

SYNOPSIS OF

**Generalization of Consecutive Ones Property of Binary
Matrices**

A THESIS

submitted by

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for the award of the degree

of

MASTER OF SCIENCE

(by Research)



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NOVEMBER 2011

1 Introduction

c1

c1 [set context:
COP -
generalization -
TPL - no opt. just 2
or 3 sentences. use
the space that the
illustration does.]

1.1 Illustration of the problem

A group of students, **Patricia**, **Pigpen**, **Snoopy**, **Woodstock**, **Violet**, **Linus**, **Charlie**, **Sally**, **Franklin**, **Schröeder** and **Lucy** enroll at the *Wallace Studies Institute* for a liberal arts programme. As part of their semester thesis, they pick a body of work to study and form the namesake study groups, “*Brief Interviews with Hideous Men*”, “*The String Theory*”, “[W]*Rhetoric and the Math Melodrama*” and “*Fate, Time, and Language: An Essay on Free Will*”^{c1}. A student will be in at least one study group and may be in more than one. For instance, as will be seen later, **Franklin** studies both “*Brief Interviews with Hideous Men*” and “*Fate, Time, and Language: An Essay on Free Will*” while **Woodstock** studies only “[W]*Rhetoric and the Math Melodrama*”.

c1 **TH:** [put bib
entries for these
works!]

Let U and \mathcal{F} represent the set of students and the set of study groups respectively and the integers n and m denote the total number students and study groups respectively. In relation to this example, these are defined in Table 1. Also given there is the study group allocation to students.

U	=	{ Pa , Pi , Sn , Wo , Vi , Li , Ch , Sa , Fr , Sc , Lu }
\mathcal{F}	=	{ B , T , W , F }
B	=	{ Ch , Sa , Fr , Sc , Lu }
T	=	{ Pa , Pi , Vi , Ch }
W	=	{ Sn , Pi , Wo }
F	=	{ Vi , Li , Ch , Fr }
n	=	$ U = 11$
m	=	$ \mathcal{F} = 4$

Table 1: Students and study groups in *Wallace Studies Institute*

The campus has a residential area *Infinite Loop* that has n single occupancy apartments reserved for the study groups’ accommodation. All these apartments are located such that the streets connecting them do *not* form loops. Fig ?? shows the street map for *Infinite Loop*. It may be noted that as a graph, it classifies as a tree.

A natural question would be to find how the students should be allocated apartments such that each study group has the *least distance to travel* for a discussion? More specifically, we are interested in enforcing additional conditions, namely, that all the

students in a study group must be next to each other; in other words, for one student to reach another fellow study group member's apartment (for all study groups the student is part of), she must not have to pass the apartment of any student who is not in that study group. To further elucidate, the apartments of students of any study group must be arranged in an exclusive unfragmented path on the street map. Exclusivity here means that the path must not have apartments from other study groups (unless that apartment is also part of *this* study group).

An intuitive approach to this problem would be to first find the paths that each study group decides to inhabit and then refine the allocation to individual students. A feasible allocation of exclusive routes to study groups is illustrated in Fig ?? and the students' allocation of apartments that obeys this route allocation is also shown^{c1}. How this is algorithmically computed is the focus of this thesis.

^{c1}TH: [in
Fig ref::fig:streetmappath]

As a special case, suppose all the apartments are on the same street or if they are all lined up on a single path, the street map becomes a tree that is just a path. Then the problem becomes what is called an *interval assignment problem*. The idea of interval assignment may not be obvious here; hence to see this, consider a different problem in *Wallace Studies Institute* where the classes for these study groups courses need to be scheduled during a day (or a week or any time period). Each study group has a bunch of courses associated with it some of which may be shared by two or more study groups. It is mandatory that a student who is a member of a study group takes all the courses associated with that group. There are slots during the day for classes to be held and the problem is to allocate class slots to courses such that all the classes of a study group are consecutive. It is debatable if this will not hamper the attention span and memory retention rate of the students but that is, regrettably, out of the scope of this thesis. The parallels between this class allocation problem and the accommodation problem can be seen as follows. The set U here, are the courses offered (say Course 101 "*Influence of post modernism in Wallace's work*", Course 102 "*A study on fragmented prose method*" and so on). In this variation of the problem, the collection \mathcal{F} is the set of study groups but the study groups are filled by course IDs (in place of students in the earlier example). For instance, Course 101 is mandatory for all study groups \mathbb{B} , \mathbb{T} , \mathbb{W} , \mathbb{F} and Course 102 is mandatory for only the \mathbb{B} group) and so on. The sequence of

