833.15	2.15	4830.88	2.60

TABLE 1. Results on CFLP instances.

The results show that, for both approaches, the time spent for solving the master problem is orders of magnitude shorter than the separation time. Therefore, computational improvements should not be expected in a more sophisticated branch-and-cut scheme where separation is executed at branch-and-bound nodes. All instances with $(|V_1|, |V_2|)$ equal to (10, 15) and (10, 20) can be consistently solved to optimality by both methods. Among instances with $(|V_1|, |V_2|)$ equal to (15, 30), GBD solves 37 instances out of 40 for $p = 0.1$, while it cannot solve any instance for $p = 0.2$ and for $p = 0.3$. Conversely, CCG still solves all instances with $p = 0.1$ and $p = 0.2$ and 10 out of 40 with $p = 0.3$. Overall, the results indicate that CCG outperforms GBD in terms of number of instances solved (330 vs 277). Concerning the number of iterations, for those rows in which both methods solve all the instances, the figure for CCG is always one order of magnitude smaller than the one for GBD. This confirms the theoretical observation that a single iteration of the former method yields a set of variables and constraints that is equivalent to a whole family of cuts generated by a number of iterations by GBD (see Section 3.2). As the computational effort for generating a single cut is comparable in the two methods, CCG turns out to be one order of magnitude faster than GBD in solving those instances and results in the best solution approach for this application.

As separation is the most time-consuming step of both algorithms, one can consider solving this problem heuristically before an exact method is applied. Figure 1 shows the results obtained by methods GBD and CCG in their default setting and with the addition of a simple strategy in which the solution of the separation problem is stopped as soon as a violated cut (resp. scenario) is detected. In this performance profile, the horizontal axis represents the time normalized with respect to the fastest method, while the vertical axis reports the fraction of instances that are solved within that time.

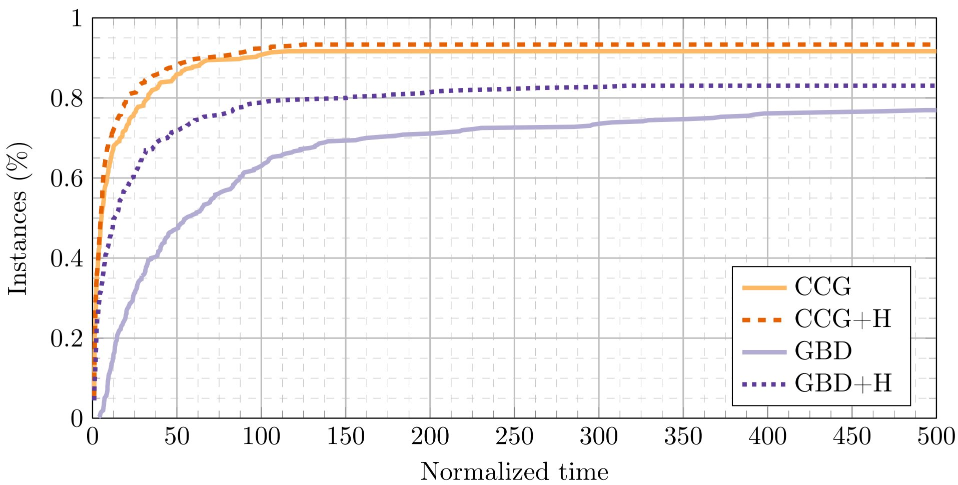

FIGURE 1. Performance profile of GBD and CCG with and without heuristic separation for the CFLP application.

The figure shows that the heuristic strategy is highly beneficial for GBD, while its effects are only marginal for CCG, which remains the best solution method.

5.2. **Resource allocation problem.** We now consider a Resource Allocation Problem (RAP) introduced by Luedtke (2010). In this problem, we are given a set I of resources that can be acquired to serve a set J of customers. Each resource $i \in I$ is associated to a unitary cost c_i, and each customer $j \in J$ has a demand d_j. We denote by μ_{ij} the service rate of resource i for customer j, i.e., how many units of the customer's demand can be served by the resource. The problem is to determine the amount of each resource to be acquired, and how to allocate resources to customers, so as to satisfy all demands at minimum cost. The deterministic version of this problem is as follows,

$$\min_{\boldsymbol{x},\boldsymbol{y}} \quad \sum_{i\in I} c_i x_i \tag{18a}$$

$$\text{s.t.} \quad \sum_{j\in J} y_{ij} \le x_i \qquad \forall i \in I \tag{18b}$$

$$\sum_{i\in I} \mu_{ij} y_{ij} \ge d_j \qquad \forall j \in J \tag{18c}$$

$$x_i \ge 0 \qquad \forall i \in I \tag{18d}$$

$$y_{ij} \ge 0 \qquad \forall (i,j) \in I \times J \tag{18e}$$

in which each variable x_i ($i \in I$) represents the acquired amount of resource i while y_{ij} ($(i,j) \in I \times J$) denotes the amount of resource i allocated to customer j. Constraints (18b) impose that allocated resources do not exceed the acquired amount, whereas constraints (18c) enforce that all demands are met.

A more realistic variant of this problem is obtained by considering that congestion affects the efficiency of resources. This may happen for example in the case of server allocation, where an increased allocation of customer demands to one server may induce delays; thus, in order to ensure that the same amount of the resource can be allocated to each customer, a larger amount of resource has to be acquired with respect to the uncongested setting.

