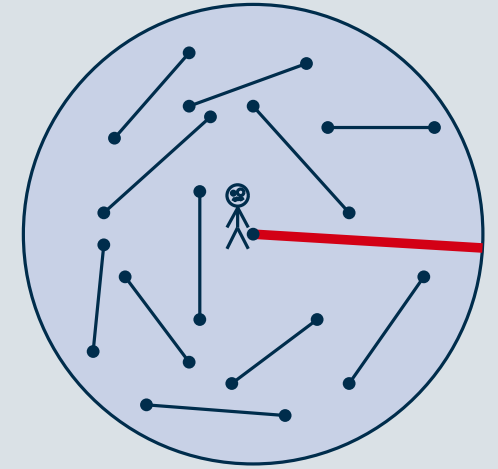


Computational Geometry

Exercise 5 *Assignment 4, 5 and Voronoi diagrams of segments*

Jean-Pierre, Marcus, Wendy

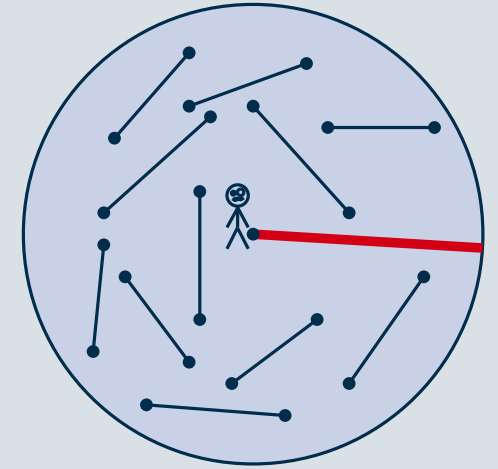
Mission Impossible + 1.5 Range Queries



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

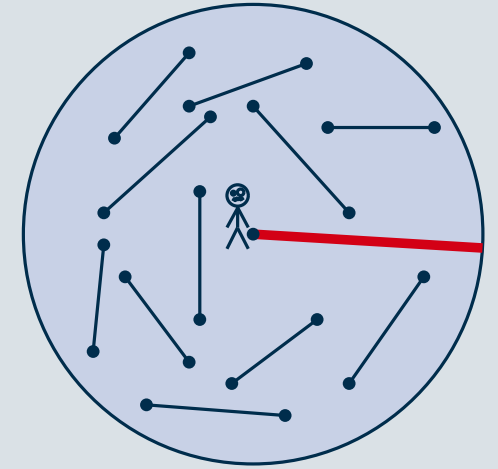


query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center



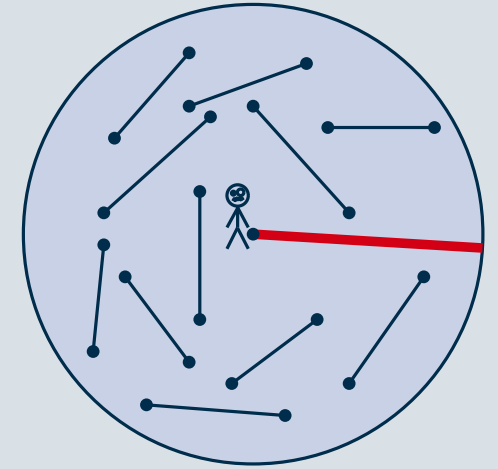
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preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

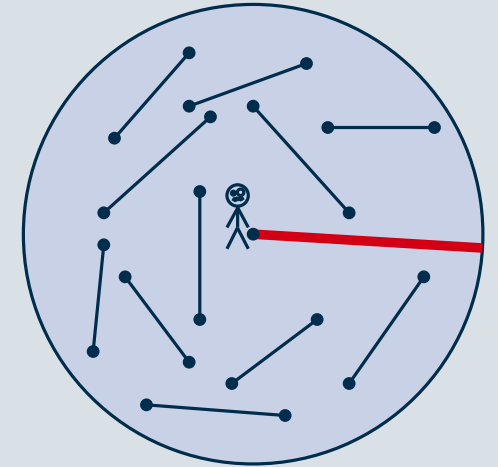
Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

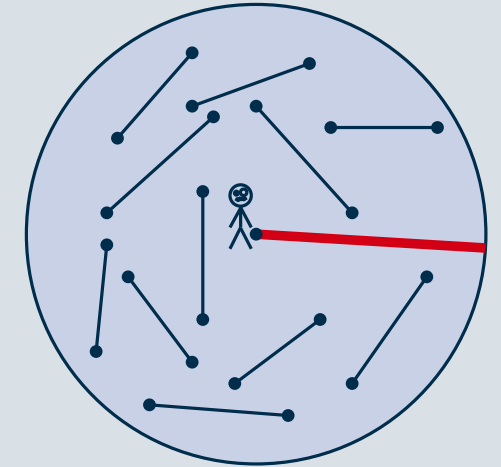
Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

Events



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

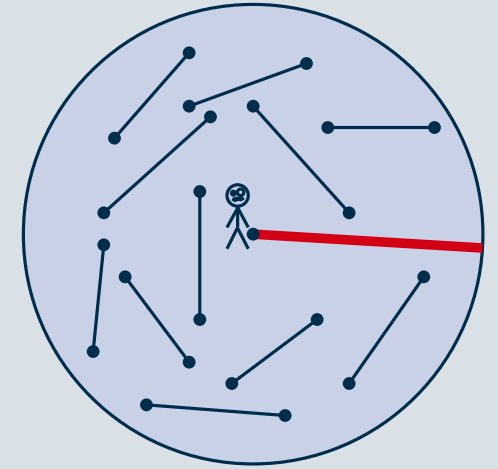
- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

Events

- start point: add wall
- end point: remove wall



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

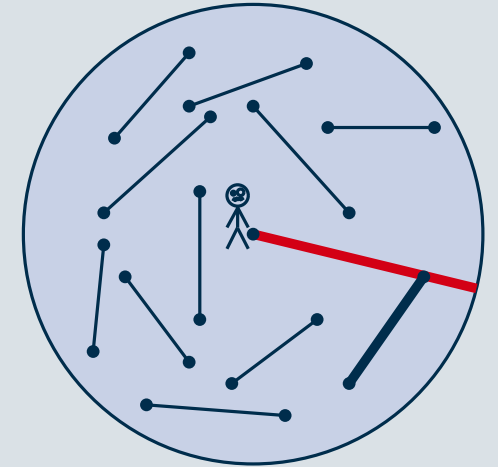
- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

Events

- start point: add wall
- end point: remove wall



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

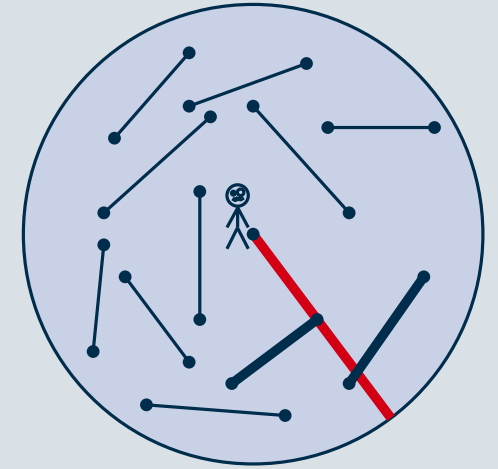
- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

Events

- start point: add wall
- end point: remove wall



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

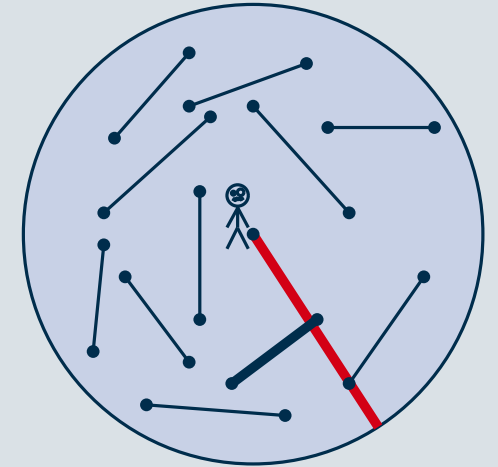
- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

Events

- start point: add wall
- end point: remove wall



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

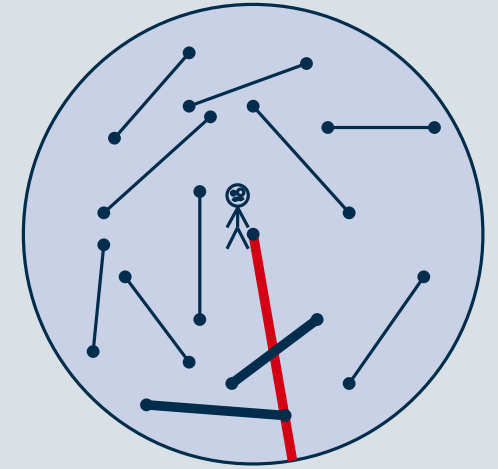
- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

Events

- start point: add wall
- end point: remove wall



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

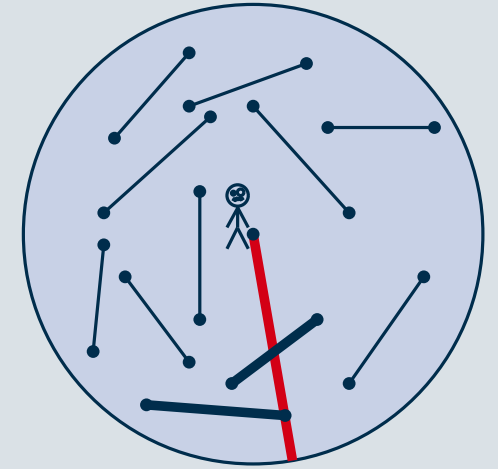
timestamp?

at $\alpha = 0$?

Events

- start point: add wall
- end point: remove wall

Queries



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

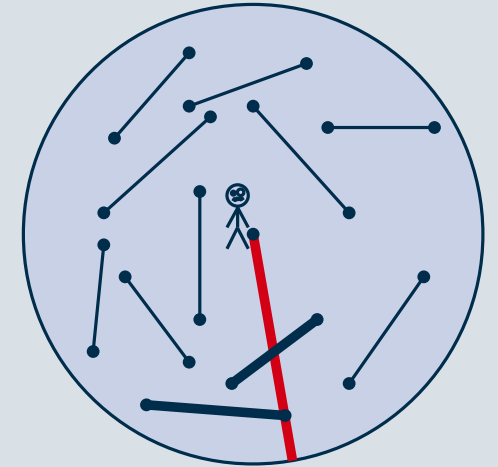
at $\alpha = 0$?

