Appendix - R Code

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# ------------------------------------------------------------------------
# Information
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#
# 14D006 Stochastic Models and Optimization
#
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# ------------------------------------------------------------------------
# Loading data
# ------------------------------------------------------------------------

# house cleaning
rm( list=ls() )

# set working directory
interactive <- TRUE
if (interactive) {
    setwd("/Users/Hans-Peter/Documents/Masters/14D006/problemsets/problemset2/code")
}

# load data
data <- as.data.frame(read.table("../data/TSM_Uruguay.txt", header=FALSE, sep=" "))
N <- nrow(data)
```

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# ------------------------------------------------------------------------
# Compute distance matrix
# ------------------------------------------------------------------------
distance.matrix <- function(data) {
    # use high dummy value for distance to itself
    dm <- matrix(10000, N, N)
    for (i in 1:N) {
        for (j in 1:N) {
            if (i != j)
                # Euclidian distance
                dm[i,j] <- round(sqrt((data[i,2] - data[j,2])**2 +
                                      (data[i,3] - data[j,3])**2),3)
        }
    }
    return(dm)
}

dm <- distance.matrix(data)
```

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# ------------------------------------------------------------------------
# Compute path length
# ------------------------------------------------------------------------
path.length <- function(dm, path) {
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    length <- 0
    N <- length(path)

    # walk through path and add up distance
    for (i in 2:N) {
        length <- length + dm[path[i-1],path[i]]
    }

    # add distance back to origin
    length <- length + dm[path[N],path[1]]
    return(length)
}
```

```r
# ----------------------------------------------------------------------
# Plot path
# ----------------------------------------------------------------------
plot.path <- function(data, path, color="red") {
    N <- length(path)

    # plot cities
    par( mar=c(0.5,0.5,0.5,0.5), mfrow=c(1,1) )
    plot(-data[,3:2], type='p', pch=16, cex=0.5, asp=1, xaxt='n', yaxt='n')

    # plot path through cities
    for (i in 2:N) {
        segments(-data[path[i-1],3], -data[path[i-1],2],
                 -data[path[i],3], -data[path[i],2], col=color)
    }
    segments(-data[path[N],3], -data[path[N],2],
             -data[path[1],3], -data[path[1],2], col=color)
}
```

```r
# ----------------------------------------------------------------------
# Nearest neighbor algorithm
# ----------------------------------------------------------------------
nn.path <- function(dm) {
    visited <- rep(0,N)
    path <- rep(0,N)

    # starting point
    city <- 1
    visited[city] <- TRUE
    path[1] <- 1

    # repeatedly visit nearest not-yet visited neighbor
    for (i in 2:N) {
        leg <- min(dm[city, !visited])

        # find index of nearest city and add it to path
        potentials <- which(dm[city,] == leg)
        for (j in 1:length(potentials)) {
            if (!visited[potentials[j]]) {
                city <- potentials[j]
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                visited[city] <- TRUE
                path[i] <- city
                break
            }
        }
    }
    return(path)
}
```

```
# ------------------------------------------------------------------------
# Insertion Heuristics
# ------------------------------------------------------------------------
insertion.path <- function(dm) {
    visited <- rep(0,N)

    # start with initial subtour
    visited[1] <- visited[2] <- visited[3] <- TRUE
    path <- c(1,2,3,1)

    while (0 %in% visited){
        # find closest unvisited city to subtour
        leg <- min(dm[!!visited, !visited])

        # find index of closest unvisited city
        potentials <- which(dm[,] == leg, arr.ind=TRUE)
        for (k in 1:nrow(potentials)) {
            if (!!visited[potentials[k,1]] & !visited[potentials[k,2]]) {
                city <- as.numeric(potentials[k,2])
                visited[city] <- TRUE
                break
            }
        }

        # find shortest detour to new city
        detour <- list(len=1000000, from=0, to=0)
        for (i in 1:(length(path)-1)) {
            pot.detour.len <- dm[path[i],city] + dm[path[i+1],city] - dm[path[i],path[i+1]]
            if (pot.detour.len < detour$len) {
                detour$len <- pot.detour.len
                detour$from <- i
                detour$to <- i+1
            }
        }
        # add detour to new path
        path <- c(path[1:detour$from], city, path[detour$to:length(path)])
    }
    return(path[1:N])
}
```

```
# ------------------------------------------------------------------------
# 2-opt path improvement
# ------------------------------------------------------------------------
two.opt.path <- function(dm, path) {
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    # (temp) add return to start
    path <- c(path, path[1])
    N <- length(path)
    changes <- TRUE

    # keep updating path until it is 2-opt path
    while (changes) {
        changes <- FALSE

        for (i in 1:(N-3)) {
            for (j in (i+2):(N-1)) {
                # if alternative path segment is shorter than current segment
                curr.len <- dm[path[i],path[i+1]] + dm[path[j],  path[j+1]]
                new.len  <- dm[path[i],path[j]]   + dm[path[i+1],path[j+1]]

                if (new.len < curr.len) {
                    # swap positions and reverse in-between segment
                    path[(i+1):j] <- path[j:(i+1)]
                    changes <- TRUE
                }
            }
        }
    }
    # return final path (without return to start)
    return(path[1:(N-1)])
}
```

```r
# ----------------------------------------------------------------------
# Run path computations and plot solutions
# ----------------------------------------------------------------------

# compute distance matrix
dm <- distance.matrix(data)

# compute nearest neighbor path
path.nn <- nn.path(dm)
path.length(dm, path.nn)
plot.path(data, path.nn, color="red")

# compute insertion heuristics path
path.insert <- insertion.path(dm)
path.length(dm, path.insert)
plot.path(data, path.insert, color="blue")

# compute 2-opt improved nearest neighbor path
path.nn.2opt <- two.opt.path(dm, path.nn)
path.length(dm, path.nn.2opt)
plot.path(data, path.nn.2opt, color="red")

# compute 2-opt improved insertion heuristics path
path.insert.2opt <- two.opt.path(dm, path.insert)
path.length(dm, path.insert.2opt)
plot.path(data, path.insert.2opt, color="blue")
```