# An Approximation Approach to Computationally Expensive Multiobjective Optimization Problems

Markus Hartikainen

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An Approximation Approach

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#### • Name: Markus Hartikainen

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- Ph. Lic. in mathematics (mathematical analysis)

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

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- The plan is to defend my thesis in 2011.

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minimize  $(f_1(x), \dots, f_k(x))$ so that  $x \in S$ 

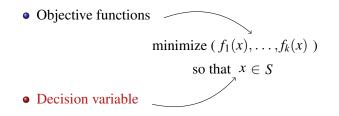
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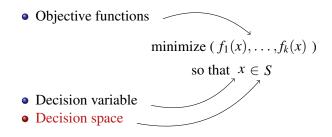
• Objective functions

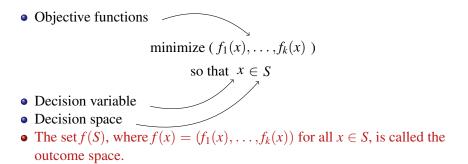
minimize ( $f_1(x), \ldots, f_k(x)$ )

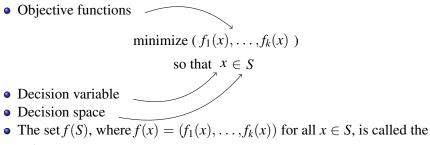
so that  $x \in S$ 

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outcome space.

• A vector  $z \in f(S)$  is called an outcome.

- Objective functions minimize (f₁(x),...,fk(x)) so that x ∈ S
  Decision space
- The set f(S), where  $f(x) = (f_1(x), \dots, f_k(x))$  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  $z_i^1 \le z_i^2$  for all i = 1, ..., k and  $z_j^1 \le z_j^2$  for some j = 1, ..., k.

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- 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.

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- 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.

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- Our approach:

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  - Use interactive multiobjective optimization (MO) methods (see e.g., [Miettinen, 1999]) for finding the preferred outcome on the approximation.
  - Find the PO solution that is closest to the preferred point by means of an achievement scalarizing function [Wierzbicki, 1986].

#### 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  $P \subset A$ .

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#### 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 DM in 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*.

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# Constructing Inherently Nondominated Complexes: Basic Definitions



Markus	Hartikainen	0

An Approximation Approach

April 12, 2010 8 / 15

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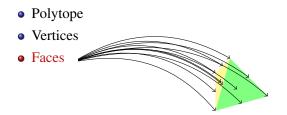
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- A complex D is a Delaunay triangulation of a finite set P ⊂ ℝ<sup>k</sup> if ∪<sub>K∈D</sub>K = conv(P) and the complex only contains "polytopes with neighbouring vertices" (see [Edelsbrunner, 1987]).

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- With minor extra conventions, this can be seen as a shape reconstruction problem as defined in [Edelsbrunner, 1998].

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# Constructing an Inherently Nondominated Complex (continued)

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# Constructing an Inherently Nondominated Complex (continued)

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$$\min_{\substack{i=1,...,k}} \max_{i=1,...,k} (s_i^1 - s_i^2)$$
  
s.t.  $s^1 \in K^1, s^2 \in K^2$  (1)

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• optimal value in problem (1) is 0 and the optimal value in optimization problem

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s.t.  $s^1 \in K^1, s^2 \in K^2$   
 $s_i^1 \le s_i^2$  for all  $i = 1, ..., k$ .  
(2)

is less than zero.

Markus Hartikainen ()

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- In a paper that we aim to submit "any day now" we propose a set of rules for doing the above.

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- 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.

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A Delaunay triangulation of *m* points in *k* dimensions contains at most O(m<sup>[k/2]</sup>) polytopes. This means that in order to find out all the dominations between polytopes, one may have to solve O(m<sup>k</sup>) optimization problems as described above. For this reason the first research question is to reduce the computational effort.

b) a) The bound of the bound

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- Any further applications are welcome. We are ready to try our approach with real world problems.

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# Thank You!

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

Markus Hartikainen ()

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