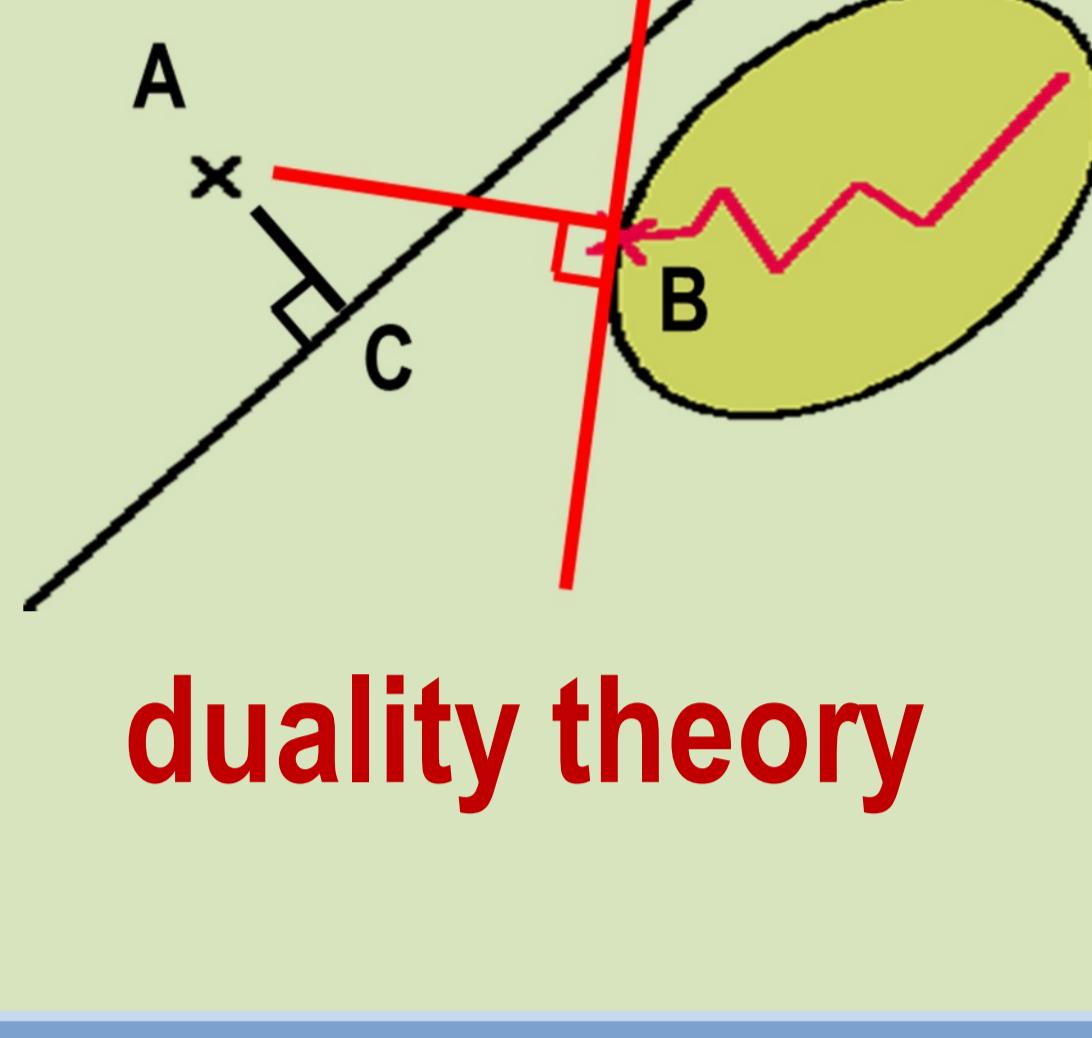
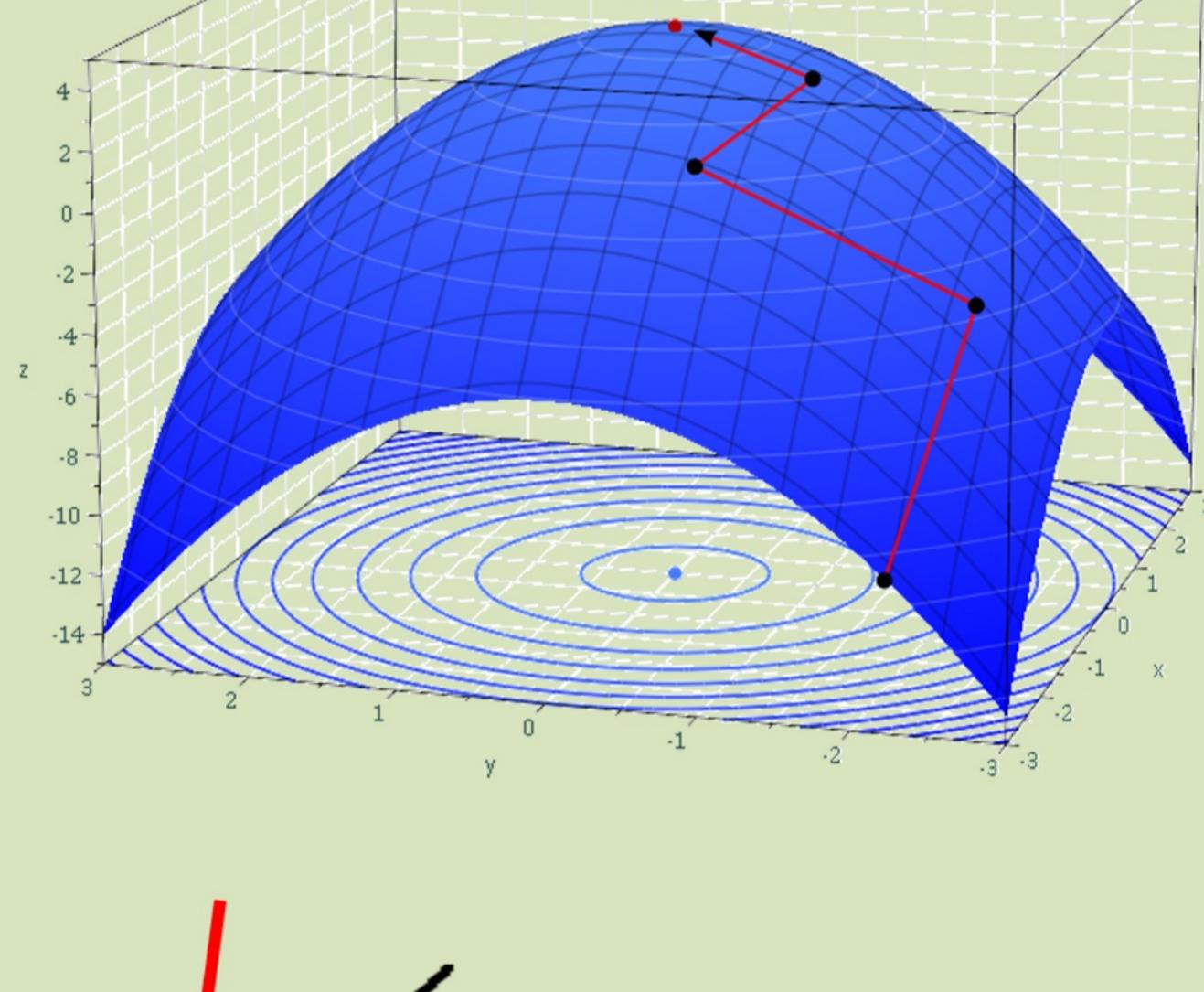


