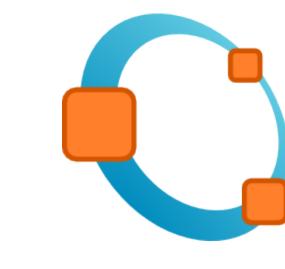
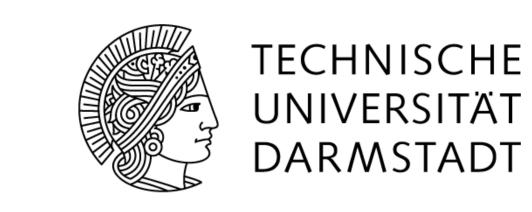




Examples for teaching mathematical programming using Octave

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Abstract

We believe that mathematical programming can be taught using surprising and nontrivial examples. Short programs shall visualise an idea. To learn how to write correct code is easier with discrete problems where rounding errors cannot conceal bugs. The lack of certain data structures (lists with $\mathcal{O}(1)$ append, queues, ...) in Octave leads to uglier code or wrong asymptotic complexity for some problems (shortest paths, minimal spanning trees, ...). You can download this poster from

https://github.com/hpodhaisky/OctConf.

```
Cellular Automatons
                       automaton.m
rule = [30, 90, 110]; n = 150;
for r = rule
 M=zeros(n,2*n); M(1,n) = 1;
 for i=2:n
   for j=2:2*n-1
     M(i,j)=bitget(r, 1+M(i-1,j-1:j+1)*[4 2 1]');
 spy(M,5); axis off; axis tight;
```

Figure: The 256 different functions $f_r: \{0,1\}^3 \to \{0,1\}$, $f_r: (x_{i-1}^i, x_i^i, x_{i+1}^i) \mapsto x_i^{i+1}$ are encoded with one value $r \in \{0, \dots, 255\}$. The evolution of the one-dimensional system over time is from top to bottom. The graphics with spy is slow.

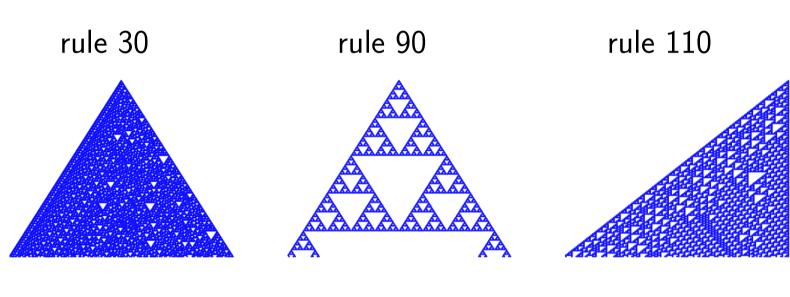


Figure: Generated with automaton.m. There is chaos, structure and even universal computation [1].

```
cells.m
k=20; n=400;
self = reshape(1:n*n,n,n);
left = self(:,[n,1:n-1]);
right = self(:,[2:n,1]);
     = self([n,1:n-1],:);
down = self([2:n,1],:);
     = floor(k*rand(n,n));
     = imagesc(Z); axis square; tic;
|for gen = 1:10000
 G = mod(Z(self)+1,k);
 i = (G==Z(down))|(G==Z(up))|(G==Z(left))|(G==Z(right));
 Z(i)=G(i); set(h, 'cdata', Z); e = toc;
 title(sprintf('%d (%5.4g fps)',gen, gen/e)); drawnow
```

Figure: A cell in state z is eaten by a neighbouring cell in state z + 1. A level of indirection makes the computation concise as well as fast.