We model congestion by means of a quadratic function, i.e., we now replace constraints (18b) by its congested counterpart

$$\sum_{j\in J} y_{ij} + b_i \Big(\sum_{j\in J} y_{ij}\Big)^2 \le x_i. \tag{19}$$

We observe that when $b_i = 0$ the problem reduces to its uncongested version. A very similar expression for congestion in resource allocation has been considered in Lodi et al. (2024) in the context of chance-constraint optimization.

In an uncertain setting, the demands of the customers are not known in advance. In particular, we model uncertainty by introducing a vector $\boldsymbol{\xi}$ of random parameters such that each customer $j \in J$ has demand $d_j = \bar{d}_j + \xi_j \tilde{d}_j$. We consider two different uncertainty sets:

- the budgeted uncertainty set as defined in the previous section, i.e., according to equation (17);
- a more general uncertainty set given by

$$\Xi^{\text{kp}} = \left\{ \boldsymbol{\xi} \in [0,1]^{|J|} : \sum_{j\in J} \tilde{d}_j \xi_j \le \beta \right\},$$

  where β is a parameter controlling the size of the set.

The second set Ξ^{kp} does not have a straightforward low-dimensional mapping to a 0-1 polytope. Nevertheless, the technique presented in Section 4.2 can be used to tackle the separation problem.

While decisions related to the amount of resources to be acquired have to be taken here and now, the assignment of these resources to customers can be defined later in time, after the actual demands materialize. Accordingly, this application can be modelled as an ARO problem, with $X = \mathbb{R}^{|I|}_{\ge 0}$ and $Y(\boldsymbol{x}, \boldsymbol{\xi})$ is defined as the set of all vectors $\boldsymbol{y} \in \mathbb{R}^{|I|\times|J|}_{\ge 0}$ fulfilling constraints (18c) and (19) with $d_j = \bar{d}_j + \tilde{d}_j \xi_j$.

5.2.1. *Instance generation.* We evaluate the performances of our algorithms on a large benchmark of random instances. The service rate values are uniformly generated in the interval $[0, 1]$. For each resource $i \in I$, the unitary cost c_i is set to $\mathcal{U}(8, 10) \sum_{j\in J} \mu_{ij}/|J|$ and the congestion coefficient b_i is randomly generated between 0 and 1. Finally, for each customer $j \in J$, the demand d_j is uniformly drawn between 1 and 50.

We generate 10 instances for each pair $(|I|, |J|)$ equal to $(10, 20)$, $(10, 30)$, $(15, 20)$, $(15, 30)$, $(20, 30)$ and $(20, 30)$. As in the previous application, uncertainty on demands is modeled by defining the ratio $\tilde{d}_j/\bar{d}_j$ equal to 0.25 and 0.50.

For the budget uncertainty set, parameter Γ is set to $\lfloor p\,|J|\rfloor$ with $p \in \{0.1, 0.2, 0.3\}$. As to the knapsack uncertainty set Ξ^{kp}, we use $\beta = \left\lceil \Gamma \sum_{j\in J} \tilde{d}_j/|J| \right\rceil$, and Γ as above. Overall, we thus have a benchmark composed by 720 instances.

5.2.2. *Results for the budgeted uncertainty set.* We first consider solving the separation problem by an affine mapping to a 0-1 polytope, as discussed in Section 4.1. Table 2 has the same structure as Table 1, and every row refers to a subset of 10 instances with the same features.