class slots for the day (or week or any time period) is analogous to the street map in the accommodation problem. It is quite obvious now why this version of the problem (where the “target graph” is a path and not any tree^{c2}) is called an interval assignment problem.

^{c2}TH: [Allowing any tree in this example could be seen as a scenario where there are parallel classes. A node falling in the path between two other nodes would mean that the corresponding is scheduled between the other two.]

The interval assignment problem to a set system is equivalent to the consecutive ones property (COP) problem in binary matrices[Hsu02, NS09]. The COP problem is to rearrange rows (columns) of a binary matrix in such a way that every column (row) has its 1s occur consecutively. If this is possible the matrix is said to have the COP. COP is a well researched combinatorial problem and has several positive results on tests for it and computing the COP permutation (i.e. the course schedule in the above illustration) which will be surveyed later in this document. Hence we are interested in extensions of COP, more specifically, the extension of interval assignment problem to tree path assignment problem (which is illustrated by the study group accommodation problem).

Section 2 gives a brief survey of COP and optimization problems related to it. Section 4 presents a summary of our results on the extension of COP namely, the tree path labeling problem.^{c1}

^{c1}TH: [update for thesis]

2 Consecutive Ones Property Testing - a Survey

In this section, a brief survey of the consecutive ones problem and its optimization problems is presented.

2.1 Matrices with COP

As seen earlier, the interval assignment problem (illustrated as the course scheduling problem in Section 1.1), is a special case of the problem we address in this thesis, namely the tree path labeling problem (illustrated as the study group accommodation problem). The interval assignment problem and COP problem are equivalent problems. In this section we will see some of the results that exists in the literature today towards solving the COP problem and optimization problems surrounding it.

Recall that a matrix with COP is one whose rows (columns) can be rearranged so that the 1s in every column (row) are in consecutive rows (columns). Figure 1 shows examples of this property. COP in binary matrices has several practical applications

M_1 :				M'_1 :				M_2 :			
c_1	c_2	c_3	c_4	c_3	c_1	c_4	c_2	d_1	d_2	d_3	d_4
1	0	1	0	1	1	0	0	1	1	0	0
0	1	0	1	0	0	1	1	0	1	1	0
1	0	0	1	0	1	1	0	0	1	0	1

Figure 1: Matrices with and without COP. M_1 has COP because by permuting its columns, c_1 - c_4 , one can obtain M'_1 where the 1s in each row are consecutive. M_2 , however, does not have COP since no permutation of its columns, d_1 - d_4 , will arrange 1s in each row consecutively [Dom08].

in diverse fields including scheduling [HL06], information retrieval [Kou77] and computational biology [ABH98]. Further, it is a tool in graph theory [Gol04] for interval graph recognition, characterization of Hamiltonian graphs, planarity testing [BL76] and in integer linear programming [HT02, HL06].

The obvious first questions after being introduced to the consecutive ones property of binary matrices are if COP can be detected efficiently in a binary matrix and if so, can the COP permutation of the matrix also be computed efficiently? Recognition of COP in a binary matrix is polynomial time solvable and the first such algorithm was given by [FG65]. A landmark result came a few years later when [Tuc72] discovered the families of forbidden submatrices that prevent a matrix from having COP and most, if not all, results that came later were based on this discovery which connected COP in binary matrices to convex bipartite graphs. In fact, the forbidden submatrices came as a corollary to the discovery that convex bipartite graphs are AT-free in [Tuc72]^{c1}. The first linear time algorithm for COP testing (COT) was invented by [BL76] using a data structure called PQ trees. Since then several COT algorithms have been invented – some of which involved variations of PQ trees [MM96, Hsu01, McC04], some involved set theory and ICPIA [Hsu02, NS09], parallel COT algorithms [AS95, BS03, CY91] and certifying algorithms [McC04].

