# An Approximation Approach to Computationally Expensive Multiobjective Optimization Problems 

Markus Hartikainen

April 12, 2010

## Table of contents

(1) Me
(2) My Dissertation
(3) A Multiobjective Optimization Problem

4 A Computationally Expensive Multiobjective Optimization Problem
(5) Inherent Nondominance

6 Constructing Inherently Nondominated Complexes
(7) Constructing an Inherently Nondominated Pareto Front Approxiation
(8) Properties of the Constructed Inherently Nondominated Pareto Front approximation
(9) Further Research
(10) References
(11) Thank You!

## Me

- Name: Markus Hartikainen


## Me

- Name: Markus Hartikainen
- Ph. Lic. in mathematics (mathematical analysis)


## Me

- Name: Markus Hartikainen
- Ph. Lic. in mathematics (mathematical analysis)
- Interested in optimization, scientific computing, statistics, pedagogy


## My Dissertation

- Area: multiobjective optimization


## My Dissertation

- Area: multiobjective optimization
- Advisors: professor Kaisa Miettinen and visiting professor Margaret M. Wiecek


## My Dissertation

- Area: multiobjective optimization
- Advisors: professor Kaisa Miettinen and visiting professor Margaret M. Wiecek
- A collection of articles


## My Dissertation

- Area: multiobjective optimization
- Advisors: professor Kaisa Miettinen and visiting professor Margaret M. Wiecek
- A collection of articles
- Two conference proceedings articles (that are to be refereed) submitted. Other one of these has been published in the report series of the department [Hartikainen et al., 2010].


## My Dissertation

- Area: multiobjective optimization
- Advisors: professor Kaisa Miettinen and visiting professor Margaret M. Wiecek
- A collection of articles
- Two conference proceedings articles (that are to be refereed) submitted. Other one of these has been published in the report series of the department [Hartikainen et al., 2010].
- One journal manuscript almost ready (to be submitted in $1-2$ weeks).


## My Dissertation

- Area: multiobjective optimization
- Advisors: professor Kaisa Miettinen and visiting professor Margaret M. Wiecek
- A collection of articles
- Two conference proceedings articles (that are to be refereed) submitted. Other one of these has been published in the report series of the department [Hartikainen et al., 2010].
- One journal manuscript almost ready (to be submitted in $1-2$ weeks).
- Two more papers planned (and I also have something on paper already).


## My Dissertation

- Area: multiobjective optimization
- Advisors: professor Kaisa Miettinen and visiting professor Margaret M. Wiecek
- A collection of articles
- Two conference proceedings articles (that are to be refereed) submitted. Other one of these has been published in the report series of the department [Hartikainen et al., 2010].
- One journal manuscript almost ready (to be submitted in $1-2$ weeks).
- Two more papers planned (and I also have something on paper already).
- The plan is to defend my thesis in 2011.


## A Multiobjective optimization problem (MOP)

$\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right)$ so that $x \in S$

## A Multiobjective optimization problem (MOP)

- Objective functions

$$
\begin{gathered}
\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right) \\
\text { so that } x \in S
\end{gathered}
$$

## A Multiobjective optimization problem (MOP)

- Objective functions

$$
\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right)
$$

- Decision variable



## A Multiobjective optimization problem (MOP)

- Objective functions

$$
\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right)
$$

- Decision variable
- Decision space



## A Multiobjective optimization problem (MOP)

- Objective functions

$$
\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right)
$$

- Decision variable
- Decision space
- The set $f(S)$, where $f(x)=\left(f_{1}(x), \ldots, f_{k}(x)\right)$ for all $x \in S$, is called the outcome space.


## A Multiobjective optimization problem (MOP)

- Objective functions

$$
\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right)
$$

- Decision variable
- Decision space
- The set $f(S)$, where $f(x)=\left(f_{1}(x), \ldots, f_{k}(x)\right)$ for all $x \in S$, is called the outcome space.
- A vector $z \in f(S)$ is called an outcome.


## A Multiobjective optimization problem (MOP)

- Objective functions

$$
\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right)
$$

- Decision variable
- Decision space
- The set $f(S)$, where $f(x)=\left(f_{1}(x), \ldots, f_{k}(x)\right)$ for all $x \in S$, is called the outcome space.
- A vector $z \in f(S)$ is called an outcome.
- An outcome $z^{1}$ is said to dominate another outcome $z^{2}$ if $z_{i}^{1} \leq z_{i}^{2}$ for all $i=1, \ldots, k$ and $z_{j}^{1} \leq z_{j}^{2}$ for some $j=1, \ldots, k$.