				Algorithm GBD					Algorithm CCG				
$\|I\|$	$\|J\|$	p	$\tilde{d}/\bar{d}$	# opt.	t_{TOT}	t_M	t_S	# Iter	# opt.	t_{TOT}	t_M	t_S	# Iter
10	20	0.1	0.25	10	208.39	0.62	207.54	194.10	10	3.21	0.12	3.03	2.80
10	20	0.1	0.50	10	218.04	0.63	217.17	205.30	10	3.31	0.10	3.14	3.00
10	20	0.2	0.25	10	1541.07	0.59	1540.22	193.10	10	22.72	0.16	22.49	2.90
10	20	0.2	0.50	10	1580.57	0.66	1579.64	200.70	10	21.38	0.10	21.21	2.80
10	20	0.3	0.25	9	4720.62	0.64	4719.68	204.67	10	72.05	0.08	71.90	3.00
10	20	0.3	0.50	7	4168.99	0.68	4167.97	211.71	9	80.03	0.12	79.84	3.22
10	30	0.1	0.25	10	4079.36	0.73	4078.26	218.70	8	45.50	0.06	45.36	2.62
10	30	0.1	0.50	10	4127.34	0.77	4126.20	222.00	10	54.33	0.10	54.15	3.00
10	30	0.2	0.25	-	-	-	-	-	6	1764.69	0.15	1764.45	2.83
10	30	0.2	0.50	-	-	-	-	-	8	1921.74	0.17	1921.48	3.38
10	30	0.3	0.25	-	-	-	-	-	4	3683.68	0.05	3683.55	2.50
10	30	0.3	0.50	-	-	-	-	-	5	3931.56	0.11	3931.38	2.40
15	20	0.1	0.25	10	517.66	1.58	515.57	375.00	10	4.00	0.12	3.81	2.70
15	20	0.1	0.50	10	552.79	1.75	550.51	386.70	10	3.99	0.18	3.73	2.60
15	20	0.2	0.25	9	4334.03	1.73	4331.67	385.33	10	36.13	0.20	35.85	2.80
15	20	0.2	0.50	9	4434.38	1.76	4432.00	393.44	10	32.31	0.08	32.15	2.70
15	20	0.3	0.25	1	4197.12	1.61	4194.91	392.00	10	143.92	0.09	143.75	3.00
15	20	0.3	0.50	1	4478.98	1.69	4476.66	389.00	10	133.22	0.18	132.95	2.80
15	30	0.1	0.25	2	5132.34	1.68	5129.85	380.50	9	54.34	0.16	54.07	2.89
15	30	0.1	0.50	2	5465.35	1.96	5462.65	397.00	10	65.39	0.14	65.08	3.10
15	30	0.2	0.25	-	-	-	-	-	10	2243.79	0.17	2243.49	3.50
15	30	0.2	0.50	-	-	-	-	-	10	2109.74	0.14	2109.48	3.40
15	30	0.3	0.25	-	-	-	-	-	6	4361.71	0.13	4361.46	2.83
15	30	0.3	0.50	-	-	-	-	-	6	4045.70	0.15	4045.44	3.00
20	20	0.1	0.25	10	990.15	3.97	985.22	579.10	10	4.70	0.10	4.50	2.80
20	20	0.1	0.50	10	968.40	3.94	963.50	571.90	10	4.56	0.09	4.37	2.70
20	20	0.2	0.25	4	4817.30	3.57	4812.77	536.00	10	38.68	0.12	38.46	2.80
20	20	0.2	0.50	4	4548.84	3.22	4544.66	505.50	10	44.88	0.18	44.59	3.20
20	20	0.3	0.25	-	-	-	-	-	10	120.76	0.14	120.52	2.80
20	20	0.3	0.50	-	-	-	-	-	10	121.90	0.13	121.66	2.90
20	30	0.1	0.25	-	-	-	-	-	10	76.22	0.24	75.85	2.70
20	30	0.1	0.50	-	-	-	-	-	10	76.55	0.16	76.25	2.70
20	30	0.2	0.25	-	-	-	-	-	10	2446.86	0.13	2446.59	2.70
20	30	0.2	0.50	-	-	-	-	-	10	2497.04	0.15	2496.75	2.80
20	30	0.3	0.25	-	-	-	-	-	4	5915.26	0.13	5914.99	3.00
20	30	0.3	0.50	-	-	-	-	-	3	5249.05	0.12	5248.78	3.00

TABLE 2. Results on RAP instances with budgeted uncertainty set and separation by an affine mapping to a 0-1 polytope.

The results show that, in this application as well, algorithm CCG outperforms GBD. Overall, the former solves 318 instances, whereas the latter solves only 120 instances. We observe that uncertainty plays a crucial role in determining the hardness of the instances, the larger $|J|$ and p, the most challenging the instance. Indeed, among the 120 instances with $|J| = 30$ and $p \geq 0.2$, GBD always fails whereas CCG proves optimality in 82 cases. As in the previous application, the average number of iterations required by CCG is consistently smaller than that of GBD, typically by two orders of magnitude, the average computing time per iteration being comparable. As may be expected, both algorithms spend most of the computing time in performing separation, requiring up to a few thousands seconds for the most challenging instances.

As an alternative approach for solving the separation problem, we also consider the KKT reformulation introduced in Section 4.2. Figure 2 shows a performance profile comparing two variants of algorithm CCG where separation is carried out by means of the mapping to a 0-1 polytope and of KKT conditions. Axes in the figure have the same meaning as in Figure 1.

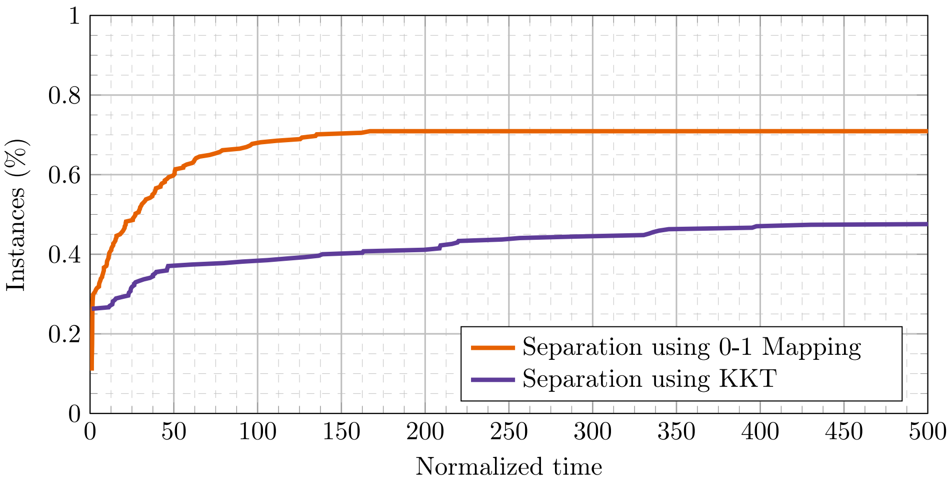

Figure 2. Performance profile of CCG on RAP instances with separation by an affine mapping to a 0-1 polytope and by KKT reformulation.