^{c1} [check]

The construction of PQ trees in [BL76] draws on the close relationship of matrices with COP to interval graphs. A PQ tree of a matrix is one that stores all row (column) permutations of the matrix that give the COP orders (there could be multiple orders of rows or columns) of the matrix. This is constructed using an elaborate linear time procedure and is also a test for planarity^{c2}. PQR trees is a generalized data structure based on PQ trees [MM96, MPT98]. [TM05] describes an improved algorithm to build

^{c2} [check check
check, both interval
graph and planarity
in this paper?]

PQR trees. ^{c3}[Hsu02] describes the simpler algorithm for COT. Hsu also invented PC trees [Hsu01]^{c4} which is claimed to be much easier to implement. [NS09] describes a characterization of consecutive ones property solely based on the cardinality properties of the set representations of the columns (rows); every column (row) is equivalent to a set that has the row (column) indices of the rows (columns) that have one entries in this column (row). This is interesting and relevant, especially to this thesis because it simplifies COT to a great degree. ^{c5}

^{c3}*GTC*: [improv in terms of what?]

^{c4}*TH*: [This result first appeared inproc ISAAC92]

^{c5}*GTC*: [it reduces the solution search space. fill in the blanks.]

[McC04] describes a different approach to COT. While all previous COT algorithms gave the COP order if the matrix has the property but exited stating negative if otherwise, this algorithm gives an evidence by way of a certificate of matrix even when it has no COP. This enables a user to verify the algorithm's result even when the answer is negative. This is significant from an implementation perspective because automated program verification is hard and manual verification is more viable. Hence having a certificate reinforces an implementation's credibility. Note that when the matrix *has* COP, the COP order is the certificate. The internal machinery of this algorithm is related to the weighted betweenness problem addressed^{c1} in [COR98]. ^{c2} ^{c3}

^{c1}*GTC*: [in what way??]

^{c2}*GTC*: [expand on the COP order graph creation and it having to be bipartite for M to have COP. and thus an odd cycle being an evidence of no COP.]

^{c3}*TH*: [where should this go?: (1) cite:jlm97 (application of PQ trees in graphics). (2) helly's theorem citation 19XXdgk-Hellystheorem-Danzer-Gruenbaum-Klee]

2.2 Optimization problems in COP

So far we have been concerned about matrices that have the consecutive ones property. However in real life applications, it is rare that data sets represented by binary matrices have COP, primarily due to the noisy nature of data available. At the same time, COP is not arbitrary and is a desirable property in practical data representation [COR98, JKC⁺04, Kou77]. In this context, there are several interesting problems when a matrix does not have COP but is "close" to having COP or is allowed to be altered to have COP. These are the optimization problems related to a matrix which does not have COP. Some of the significant problems are surveyed in this section.

^{c4c5} [Tuc72] showed that a matrix that does not have COP have certain substructures that prevent it from having COP. Tucker classified these forbidden substructures into five classes of submatrices. This result is presented in the context of convex bipartite graphs which [Tuc72] proved to be AT-free^{c6}. By definition, convex bipartite graph have half adjacency matrices that have COP on either rows or columns (graph is biconvex if

^{c4}*TH*: [- sect 4.1 in cite:d08phd has many results surveyed. hardness results, approx. results. results are usually for a class of matrices (a,b) where number 1s in columns and rows are restricted to a and b - problem of flipping at most k entries of M to make it attain COP. this is NP complete cite:b75-phd]

^{c5}*TH*: [(1) scite:lb62 showed that interval graphs are AT-free. describe AT (2) show the close relationship b/w COP and graphs sec 2.2, pg 31]

^{c6}*TH*: [check this up. give details. - doms']

it has COP on both)[Dom08]. A half adjacency matrix is a binary matrix representing a bipartite graph as follows. The set of rows and the set of columns form the two partitions of the graph. Each row node is adjacent to those nodes that represent the columns that have ones in the corresponding row. [Tuc72] proves that this bipartite graph has no asteroidal triple if and only if the matrix has COP and goes on to identify the forbidden substructures for these bipartite graphs. The matrices corresponding to these substructures are the forbidden submatrices.