## A Multiobjective optimization problem (MOP)

- Objective functions

$$
\operatorname{minimize}\left(f_{1}(x), \ldots, f_{k}(x)\right)
$$

- Decision variable
- Decision space

- The set $f(S)$, where $f(x)=\left(f_{1}(x), \ldots, f_{k}(x)\right)$ for all $x \in S$, is called the outcome space.
- A vector $z \in f(S)$ is called an outcome.
- An outcome $z^{1}$ is said to dominate another outcome $z^{2}$ if $z_{i}^{1} \leq z_{i}^{2}$ for all $i=1, \ldots, k$ and $z_{j}^{1} \leq z_{j}^{2}$ for some $j=1, \ldots, k$.
- A decision variable $x \in S$ is called a Pareto optimal (PO) solution if there does not exist an outcome $z \in f(S)$ that dominates $f(x)$ and the outcome $f(x)$ given by a PO solution $x$ is called a PO outcome.


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.
- Calculating PO solutions is time consuming.


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.
- Calculating PO solutions is time consuming.
- The computational expense for getting a "good representation" of PO solutions is unacceptable.


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.
- Calculating PO solutions is time consuming.
- The computational expense for getting a "good representation" of PO solutions is unacceptable.
- Interactive methods fail because the decision maker (DM) gets anxious while waiting for new solutions to be computed according to his/her preferences.


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.
- Calculating PO solutions is time consuming.
- The computational expense for getting a "good representation" of PO solutions is unacceptable.
- Interactive methods fail because the decision maker (DM) gets anxious while waiting for new solutions to be computed according to his/her preferences.
- Our approach:


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.
- Calculating PO solutions is time consuming.
- The computational expense for getting a "good representation" of PO solutions is unacceptable.
- Interactive methods fail because the decision maker (DM) gets anxious while waiting for new solutions to be computed according to his/her preferences.
- Our approach:
(1) Construct an approximation of the Pareto front (PF) based on a small set of PO outcomes.


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.
- Calculating PO solutions is time consuming.
- The computational expense for getting a "good representation" of PO solutions is unacceptable.
- Interactive methods fail because the decision maker (DM) gets anxious while waiting for new solutions to be computed according to his/her preferences.
- Our approach:
(1) Construct an approximation of the Pareto front (PF) based on a small set of PO outcomes.
(2) Use interactive multiobjective optimization (MO) methods (see e.g., [Miettinen, 1999]) for finding the preferred outcome on the approximation.


## A Computationally Expensive MOP

- Calculation of objective functions is computationally expensive.
- Calculating PO solutions is time consuming.
- The computational expense for getting a "good representation" of PO solutions is unacceptable.
- Interactive methods fail because the decision maker (DM) gets anxious while waiting for new solutions to be computed according to his/her preferences.
- Our approach:
(1) Construct an approximation of the Pareto front (PF) based on a small set of PO outcomes.
(2) Use interactive multiobjective optimization (MO) methods (see e.g., [Miettinen, 1999]) for finding the preferred outcome on the approximation.
(3) Find the PO solution that is closest to the preferred point by means of an achievement scalarizing function [Wierzbicki, 1986].


## A Pareto front approximation $\Rightarrow$ inherent nondominance

## Definition

A set $A \subset \mathbb{R}^{k}$ is called inherently nondominated (IND) if there does not exist $z^{1}, z^{2} \in A$ so that $z^{1}$ dominates $z^{2}$. An IND set $A$ is called an IND PF approximation based on $P$, if $P \subset \mathbb{R}^{k}$ is a finite set of PO outcomes and $P \subset A$.

## A Pareto front approximation $\Rightarrow$ inherent nondominance

## Definition

A set $A \subset \mathbb{R}^{k}$ is called inherently nondominated (IND) if there does not exist $z^{1}, z^{2} \in A$ so that $z^{1}$ dominates $z^{2}$. An IND set $A$ is called an IND PF approximation based on $P$, if $P \subset \mathbb{R}^{k}$ is a finite set of PO outcomes and $P \subset A$.

