Programming Assignment 2

Computer Science 110-03

Fall 2011

1   The Bisection Method

Most of us have spent years solving equations in math classes. For example, most of us know that we can solve the equation $x^2 + x - 1 = 0$ either by factoring or by using the quadratic formula. For assignment 2 we'll put the computer to work solving equations similar to this, equations that have the form $f(x) = 0$.

One of the most reliable methods for solving these equations is the *bisection method*. In the bisection method we start with two x values a and b. The two values should have the property that either $f(a) < 0$ and $f(b) > 0$ or $f(a) > 0$ and $f(b) < 0$. In other words, $f(a)$ and $f(b)$ have opposite signs. If the function $f(x)$ is reasonably nice (e.g., a polynomial), then we're guaranteed that $f(c) = 0$ for some c between a and b. See Figure 1.

The bisection method tries to focus in on c by dividing the interval from a to b in half. In Figure 2 $e = (a + b)/2$, we can see that the interval from a to e contains c. Furthermore, the size of the interval from a to e is half as long as the original interval. If we repeat this process with e replacing b in our formula, we'll get a new e that's even closer to c.

It's easy to come up with a picture in which we need to replace a with e instead. (Draw a picture!) So how do we decide which should be replaced? Well, the key property that a and b have is that $f(a)$ and $f(b)$ have opposite signs: this guarantees us that c is between them. So we want to make sure that when we replace a or b with e, the "new" a and b will have the property that $f(a)$ and $f(b)$ have opposite signs. How can we do this? Just check that their product is negative:

```
if f(a)*f(e) < 0:
    b = e
else:    # f(e)*f(b) < 0
    a = e
```

This gives us the start of an algorithm:

```
e = (a + b)/2
while the estimate e isn't good enough:
    if f(a)*f(e) < 0:
        b = e
    else
        a = e
    # new estimate
    e = (a + b)/2
```

To turn this into Python code, we need to decide when to exit from the loop.

In general, the bisection method doesn't find the exact solution. For example, if $f(x) = 3x - 1$, then $c = 1/3$ which can't be represented exactly in binary. So we can't try something like

Quadratic Prog Volume 2

Panos Y. Papalambros,Douglass J. Wilde

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   Encyclopedia of Optimization Christodoulos A. Floudas,Panos M. Pardalos,2008-09-04 The goal of the Encyclopedia of Optimization is to introduce the reader to a complete set of topics that show the spectrum of research the richness of ideas and the breadth of applications that has come from this field The second edition builds on the success of the former edition with more than 150 completely new entries designed to ensure that the reference addresses recent areas where optimization theories and techniques have advanced Particularly heavy attention resulted in health science and transportation with entries such as Algorithms for Genomics Optimization and Radiotherapy Treatment Design and Crew Scheduling

   Handbook of Combinatorial Optimization Ding-Zhu Du,Panos M. Pardalos,2013-03-14 Combinatorial or discrete optimization is one of the most active fields in the interface of operations research computer science and applied math ematics Combinatorial optimization problems arise in various applications including communications network design VLSI design machine vision air line crew scheduling corporate planning computer aided design and man ufacturing database query design cellular telephone frequency assignment constraint directed reasoning and computational biology Furthermore combinatorial optimization problems occur in many diverse areas such as linear and integer programming graph theory artificial intelligence and number theory All these problems when formulated mathematically as the minimization or maximization of a certain function defined on some domain have a commonality of discreteness Historically combinatorial optimization starts with linear programming Linear programming has an entire range of important applications including production planning and distribution personnel assignment finance alloca tion of economic resources circuit simulation and control systems Leonid Kantorovich and Tjalling Koopmans received the Nobel Prize 1975 for their work on the optimal allocation of resources Two important discover ies the ellipsoid method 1979 and interior point approaches 1984 both provide polynomial time algorithms for linear programming These algo rithms have had a profound effect in combinatorial optimization Many polynomial time solvable combinatorial optimization problems are special cases of linear programming e g matching and maximum flow In addi tion linear programming relaxations are often the basis for many approxi mation algorithms for solving NP hard problems e g dualheuristics   **Scientific and Technical Aerospace Reports** ,1991

   Computer Aided Optimal Design: Structural and Mechanical Systems Carlos A. Mota Soares,2012-12-06 This book contains the edited version of lectures and selected papers presented at the NATO ADVANCED STUDY INSTITUTE ON COMPUTER AIDED OPTIMAL DESIGN Structural and Mechanical Systems held in Tr6ia Portugal 29th June to 11th July 1986 and organized by CEMUL Center of Mechanics and Materials of the Technical University of Lisbon The Institute was attended by 120 participants from 21 countries including leading scientists and engineers from universities research institutions and industry and Ph D students Some participants presented invited and contributed papers during the Institute and almost all participated actively in discussions on scientific aspects during the Institute The Advanced Study Institute

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most fundamental and lasting contributions This book presents the results of the eighteenth edition of Robotics Research ISRR17 offering a collection of a broad range of topics in robotics This symposium took place in Puerto Varas Chile from December 11th to December 14th 2017 The content of the contributions provides a wide coverage of the current state of robotics research the advances and challenges in its theoretical foundation and technology basis and the developments in its traditional and new emerging areas of applications The diversity novelty and span of the work unfolding in these areas reveal the field s increased maturity and expanded scope and define the state of the art of robotics and its future direction

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