The figure shows that exploiting the affine mapping to a 0-1 polytope is highly beneficial compared to using the KKT-based reformulation. For instance, the 0-1 mapping solves 70% of the instances, and 68% of them are solved with a normalized time less than 100. Despite being less efficient, the KKT approach is still able to solve 48% of the instances within the time limit, with 38% of them within a normalized time less than 100.

5.2.3. *Comparison with static robust optimization.* The results from the previous section indicate that algorithm CCG is able to solve medium-size instances. The algorithm produces a series of non-decreasing lower bounds that converge to the optimal objective function value. However, if the time limit is reached before convergence, as it may happen for large instances, no feasible solution is returned. In this case, the quality of the computed lower bound can be evaluated by comparison with a feasible solution. To this end, we consider the heuristic solution obtained by solving the static robust version of RAP, in which all decisions are taken before the uncertainty is revealed, i.e., in a single stage. This results in a convex optimization problem, which can be solved in polynomial time (in our implementation using Mosek this requires a few seconds).

In Table 3, we report the percentage gap between the optimal value of the static robust problem and that of the adjustable robust problem. In the table, we only consider those instances for which algorithm CCG was able to find a provably optimal solution. The gap is computed as

$$\text{gap}_{\text{RO}} = \frac{v_{\text{RO}} - v_{\text{ARO}}}{v_{\text{ARO}}} \times 100,$$

where v_{RO} and v_{ARO} denote the optimal value of the static and of the adjustable robust problem, respectively (note that we always have $v_{\text{RO}} \geq v_{\text{ARO}} > 0$).

Algorithm CCG											
$\lvert I\rvert$	$\lvert J\rvert$	p	$\tilde{d}/\bar{d}$	# opt.	gap_{RO} (%)	$\lvert I\rvert$	$\lvert J\rvert$	p	$\tilde{d}/\bar{d}$	# opt.	gap_{RO} (%)
10	20	0.1	0.25	10	39.7	15	30	0.1	0.25	9	39.1
10	20	0.1	0.50	10	81.1	15	30	0.1	0.50	10	79.8
10	20	0.2	0.25	10	29.3	15	30	0.2	0.25	10	28.7
10	20	0.2	0.50	10	56.6	15	30	0.2	0.50	10	55.5
10	20	0.3	0.25	10	21.2	15	30	0.3	0.25	6	19.8
10	20	0.3	0.50	9	39.9	15	30	0.3	0.50	6	36.8
10	30	0.1	0.25	8	40.3	20	20	0.1	0.25	10	36.7
10	30	0.1	0.50	10	82.2	20	20	0.1	0.50	10	74.6
10	30	0.2	0.25	6	29.9	20	20	0.2	0.25	10	27.1
10	30	0.2	0.50	8	57.9	20	20	0.2	0.50	10	52.5
10	30	0.3	0.25	4	20.8	20	20	0.3	0.25	10	19.8
10	30	0.3	0.50	5	38.0	20	20	0.3	0.50	10	36.8
15	20	0.1	0.25	10	39.1	20	30	0.1	0.25	10	38.4
15	20	0.1	0.50	10	80.0	20	30	0.1	0.50	10	78.2
15	20	0.2	0.25	10	29.2	20	30	0.2	0.25	10	28.2
15	20	0.2	0.50	10	56.5	20	30	0.2	0.50	10	54.3
15	20	0.3	0.25	10	21.6	20	30	0.3	0.25	4	19.1
15	20	0.3	0.50	10	40.2	20	30	0.3	0.50	3	34.3

TABLE 3. Average percentage gap between the static and the adjustable robust problem on medium-size instances (computed over instances solved to optimality only).

Our results show that the average gap between the static and adjustable robust problems is always larger than 19% and can be as large as 82.2 % for instances with 10 resources and 30 customers with $p = 0.1$ and $\tilde{d}/\bar{d} = 0.5$. This quantifies the advantage of an approach based on recourse actions to be taken after uncertainty reveals in terms of reduced conservatism of the robust solution. We further observe that the gap increases with the maximum deviation $\tilde{d}/\bar{d}$. Conversely, increasing the value of p typically reduces the gap between the static and the adjustable problem. Note that this was to be expected since, as p increases, the number of maximally impacted demands increases which leads to more conservative decisions.

Finally, we introduce additional larger instances with $(|I|, |J|)$ equal to $(25, 30)$, $(25, 40)$, $(30, 30)$ and $(30, 40)$, most of which cannot be solved to optimality by using algorithm CCG. In this case, given the upper bound obtained by solving the static robust optimization problem (say, v_{RO}) and the lower bound computed by algorithm CCG at the time limit (say, lb_{ARO}) one can compute an optimality gap as

$$\text{gap}_{\text{opt}} = \frac{v_{\text{RO}} - lb_{\text{ARO}}}{lb_{\text{ARO}}} \times 100.$$

Table 4 reports the results on large instances, and gives the number of instances solved to optimality and the optimality gap computed over all the instances. For