Events

- start point: add wall
- end point: remove wall

Queries

- ask for time $= \alpha$
- output all walls currently in sweep line state



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

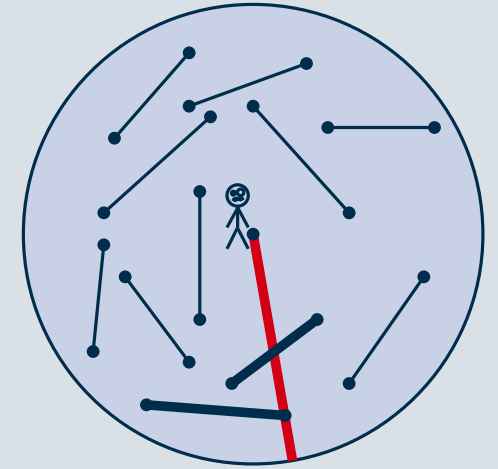
Events

- start point: add wall
- end point: remove wall

Queries

- ask for time $= \alpha$
- output all walls currently in sweep line state

Why $O(\log(n) + k)$?



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

- walls that intersect sweep line
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

at $\alpha = 0$?

Events

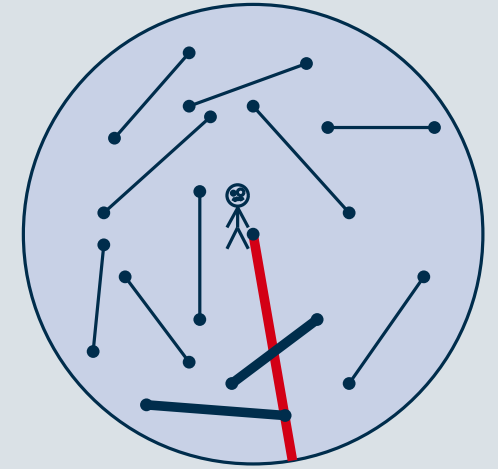
- start point: add wall
- end point: remove wall

But wait! What about space?

Queries

- ask for time $= \alpha$
- output all walls currently in sweep line state

Why $O(\log(n) + k)$?



query: $O(\log(n) + k)$
preprocessing: $O(n \log(n))$

Mission Impossible + 1.5 Range Queries

Persistent Rotating Sweep Line

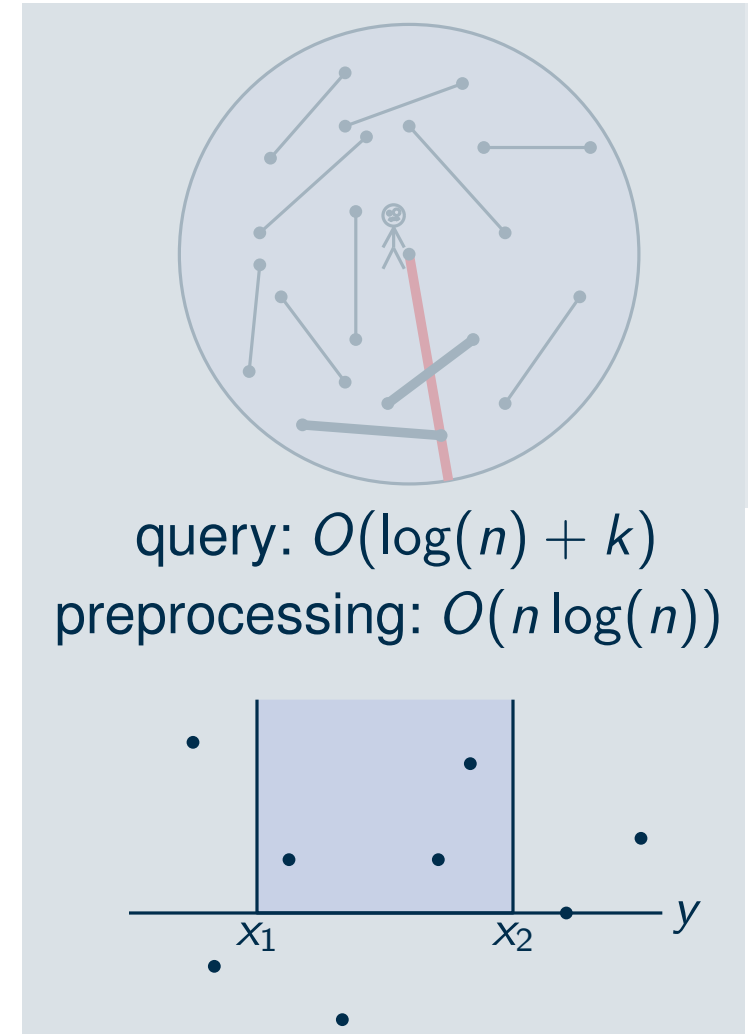
- walls that intersect sweep line
 - sort by distance to center
 - data structure: persistent binary search tree
- timestamp?

Events

- start point: add wall
- end point: remove wall

Queries

- ask for time = α
 - output all walls currently in sweep line state
- Why $O(\log(n) + k)$?



Mission Impossible + 1.5 Range Queries

Persistent ~~Rotating~~ Sweep Line

- ~~walls~~ that ~~intersect~~ sweep line
points are above
- sort by distance to center
- data structure: persistent binary search tree

timestamp?

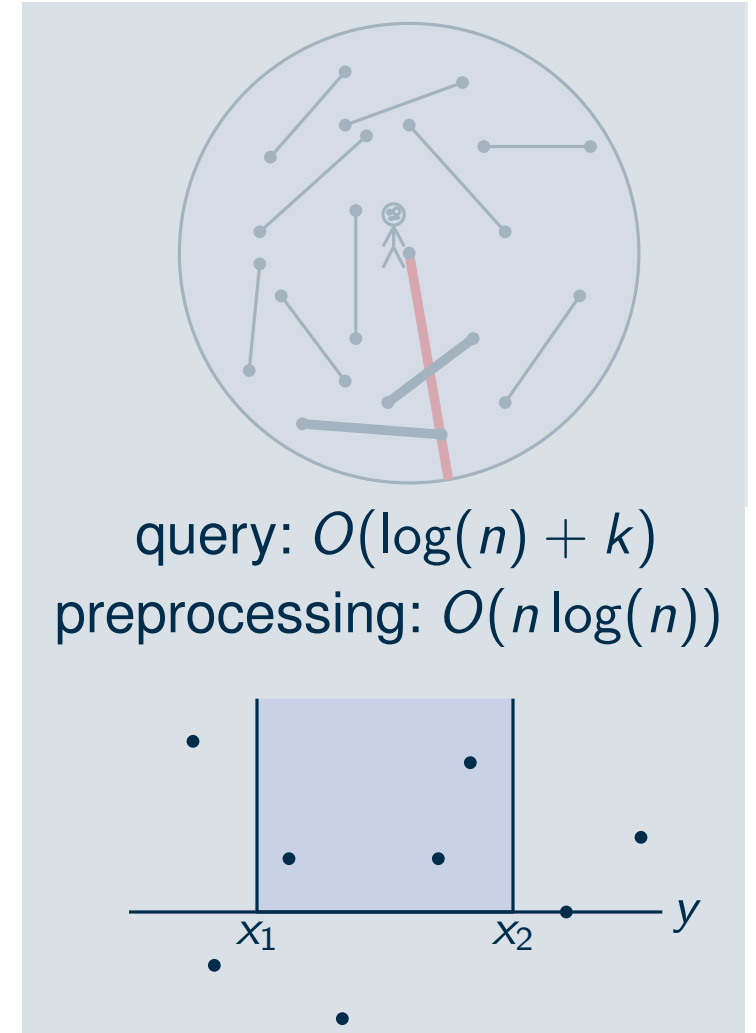
Events

- start point: add wall
- end point: remove wall

Queries

- ask for time = α
- output all walls currently in sweep line state

Why $O(\log(n) + k)$?



Mission Impossible + 1.5 Range Queries

Persistent ~~Rotating~~ Sweep Line

- ~~walls~~ that ~~intersect~~ sweep line
points are above
- sort by ~~distance to center~~ x-coordinate timestamp?
- data structure: persistent binary search tree

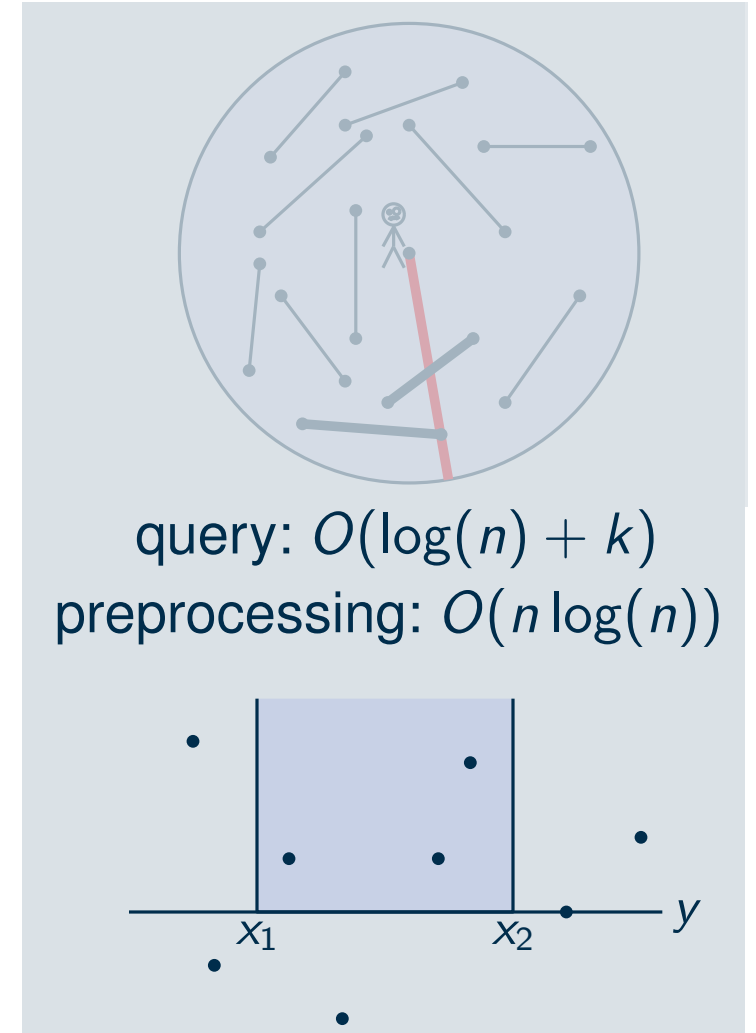
Events

- start point: add wall
- end point: remove wall

Queries

- ask for time = α
- output all walls currently in sweep line state

Why $O(\log(n) + k)$?



