

Assignment-2

Software Systems Lab

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- Characteristics of Dynamic Programming

- ① *Overlapping Sub-problems*

1

Subproblems are smaller versions of the original problem. Any problem has overlapping sub-problems if finding its solution involves solving the same subproblem multiple times.

- ② *Optimal Substructure*

2

Any problem has optimal substructure property if its overall optimal solution can be constructed from the optimal solutions of its subproblems.

- **Top-down with Memoization**

1

In this approach, we try to solve the bigger problem by recursively finding the solution to smaller sub-problems. Whenever we solve a sub-problem, we cache its result so that we don't end up solving it repeatedly if it's called multiple times. Instead, we can just return the saved result.

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- **Bottom-up with Tabulation**

2

Tabulation is the opposite of the top-down approach and avoids recursion. In this approach, we solve the problem “bottom-up” (i.e. by solving all the related sub-problems first).

- Divide and Conquer
- Greedy Algorithm
- Dynamic Programming

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Divide and Conquer

Example:

Quick-Sort: The average case run time of quick sort is $O(n * \log n)$. This case happens when we don't exactly get evenly balanced partitions.

Divide and Conquer

Example:

Merge Sort: The time complexity of Merge Sort is $O(n * \log n)$.

Merge Sort is useful for sorting linked lists in $O(n * \log n)$ time.

- Divide and Conquer
 - ▶ Greedy Algorithm
 - ▶▶ Dynamic Programming

List of Data Structures

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- Non-Primitive
 - *Linear*

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 - Static
 - Array
 - String
 - Dynamic
 - Linked List
 - Stack
 - Queue
 - *Non-Linear*
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 - Graph

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Data Structures

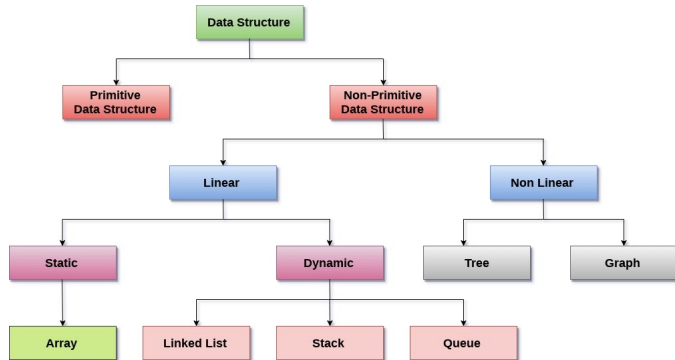


Figure: 1

Algorithm	Best Case	Average Case	Worst Case
Linear Search	$O(1)$	$O(n)$	$O(n)$
Binary Search	$O(1)$	$O(\log n)$	$O(\log n)$
Bubble Sort	$O(n)$	$O(n^2)$	$O(n^2)$
Selection Sort	$O(n^2)$	$O(n^2)$	$O(n^2)$

Table: 1

Theorem (Trigonometric Identity)

$$\sin^2\theta + \cos^2\theta = 1$$

Proof.

Let a, b, c be lengths of right angled triangle.

By definition,

$$\sin\theta = b/c \left(\frac{\text{opposite side}}{\text{hypotenuse}} \right)$$

$$\cos\theta = a/c \left(\frac{\text{adjacent side}}{\text{hypotenuse}} \right)$$

$$\sin^2\theta + \cos^2\theta = \frac{b^2}{c^2} + \frac{a^2}{c^2} = \frac{a^2+b^2}{c^2}$$

From Pythagoras' Theorem,

$$c^2 = a^2 + b^2$$

$$\frac{a^2+b^2}{c^2} = 1 \implies \sin^2\theta + \cos^2\theta = 1$$

Hence, Proved.



Multi-line Equations

$$\begin{aligned} f(x) = & x^6 + 7x^3y + 50x^3y^2 + 12x^2y^4 \\ & - 19x^5y^4 - 10x^7y^6 + 7y^4 - m^3n^3 \end{aligned}$$

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$$\begin{aligned} \rho\Delta x\Delta y\Delta z\Delta\tau\partial_t c_i(t, x, \tau) = & \rho\Delta x\Delta y\Delta z\Delta\tau(p_i - d_i) \\ & - \rho\Delta y, \Delta z\Delta\tau[q_{i,x}(t, x + \Delta x/2, y, z, \tau) \\ & \quad - q_{i,x}(t, x - \Delta x/2, y, z, \tau)] \\ & - \rho\Delta x, \Delta z\Delta\tau[q_{i,y}(t, x, y + \Delta y/2, y, z, \tau) \\ & \quad - q_{i,y}(t, x, y - \Delta y/2, z, z, \tau)] \\ & - \rho\Delta x\Delta y\Delta\tau[q_{i,z}(t, x, y, z + \Delta z/2, \tau) \\ & \quad - q_{i,z}(t, x, y, z - \Delta z/2, \tau)] \end{aligned}$$