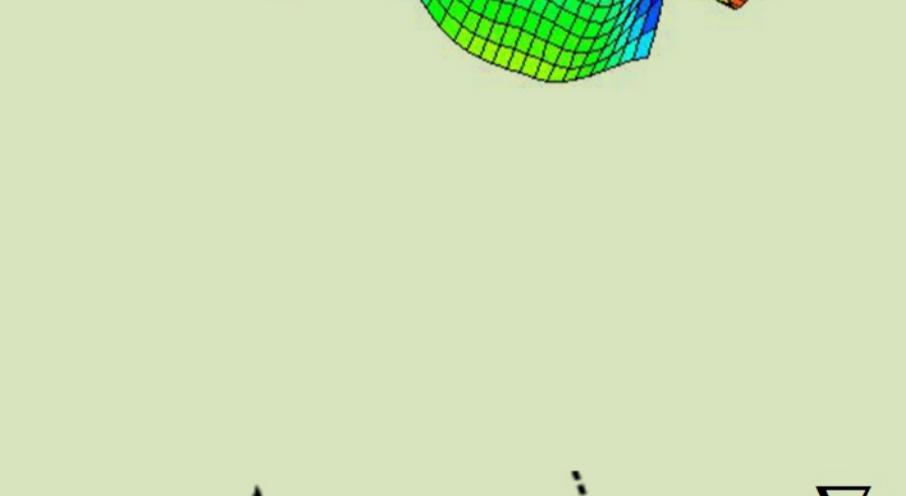
OPTIMIZATION

courses