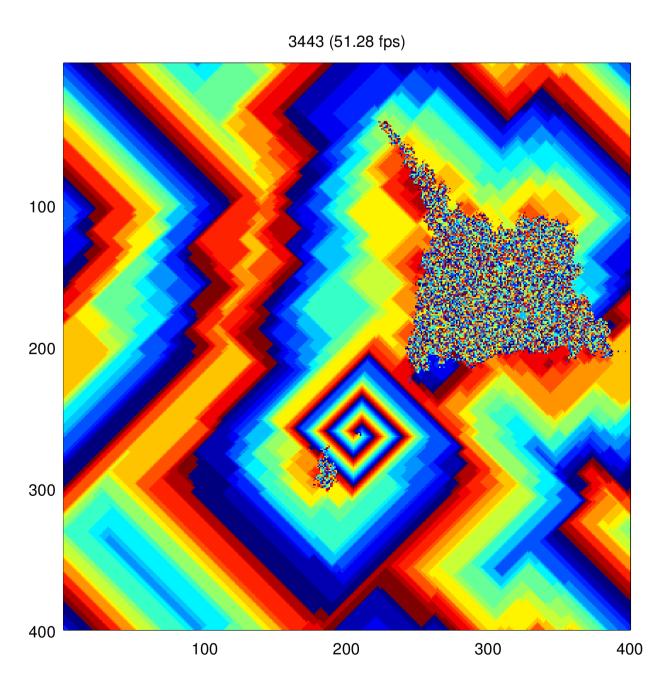


Figure: Life in a cyclic world [2], generated with cells.m. This is a snapshot of recursion to avoid maintaining a stack of coordinates. Line segments are a movie in which rotating spirals arise out of chaos.

Reaction diffusion equations

```
grayscott.m
function grayscott
m = 150; L = 2; tau = 0.1; u = ones(m,m); v = zeros(m,m);
[xx, yy] = meshgrid(linspace(0,L,m));
u(m/2+(1:20), m/2+(1:20)) = 1/2+0.1*(rand(20,20)-1);
v(m/2+(1:20), m/2+(1:20)) = 1/4+0.05*(rand(20,20)-1);
for k=0:1000000
  [du,dv] = f(u, v); u = u+tau*du; v = v+tau*dv;
  if mod(k,50)==0, contourf(xx,yy,u,linspace(0.1,0.9,4))
    title(['time t=',num2str(tau*k)]);
    axis equal; axis square; axis tight; axis off; drawnow
function [du,dv]=f(u,v)
m = 150; ip = [2:m,1]; im = [m,1:m-1]; Du = 2e-5; Dv = 1e-5;
```

Figure: Solving $u_t = D_u \Delta u - uv^2 + F(1-u), v_t = D_v \Delta v + uv^2 - (F+k)v$ with periodic boundary conditions using central differences for the Laplacians and the explicit Euler method for integration.

L = 2; h = L/m; F = 0.03; k = 0.055; $r = u.*v.^2$;

diffu = $Du/h^2*(u(ip,:)+u(im,:)+u(:,ip)+u(:,im)-4*u);$

diffv = $Dv/h^2*(v(ip,:)+v(im,:)+v(:,ip)+v(:,im)-4*v);$

du = diffu - r + F*(1-u); dv = diffv + r - (F+k)*v;

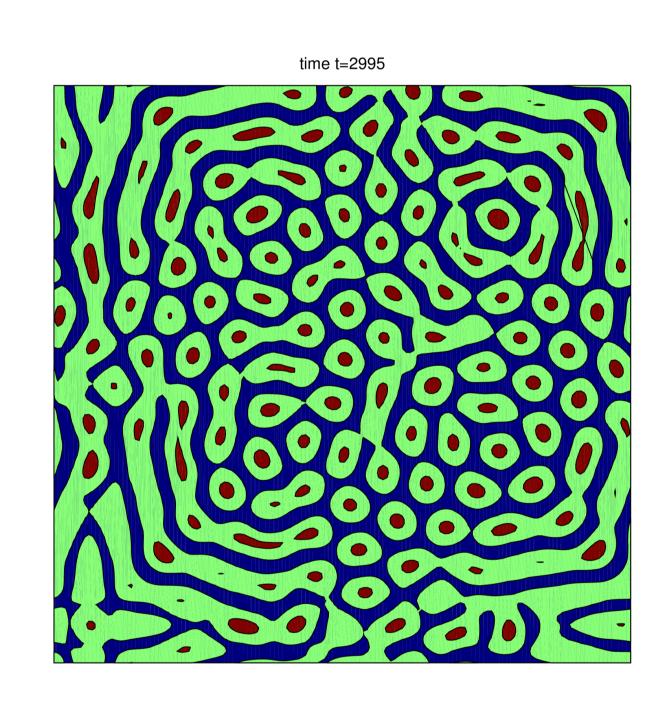


Figure: Self-organization in the Gray-Scott reaction-diffusion system [3], generated with grayscott.m.

