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Heuristics

Exploit special structure of instances occurring in practice

Consider algorithms that do not compute the optimal

solution but provide solutions that are close to optimal

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Definition 1

An α -approximation for an optimization problem is a polynomial-time algorithm that for all instances of the problem produces a solution whose value is within a factor of α of the value of an optimal solution.

Why approximation algorithms?

- Approximation algorithms for hard problems.
- A good theoretical foundation for analyzing heuristics.
- Provides a metric to compare the difficulty of various optimization problems.
- Proving theorems may give a deeper theoretical understanding which in turn leads to new algorithms.
- Approximation.

Why not?

- ▶ Sometimes the results are very pessimistic due to the fact that an algorithm has to provide a close-to-optimum solution on every instance.

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Definition 2

An optimization problem $P = (\mathcal{I}, \text{sol}, m, \text{goal})$ is in **NPO** if

- ▶ $x \in \mathcal{I}$ can be **decided** in polynomial time
- ▶ $y \in \text{sol}(\mathcal{I})$ can be **verified** in polynomial time
- ▶ m can be computed in polynomial time
- ▶ $\text{goal} \in \{\text{min}, \text{max}\}$

In other words: the decision problem **is there a solution y with $m(x, y)$ at most/at least z** is in NP.

- ▶ x is problem instance
- ▶ y is candidate solution
- ▶ $m^*(x)$ cost/profit of an optimal solution

Definition 3 (Performance Ratio)

$$R(x, y) := \max \left\{ \frac{m(x, y)}{m^*(x)}, \frac{m^*(x)}{m(x, y)} \right\}$$

Definition 4 (r -approximation)

An algorithm A is an r -approximation algorithm iff

$$\forall x \in \mathcal{I} : R(x, A(x)) \leq r ,$$

and A runs in polynomial time.

Definition 5 (PTAS)

A PTAS for a problem P from NPO is an algorithm that takes as input $x \in \mathcal{I}$ and $\epsilon > 0$ and produces a solution y for x with

$$R(x, y) \leq 1 + \epsilon .$$

The running time is polynomial in $|x|$.

approximation with arbitrary good factor... fast?

Problems that have a PTAS

Scheduling. Given m jobs with known processing times; schedule the jobs on n machines such that the MAKESPAN is minimized.

Definition 6 (FPTAS)

An FPTAS for a problem P from NPO is an algorithm that takes as input $x \in \mathcal{I}$ and $\epsilon > 0$ and produces a solution y for x with

$$R(x, y) \leq 1 + \epsilon .$$

The running time is polynomial in $|x|$ and $1/\epsilon$.

approximation with arbitrary good factor... fast!

Problems that have an FPTAS

KNAPSACK. Given a set of items with profits and weights choose a subset of total weight at most W s.t. the profit is maximized.

Definition 7 (APX – approximable)

A problem P from NPO is in APX if there exist a constant $r \geq 1$ and an r -approximation algorithm for P .

constant factor approximation...

Problems that are in APX

MAXCUT. Given a graph $G = (V, E)$; partition V into two disjoint pieces A and B s. t. the number of edges between both pieces is maximized.

MAX-3SAT. Given a 3CNF-formula. Find an assignment to the variables that satisfies the maximum number of clauses.

Problems with polylogarithmic approximation guarantees

- ▶ Set Cover
- ▶ Minimum Multicut
- ▶ Sparsest Cut
- ▶ Minimum Bisection

There is an r -approximation with $r \leq \mathcal{O}(\log^c(|x|))$ for some constant c .

Note that only for some of the above problem a matching lower bound is known.

There are really difficult problems!

Theorem 8

For any constant $\epsilon > 0$ there does not exist an $\Omega(n^{1-\epsilon})$ -approximation algorithm for the maximum clique problem on a given graph G with n nodes unless $P = NP$.

Note that an n -approximation is trivial.

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There are weird problems!

Asymmetric k -Center admits an $\mathcal{O}(\log^* n)$ -approximation.

There is no $o(\log^* n)$ -approximation to Asymmetric k -Center unless $NP \subseteq DTIME(n^{\log \log \log n})$.

Class APX not important in practise.

Instead of saying **problem P is in APX** one says **problem P admits a 4-approximation**.

One only says that a problem is **APX-hard**.