- An IND PF approximation


## A Pareto front approximation $\Rightarrow$ inherent nondominance

## Definition

A set $A \subset \mathbb{R}^{k}$ is called inherently nondominated (IND) if there does not exist $z^{1}, z^{2} \in A$ so that $z^{1}$ dominates $z^{2}$. An IND set $A$ is called an IND PF approximation based on $P$, if $P \subset \mathbb{R}^{k}$ is a finite set of PO outcomes and $P \subset A$.

- An IND PF approximation
- can be searched with interactive MO methods for a preferred solution.


## A Pareto front approximation $\Rightarrow$ inherent nondominance

## Definition

A set $A \subset \mathbb{R}^{k}$ is called inherently nondominated (IND) if there does not exist $z^{1}, z^{2} \in A$ so that $z^{1}$ dominates $z^{2}$. An IND set $A$ is called an IND PF approximation based on $P$, if $P \subset \mathbb{R}^{k}$ is a finite set of PO outcomes and $P \subset A$.

- An IND PF approximation
- can be searched with interactive MO methods for a preferred solution.
- avoids misleading the DM in what is attainable and what not.


## A Pareto front approximation $\Rightarrow$ inherent nondominance

## Definition

A set $A \subset \mathbb{R}^{k}$ is called inherently nondominated (IND) if there does not exist $z^{1}, z^{2} \in A$ so that $z^{1}$ dominates $z^{2}$. An IND set $A$ is called an IND PF approximation based on $P$, if $P \subset \mathbb{R}^{k}$ is a finite set of PO outcomes and $P \subset A$.

- An IND PF approximation
- can be searched with interactive MO methods for a preferred solution. See [Hartikainen et al., 2010]
- avoids misleading the DMin what is attainable and what not.


## A Pareto front approximation $\Rightarrow$ inherent nondominance

## Definition

A set $A \subset \mathbb{R}^{k}$ is called inherently nondominated (IND) if there does not exist $z^{1}, z^{2} \in A$ so that $z^{1}$ dominates $z^{2}$. An IND set $A$ is called an IND PF approximation based on $P$, if $P \subset \mathbb{R}^{k}$ is a finite set of PO outcomes and $P \subset A$.

- An IND PF approximation
- can be searched with interactive MO methods for a preferred solution. See [Hartikainen et al., 2010]
- avoids misleading the DMin what is attainable and what not.
- Also the (actual) PF is by definition an IND PF approximation based on any set of PO outcomes $P$.


## Constructing Inherently Nondominated Complexes: Basic Definitions

## Constructing Inherently Nondominated Complexes: Basic Definitions

- Polytope



## Constructing Inherently Nondominated Complexes: Basic Definitions

- Polytope
- Vertices



## Constructing Inherently Nondominated Complexes: Basic Definitions

- Polytope
- Vertices
- Faces



## Constructing Inherently Nondominated Complexes: Basic Definitions

- Polytope
- Vertices
- Faces
- A collection of polytopes is a complex if


## Constructing Inherently Nondominated Complexes: Basic Definitions

- Polytope
- Vertices
- Faces
- A collection of polytopes is a complex if
(1) every face of a polytope in the collection is also in the collection and


## Constructing Inherently Nondominated Complexes: Basic Definitions

- Polytope
- Vertices
- Faces
- A collection of polytopes is a complex if
(1) every face of a polytope in the collection is also in the collection and
(2) an intersection of two polytopes in the collection is a face of each of them.


## Constructing Inherently Nondominated Complexes: Basic Definitions

- Polytope
- Vertices
- Faces
- A collection of polytopes is a complex if
(1) every face of a polytope in the collection is also in the collection and
(2) an intersection of two polytopes in the collection is a face of each of them.
- A complex $\mathcal{D}$ is a Delaunay triangulation of a finite set $P \subset \mathbb{R}^{k}$ if $\cup_{K \in \mathcal{D}} K=\operatorname{conv}(P)$ and the complex only contains "polytopes with neighbouring vertices" (see [Edelsbrunner, 1987]).


## Constructing an Inherently Nondominated Complex

- A complex $\mathcal{K}$ is said to be IND if the set $\cup_{K \in \mathcal{K}} K$ is IND.


## Constructing an Inherently Nondominated Complex

- A complex $\mathcal{K}$ is said to be IND if the set $\cup_{K \in \mathcal{K}} K$ is IND.
- A polytope $K^{1}$ is said to dominate another polytope $K^{2}$ if there exists $s^{1} \in K^{1}$ and $s^{2} \in K^{2}$ so that $s^{1}$ dominates $s^{2}$.