Algorithm CCG											
$\|I\|$	$\|J\|$	p	$\tilde{d}/\bar{d}$	# opt.	gap_{opt} (%)	$\|I\|$	$\|J\|$	p	$\tilde{d}/\bar{d}$	# opt.	gap_{opt} (%)
25	30	0.1	0.25	10	39.1	30	30	0.1	0.25	10	36.6
25	30	0.1	0.50	10	80.2	30	30	0.1	0.50	10	74.6
25	30	0.2	0.25	0	29.0	30	30	0.2	0.25	0	27.4
25	30	0.2	0.50	0	56.2	30	30	0.2	0.50	0	53.2
25	30	0.3	0.25	0	21.2	30	30	0.3	0.25	0	20.7
25	30	0.3	0.50	0	39.3	30	30	0.3	0.50	0	38.1
25	40	0.1	0.25	2	38.8	30	40	0.1	0.25	5	38.4
25	40	0.1	0.50	6	79.3	30	40	0.1	0.50	1	78.6
25	40	0.2	0.25	0	29.7	30	40	0.2	0.25	0	29.1
25	40	0.2	0.50	0	56.7	30	40	0.2	0.50	0	56.5
25	40	0.3	0.25	0	21.9	30	40	0.3	0.25	0	21.8
25	40	0.3	0.50	0	40.1	30	40	0.3	0.50	0	40.4

TABLE 4. Average optimality gap between the static robust problem and the best lower bound returned by algorithm CCG at the time limit on larger instances (computed over all instances).

instances that are solved to optimality, $lb_{\text{ARO}} = v_{\text{ARO}}$, and hence the gap is computed with respect to the optimal adjustable robust optimization value.

The results show that the observed gaps are comparable to those found in the previous table. This suggests that $lb_{\text{ARO}} \approx v_{\text{ARO}}$, i.e., algorithm CCG is capable of producing tight lower bounds even for larger instances. Nevertheless, proving the optimality of these bounds remains challenging in general within the given time limit.

5.2.4. *Results for the continuous knapsack uncertainty set.* We now consider the continuous knapsack uncertainty set Ξ^{kp}. In these experiments, we only evaluate the performance of the CCG algorithm, which was earlier shown to outperform the GBD approach. Moreover, the heuristic strategy for separation is also not considered since, in that setting, its effect is only marginal; see Section 5.1.2. Table 5 reports the numerical results, each row referring to a subset of 10 instances having the same features.

The results show that the knapsack uncertainty set Ξ^{kp} leads to much more challenging problems than the budgeted uncertainty set. Indeed, computing times are two orders of magnitude larger than their counterparts. While the computing time of the master is negligible, the most time consuming part of the algorithm is separation. As in the previous case, the uncertainty parameter p plays a crucial role in the hardness of the instances. For instance, when considering 10 facilities and 20 customers, CCG solves all the 20 instances with $p = 0.1$, only 4 of them with $p = 0.2$, and none with $p = 0.3$. The largest instances that can be solved within the time limit are those with 20 facilities and 20 customers with an uncertainty parameter $p = 0.1$. Conversely, when considering the budgeted uncertainty set and separation via an identity mapping to 0-1 polytope, we were able to solve instances of larger size and with a larger value of p. This is not surprising since KKT reformulation introduces more variables and constraints than the 0-1 mapping. Moreover, the linearized complementarity constraints in KKT reformulation involve M values which are larger than the bounds used to linearized bilinear terms in the 0-1 mapping approach. For more details, we refer to the recent work Lefebvre et al. (2025).

6. Conclusions

In this paper, we consider general Adjustable Robust Optimization problems in which the second-stage feasible set is defined by means of convex constraints. These problems can be recast into a formulation with infinitely many constraints, to be handled via a separation approach. By means of Fenchel duality, we are able to express the separation problem as a non-convex problem, allowing the derivation of solution schemes based on either generalized Benders decomposition or column-and-constraint generation. Finally, we show that, for the relevant case in which the uncertainty set is a polytope, the separation problem can be expressed as a convex MINLP formulation, allowing us to embed state-of-the-art MINLPs algorithms into an effective solution approach. Computational experiments on two different applications compare the alternative solution schemes, and provide insights on their relative performances when solving this class of problems.

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				Algorithm CCG				
$\|V_1\|$	$\|V_2\|$	p	$\tilde{d}/\bar{d}$	# opt.	t_{TOT}	t_M	t_S	# Iter
10	20	0.1	0.25	10	1238.42	0.10	1238.27	2.50
10	20	0.1	0.50	10	2316.82	0.13	2316.64	2.80
10	20	0.2	0.25	3	4382.48	0.21	4382.19	4.00
10	20	0.2	0.50	1	4680.02	0.17	4679.75	5.00
10	20	0.3	0.25	-	-	-	-	-
10	20	0.3	0.50	-	-	-	-	-
15	20	0.1	0.25	8	2776.59	0.07	2776.46	3.00
15	20	0.1	0.50	8	2524.01	0.09	2523.86	3.12
15	20	0.2	0.25	2	4688.58	0.07	4688.45	3.00
15	20	0.2	0.50	2	6671.90	0.07	6671.78	3.00
15	20	0.3	0.25	-	-	-	-	-
15	20	0.3	0.50	-	-	-	-	-
20	20	0.1	0.25	6	3058.98	0.11	3058.79	3.33
20	20	0.1	0.50	7	4030.51	0.11	4030.33	3.29
20	20	0.2	0.25	-	-	-	-	-
20	20	0.2	0.50	-	-	-	-	-
20	20	0.3	0.25	-	-	-	-	-
20	20	0.3	0.50	-	-	-	-	-

Table 5. Results on RAP instances with the knapsack uncertainty set and separation by KKT reformulation.

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Appendix A. Additional Proofs

In this appendix, we give additional proofs of results used throughout this paper. We refer to Ben-Tal et al. (2014) for useful convex conjugate calculus rules.

A.1. Σ_2^P-hardness of problem (P).