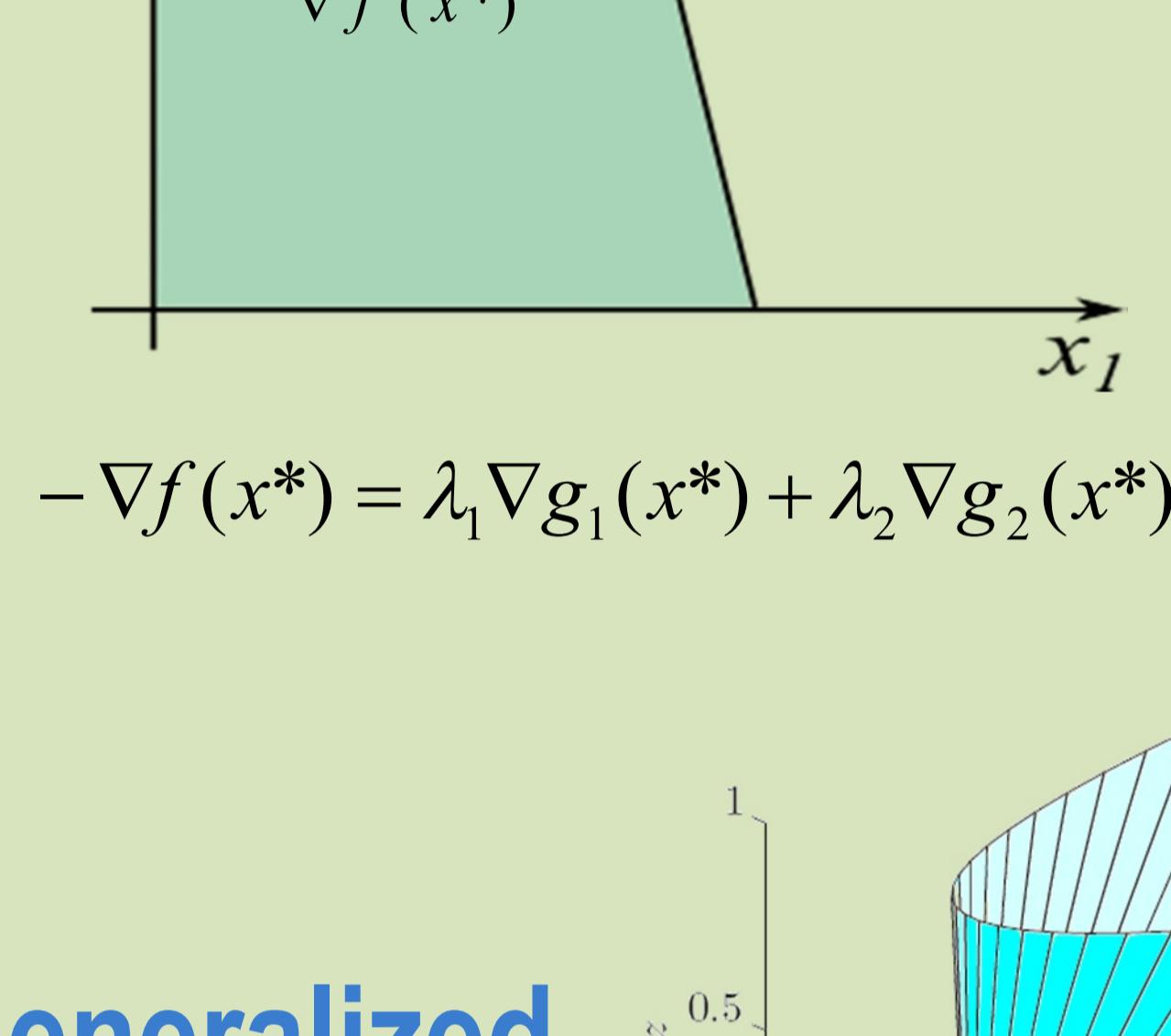
Introduction to optimization



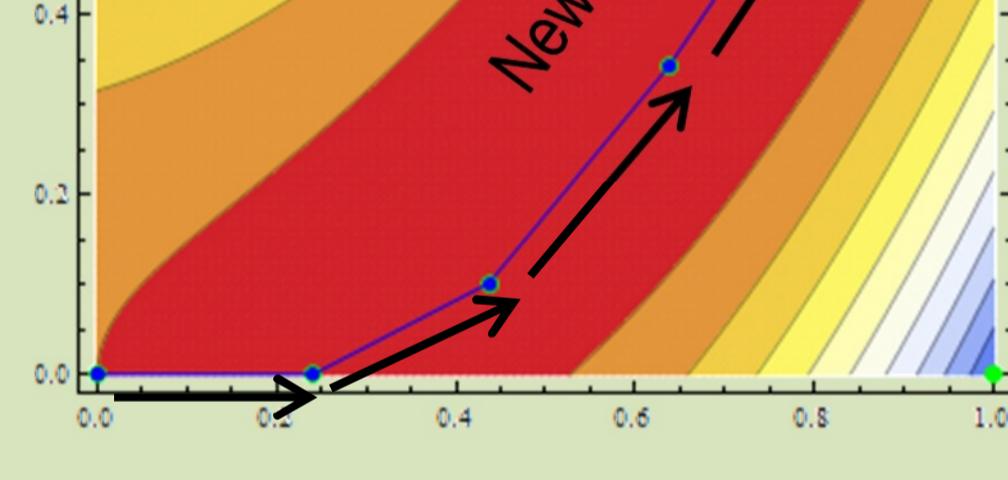