Mission Impossible + 1.5 Range Queries

Persistent ~~Rotating~~ Sweep Line

- ~~walls~~ that ~~intersect~~ sweep line ^{points are above}
- sort by ~~distance to center~~ ^{x-coordinate}
- data structure: persistent binary search tree

timestamp?

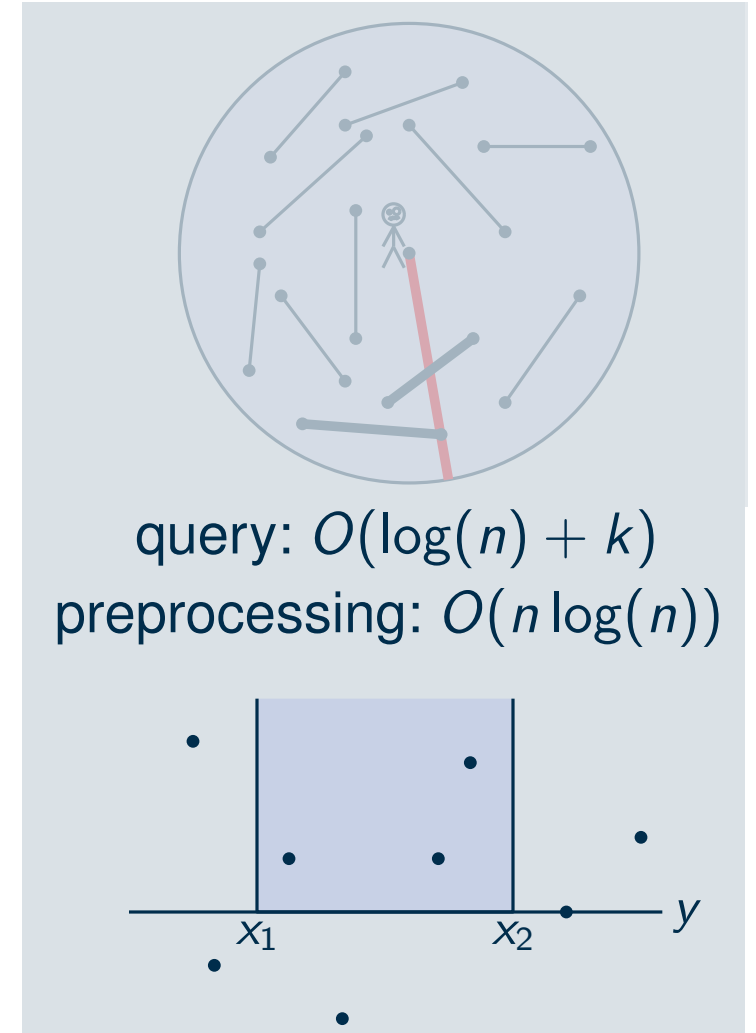
Events

- start point: add ~~wall~~ ^{point}
- ~~end point: remove wall~~

Queries

- ask for time = α
- output all walls currently in sweep line state

Why $O(\log(n) + k)$?



Mission Impossible + 1.5 Range Queries

Persistent ~~Rotating~~ Sweep Line

- ~~walls~~ that ~~intersect~~ sweep line
points are above
- sort by ~~distance to center~~
x-coordinate
- data structure: persistent binary search tree

timestamp?

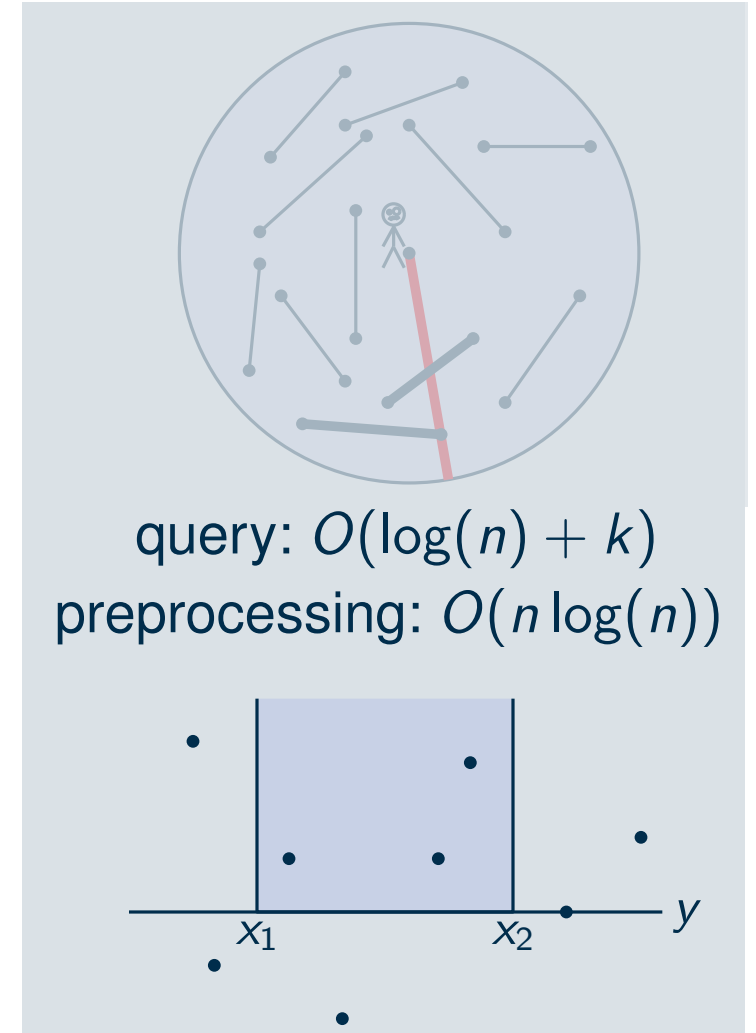
Events

- start point: add ~~wall~~
point
- ~~end point: remove wall~~

Queries

- ask for time = ~~α~~
 y
- output all walls currently in sweep line state

Why $O(\log(n) + k)$?



Mission Impossible + 1.5 Range Queries

Persistent ~~Rotating~~ Sweep Line

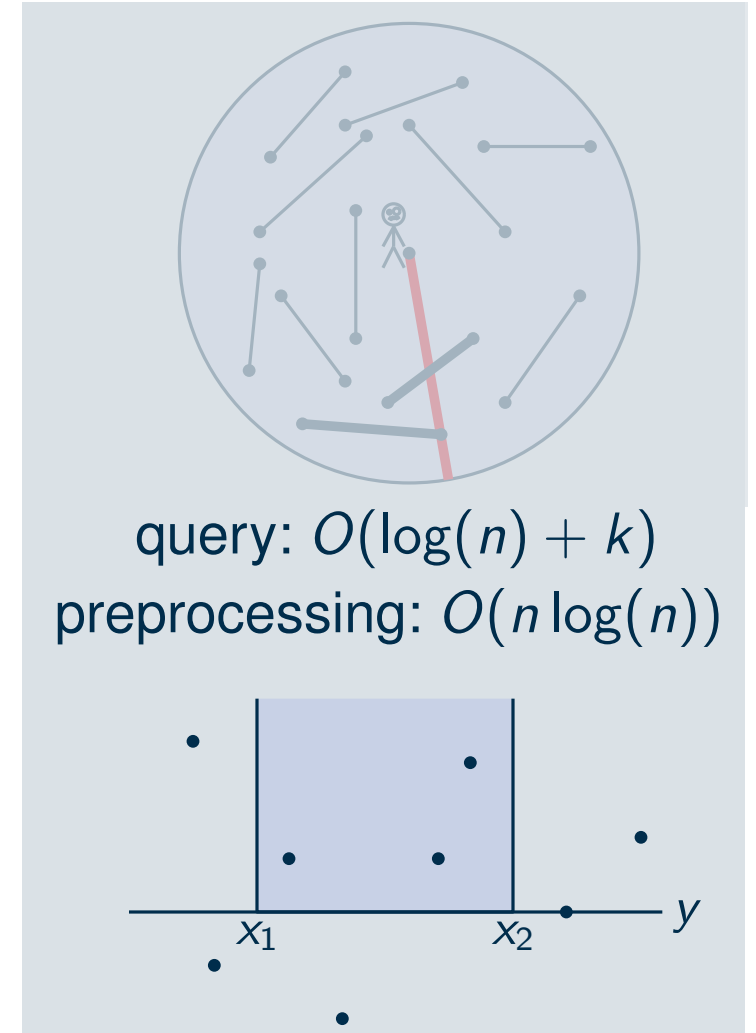
- ~~walls~~ that ~~intersect~~ sweep line
points are above
 - sort by ~~distance to center~~
x-coordinate
 - data structure: persistent binary search tree
- timestamp?

Events

- start point: add ~~wall~~
point
- ~~end point: remove wall~~

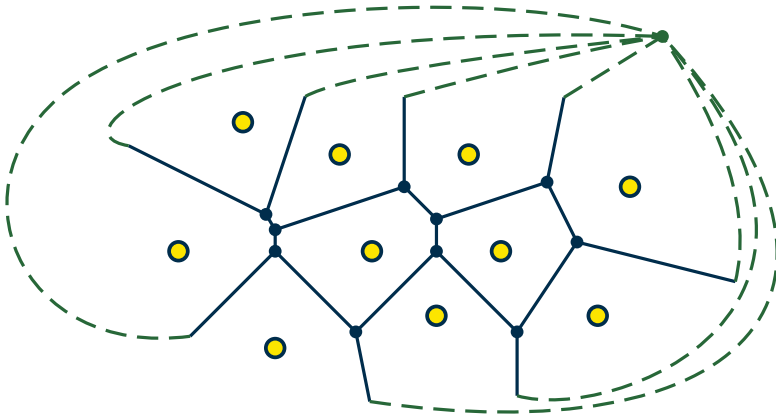
Queries

- ask for time = ~~α~~
 y
 - ~~output all walls currently in sweep line state~~
find x_1 , output all between x_1 and x_2
- Why $O(\log(n) + k)$?