We show that problem (P) is at least Σ_2^P-hard by reduction from the bilevel knapsack problem with interdiction constraints.

A.1.1. *Equivalence between binary linear optimization and concave minimization.*

In this section, we first show an intermediate result by considering the binary linear optimization problem

$$\min_{\boldsymbol{x}} \quad \boldsymbol{c}^\top \boldsymbol{x} \quad \text{s.t.} \quad \boldsymbol{A}\boldsymbol{x} \geq \boldsymbol{b}, \quad \boldsymbol{x} \in \{0,1\}^n. \tag{20}$$

The following theorem introduces a non-convex continuous reformulation of (20).

Theorem 10. *There exists a finite penalty parameter $\rho > 0$ such that the binary problem (20) and*

$$\min_{\boldsymbol{x}} \quad \boldsymbol{c}^\top \boldsymbol{x} + \rho \sum_{j=1}^{n} \min\{x_j, 1 - x_j\} \quad \textit{s.t.} \quad \boldsymbol{A}\boldsymbol{x} \geq \boldsymbol{b}, \quad \boldsymbol{x} \in [0,1]^n, \tag{21}$$

have the same objective function value. In addition, the penalty parameter ρ can be computed in time which is polynomial in the size of the input data $\boldsymbol{c}$*,* $\boldsymbol{A}$ *and* $\boldsymbol{b}$*.*

Proof. It is well-known, e.g., from Vicente et al. (1996), that problem (20) is equivalent to the bilevel problem

$$\begin{aligned}
\min_{\boldsymbol{x},\boldsymbol{y}} \quad & \boldsymbol{c}^\top \boldsymbol{x} \\
\text{s.t.} \quad & \boldsymbol{A}\boldsymbol{x} \geq \boldsymbol{b}, \quad \boldsymbol{x} \in [0,1]^n, \\
& \boldsymbol{e}^\top \boldsymbol{y} = 0, \\
& \boldsymbol{y} \in \arg\max_{\boldsymbol{y}'} \quad \boldsymbol{e}^\top \boldsymbol{y}' \\
& \qquad\qquad \text{s.t.} \quad \boldsymbol{y}' \leq \boldsymbol{x}, \\
& \qquad\qquad\qquad\; \boldsymbol{y}' \leq \boldsymbol{e} - \boldsymbol{x}.
\end{aligned}$$

In this problem, the follower wants to maximize $\boldsymbol{e}^\top \boldsymbol{y}' = \sum_{j=1}^{n} \min\{x_j, 1 - x_j\}$, i.e., the sum of the fractionalities of the x variables, whereas the leader imposes this figure be zero. This bilevel problem is equivalent to its KKT reformulation

$$\min_{\boldsymbol{x},\boldsymbol{y},\boldsymbol{\lambda},\boldsymbol{\mu},\boldsymbol{z},\boldsymbol{z}'} \quad \boldsymbol{c}^\top \boldsymbol{x} \tag{22a}$$

$$\text{s.t.} \quad \boldsymbol{A}\boldsymbol{x} \geq \boldsymbol{b}, \quad \boldsymbol{x} \in [0,1]^n, \tag{22b}$$

$$\boldsymbol{e}^\top \boldsymbol{y} = 0, \tag{22c}$$

$$\boldsymbol{y} \leq \boldsymbol{x}, \quad \boldsymbol{y} \leq \boldsymbol{e} - \boldsymbol{x} \tag{22d}$$

$$\boldsymbol{\lambda} + \boldsymbol{\mu} = \boldsymbol{e}, \tag{22e}$$

$$\boldsymbol{0} \leq \boldsymbol{x} - \boldsymbol{y} \leq M\boldsymbol{z}, \quad \boldsymbol{0} \leq \boldsymbol{\lambda} \leq M(\boldsymbol{e} - \boldsymbol{z}) \tag{22f}$$

$$\boldsymbol{0} \leq \boldsymbol{e} - \boldsymbol{x} - \boldsymbol{y} \leq M\boldsymbol{z}', \quad \boldsymbol{0} \leq \boldsymbol{\mu} \leq M(\boldsymbol{e} - \boldsymbol{z}') \tag{22g}$$

$$\boldsymbol{z}, \boldsymbol{z}' \in \{0,1\}^n. \tag{22h}$$

Complementarity constraints have been linearized by introducing new binary variables $\boldsymbol{z}$ and $\boldsymbol{z}'$ and by using a sufficiently large value M, which can be computed in polynomial time according to Buchheim (2023). We now apply the results from Gu et al. (2020) to move constraint (22c) in the objective function as a penalization term. By doing so, one obtains the equivalent problem

$$\begin{aligned} \min_{\boldsymbol{x},\boldsymbol{y},\boldsymbol{\lambda},\boldsymbol{\mu},\boldsymbol{z},\boldsymbol{z}'} \quad & \boldsymbol{c}^\top \boldsymbol{x} + \rho |\boldsymbol{e}^\top \boldsymbol{y}| \\ \text{s.t.} \quad & (22b), (22d)\text{–}(22h). \end{aligned}$$

Here, $\rho > 0$ is a sufficiently large penalty parameter. The existence of a finite parameter ρ has been estabilished in Giannessi and Tardella (1998), whereas the possibility to compute its value in polynomial time has been shown in Lefebvre and Schmidt (2024). □

A.1.2. *Reduction from the bilevel knapsack problem with interdiction constraints.* We now show that any instance of the bilevel knapsack problem with interdiction constraints can be formulated as an instance of problem (P) by means of a polynomial-time transformation.