Once a matrix has been detected to not have COP (using any of the COT algorithms mentioned earlier), it is naturally of interest to find out the smallest (in terms of number of rows and/or columns and/or number of entries that are 1s) forbidden substructure. [Dom08] discusses a couple of algorithms which are efficient if the number of ones in a row is small. This is of significance in the case of sparse matrices where this number is much lesser than the number of columns. $(*, \Delta)$ -matrices are matrices with no restriction on number of 1s in any column but has at most Δ 1s in any row. MIN COS-R (MIN COS-C), MAX COS-R (MAX COS-C) are similar problems which deals with inducing COP on a matrix. In MIN COS-R (MIN COS-C) the question is to find the minimum number of rows (columns) that must be deleted to result in a matrix with COP. In the dual problem MAX COS-R (MAX COS-C) the search is for the maximum number of rows (columns) that induces a submatrix with COP. Given a matrix M with no COP, [Boo75] shows that finding a submatrix M' with all columns^{c1} but a maximum cardinality subset of rows such that M' has COP is NP complete. [HG02] corrects an error of the abridged proof of this reduction as given in [GJ79]. [Dom08] discusses all these problems in detail giving an extensive survey of the previously existing results which are almost exhaustively all approximation results and hardness results. Taking this further, [Dom08] presents new results in the area of parameterized algorithms for this problem^{c2}.

^{c1} [check if b75 deals with COP col or COP row, also is it any submatrix with k less than r rows or submatrix must have all columns?]

^{c2} *TH*: [elaborate - what are the results?]

Another problem is to find the minimum number of entries in the matrix that can be toggled to result in a matrix with COP. [Vel85] discusses approximation of COP AUGMENTATION which is the problem of changing the minimum number of zero entries to 1s so that the resulting matrix has COP. As mentioned earlier, this problem is known to be NP complete due to [Boo75]. [Vel85] also proves, using a reduction to the longest

path problem, ^{c3} that finding a Tucker’s forbidden submatrix of at least k rows is NP complete. ^{c4 c5}

^{c3} [or is it a survey of another result? check.]

^{c4} [how is this different from booth’s 75 result??]

^{c5} *TH*: [where should this go? cite|tz04 (approx submatrix with COP sparse matrices)]

[JKC⁺04] discusses the use of matrices with almost-COP (instead of one block of consecutive 1s, they have x blocks, or *runs*, of consecutive 1s and x is not too large) in the storage of very large databases. The problem is that of reordering of a binary matrix such that the resulting matrix has at most k runs of 1s. This is proven to be NP hard using a reduction from the hamiltonian path problem. ^{c1 c2c3 c4 c5}

^{c1} *TH*: [Theorem 2.1 in jkckv]

3 Generalization of COP - The Motivation

^{c2} *TH*: [(1) A connection of COP problem to the travelling salesman problem is also introduced, what does this mean? – COP can be used as a tool to reorder $0.5T \leq runs(M) \leq T$. (2) The optimization version of the k -run problem, i.e. minimization of number of blocks of ones is proven to be NP complete by cite:k77]

As seen in Section 2.1, [NS09] describes a characterization of consecutive ones property based on the cardinality properties of the set representations of the columns. This result is very relevant to this thesis because aside from it simplifying COT to a great degree, our generalization problem is motivated by their results.

^{c3} [are these two the same?]

The result in [NS09] characterizes interval assignments to the sets which can be obtained from a single permutation of the rows. They show that for each set, the cardinality of the interval assigned to it must be same as the cardinality of the set, and the intersection cardinality of any two sets must be same as the intersection cardinality of the corresponding intervals. While this is obviously a necessary condition, this result shows this is also sufficient. [NS09] calls such an interval assignment an Intersection Cardinality Preserving Interval Assignment (ICPIA). This paper generalizes the idea from [Hsu02] of decomposing a given binary matrix into prime matrices for COT and describes an algorithm to test if an ICPIA exists for a given set system.