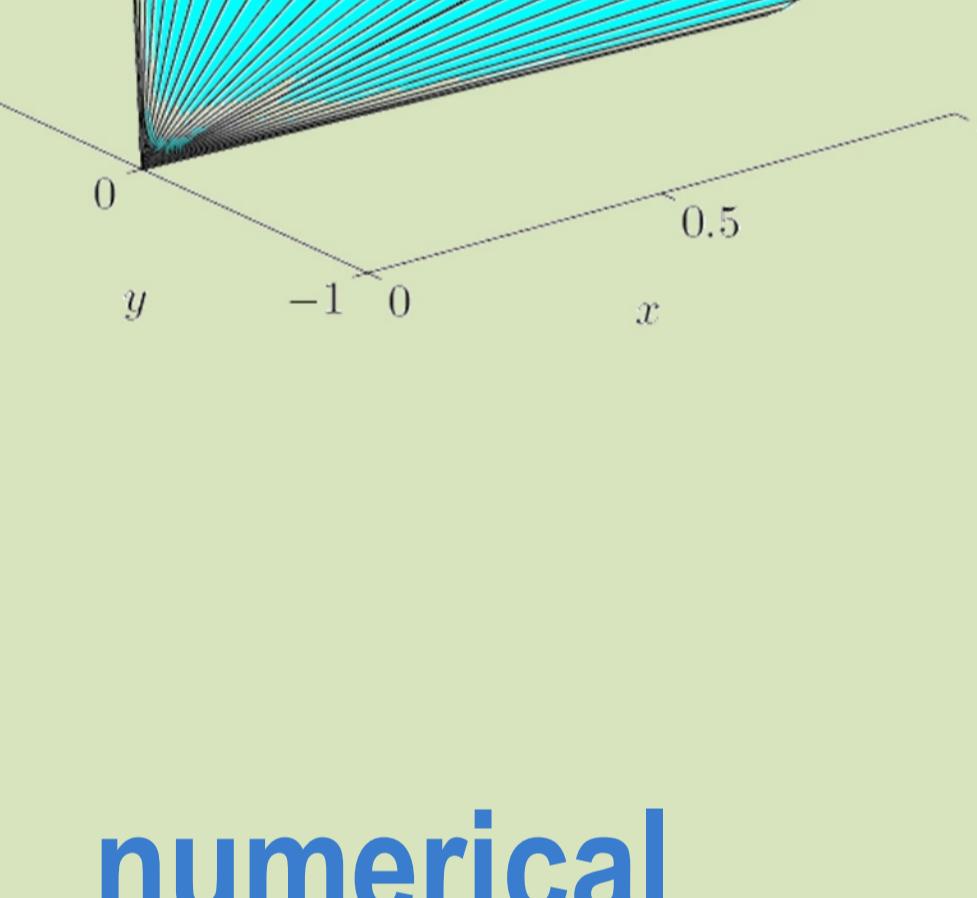
Nonlinear programming



