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1.2. Linear Programming: A Graphical Perspective in R2 13 The feasible region is shown in Figure 1.4. The LP has alternative optimal solutions that fall on the segment connecting $x = \begin{bmatrix} 3 \\ 1 \end{bmatrix}$ to $x = \begin{bmatrix} 6 \\ 0 \end{bmatrix}$. Each such solution has an objective value of $z = 12$, and the parametric representation of the segment is given by $x = \begin{bmatrix} 3t+6(1-t) \\ t+0(1-t) \end{bmatrix} = \begin{bmatrix} 6-3t \\ t \end{bmatrix}$, where $0 \le t \le 1$.

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STUDENT'S SOLUTIONS MANUAL Introduction to Linear Programming by L. N. Vaserstein Last updated November 29, 2016 This manual includes: corrections to the textbook, additional references, answers and solutions for exercises the textbook, tips, hints, and remarks.

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Solution Manual For: Introduction to Linear Optimization by Dimitris Bertsimas & John N. Tsitsiklis John L. Weatherwax∗ November 22, 2007 Introduction Acknowledgements Special thanks to Dave Monet for helping find and correct various typos in these solutions. Chapter 1 (Introduction) Exercise 1.1 Since f(·) is convex we have that

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Section 1.1. Solutions Chapter 1. SECTION 1.1 1.1.9 www. For any $x, y \in Rn$, from the second order expansion (see Appendix A, Proposition A.23) we have. $f(y)-f(x)=(y-x)\nabla f(x)+ \frac{1}{2}(y-x)\nabla^2 f(z)(y-x)$, (1) where z is some point of the line segment joining x and y.

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The linear programming part consists of Chapters 3 to 8. In Chapter 3 the simplex method is developed in detail, and in Chapter 4 the initiation of the simplex method by the use of artificial variables and the problem of degeneracy and cycling along with geometric concepts are discussed.

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