Voronoi Diagram

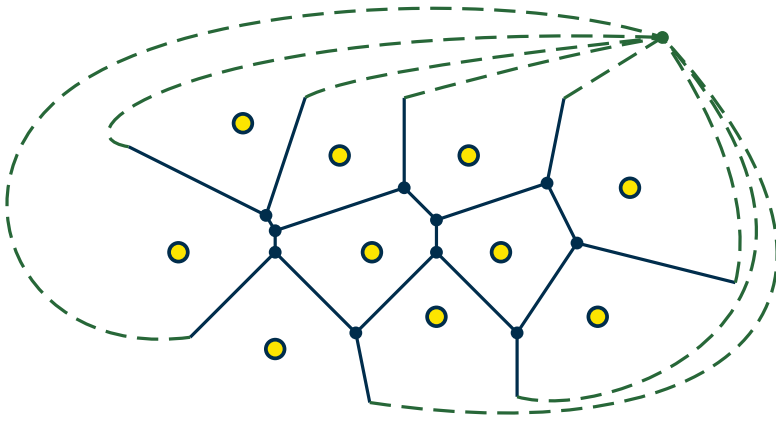
Size of Voronoi Diagram



- add vertex to collect loose edges

Voronoi Diagram

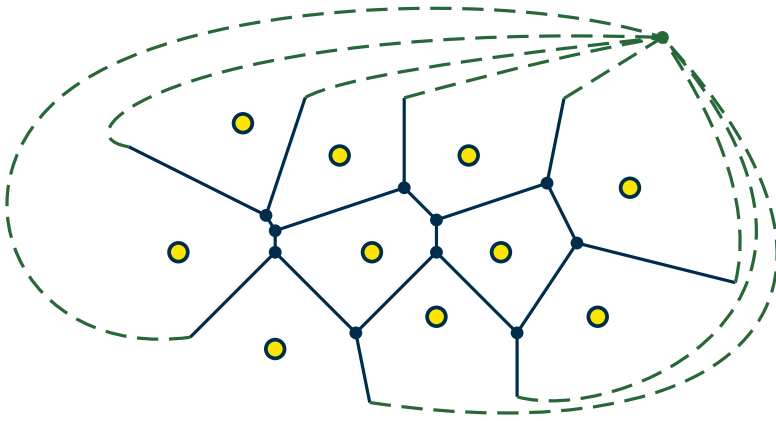
Size of Voronoi Diagram



- add vertex to collect loose edges
- n faces

Voronoi Diagram

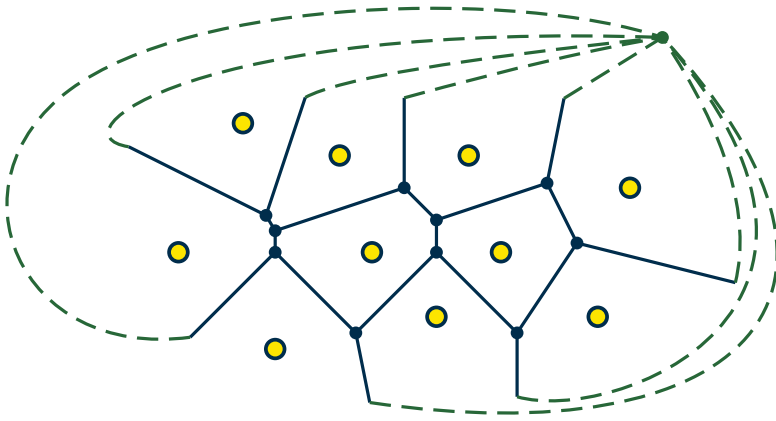
Size of Voronoi Diagram



- add vertex to collect loose edges
- n faces
- $v + 1$ vertices, with degree ≥ 3

Voronoi Diagram

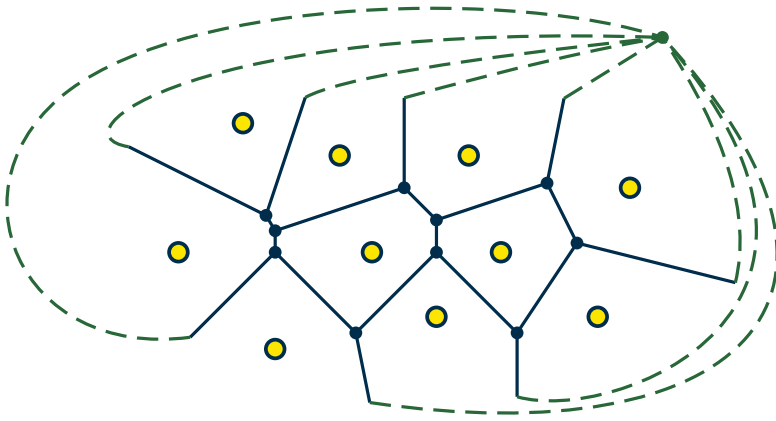
Size of Voronoi Diagram



- add vertex to collect loose edges
- n faces
- $v + 1$ vertices, with degree ≥ 3
- m edges with $2m \geq 3(v + 1)$

Voronoi Diagram

Size of Voronoi Diagram

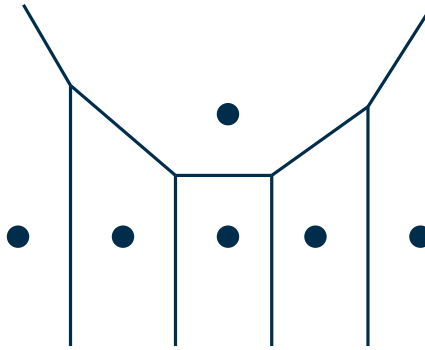
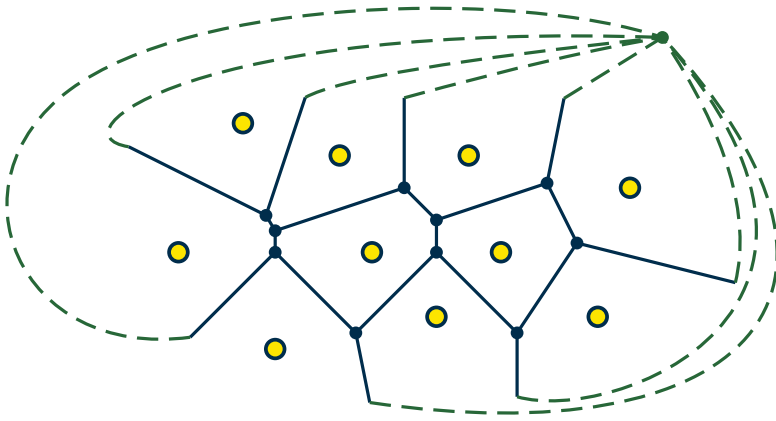


- add vertex to collect loose edges
- n faces
- $v + 1$ vertices, with degree ≥ 3
- m edges with $2m \geq 3(v + 1)$
- use Euler's formula

Voronoi Diagram

Size of Voronoi Diagram

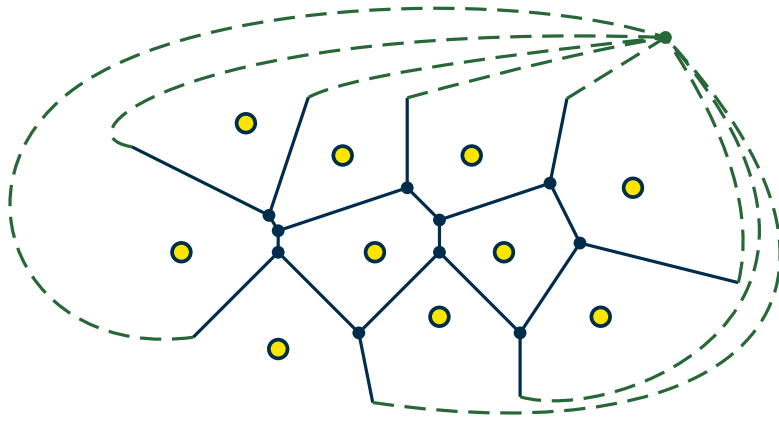
$\Omega(n \log(n))$ lower bound



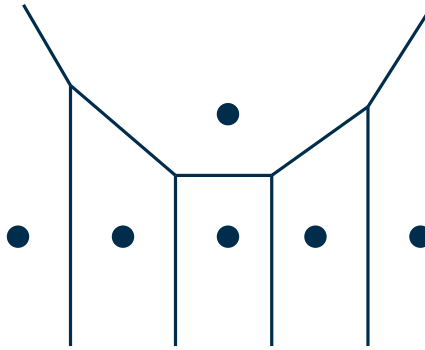
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Voronoi Diagram

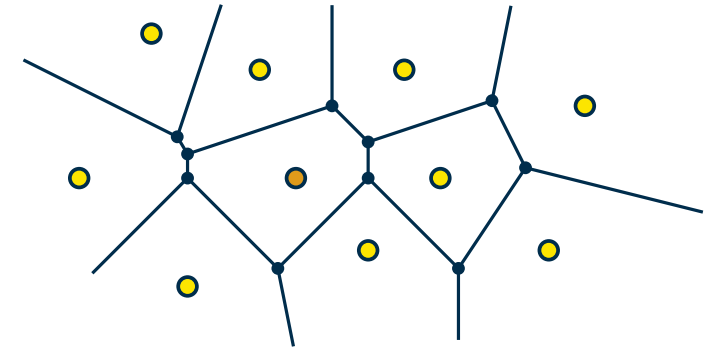
Size of Voronoi Diagram



$\Omega(n \log(n))$ lower bound



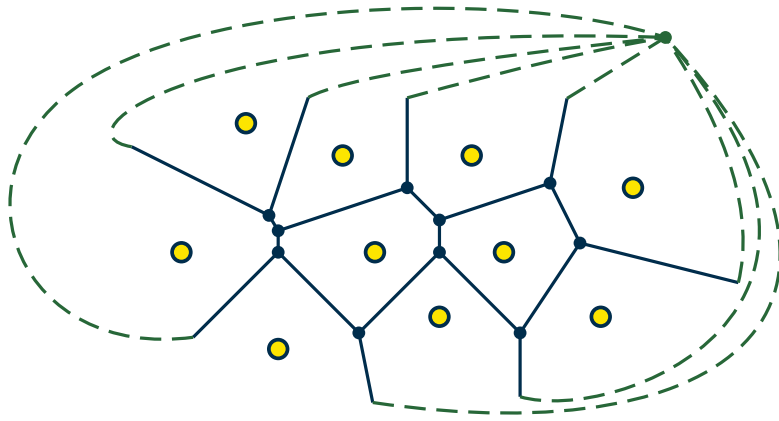
Find closest point



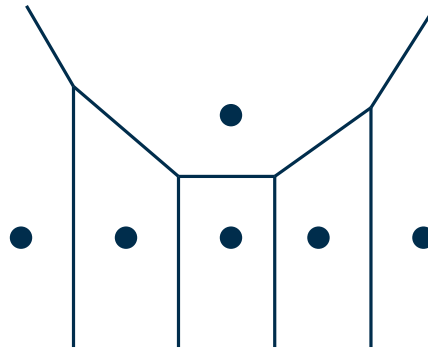
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Voronoi Diagram