^{c4} *TH*: [what is the reduction?]

^{c5} *TH*: [other problems similar to COP – cite:ck196 (ILP, circ ones, one drop) – cite:th98 (generalization of COP – minimax, biotonic column) Tucker]

The tree path labeling problem is a natural generalization of the interval assignment problem or the COP problem. The problem is defined as follows – given a set system \mathcal{F} from a universe U and a tree T , does there exist a bijection from U to the vertices of T such that each set in the system maps to a path in T . We refer to this as the *tree path labeling problem* for an input set system, target tree pair – (\mathcal{F}, T) . As a special case if the tree T is a path, the problem becomes the interval assignment problem. We focus on the question of generalizing the notion of an ICPIA [NS09] to characterize feasible path assignments. We show that for a given set system \mathcal{F} , a tree T , and an assignment

of paths from T to the sets, there is a feasible bijection between U and $V(T)$ if and only if all intersection cardinalities among any three sets (not necessarily distinct) is same as the intersection cardinality of the paths assigned to them and the input passes a filtering algorithm (described in this paper) successfully. This characterization gives a natural data structure that stores all the relevant feasible bijections between U and $V(T)$. This reduces the search space for the solution considerably from the universe of all possible bijections between U and $V(T)$ to only those bijections that maintain the characterization^{c6}. Further, the filtering algorithm is also an efficient algorithm to test if a tree path labeling to the set system is feasible.

^{c6}TH: [RE-WORD]

4 Summary of results

As we saw earlier by the result in [NS09], pairwise intersection cardinality preservation is necessary and sufficient for an interval assignment to be feasible for a given hypergraph^{c0} and thus is a characterization for COP. In our work we extend this characterization and find that trio-wise intersection cardinality preservation makes a tree path labeling (TPL) feasible, which is a generalization of the COP problem. This problem, FEASIBLE TREE PATH LABELING^{c0}, is defined as follows.

FEASIBLE TREE PATH LABELING

Input	A hypergraph \mathcal{F} with vertex set U , a tree T and a bijection $\ell : \mathcal{F} \rightarrow \mathcal{P}$, where \mathcal{P} is a set of paths from T .
Question	Does there exist a bijection $\phi : U \rightarrow V(T)$ such that ϕ when applied on any hyperedge in \mathcal{F} will give the path mapped to it by the given tree path labeling ℓ . i.e., $\ell(S) = \{\phi(x) \mid x \in S\}$, for every hyperedge $S \in \mathcal{F}$.

We give a necessary and sufficient condition for FEASIBLE TREE PATH LABELING to output in affirmative. This characterization can be checked in polynomial time. The most interesting consequence is that in our constructive procedure, it is sufficient to

^{c0}A *hypergraph* is an alternate representation of a set system and will be used through out this section.

^{c0}A *tree path labeling* ℓ is a bijection of paths from the target tree T to the hyperedges in given hypergraph \mathcal{F} .

iteratively check if three-way intersection cardinalities are preserved. In other words, in each iteration, it is sufficient to check if the intersection of any three hyperedges is of the same cardinality as the intersection of the corresponding paths. Thus this generalizes the well studied question of the feasible interval assignment problem which is the special case when the target tree T is simply a path [Hsu02, NS09].

Aside from checking if a given TPL is feasible, we also solve the problem of computing a feasible TPL for a given hypergraph and target tree, if one exists. This problem, **COMPUTE FEASIBLE PATH LABELING**, is defined as follows.

COMPUTE FEASIBLE PATH LABELING

Input	A hypergraph \mathcal{F} with vertex set U and a tree T .
Question	Does there exist a set of paths \mathcal{P} from T and a bijection $\ell : \mathcal{F} \rightarrow \mathcal{P}$, such that FEASIBLE TREE PATH LABELING returns true on (\mathcal{F}, T, ℓ) .

We present a polynomial time algorithm for **COMPUTE FEASIBLE PATH LABELING** when the target tree T belongs to a special class of trees called *k-subdivided stars* and when the hyperedges in the hypergraph \mathcal{F} have at most $k + 2$ vertices. The examples of *k-subdivided stars* given in Figure 2 makes the definition clear.