Lindenmayer's L-systems

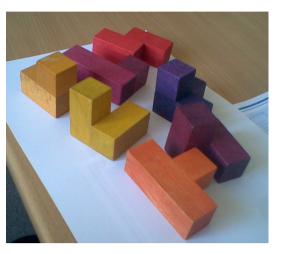
```
function lsystem(rule, scale, phi, psi, depth)
G = F(rule, scale, phi, psi, depth, 0, 0, 1j, []);
plot(real(G), imag(G))
function [G,x,dx,k] = F(r, s, phi, psi, gen, k, x, dx, G)
if gen==0, seg = [x, x+dx]; G = [G, seg]; x = seg(2);
 while k < length(r)
   k = k + 1;
    switch r(k)
    case 'F'; [G,x,dx,^{\sim}] = F(r,s,phi,psi,gen-1,0,x,dx,G);
    case '+'; dx = exp(phi*1j) * dx;
    case '-'; dx = exp(-psi*1j) * dx;
    case '['; [G, \tilde{,}, \tilde{,}k] = F(r,s,phi,psi,gen,k,x,s*dx,G);
    case ']'; G = [G, nan]; break;
    end
```

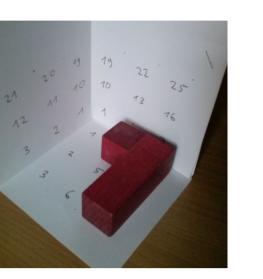
Figure: Adapted from [4]. We use complex multiplication for rotation and separated by NaNs for efficient plotting.

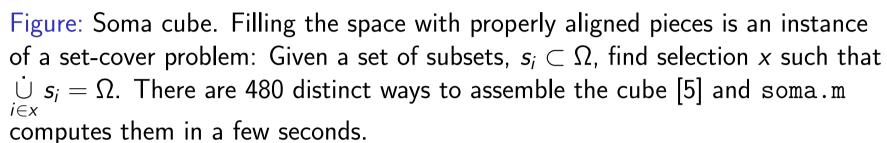
F[+F][-F][++F][--F] FF-[-F+F+F]+[+F-F-F]

Figure: Plants as generated with lsystem.m, cf. [4].

Soma cube







soma.m

pieces = $\{[1 \ 2 \ 3 \ 4], [1 \ 2 \ 4], [1 \ 2 \ 3 \ 5], [1 \ 2 \ 5 \ 6], ...$

 $[1 \ 2 \ 4 \ 10], [1,2,4,11], [1,2,4,13]$; % 3x3x3 = 27

```
for k=1:length(pieces)
  if k==1, T1 = pieces\{k\};
  else, T1 = rotations(pieces{k}); end
  for l=1:size(T1,1)
    T2=shifts(T1(1,:));
    for i=1:size(T2,1)
      c = zeros(34,1); c([T2(i,:),27+k]) = 1;
      A(:,col)=c; col=col+1;
tic, X=backtrack(A,[],1:size(A,2)), toc
function t = normal(xyz)
x=xyz(1,:);y=xyz(2,:);z=xyz(3,:);
t=sort(sub2ind([3,3,3],x-min(x)+1,y-min(y)+1,z-min(z)+1));
function T = rotations(t)
T=[t]; l=1;
Dx = [1 \ 0 \ 0; \ 0 \ 0 \ -1; \ 0 \ 1 \ 0];
Dy=[0 \ 0 \ -1; \ 0 \ 1 \ 0; \ 1 \ 0];
Dz = [0 -1 0; 1 0 0; 0 0 1];
G1={eye(3),Dz,Dz^2,Dz^3,Dy,Dy^3};
G2=\{eye(3),Dx,Dx^2,Dx^3\};
[x,y,z] = ind2sub([3,3,3],t);
for g1=G1
 for g2=G2
    D=g1\{:\}*g2\{:\}; s=normal(D*[x;y;z]);
    if all(any(T~=repmat(s,1,1),2)), T=[T;s]; l=l+1; end
function T = shifts(t)
T=[]; [x,y,z]=ind2sub([3,3,3],t);
for i=max(x):3
  for j=max(y):3
    for k=max(z):3
      s=sub2ind([3,3,3],x+i-max(x),y+j-max(y),z+k-max(z));
     T=[T;s];
function X = backtrack(A,x,active)
b=^{(sum(A(:,x),2))};
if all(b==0), X=x; somadraw(A,x);
 n = length(active); X = [];
  [egal, criticalb] = min(sum(A(b,active),2));
  bs = find(b); k = bs(criticalb);
  for w = active(find(A(k,active)==1))
```

an=active(all((A(:,active) & repmat(A(:,w),1,n))==0));

```
X=[X,backtrack(A,[x;w],an)];
```