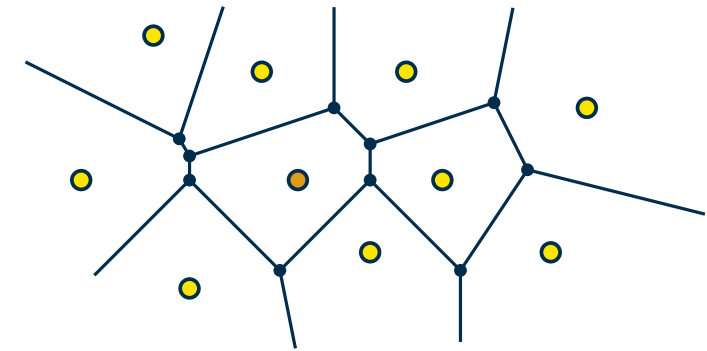
Size of Voronoi Diagram



$\Omega(n \log(n))$ lower bound



Find closest point



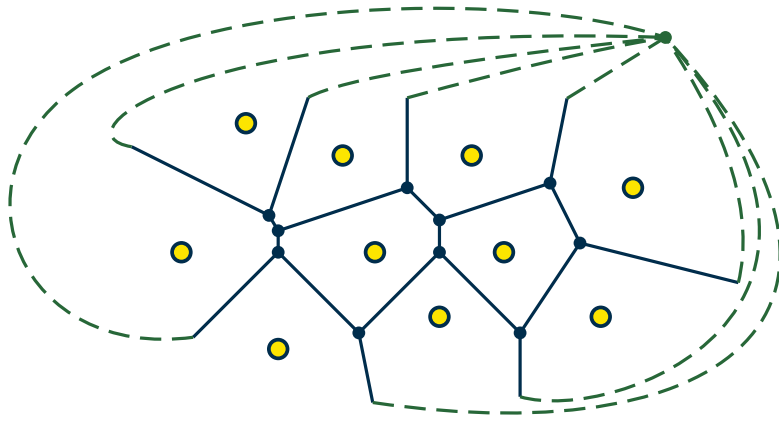
why?

- add vertex to collect loose edges
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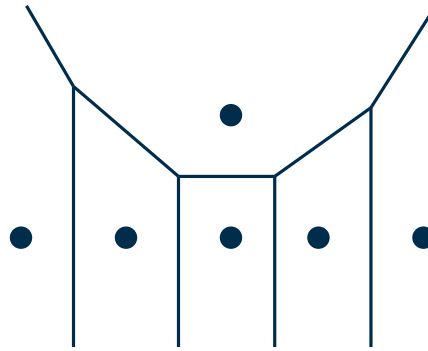
- closest point is in neighbor cell

Voronoi Diagram

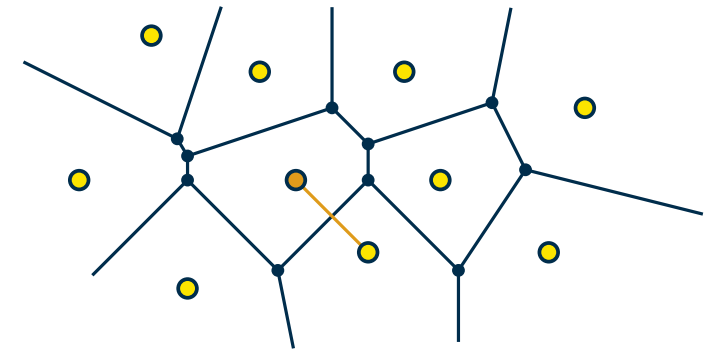
Size of Voronoi Diagram



$\Omega(n \log(n))$ lower bound



Find closest point



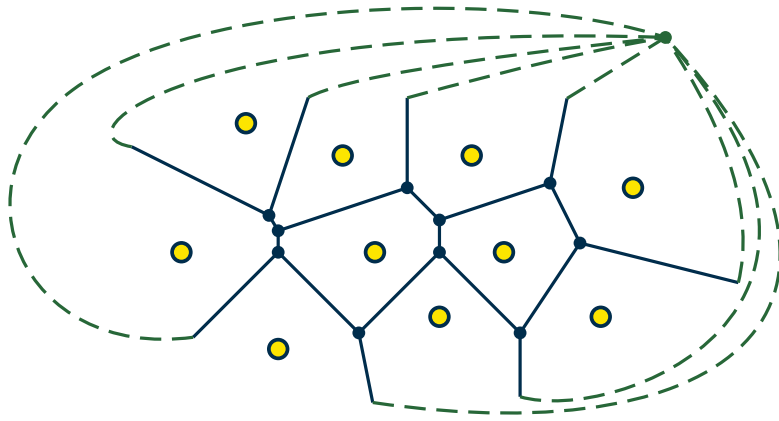
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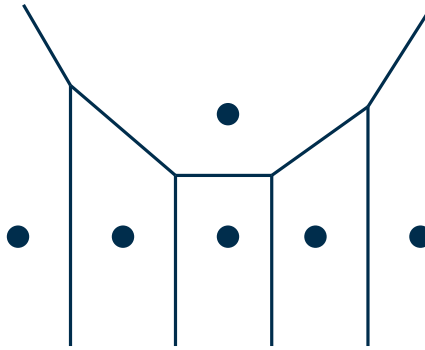
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Voronoi Diagram

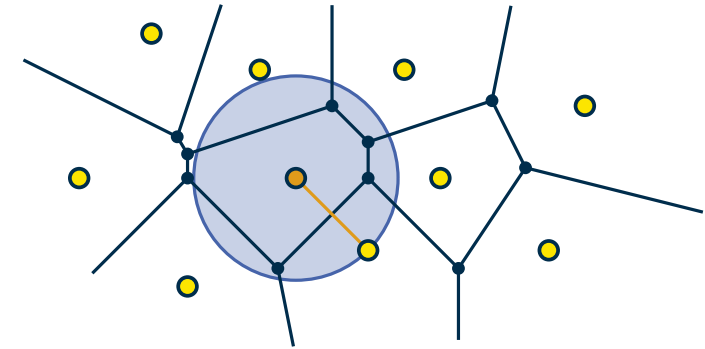
Size of Voronoi Diagram



$\Omega(n \log(n))$ lower bound



Find closest point



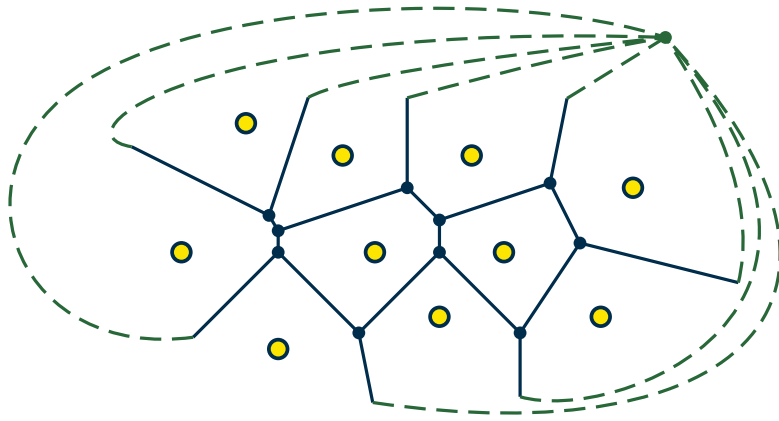
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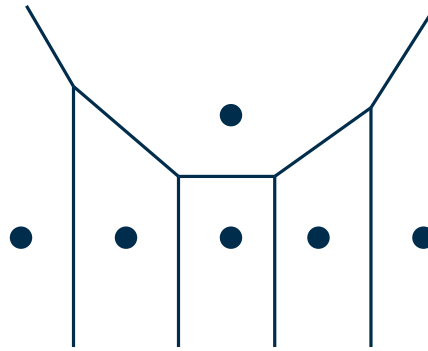
- closest point is in neighbor cell

Voronoi Diagram

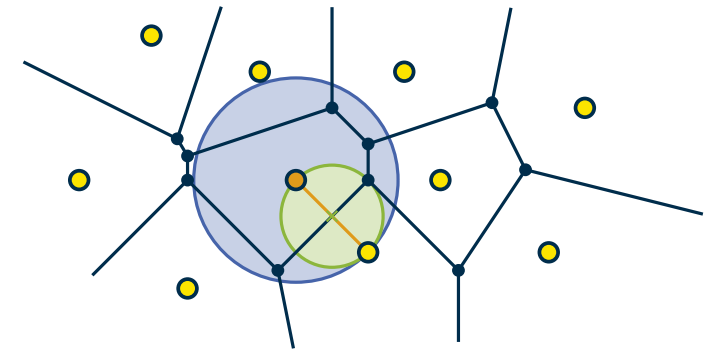
Size of Voronoi Diagram



$\Omega(n \log(n))$ lower bound



Find closest point



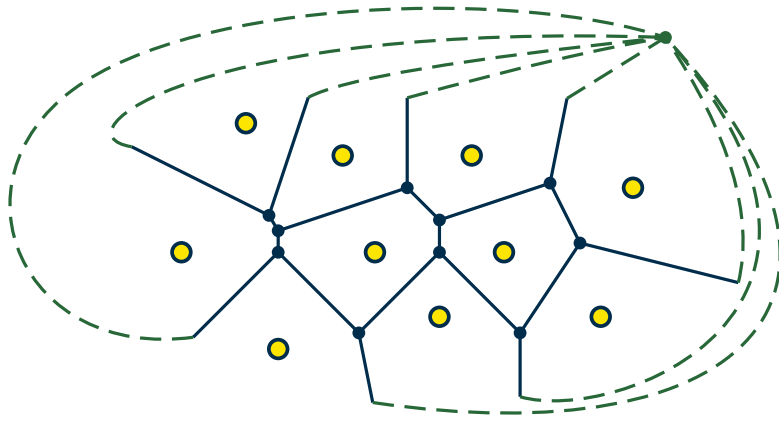
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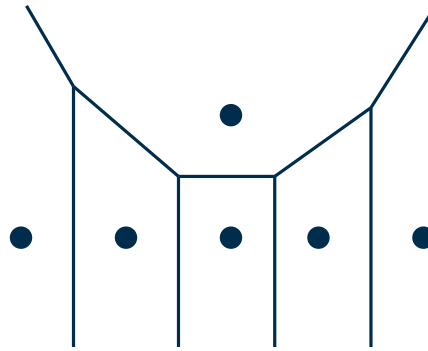
- closest point is in neighbor cell