## Constructing an Inherently Nondominated Complex

- A complex $\mathcal{K}$ is said to be IND if the set $\cup_{K \in \mathcal{K}} K$ is IND.
- A polytope $K^{1}$ is said to dominate another polytope $K^{2}$ if there exists $s^{1} \in K^{1}$ and $s^{2} \in K^{2}$ so that $s^{1}$ dominates $s^{2}$.
- Theorem: A complex $\mathcal{K}$ is IND if and only if there does not exist $K^{1}, K^{2} \in \mathcal{K}$ so that $K^{1}$ dominates $K^{2}$.


## Constructing an Inherently Nondominated Complex

- A complex $\mathcal{K}$ is said to be IND if the set $\cup_{K \in \mathcal{K}} K$ is IND.
- A polytope $K^{1}$ is said to dominate another polytope $K^{2}$ if there exists $s^{1} \in K^{1}$ and $s^{2} \in K^{2}$ so that $s^{1}$ dominates $s^{2}$.
- Theorem: A complex $\mathcal{K}$ is IND if and only if there does not exist $K^{1}, K^{2} \in \mathcal{K}$ so that $K^{1}$ dominates $K^{2}$.
- We aim to construct a complex that is an IND PF approximation.


## Constructing an Inherently Nondominated Complex

- A complex $\mathcal{K}$ is said to be IND if the set $\cup_{K \in \mathcal{K}} K$ is IND.
- A polytope $K^{1}$ is said to dominate another polytope $K^{2}$ if there exists $s^{1} \in K^{1}$ and $s^{2} \in K^{2}$ so that $s^{1}$ dominates $s^{2}$.
- Theorem: A complex $\mathcal{K}$ is IND if and only if there does not exist $K^{1}, K^{2} \in \mathcal{K}$ so that $K^{1}$ dominates $K^{2}$.
- We aim to construct a complex that is an IND PF approximation.
- The aim is thus to construct such a complex $\mathcal{K}$ that $\{p\} \in \mathcal{K}$ for all $p \in P$ and there does not exist $K^{1}, K^{2} \in \mathcal{K}$ so that $K^{1}$ dominates $K^{2}$.


## Constructing an Inherently Nondominated Complex

- A complex $\mathcal{K}$ is said to be IND if the set $\cup_{K \in \mathcal{K}} K$ is IND.
- A polytope $K^{1}$ is said to dominate another polytope $K^{2}$ if there exists $s^{1} \in K^{1}$ and $s^{2} \in K^{2}$ so that $s^{1}$ dominates $s^{2}$.
- Theorem: A complex $\mathcal{K}$ is IND if and only if there does not exist $K^{1}, K^{2} \in \mathcal{K}$ so that $K^{1}$ dominates $K^{2}$.
- We aim to construct a complex that is an IND PF approximation.
- The aim is thus to construct such a complex $\mathcal{K}$ that $\{p\} \in \mathcal{K}$ for all $p \in P$ and there does not exist $K^{1}, K^{2} \in \mathcal{K}$ so that $K^{1}$ dominates $K^{2}$.
- With minor extra conventions, this can be seen as a shape reconstruction problem as defined in [Edelsbrunner, 1998].


## Constructing an Inherently Nondominated Complex (continued)

- Theorem: A polytope $K^{1}$ dominates another polytope $K^{2}$ if and only if either


## Constructing an Inherently Nondominated Complex (continued)

- Theorem: A polytope $K^{1}$ dominates another polytope $K^{2}$ if and only if either
(1) the optimal value in optimization problem

$$
\begin{align*}
& \min \\
& \text { s.t. } s^{1} \in K^{1}, s^{2} \in K^{2}
\end{align*} \max _{i=1, \ldots, k}\left(s_{i}^{1}-s_{i}^{2}\right)
$$

is less than 0 or

## Constructing an Inherently Nondominated Complex (continued)

- Theorem: A polytope $K^{1}$ dominates another polytope $K^{2}$ if and only if either
(1) the optimal value in optimization problem

$$
\begin{align*}
& \min \\
& \text { s.t. } s^{1} \in K^{1}, s^{2} \in K^{2} \tag{1}
\end{align*}
$$

is less than 0 or
(2) optimal value in problem (1) is 0 and the optimal value in optimization problem

$$
\begin{array}{ll}
\min & \sum_{i=1}^{k}\left(s_{i}^{1}-s_{i}^{2}\right)  \tag{2}\\
\text { s.t. } & s^{1} \in K^{1}, s^{2} \in K^{2} \\
& s_{i}^{1} \leq s_{i}^{2} \text { for all } i=1, \ldots, k
\end{array}
$$

is less than zero.