Figure: We calculate valid placements for each piece in an empty cube (using rotations [6] and shift, whereas the L shaped piece No. 1 is not rotated to fix the rotational symmetry). The physical space $3 \times 3 \times 3$ is extended by seven components to mark the number of the piece, leading to Ax = b with $A \in \{0,1\}^{34 imes 550}$, $x \in \{0,1\}^{550}$ and $b = [1,\ldots,1]^ op$ which is solved by backtracking.

```
function somadraw(A,u)
Vertices = [ 0 0 0; 0 0 1; 0 1 0; 0 1 1
            1 0 0; 1 0 1; 1 1 0; 1 1 1 ];
Faces = [1 2 6 5; 1 2 4 3; 1 3 7 5;
        2 4 8 6; 3 4 8 7; 5 6 8 7 ];
cm = jet(7); view(3); axis([0 3 0 3 0 3]);
axis equal; axis off; cla
for k=u'
  f=(1:7)*A(28:end,k);
  for i = find(A(1:27,k))';
   [x,y,z] = ind2sub([3,3,3],i);
    patch('Vertices',0.9*Vertices+repmat([x y z]-1,8,1), ...
     'Faces', Faces, 'EdgeColor', 'k',...
     'FaceVertexCData',cm(f,:),'FaceColor','flat');
  end, drawnow
```

Figure: We're drawing complete and incomplete solutions during the calculation.

Singular value decomposition Data compression

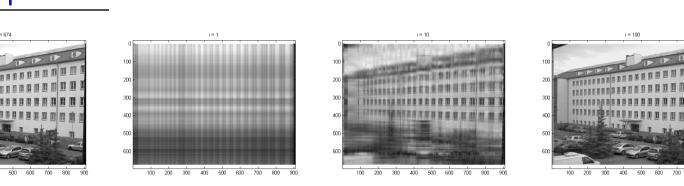


Figure: Decomposition of a given bitmap and its reconstructions using 1, 10 and 100 modes using datacompression.m

```
datacompression.m
function datacompression(file)
A = double(imread(file));
[m,n] = size(A);
[U,S,V] = svd(A);
St = zeros(size(S));
for i = 1 : min(m,n)
    St(i,i) = S(i,i);
    At = U*St*V';
                           % reconstruction using
    imagesc(At);axis equal; % just a few singular values
    title(sprintf('i = %d',i));
```

Figure: We handle the grayscale image as matrix input and reconstruct it step-by-step using its principal components aquired by Octave's svd.m routine.

Face recognition



Figure: Adjusting the face orientation and eye position using graphical user

```
adjustportrait.m
function adjustportraits(flag)
if nargin==0, flag = 'start'; end
switch flag
case 'start' % Initialize GUI
 f = figure('Units','Normalized','DefaultUicontrolUnits',...
          'Normalized', 'Position', [.1 .1 .8 .8]);
 ud.axes(1) = axes('Parent',f,'Position',[.05 .05 .4 .9]);
 ud.axes(2) = axes('Parent',f,'Position',[.8 .05 .18 .5]);
 ud.button(1) = uicontrol(f, 'Position', [.55 .9 .2 .05], ...
    'String', 'right eye', 'FontSize', 20, 'Callback', ...
        'adjustportraits(''sr'')');
 ud.check(1) = uicontrol(f, 'Position', [.8.9.05.05], ...
```

'Style', 'Text', 'FontSize', 20, 'String', ''); ud.button(2) = uicontrol(f,'Position',[.55 .8 .2 .05],... 'String', 'left eye', 'FontSize', 20, 'Callback', ... 'adjustportraits(''sl'')'); ud.check(2) = uicontrol(f,'Position',[.8 .8 .05 .05],... 'Style','Text','FontSize',20,'String',''); ud.button(4) = uicontrol(f, 'Position', [.55 .6 .2 .05], ... 'String','Okay','FontSize',20,'Callback',... 'adjustportraits(''calculate'')');

Figure: Building the graphical user interface with uicontrol.m, code snippet

ud.button(5) = uicontrol(f,'Position',[.55 .5 .2 .05],...

