CSC279 HW3

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Question 10

(PART A)

Parametrizing the Segment pq:
Let $p = (x_0, y_0)$ and $q = (x_1, y_1)$ be the endpoints of the segment pq. Any point $x(t)$ on pq can be expressed as:

$$x(t) = (1-t)p + tq = ((1-t)x_0 + tx_1, (1-t)y_0 + ty_1),\ t \in [0,1]$$

Dual Lines Corresponding to Points on pq:
The dual line $\hat{x}(t)$ Corresponding to $x(t)$ is:

$$y = A(t)x - B(t)$$

where:

$$A(t) = (1-t)x_0 + tx_1$$
$$B(t) = (1-t)y_0 + ty_1$$

Now we can express rewrite the equation of $\hat{x}(t)$ as:

$$y = [x_0 + t(x_1 - x_0)]x - [y_0 + t(y_1 - y_0)]$$
$$= x_0 x - y_0 + t[(x_1 - x_0)x - (y_1 - y_0)]$$

Let:

$$D = (x_1 - x_0)x - (y_1 - y_0)$$

Then:

$$y = x_0 x - y_0 + tD$$

For a fixed x, y varies linearly with t from $y = x_0 x - y_0$ (when $t = 0$) to $y = x_1 x - y_1$ (when $t = 1$). The Union of all dual lines $\hat{x}(t)$ for $t \in [0,1]$ is the set of all points (x, y) in the plane satisfying:

$$\min(y_0, y_1) \leq y - x \cdot \min(x_0, x_1) \leq \max(y_0, y_1)$$

Equivilantly, by eliminating parameter t, we can get similar inequality:
We aim to eliminate the parameter t from the parametric equations to describe the union of dual lines $\hat{x}(t)$.
Solving for t:

$$t = \frac{y - x_0 x + y_0}{D}$$

Note: The sign of D affects the inequality direction.
If $D > 0$, then $0 \leq \frac{y-x_0x+y_0}{D} \leq 1 \Rightarrow 0 \leq y - x_0x + y_0 \leq D$.
If $D < 0$, then $0 \geq \frac{y-x_0x+y_0}{D} \geq 1 \Rightarrow D \leq y - x_0x + y_0 \leq 0$.
Both cases can be unified by the product inequality:

$$(y - x_0x + y_0)(y - x_1x + y_1) \leq 0$$

This inequality describes the region between the lines $y = x_0x - y_0$ and $y = x_1x - y_1$, where the expressions $y - x_0x + y_0$ and $y - x_1x + y_1$ have opposite signs or are zero.
Hence, the union of all dual lines is:

$$(y - x_0x + y_0)(y - x_1x + y_1) \leq 0$$

This inequality describes all points (x, y) that lie between $y = x_0x - y_0$, $y = x_1x - y_1$. which forms a region called a "double wedge".

(PART B)

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Input:
    S = { s_i | i = 1 to n }

output:
    l_max # Line has max. intersections point with other sections

Algorithm FindMaxIntersectingLine(S):
    Initialize an empty list L_dual_lines.

    For each segement s_i in S do:
        Let p_i = (x_{0i}, y_{0i}) and q_i = (x_{1i}, y_{1i})
        Compute the dual lines:
            L_{p_i}: y = x_{0i} x - y_{0i}
            L_{q_i}: y = x_{1i} x - y_{01}
        Add L_{p_i} and L_{q_i} to L_dual_lines.

    Construct the arrangement A of the lines in L_dual_lines:
        # TIME COMPLEXITY: O(n^2logn)
        Use the line sweep algorithm to compute the A.
        Store the faces, edges, and vertices of the A.

    Initialize count c_f = 0 for a starting PLANE f_0 at INFINITY

    Traverse arrangement A to label each face with the number
    of double wedges covering it:
        # TIME COMPLEXITY: O(n^2)
        For each edge e in A:
            Determine which double wedges have boundaries along e
            For each face f adjacent to e:
                *c_{f'} is the count of the adjacent face before crossing e
                If crossing e enters a double wedge W_i, then c_f = c_{f'} + 1
                If crossing e exits a double wedge W_i, then c_f = c_{f'} - 1

    Keep track of the face f_max with the maximum count c_max during traversal

    Let (a_max, b_max) be a point inside face f_max.

