

CSE 417 Algorithms

Lecture 20, Autumn 2020
Dynamic Programming

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Announcements

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Reading

- Dynamic Programming Examples:
 - 6.1-6.2, **Weighted Interval Scheduling**
 - 6.3 **Segmented Least Squares**
 - 6.4 **Knapsack and Subset Sum**
 - 6.6 String Alignment
 - 6.7* String Alignment in linear space
 - 6.8 Shortest Paths (again)
 - 6.9 Negative cost cycles
 - How to make an infinite amount of money

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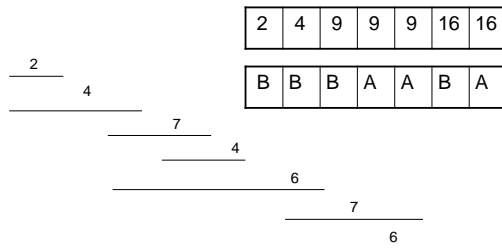
Dynamic Programming

- Key ideas
 - Construct optimization function
 - Express solution in terms of sub problems
 - Order sub problems to avoid recomputation
- Important detail
 - Record information to construct solution

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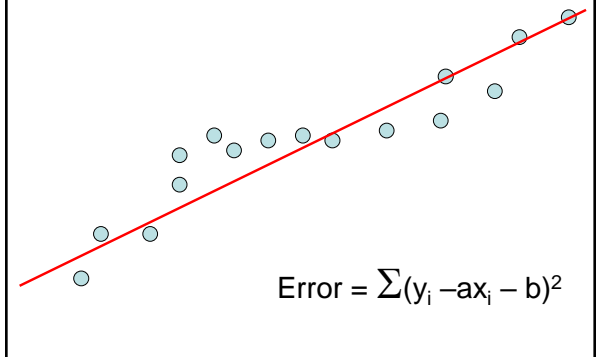
Weighted Interval Scheduling

$Opt[j] = \max (Opt[j - 1], w_j + Opt[p[j]])$
Record which case is used in Opt computation

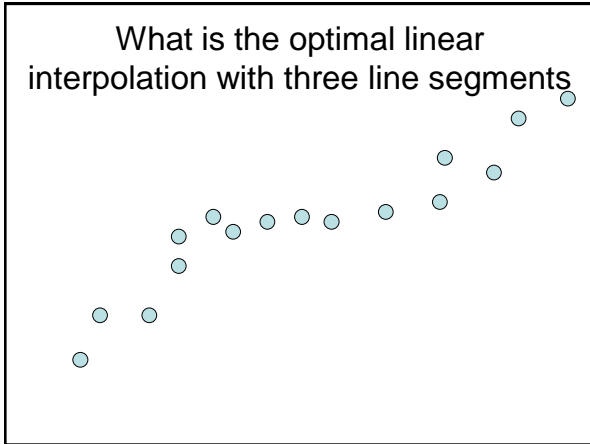


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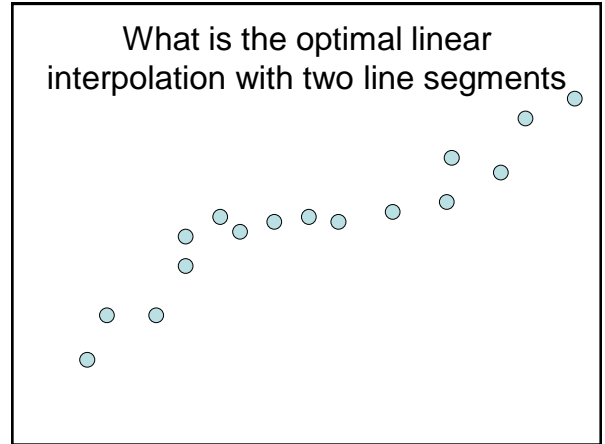
Optimal linear interpolation