Voronoi Diagram

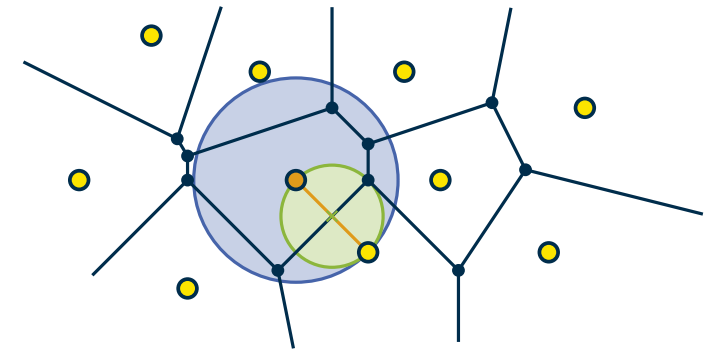
Size of Voronoi Diagram



$\Omega(n \log(n))$ lower bound



Find closest point



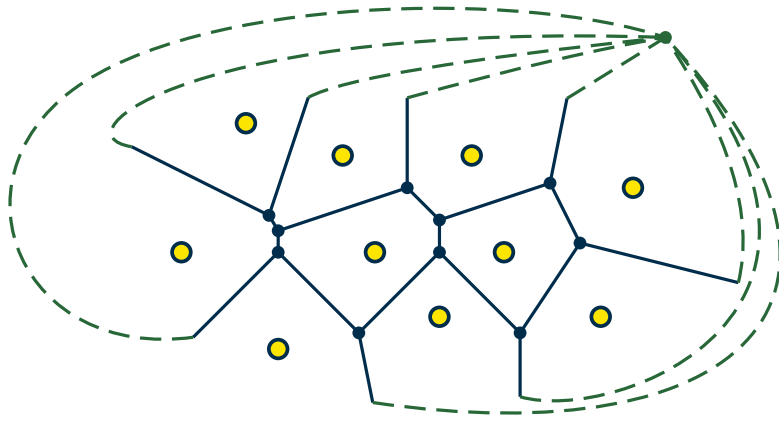
why?

- add vertex to collect loose edges
- n faces
- $v + 1$ vertices, with degree ≥ 3
- m edges with $2m \geq 3(v + 1)$
- use Euler's formula

- closest point is in neighbor cell
- mid point lies on edge of cell

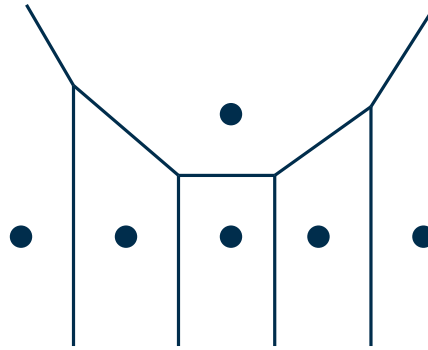
Voronoi Diagram

Size of Voronoi Diagram

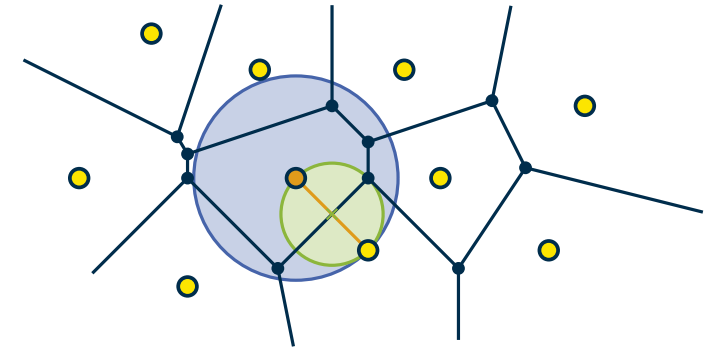


- add vertex to collect loose edges
- n faces
- $v + 1$ vertices, with degree ≥ 3
- m edges with $2m \geq 3(v + 1)$
- use Euler's formula

$\Omega(n \log(n))$ lower bound



Find closest point



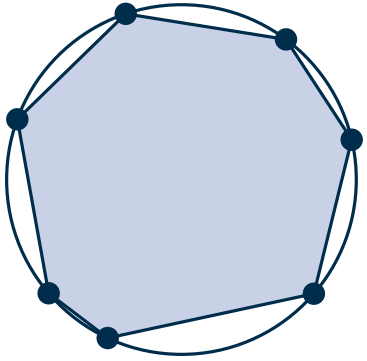
why?

- closest point is in neighbor cell
- mid point lies on edge of cell
- for each point: try all neighbors in VD

Running time?

Assignment 5

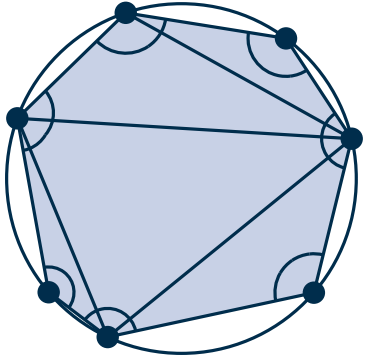
Triangulation of Concentric Points



find optimal triangulation
(smallest angle vector)

Assignment 5

Triangulation of Concentric Points

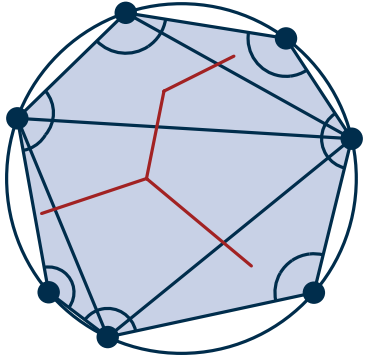


find optimal triangulation
(smallest angle vector)

- maximum angle vector \Leftrightarrow maximum length vector

Assignment 5

Triangulation of Concentric Points

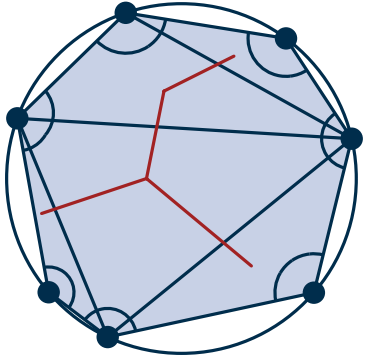


find optimal triangulation
(smallest angle vector)

- maximum angle vector \Leftrightarrow maximum length vector
- weak dual graph is a path in optimal triangulation

Assignment 5

Triangulation of Concentric Points

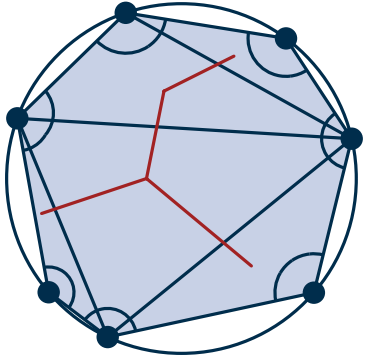


find optimal triangulation
(smallest angle vector)

- maximum angle vector \Leftrightarrow maximum length vector
- weak dual graph is a path in optimal triangulation
- algorithm try to maximize leaves of path

Assignment 5

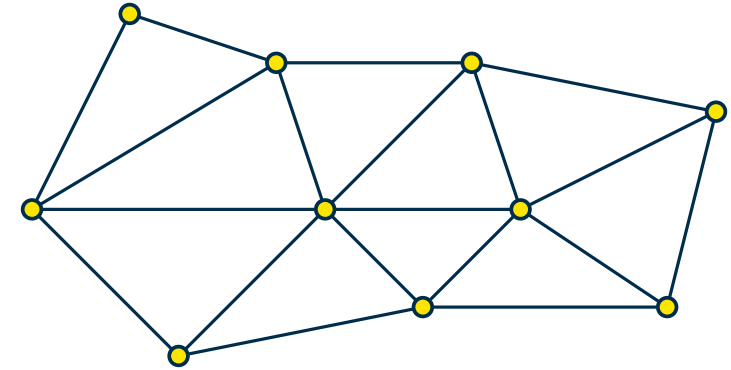
Triangulation of Concentric Points



find optimal triangulation
(smallest angle vector)

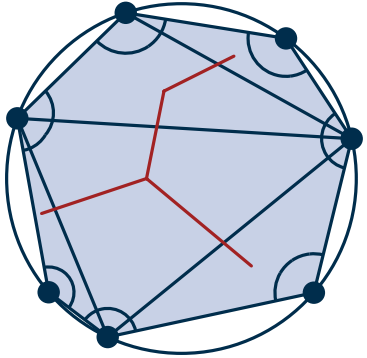
- maximum angle vector \Leftrightarrow maximum length vector
- weak dual graph is a path in optimal triangulation
- algorithm try to maximize leaves of path

MST \subseteq Delaunay



Assignment 5

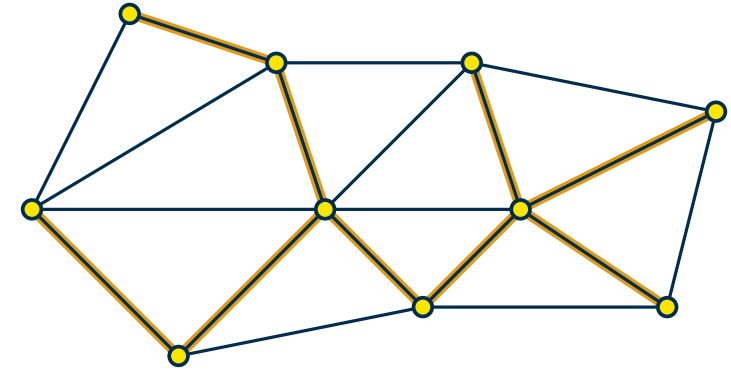
Triangulation of Concentric Points



find optimal triangulation
(smallest angle vector)