Consider the interdiction knapsack problem

$$\min_{\boldsymbol{x} \in K^1} \max_{\boldsymbol{\xi} \in K^2(\boldsymbol{x})} \boldsymbol{p}^\top \boldsymbol{\xi} \tag{23}$$

with

$$\begin{aligned} K^1 &:= \left\{ \boldsymbol{x} \in \{0,1\}^n : \boldsymbol{v}^\top \boldsymbol{x} \le C_u \right\}, \\ K^2(\boldsymbol{x}) &:= \left\{ \boldsymbol{\xi} \in \{0,1\}^n : \boldsymbol{w}^\top \boldsymbol{\xi} \le C_\ell, \quad \boldsymbol{\xi} \le \boldsymbol{e} - \boldsymbol{x} \right\}. \end{aligned}$$

As shown in Fischetti et al. (2019), the interdiction knapsack problem can be reformulated as

$$\min_{\boldsymbol{x} \in K^1} \max_{\boldsymbol{\xi} \in K^3} \sum_{j=1}^n p_j x_j (1 - \xi_j), \quad \text{with} \quad K^3 := \left\{ \boldsymbol{\xi} \in \{0,1\}^n : \boldsymbol{w}^\top \boldsymbol{\xi} \le C_\ell \right\}.$$

By applying Theorem (10) to the inner problem, it holds that there exists a finite penalty parameter $\rho > 0$ which can be computed in polynomial time so that problem (23) is equivalent to

$$\min_{\boldsymbol{x} \in K^1} \max_{\boldsymbol{\xi} \in \overline{K^3}} \sum_{j=1}^n p_j x_j (1 - \xi_j) - \rho \sum_{j=1}^n \min\{\xi_j, 1 - \xi_j\},$$

where $\overline{K^3}$ denotes the continuous relaxation of K^3. Again, this problem can be reformulated as

$$\begin{aligned} \min_{\boldsymbol{x} \in K^1} \max_{\boldsymbol{\xi} \in \overline{K^3}} \min_{y_0, \boldsymbol{y}} \quad & y_0 - \rho \boldsymbol{e}^\top \boldsymbol{y} \\ \text{s.t.} \quad & y_0 \ge \sum_{j=1}^n p_j x_j (1 - \xi_j), \\ & \boldsymbol{y} \le \boldsymbol{\xi}, \\ & \boldsymbol{y} \le \boldsymbol{e} - \boldsymbol{\xi}, \end{aligned}$$

which is of the form of problem (P) with polyhedral uncertainty set.

A.2. **Proof of Example 2.** As stated in the example, assume that each function g_i $(i = 0, \dots, m)$ be generically defined by means of ℓ_p-norms, i.e., we have

$$g_i(\boldsymbol{x}, \boldsymbol{y}) = \left|\left| \boldsymbol{K}_X^i \boldsymbol{x} + \boldsymbol{K}_Y^i \boldsymbol{y} + \boldsymbol{\chi}^i \right|\right|_{p_i} + \boldsymbol{t}^i \boldsymbol{x} + \boldsymbol{w}^i \boldsymbol{y} + b_i.$$

A.2.1. *Computing convex conjugates.* Before applying Theorem 1, we first compute the convex conjugate of a generic functions g_i for some fixed $i \in \{0, \ldots, m\}$. To this end, let us rewrite $g_i|_{\boldsymbol{x}}$ as

$$g_i|_{\boldsymbol{x}}(\boldsymbol{y}) = h_1(\boldsymbol{y}) + \boldsymbol{t}^i\boldsymbol{x} + \boldsymbol{w}^i\boldsymbol{y} - b_i,$$

with $h_1(\boldsymbol{y}) = \left|\left|\boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{K}_Y^i\boldsymbol{y} + \boldsymbol{\chi}^i\right|\right|_{p_i}$. By addition to an affine function, it holds

$$g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi}) = h_1^*(\boldsymbol{\pi} - \boldsymbol{w}^i) - \boldsymbol{t}^i\boldsymbol{x} + b_i. \tag{24}$$

Now, we may write h_1 as

$$h_1(\boldsymbol{y}) = h_2(\boldsymbol{K}_Y^i\boldsymbol{y})$$

with $h_2(\boldsymbol{y}) = \left|\left|\boldsymbol{y} + \boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{\chi}^i\right|\right|_{p_i}$. By composition with a linear mapping and since $\operatorname{dom}(h_2) = \mathbb{R}^{n_Y}$, we have

$$h_1^*(\boldsymbol{\pi}) = \inf_{\boldsymbol{\alpha}}\{h_2^*(\boldsymbol{\alpha}) : {\boldsymbol{K}_Y^i}^T\boldsymbol{\alpha} = \boldsymbol{\pi}\}.$$

In turn, together with (24), we have

$$g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi}) = \inf_{\boldsymbol{\alpha}}\{h_2^*(\boldsymbol{\alpha}) : {\boldsymbol{K}_Y^i}^T\boldsymbol{\alpha} = \boldsymbol{\pi} - \boldsymbol{w}^i\} - \boldsymbol{t}^i\boldsymbol{x} + b_i. \tag{25}$$