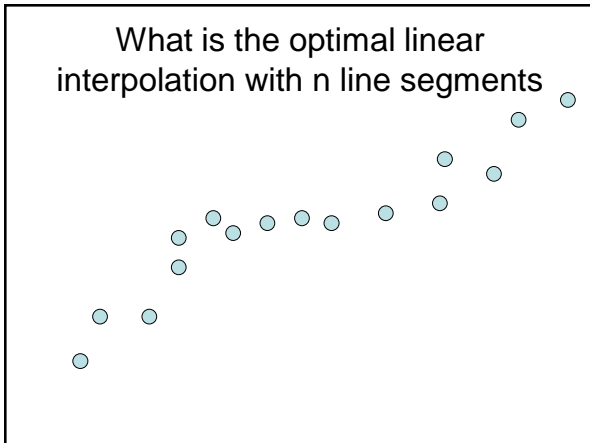
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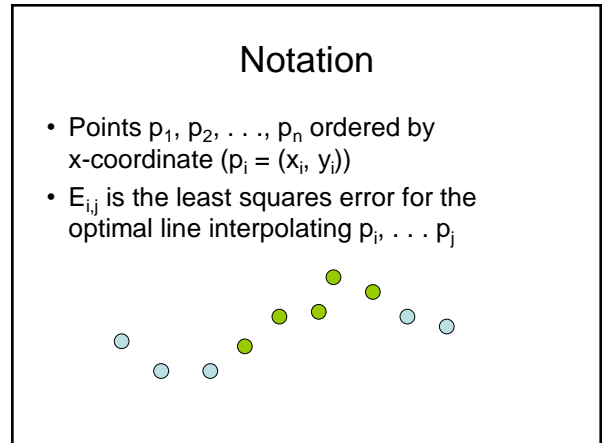
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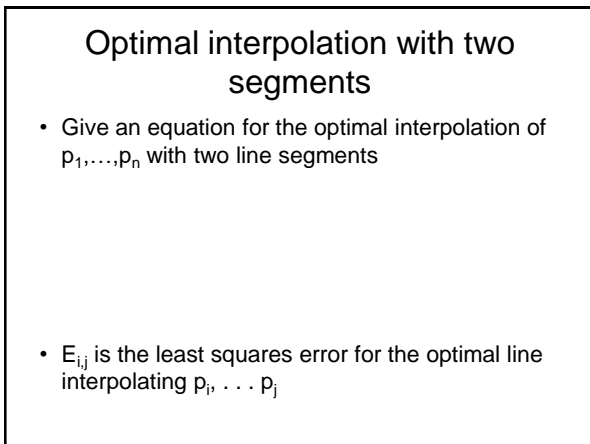
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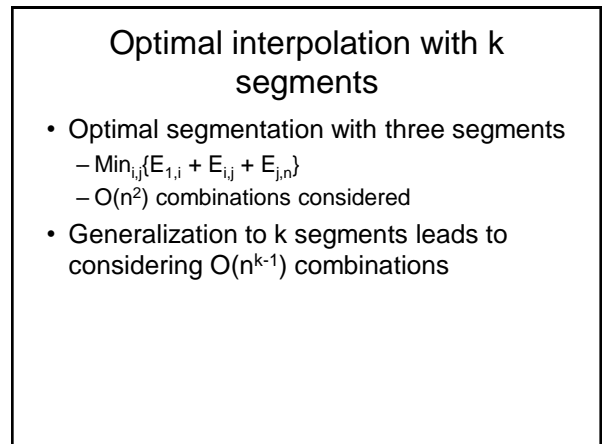
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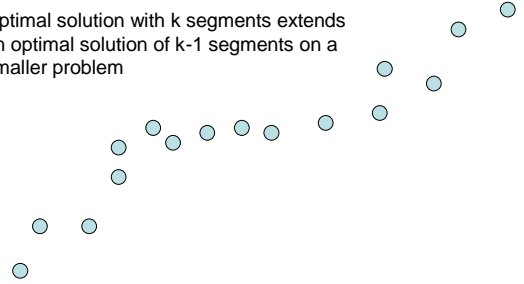
$Opt_k[j]$: Minimum error approximating $p_1 \dots p_j$ with k segments

How do you express $Opt_k[j]$ in terms of $Opt_{k-1}[1], \dots, Opt_{k-1}[j]$?

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Optimal sub-solution property

Optimal solution with k segments extends an optimal solution of $k-1$ segments on a smaller problem



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Optimal multi-segment interpolation

Compute $Opt[k, j]$ for $0 < k < j < n$

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for j = 1 to n
  Opt[1, j] = E1,j;

for k = 2 to n-1
  for j = 2 to n
    t = E1,j
    for i = 1 to j-1
      t = min(t, Opt[k-1, i] + Ei,j)
    Opt[k, j] = t
  
```

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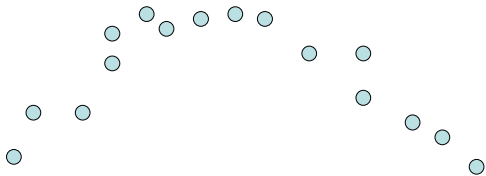
Determining the solution

- When $Opt[k, j]$ is computed, record the value of i that minimized the sum
- Store this value in an auxiliary array
- Use to reconstruct solution

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Variable number of segments

- Segments not specified in advance
- Penalty function associated with segments
- Cost = Interpolation error + $C \times \#Segments$



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Penalty cost measure

- $Opt[j] = \min(E_{1,j}, \min_i(Opt[i] + E_{i,j} + P))$

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