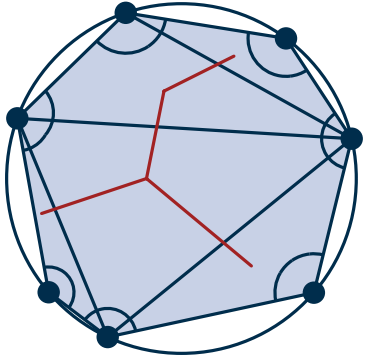
- maximum angle vector \Leftrightarrow maximum length vector
- weak dual graph is a path in optimal triangulation
- algorithm try to maximize leaves of path

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Assignment 5

Triangulation of Concentric Points



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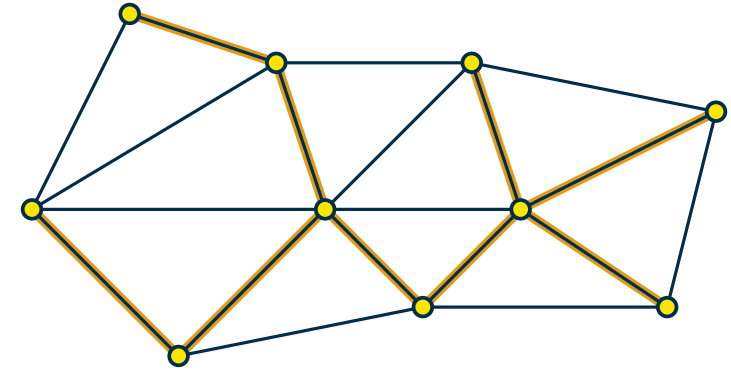
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Foldability of Mountain/Valley Patterns



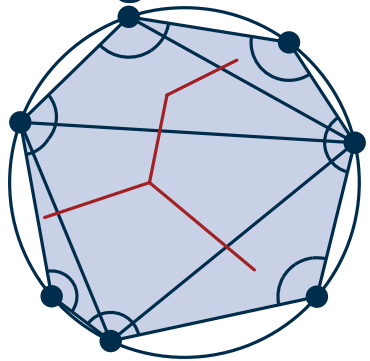
- test foldability in $O(n)$

MST \subseteq Delaunay



Assignment 5

Triangulation of Concentric Points



find optimal triangulation
(smallest angle vector)

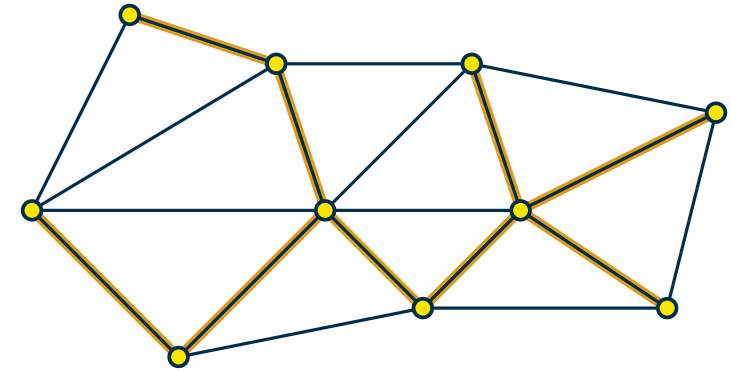
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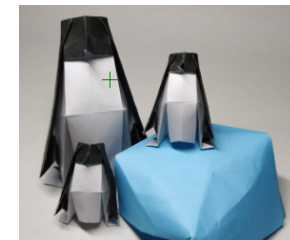


- test foldability in $O(n)$

MST \subseteq Delaunay



Creative Outlet

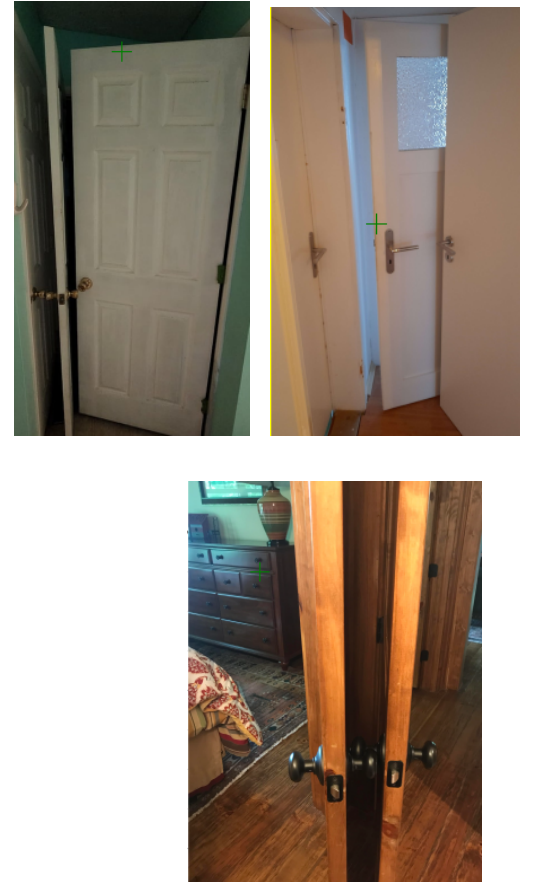


Blocking Doors

- doors are weird and can block each other

Blocking Doors

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Blocking Doors

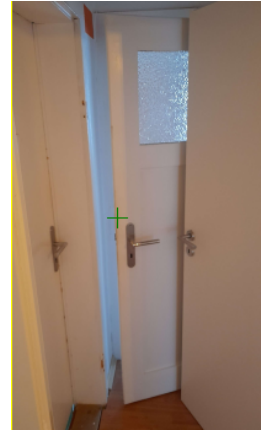
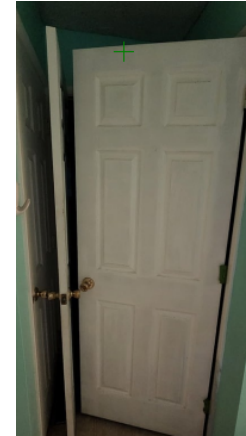
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Problem: BLOCKINGDOORS

(BA Oğuz)

Given: Set of rectangular rooms with a set of doors

Is it possible to assign every door a hinge and an opening direction such that no doors block each other?



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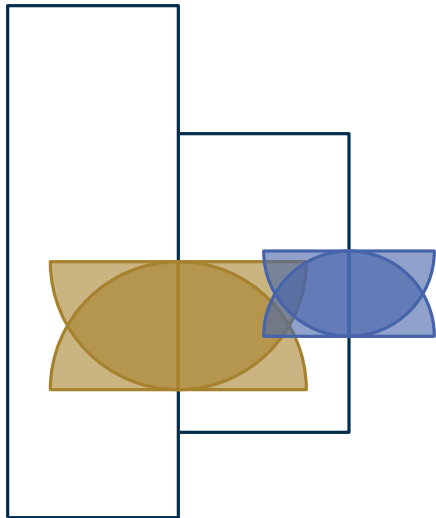
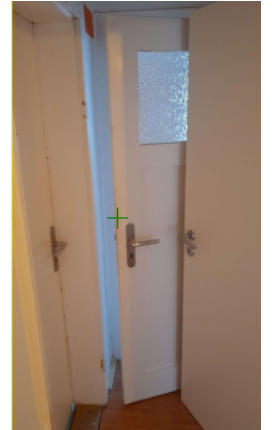
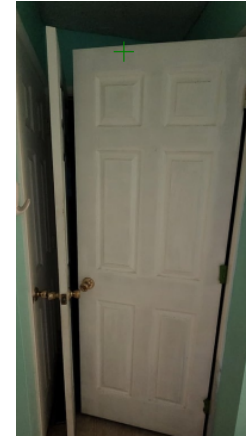
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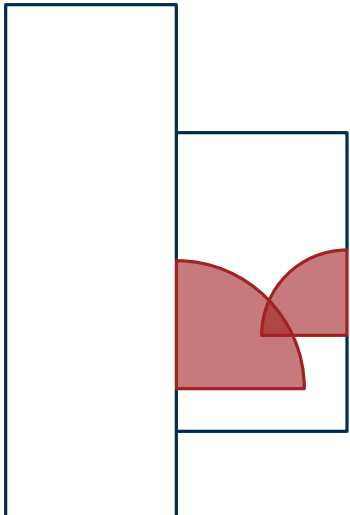
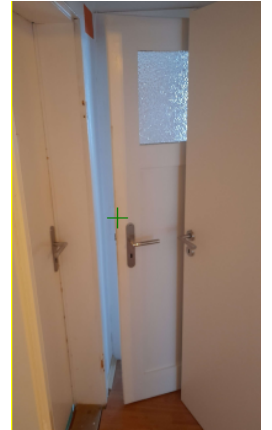
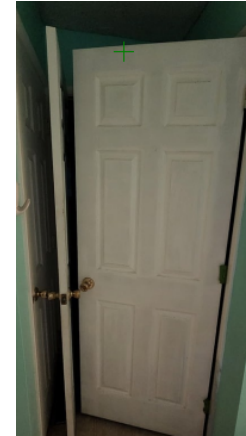
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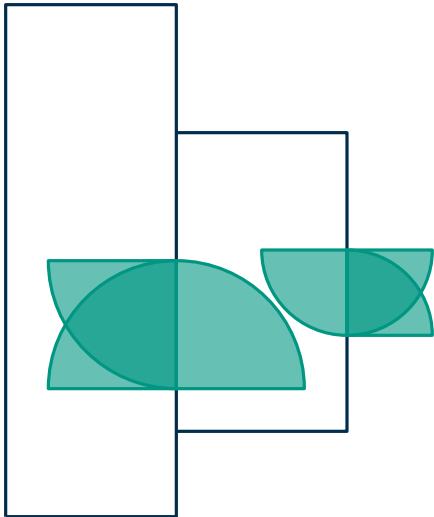
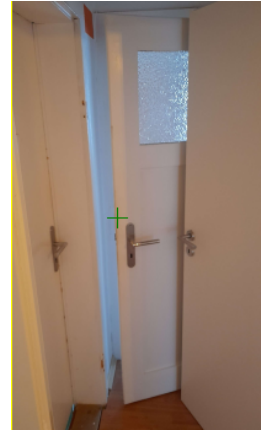
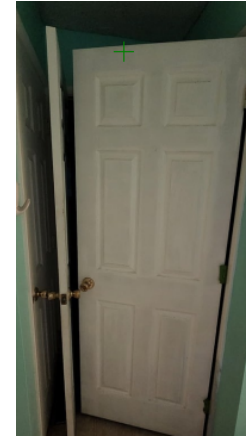
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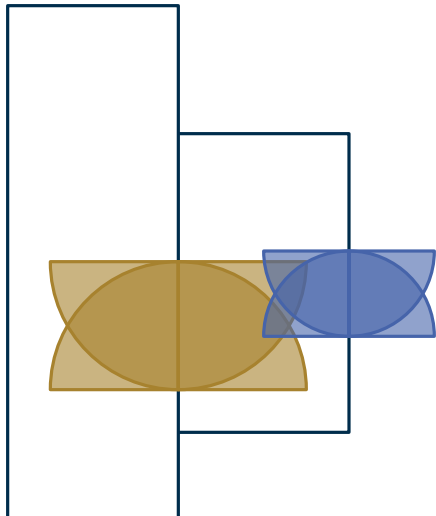
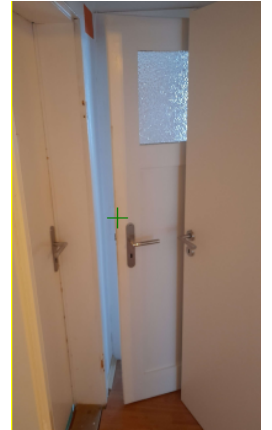
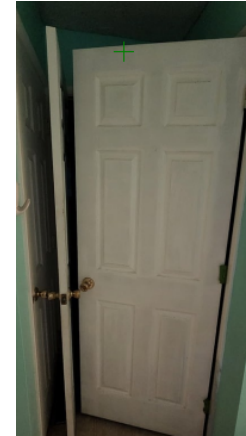
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- Show that BLOCKINGDOORS is NP-hard.