optimality conditions

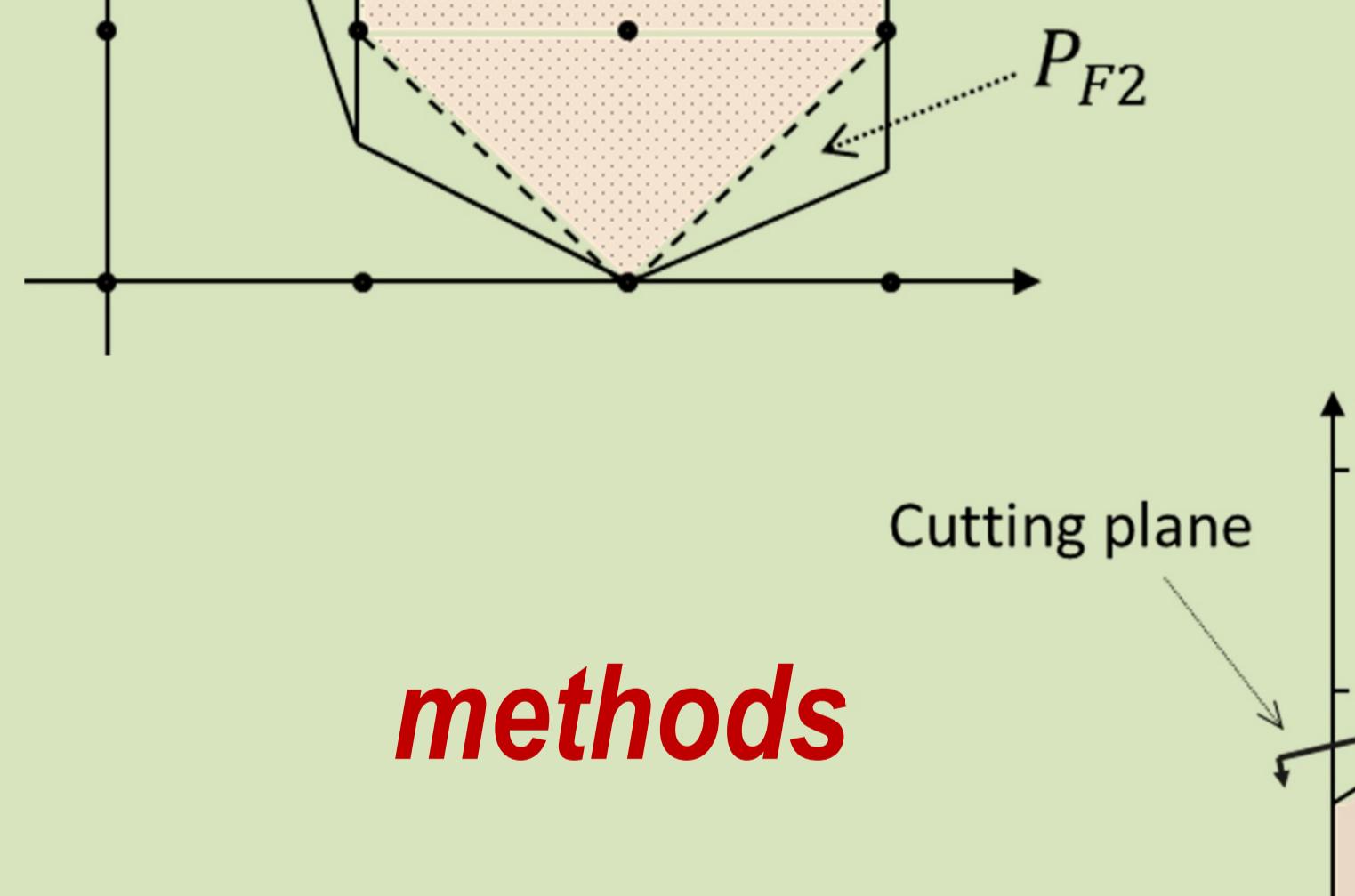


generalized convexity