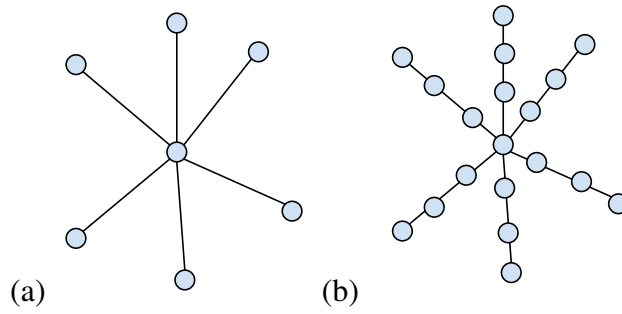


Figure 2: Examples of *k-subdivided stars*. (a) $k = 0$ (b) $k = 2$

COMPUTE k -SUBDIVIDED STAR PATH LABELING

Input	A hypergraph \mathcal{F} with vertex set U such that every hyperedge $S \in \mathcal{F}$ is of cardinality atmost $k + 2$ and a k -subdivided star T .
Question	Does there exist a set of paths \mathcal{P} from T and a bijection $\ell : \mathcal{F} \rightarrow \mathcal{P}$, such that FEASIBLE TREE PATH LABELING returns true on (\mathcal{F}, T, ℓ) .

In spite of this restricted case we consider, we believe that our results are of significant interest in understanding the nature of GRAPH ISOMORPHISM which is polynomial time solvable in interval graphs while being hard on path graphs[KKLV10].

^{c1}

^{c1} [give gyan on why ktree is so.]

We also have an algorithm for solving COMPUTE FEASIBLE PATH LABELING with no restrictions which runs in exponential time and explores a partial order theory of matrices related to FTPL. This po theory gives interesting insight into the problem of finding path labeling from T by decomposing it into smaller subproblems of finding path labeling of subsets of \mathcal{F} from subtrees of T .^{c2}

^{c2} *TH*: [The connection of TPL to graph isomorphism will be made later in the document]

5 Conclusion

Our results also have close connection to recognition of path graphs and connection to path graph isomorphism. Graphs which can be represented as the intersection graph of paths in a tree are called *path graphs*[Gol04]. Thus given a hypergraph \mathcal{F} , it can be viewed as paths in a tree, if and only if the intersection graph of \mathcal{F} is a *path graph*. Path graphs are a subclass of chordal graphs since chordal graphs are combinatorially characterized as the intersection graphs of subtrees of a tree. Path graphs are well studied in the literature [Ren70, Gav78, BP92, Gol04]. Checking if a graph is a path graph can be done in polynomial time by the results of [Gav78, Sch93]. However, this is only a necessary condition for our question.^{c3} On the other hand, path graph isomorphism is known to be isomorphism-complete; see for example [KKLV10]. Therefore, ^{c4}it is unlikely that we can solve the problem of finding feasible path labeling ℓ for a given \mathcal{F} and tree T .^{c5}It is definitely interesting to classify the kinds of trees and hypergraphs

^{c3} Indeed, our work provides a sufficient condition for a related problem: that is whether a path assignment to be feasible?

^{c4} WHY?

^{c5} ELABORATE

for which feasible path labelings can be found efficiently. ^{c6}These results would form a natural generalization of COP testing and interval graph isomorphism, culminating in Graph Isomorphism itself.