Build gadgets!



Blocking Doors

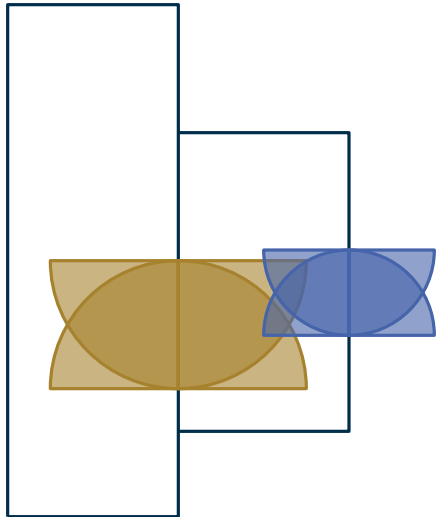
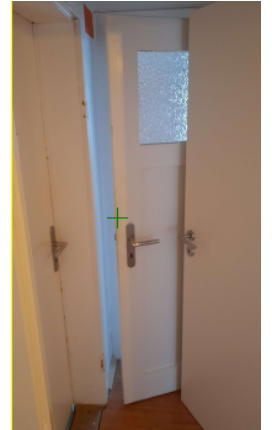
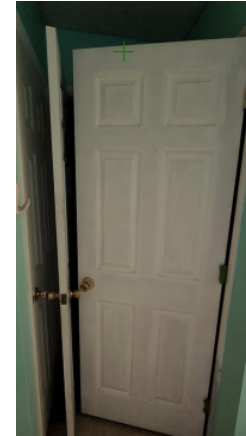
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- Show that BLOCKINGDOORS is NP-hard.

- Is it NP-complete?

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Blocking Doors

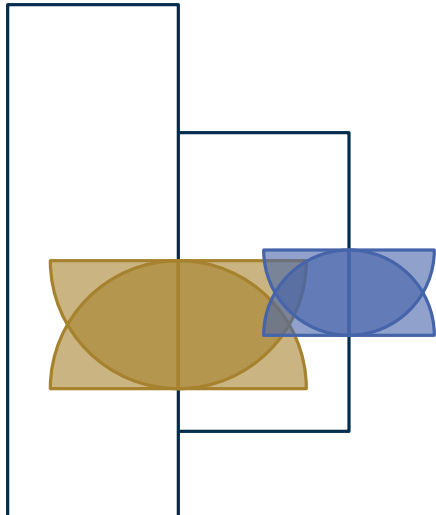
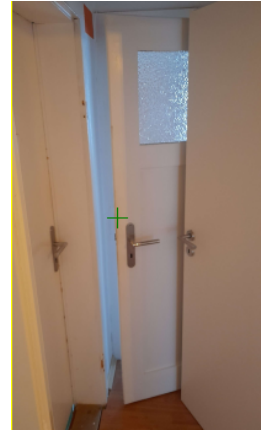
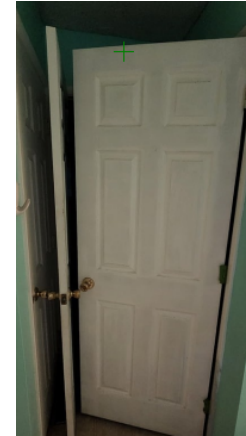
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- Show that BLOCKINGDOORS is NP-hard.
- Is it NP-complete?
- Complexity if the side of the hinge is given for each door?

Build gadgets!



Blocking Doors

Problem: BLOCKINGDOORS

(BA Oğuz)

Given: Set of rectangular rooms with a set of doors

Is it possible to assign every door a hinge and an opening direction such that no doors block each other?

- Show that BLOCKING DOORS is NP-hard by reduction from PLANAR MONOTONE RECTILINEAR 3-SAT.

Blocking Doors

Problem: BLOCKINGDOORS

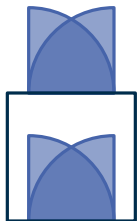
(BA Oğuz)

Given: Set of rectangular rooms with a set of doors

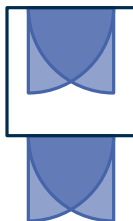
Is it possible to assign every door a hinge and an opening direction such that no doors block each other?

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Variables



true



false

Blocking Doors

Problem: BLOCKINGDOORS

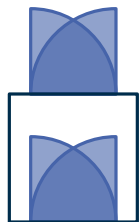
(BA Oğuz)

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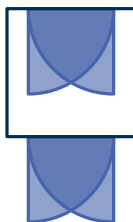
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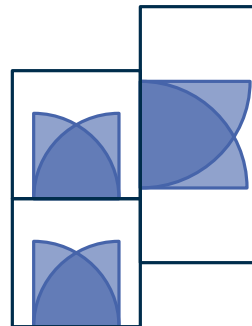


true



false

Transport



Blocking Doors

Problem: BLOCKINGDOORS

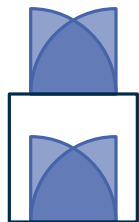
(BA Oğuz)

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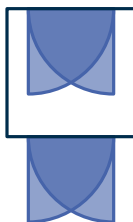
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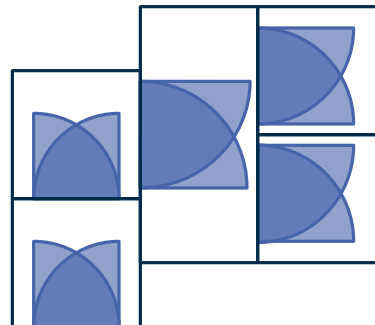


true



false

Transport + Split



Blocking Doors

Problem: BLOCKINGDOORS

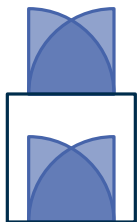
(BA Oğuz)

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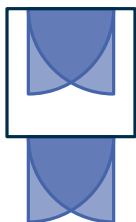
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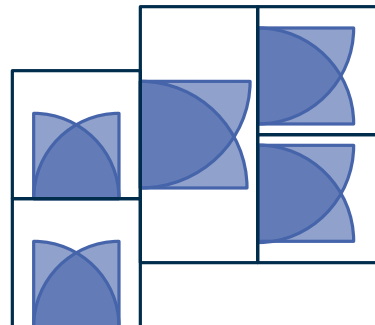


true

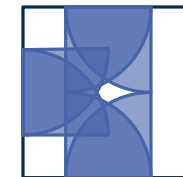


false

Transport + Split



Clauses



Blocking Doors

Problem: BLOCKINGDOORS

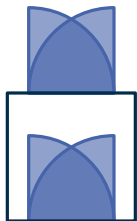
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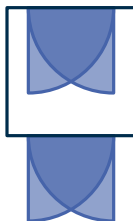
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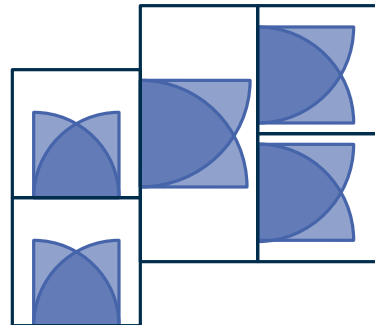


true

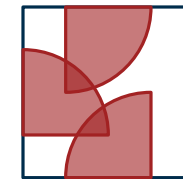


false

Transport + Split



Clauses



Blocking Doors

Problem: BLOCKINGDOORS

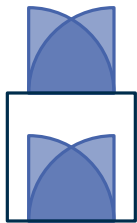
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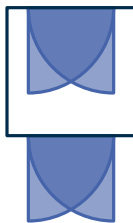
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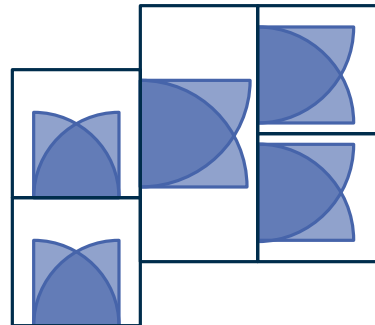


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Transport + Split



Clauses



Blocking Doors

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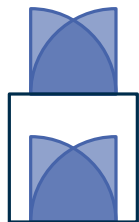
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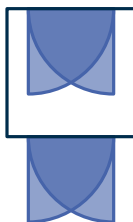
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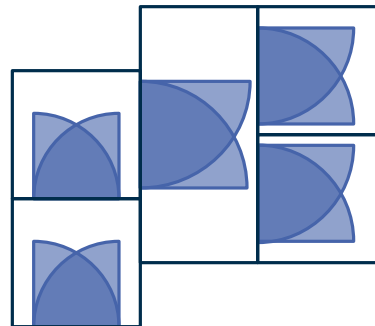


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Clauses

