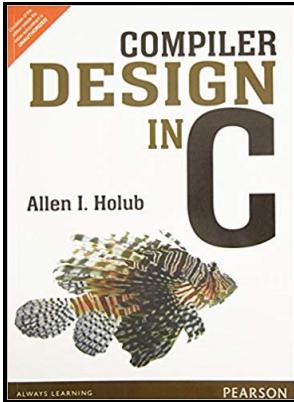


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How to calculate Complexity of an Algorithm? (+ different Notations)

Comparing the Google and IBM architectures of the same size, we expect planners should be able to find equal or shorter makespan plans given that they have the same overall shape except that the IBM ones have some additional connections.

Third generation compiler design

For the Graph Coloring problem, each qstate represents a vertex-color combination. Underlined values are the best makespan produced by any planner when this best makespan is worse than the analytical bound. Additionally, we apply a planning approach to initialization.

Third generation compiler design

Bound TFD OPTIC LPG SGPLAN 4×3 Grid 19 20 35 16 13 4×4 Grid 20 30 56 20 38 5×4 Grid 24 54 116 79 46 8×3 Grid 35 25 53
 $36 - 4 \times 3$ Line 64 51 77 48 90 4×4 Line 80 71 116 107 177 5×4 Line 100 118 - 140 194 8×3 Line 128 81 - 157 267 Table 2: Comparing against analytical bounds for special hardware architectures: grid and line.

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More importantly, decoherence effects can destroy the computation in a short time and thus minimizing computation time is therefore vital to obtain results on near-term quantum hardware that does not support significant quantum error correction. Planning Domain Description Language PDDL : The de-facto standard modeling languages used by many domain-independent planners.

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