^{c6} REWORD

^{c1} As it will be described in detail later in this document, isomorphism of certain classes of graphs, namely chordal graphs, have a close relationship with consecutive ones property and generalizations of it. This is perhaps because of how closely COP of a matrix relates to properties of graphs derived from matrices as seen in the following results. ^{c2} A well known result in perfect graph theory is that the maximal cliques of an interval graph G can be linearly ordered such that for all $v \in V(G)$, cliques containing v are consecutive in the

^{c1} [MAKE CONNECTION TO PATH GRAPH ISOMORPHISM HERE]

^{c2} TH: [peo exists iff chordal, lexicographic BFS [tag:chordalGraph]]

ordering [GH64]. This clearly means that a graph G is an interval graph if and only if ^{c3} maximal clique vertex incidence matrix of G has COP. Also, maximal cliques of any chordal graph can be enumerated in polytime $O(m+n)$ ^{c4}. [FG65] uses these results to give the first polynomial time algorithm for COT. ^{c5} A bipartite graph is convex (on R) if and only if its half adjacency matrix has COP on rows. The results in [BL76] on COT are based on the result that interval graphs are AT-free chordal graphs. ^{c6}

^{c3} [verify from paper the statement of claim.]

^{c4} [citation?!]

^{c5} TH: [check, how do they use it?]

^{c6} [the latter being Tucker's?]

^{c7}

Complexity challenges: Canonization is an important tool in graph isomorphism. Invention of a deterministic method of canonization for any class of graphs naturally results in an algorithm for isomorphism. All that is required is to check if the canons of two graphs are the same. Thus complexity of graph isomorphism can be studied by studying canonization methods. While general graph isomorphism remains elusive in terms of hardness, canonization has been studied for smaller classes of graphs thus giving complexity/hardness results for them.

^{c7} TH: [(1) How COP (and TPL) relates to interval graph isomorphism (and path graph isomorphism) move/summarize what is already in Motivation section.(2) TBD survey – see blue notes under Graph Isomorphism. namely citations in cite:aas93 (3) a brief on heirarchy of chordal graphs, path graphs, interval graphs, peo, clique tree etc. and results. (4) interval graphs are incomparability graphs, see Golumbic. [tag:classification] (5) finding min length hole in bipartite graph is polynomial time [Sec 3.3.2 in cite:d08phd] (6) theorem 2.2 in cite:d08phd - G is union of v.d. caterpillars iff M has COP in rows. M is edge vertex incidence matrix $(*, 2)$ of G]

In 1992, [Lin92] made an important discovery that tree isomorphism is in logspace. It was done by inventing a method of canonization of trees using a logspace depth first traversal algorithm. ^{c8}.

^{c8} [confirm the statement of claim]

[KKLV10] proved that interval graph canonization is also in logspace thus drawing logspace conclusions about COT. Interval graphs are FP+C (fixed point with counting) definable ^{c9} and [Lau09] showed that this implies that it captures PTIME. ^{c10} This result

^{c9} [elucidate]

^{c10} [elucidate]

along with that of undirected graph reachability being in logspace [Rei08], [KKLV10] proved their logspace result.

c1

c1 *TH:* [(1) the interesting survey in conclusion section of kklv10 (2) [[[COP helping some problems with hardness]]] having COP in the input structure makes some problems less hard than in a general input. – min set cover problem is known to be NP hard. so is min hitting set. these two problems are equivalent cite-adp80 – – complexity results: log factor polynomial time approximable cite-f98, W[2]-complete with solution size as parameter cite-df99 – a couple of generalizations: – – min degree hypergraph (MDH) problem – – red blue covering (RBSC) problem — cite-d08phd Chapter 5. — what are cite-d08phd results — Rectangle stabbing — see cite-d08phd Chapter 6?]

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6 Proposed Contents of the Thesis

The outline of the thesis is as follows:

Chapter 1 - Introduction

Section 1.1 Consecutive Ones Testing

Section 1.2 Matrix modification to attain COP or “almost” COP

Section 1.3 Graph Isomorphism

Section 1.4 Logspace complexity of graph canonization using COP

Section 1.5 Motivation, Objective and Scope of Thesis

Section 1.6 Summary of Results

Section 1.7 Organization of document

Chapter 2 - Consecutive ones property

Section 2.1 Characterization of COP

Section 2.2 Recognition of COP

Section 2.3 Alteration to matrices to get COP

Section 2.4 Complexity of certain COP variations

Chapter 3 - Other problems related to COP

Chapter 4 Research

Section 4.1 Tree path labeling of path hypergraphs

Section 4.2 Extension of po theory from [NS09]

Chapter 5 - Conclusion

Chapter 6 - Bibliography