Then, let us rewrite h_2 as

$$h_2(\boldsymbol{y}) = h_3(\boldsymbol{y} + \boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{\chi}^i)$$

with $h_3(\boldsymbol{y}) = ||\boldsymbol{y}||_{p_i}$. Thus, by translation of argument, we have

$$h_2^*(\boldsymbol{\pi}) = h_3^*(\boldsymbol{\pi}) - (\boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{\chi}^i)^T\boldsymbol{\pi}. \tag{26}$$

Now, h_3 being a norm, its convex conjugate is the indicator of the unit ball for the dual norm, i.e.,

$$h_3^*(\boldsymbol{\pi}) = \delta(\boldsymbol{\pi}|B_{p_i'}(\boldsymbol{0}, 1))$$

with $1/p_i + 1/p_i' = 1$. Together with (25) and (26), we have

$$g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi}) = \inf_{\boldsymbol{\alpha}}\left\{\delta(\boldsymbol{\alpha}|B_{p_i'}(\boldsymbol{0},1)) - (\boldsymbol{K}_X^i\boldsymbol{x}+\boldsymbol{\chi}^i)^T\boldsymbol{\alpha} : {\boldsymbol{K}_Y^i}^T\boldsymbol{\alpha} = \boldsymbol{\pi} - \boldsymbol{w}^i\right\} - \boldsymbol{t}^i\boldsymbol{x} + b_i. \tag{27}$$

By optimality in (27), we get

$$g_i|_{\boldsymbol{x}}^*(\boldsymbol{\pi}) = \inf_{\boldsymbol{\alpha}}\ \{-(\boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{\chi}^i)^T\boldsymbol{\alpha} - \boldsymbol{t}^i\boldsymbol{x} + b_i\} \tag{28a}$$

$$\text{s.t.} {\boldsymbol{K}_Y^i}^T\boldsymbol{\alpha} = \boldsymbol{\pi} - \boldsymbol{w}^i \tag{28b}$$

$$||\boldsymbol{\alpha}||_{p_i'} \leq 1 \tag{28c}$$

$$\boldsymbol{\alpha} \in \mathbb{R}^{n_Y}. \tag{28d}$$

A.2.2. *Applying Theorem 1.* We now rewrite (28) and replace $\boldsymbol{\pi}$ with $\boldsymbol{u}^i/\lambda_i$ and $\boldsymbol{\alpha}$ with $\boldsymbol{\alpha}^i$. By scalar multiplication with λ_i, we get

$$\begin{aligned}\lambda_i g_i|_{\boldsymbol{x}}^*(\boldsymbol{u}^i/\lambda_i) = \inf_{\boldsymbol{\alpha}^i}\ & \lambda_i\left(-(\boldsymbol{K}_X^i\boldsymbol{x} + \boldsymbol{\chi}^i)^T\boldsymbol{\alpha}^i - \boldsymbol{t}^i\boldsymbol{x} + b_i\right)\\ \text{s.t.} & {\boldsymbol{K}_Y^i}^T\boldsymbol{\alpha}^i = \boldsymbol{u}^i/\lambda_i - \boldsymbol{w}^i\\ & ||\boldsymbol{\alpha}||_{p_i'} \leq 1\\ & \boldsymbol{\alpha}^i \in \mathbb{R}^{n_Y}.\end{aligned}$$

Then, by introducing $\boldsymbol{z}^i = \lambda_i \boldsymbol{\alpha}^i$, we have

$$\begin{aligned}\lambda_i g_i|^*_{\boldsymbol{x}}(\boldsymbol{u}^i/\lambda_i) = \inf_{\boldsymbol{z}^i} \; & \{-(\boldsymbol{K}^i_X \boldsymbol{x} + \boldsymbol{\chi}^i)^T \boldsymbol{z}^i + \lambda_i(b_i - \boldsymbol{t}^i \boldsymbol{x})\} \\ \text{s.t.} & {\boldsymbol{K}^i_Y}^T \boldsymbol{z}^i = \boldsymbol{u}^i - \lambda_i \boldsymbol{w}^i \\ & \left|\left|\boldsymbol{z}^i\right|\right|_{p'_i} \leq \lambda_i \\ & \boldsymbol{z}^i \in \mathbb{R}^{n_Y}.\end{aligned}$$

By substitution into Theorem 1, we obtain the following model:

$$\begin{aligned}\sup & \sum_{i=0}^{m} \big((\boldsymbol{K}^i_X \boldsymbol{x} + \boldsymbol{\chi}^i)^T \boldsymbol{z}^i + \lambda_i(\boldsymbol{t}^i \boldsymbol{x} - b_i)\big) + \boldsymbol{\lambda}^T \boldsymbol{F}(\boldsymbol{x})\boldsymbol{\xi} - \lambda_0 x_0 \\ \text{s.t.} & \sum_{i=0}^{m} \left({\boldsymbol{K}^i_Y}^T \boldsymbol{z}^i + \lambda_i \boldsymbol{w}^i\right) = \boldsymbol{0} \\ & \left|\left|\boldsymbol{z}^i\right|\right|_{p'_i} \leq \lambda_i \qquad i = 0, 1, ..., m \\ & \boldsymbol{z}^i \in \mathbb{R}^{n_Y} \qquad i = 0, 1, ..., m \\ & (\lambda_0, \boldsymbol{\lambda}) \in \Lambda \\ & \boldsymbol{\xi} \in \Xi.\end{aligned}$$

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