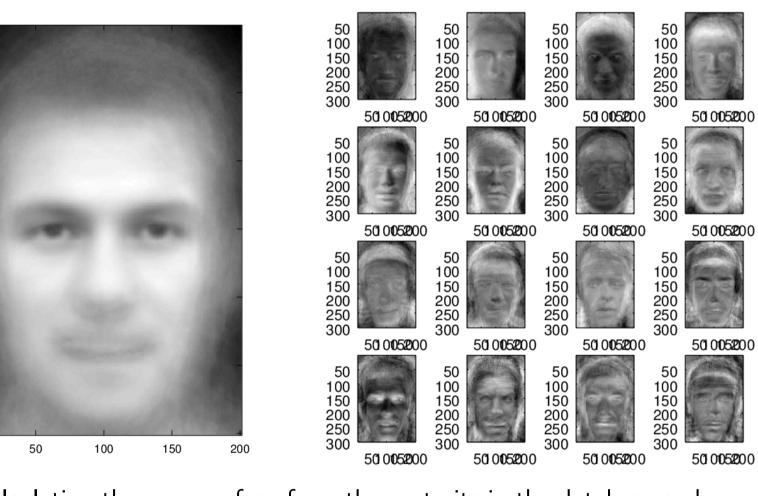


Figure: Calculating the average face from the portraits in the database and

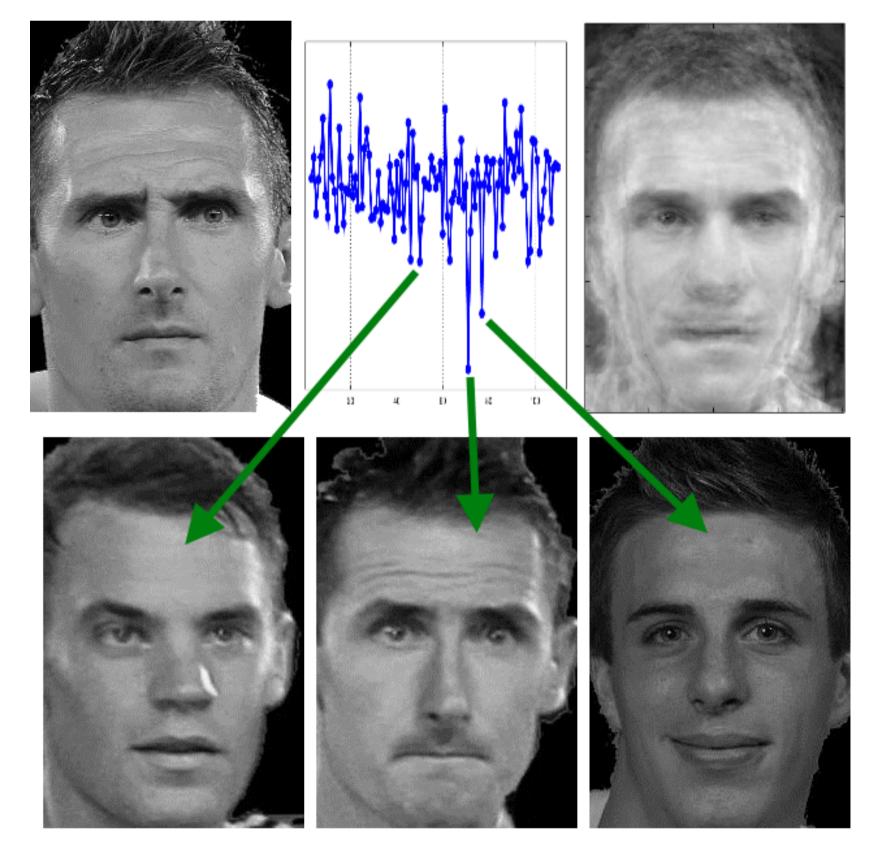


Figure: Best approximation of a picture not in the database and guesses based on eigenface estimation

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https:

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