## Constructing an IND PF Approximation

- So we have


## Constructing an IND PF Approximation

- So we have
- a way to compute a finite set of PO solutions to computationally expensive MOP (a suitable a posteriori method),


## Constructing an IND PF Approximation

- So we have
- a way to compute a finite set of PO solutions to computationally expensive MOP (a suitable a posteriori method),
- a way to construct all the polytopes given by neighboring vertices (Delaunay triangulation of the PO outcomes) and


## Constructing an IND PF Approximation

- So we have
- a way to compute a finite set of PO solutions to computationally expensive MOP (a suitable a posteriori method),
- a way to construct all the polytopes given by neighboring vertices (Delaunay triangulation of the PO outcomes) and
- a way to find out all the dominations between polytopes (by solving problems (1) and (2)).


## Constructing an IND PF Approximation

- So we have
- a way to compute a finite set of PO solutions to computationally expensive MOP (a suitable a posteriori method),
- a way to construct all the polytopes given by neighboring vertices (Delaunay triangulation of the PO outcomes) and
- a way to find out all the dominations between polytopes (by solving problems (1) and (2)).
- We want to remove polytopes from the Delaunay triangulation so that there are no polytopes in the resulting collection of polytopes (which can be shown to be a complex) that dominate each other.


## Constructing an IND PF Approximation

- So we have
- a way to compute a finite set of PO solutions to computationally expensive MOP (a suitable a posteriori method),
- a way to construct all the polytopes given by neighboring vertices (Delaunay triangulation of the PO outcomes) and
- a way to find out all the dominations between polytopes (by solving problems (1) and (2)).
- We want to remove polytopes from the Delaunay triangulation so that there are no polytopes in the resulting collection of polytopes (which can be shown to be a complex) that dominate each other.
- In a paper that we aim to submit "any day now" we propose a set of rules for doing the above.


## Properties of the Constructed IND PF Approximation

- The constructed approximation $\mathcal{K}$ is a complex.


## Properties of the Constructed IND PF Approximation

- The constructed approximation $\mathcal{K}$ is a complex.
- The singleton $\{p\}$ is in the approximation for all $p \in P$.


## Properties of the Constructed IND PF Approximation

- The constructed approximation $\mathcal{K}$ is a complex.
- The singleton $\{p\}$ is in the approximation for all $p \in P$.
- The constructed approximation is maximal in a way that for all $K \in \mathcal{D} \backslash \mathcal{K}$ the collection of polytopes $\mathcal{K} \cup\{K\}$ is not IND.


## Properties of the Constructed IND PF Approximation

- The constructed approximation $\mathcal{K}$ is a complex.
- The singleton $\{p\}$ is in the approximation for all $p \in P$.
- The constructed approximation is maximal in a way that for all $K \in \mathcal{D} \backslash \mathcal{K}$ the collection of polytopes $\mathcal{K} \cup\{K\}$ is not IND.
- Some error estimates for the approximation can be given: For a given point $s$ in $\cup_{K \in \mathcal{K}} K$ we can estimate $d(s) \in \mathbb{R}^{k}$ so that


## Properties of the Constructed IND PF Approximation

- The constructed approximation $\mathcal{K}$ is a complex.
- The singleton $\{p\}$ is in the approximation for all $p \in P$.
- The constructed approximation is maximal in a way that for all $K \in \mathcal{D} \backslash \mathcal{K}$ the collection of polytopes $\mathcal{K} \cup\{K\}$ is not IND.
- Some error estimates for the approximation can be given: For a given point $s$ in $\cup_{K \in \mathcal{K}} K$ we can estimate $d(s) \in \mathbb{R}^{k}$ so that
(1) there exists an outcome $z \in f(S)$ that is at least as good as $s+d(s)$ in all objectives and


## Properties of the Constructed IND PF Approximation

- The constructed approximation $\mathcal{K}$ is a complex.
- The singleton $\{p\}$ is in the approximation for all $p \in P$.
- The constructed approximation is maximal in a way that for all $K \in \mathcal{D} \backslash \mathcal{K}$ the collection of polytopes $\mathcal{K} \cup\{K\}$ is not IND.
- Some error estimates for the approximation can be given: For a given point $s$ in $\cup_{K \in \mathcal{K}} K$ we can estimate $d(s) \in \mathbb{R}^{k}$ so that
(1) there exists an outcome $z \in f(S)$ that is at least as good as $s+d(s)$ in all objectives and
(2) there does not exist an outcome $z \in f(S)$ that dominates $s-d(s)$.