    Compute the line l_max in the primal plane corresponding to (a_max, b_max):
        l_max: y = a_max x - b_max

    Return l_max
```

Question 11

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Input:
    Simple polygon P given as a list of vertices [v1, v2, ..., vn] in order
Output:
    Whether there exists a line l such that P is monotone w.r.t. l

Algorithm DetermineMonotonicity(P):
    BadIntervals = empty_list()

    # TIME COMPLEXITY: O(n)
    For i from i to n:
        v_prev = P[(i - 2) mod n]
        v = P[i - 1]
        v_next = P[i mod n]
        Compute vectors e1 = v - v_prev
        Compute vectors e2 = v_next - v
        Compute cross product cp = e1.x * e2.y - e1.y * e2.x
        If cp < 0 (vertex is concave):
            Compute angles a1 = atan2(e1.y, e1.x) mod 2PI
            Compute angles a2 = atan2(e2.y, e2.x) mod 2PI
            Let Interval = [a2, a1] if a1 > a2 else [a2, a1 + 2PI]
            Normalize Interval to [0, 2PI)
            Add Interval to BadIntervals

    # TIME COMPLEXITY: O(nlogn)
    Sort BadIntervals by their start angles
    Merge overlapping intervals in BadIntervals to get a list of disjoint intervals

    If the merged intervals cover [0, 2PI):
        return FALSE

    return TRUE
```

Question 12

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Input:
    RedPoints = [ (x1, y1), (x2, y2), ..., (xn, yn) ]
    BluePoints = [ (x1', y1'), (x2', y2'), ..., (xn', yn') ]

Output:
    Coefficients (a, b, c) defining the parabola y = a x^2 + b x + c
    or report "No solution exists" if impossible

Algorithm FindSeparatingParabola(RedPoints, BluePoints):
    Initialize an empty list Constraints = []

    # NOTE: e is a small positive number
    # TIME COMPLEXITY: O(n)
    For each red point (x_i, y_i) in RedPoints do:
        Make inequality:
            a x_i^2 + b x_i + c - y_i < 0
        Convert to standard LP form (inequalities with <=):
            a x_i^2 + b x_i + c - y_i <= -e
        Add this to Constraints

    # TIME COMPLEXITY: O(n)
    For each blue point (x_j, y_j) in RedPoints do:
        Make inequality:
            a x_j^2 + b x_j + c - y_j > 0
        Convert to standard LP form (inequalities with <=):
            -a x_j^2 - b x_j - c + y_j <= -e
        Add this to Constraints

    ObjectiveFunction: Minimize 0

    # TIME COMPLEXITY: O(n)
    Solution = LinearProgramming(Constraints, ObjectiveFunction)

    If Solution is feasible then:
       Output "Parabola found with coefficients:"
       Output "a =", Solution.a
       Output "b =", Solution.b
       Output "c =", Solution.c

    Output "No solution exists"
```

Question 13

For this question, we use an approximation to replace L_2 norm in order to use LP.

$$\begin{cases} r \geq 0 \\ w \geq 0 \\ \forall i \in \{1, \ldots, n\}, \forall j \in \{1, \ldots, k\} : \\ \quad (p_{i,x} - c_x) \cos\theta_j + (p_{i,y} - c_y) \sin\theta_j \geq r \cos\left(\frac{\pi}{k}\right) \\ \quad (p_{i,x} - c_x) \cos\theta_j + (p_{i,y} - c_y) \sin\theta_j \leq (r + w) \sec\left(\frac{\pi}{k}\right) \end{cases}$$

Variables

- c_x, c_y: Coordinates of the center c of the annulus
- $r \geq 0$: Inner Radius
- $w \geq 0$: Width of the annulus ($w = R - r$)

Objective Function:

$$\min w$$

Constraint:

1. $r \geq 0,\ w \geq 0$
2. To approximate L_1 norm, we pick k directions. For a regular k-gon inscribed in the unit circle, define angles:

$$\theta_j = \frac{2\pi j}{k}, \quad j = 1, 2, \ldots, k$$

3. Compute unit vectors in these directions:

$$u_j = (\cos\theta_j, \sin\theta_j)$$

4. For each point $p_i = (p_{i,x}, p_{i,y})$ and each direction u_j:
   - Inner Boundary Constraint:

$$(p_{i,x} - c_x) \cos\theta_j + (p_{i,y} - c_y) \sin\theta_j \geq r \cos\left(\frac{\pi}{k}\right)$$

   - Outer Boundary Constraint:

$$(p_{i,x} - c_x) \cos\theta_j + (p_{i,y} - c_y) \sin\theta_j \leq (r + w) \sec\left(\frac{\pi}{k}\right)$$

   The factors $\cos\left(\frac{\pi}{k}\right)$ and $\sec\left(\frac{\pi}{k}\right)$ adjust for the approximation error due to replacing the circle with a regular k-gon.