

Linear Programming Duality

K. Subramani¹

¹Lane Department of Computer Science and Electrical Engineering
West Virginia University

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Outline

1 Preliminaries

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 - Complementary Slackness
- 2 Foundations of Duality
 - Weak and Strong Duality theorems

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- 4 Approximation Algorithms

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Forms of linear programs, standard, canonical, etc. Feasible solution, optimal solution (z^), unboundedness.*

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- 5 *If there exist primal and dual solutions with matching objective function values, then both must be optimal!*
- 6 *Consider $\mathbf{x} = (\frac{7}{4}, 0, \frac{11}{4})$ and $\mathbf{y} = (2, 1)$ for the example discussed above.*

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Primal and Dual forms

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Primal (**P**):

$$z = \min \sum_{j=1}^n c_j \cdot x_j$$

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Theorem (Weak Duality)

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$$\sum_{i=1}^n c_j \cdot x_j \geq \sum_{j=1}^n \left(\sum_{i=1}^m a_{ij} \cdot y_i \right) \cdot x_j \quad (\text{since } \mathbf{y} \text{ is dual feasible } (\mathbf{y} \cdot \mathbf{A} \leq \mathbf{c}) \text{ and } \mathbf{x} \geq 0) \quad (1)$$

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$$\sum_{i=1}^n c_j \cdot x_j \geq \sum_{j=1}^n \left(\sum_{i=1}^m a_{ij} \cdot y_i \right) \cdot x_j \quad (\text{since } \mathbf{y} \text{ is dual feasible } (\mathbf{y} \cdot \mathbf{A} \leq \mathbf{c}) \text{ and } \mathbf{x} \geq 0) \quad (1)$$

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The Strong Duality Theorem

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Proof.

Continuity of variables and the objective functions. □

Outline

- 1 Preliminaries
- 2 **Foundations of Duality**
 - Weak and Strong Duality theorems
- 3 **Complementary Slackness**
- 4 Min-Max Relations and Maximum Flow
- 5 Approximation Algorithms

Complementary Slackness

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For each $1 \leq j \leq n$: either $x_j = 0$,

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- (vii) Hence, $\mathbf{s}^*\cdot\mathbf{x}^* = \mathbf{0}$ and $\mathbf{y}^*\cdot\mathbf{t}^* = \mathbf{0}$,

Proof of Complementary Slackness

Proof.

- (i) Recall that the primal is $\min_{\mathbf{A}\cdot\mathbf{x}\geq\mathbf{b}, \mathbf{x}\geq\mathbf{0}} \mathbf{c}\cdot\mathbf{x}$ and the dual is $\max_{\mathbf{y}\cdot\mathbf{A}\leq\mathbf{c}, \mathbf{y}\geq\mathbf{0}} \mathbf{b}\cdot\mathbf{y}$.
- (ii) Let $(\mathbf{x}^*, \mathbf{y}^*)$ denote an optimal primal-dual pair.
- (iii) Define $\mathbf{t}^* = \mathbf{A}\cdot\mathbf{x}^* - \mathbf{b}$ and $\mathbf{s}^* = \mathbf{c} - \mathbf{y}^*\cdot\mathbf{A}$.
Clearly, $\mathbf{t}^* \geq \mathbf{0}$ and $\mathbf{s}^* \geq \mathbf{0}$.
- (iv) We have,

$$\begin{aligned}\mathbf{c}\cdot\mathbf{x}^* &= (\mathbf{s}^* + \mathbf{y}^*\cdot\mathbf{A})\cdot\mathbf{x}^* \\ &= \mathbf{s}^*\cdot\mathbf{x}^* + \mathbf{y}^*\cdot\mathbf{A}\cdot\mathbf{x}^* \\ &= \mathbf{s}^*\cdot\mathbf{x}^* + \mathbf{y}^*\cdot(\mathbf{t}^* + \mathbf{b}) \\ &= \mathbf{s}^*\cdot\mathbf{x}^* + \mathbf{y}^*\cdot\mathbf{t}^* + \mathbf{y}^*\cdot\mathbf{b}\end{aligned}$$

- (v) But $\mathbf{c}\cdot\mathbf{x}^* = \mathbf{y}^*\cdot\mathbf{b}$.
- (vi) It follows that, $\mathbf{s}^*\cdot\mathbf{x}^* + \mathbf{y}^*\cdot\mathbf{t}^* = \mathbf{0}$.
- (vii) Hence, $\mathbf{s}^*\cdot\mathbf{x}^* = \mathbf{0}$ and $\mathbf{y}^*\cdot\mathbf{t}^* = \mathbf{0}$, since $\mathbf{x}^*, \mathbf{y}^*, \mathbf{s}^*, \mathbf{t}^* \geq \mathbf{0}$.

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The Max-Flow Problem

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Note

It may be possible to exploit the combinatorial structure of the dual program and design algorithms that are faster than general purpose linear programs.

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