## Properties of the Constructed IND PF Approximation

- The constructed approximation $\mathcal{K}$ is a complex.
- The singleton $\{p\}$ is in the approximation for all $p \in P$.
- The constructed approximation is maximal in a way that for all $K \in \mathcal{D} \backslash \mathcal{K}$ the collection of polytopes $\mathcal{K} \cup\{K\}$ is not IND.
- Some error estimates for the approximation can be given: For a given point $s$ in $\cup_{K \in \mathcal{K}} K$ we can estimate $d(s) \in \mathbb{R}^{k}$ so that
(1) there exists an outcome $z \in f(S)$ that is at least as good as $s+d(s)$ in all objectives and
(2) there does not exist an outcome $z \in f(S)$ that dominates $s-d(s)$.
- A preferred point on the approximation can be searched with interactive multiobjective optimization methods, because the approximation is IND and the approximation can be parametrized.


## Further Research

- A Delaunay triangulation of $m$ points in $k$ dimensions contains at most $O\left(m^{\lceil k / 2\rceil}\right)$ polytopes. This means that in order to find out all the dominations between polytopes, one may have to solve $O\left(m^{k}\right)$ optimization problems as described above. For this reason the first research question is to reduce the computational effort.


## Further Research

- A Delaunay triangulation of $m$ points in $k$ dimensions contains at most $O\left(m^{\lceil k / 2\rceil}\right)$ polytopes. This means that in order to find out all the dominations between polytopes, one may have to solve $O\left(m^{k}\right)$ optimization problems as described above. For this reason the first research question is to reduce the computational effort.
- The next step is to develop better methods for finding the preferred point on the approximation.


## Further Research

- A Delaunay triangulation of $m$ points in $k$ dimensions contains at most $O\left(m^{\lceil k / 2\rceil}\right)$ polytopes. This means that in order to find out all the dominations between polytopes, one may have to solve $O\left(m^{k}\right)$ optimization problems as described above. For this reason the first research question is to reduce the computational effort.
- The next step is to develop better methods for finding the preferred point on the approximation.
- We have already (in a proceedings paper that has been submitted to a conference) applied this approach combined with the NIMBUS method to solving the heat exchanger network synthesis.


## Further Research

- A Delaunay triangulation of $m$ points in $k$ dimensions contains at most $O\left(m^{\lceil k / 2\rceil}\right)$ polytopes. This means that in order to find out all the dominations between polytopes, one may have to solve $O\left(m^{k}\right)$ optimization problems as described above. For this reason the first research question is to reduce the computational effort.
- The next step is to develop better methods for finding the preferred point on the approximation.
- We have already (in a proceedings paper that has been submitted to a conference) applied this approach combined with the NIMBUS method to solving the heat exchanger network synthesis.
- Any further applications are welcome. We are ready to try our approach with real world problems.


## References

H. Edelsbrunner. Algorithms in Combinatorial Geometry. Springer, New York, 1987.
H. Edelsbrunner. Shape Reconstruction with Delaunay Complex. In C. L. Lucchesi and A. V. Moura, editors, LATIN'98: Theoretical Informatics. Springer, Berlin, 1998.
M. Hartikainen, K. Miettinen, and M. M. Wiecek. Inherent Non-Dominance - Pareto Front Approximations for Decision Making, 2010. University of Jyväskylä, Reports of the Department of Mathematical Information Technology, Series B. Scientific Computing, Number B2/2010.
K. Miettinen. Nonlinear Multiobjective Optimization. Kluwer Academic Publishers, Boston, 1999.
A. Wierzbicki. On the Completeness and Constructiveness of Parametric Characterizations to Vector Optimization Problems. OR Spectrum, 8: 73-87, 1986.

## Thank You!

For further details or if you have ideas please contact Markus Hartikainen (markus.e.hartikainen@jyu.fi)