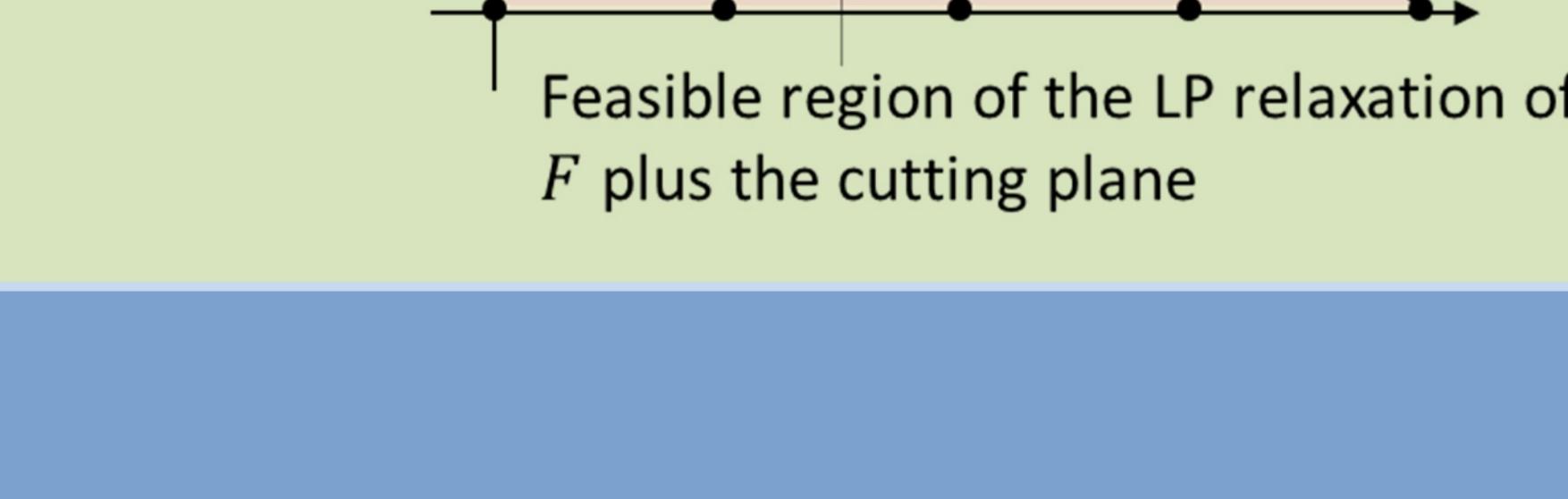


numerical algorithms

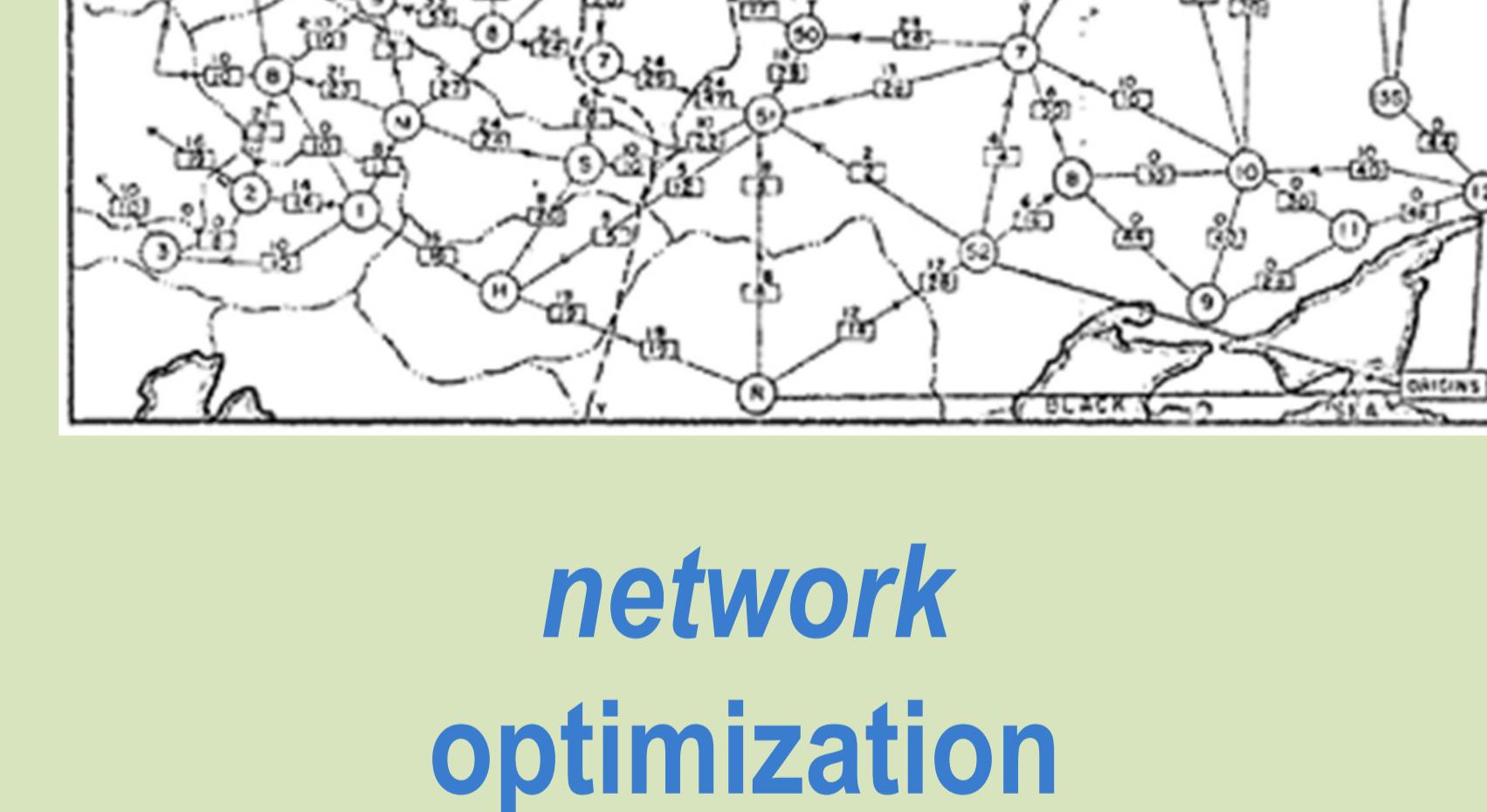
Integer optimization



methods



combinatorial optimization



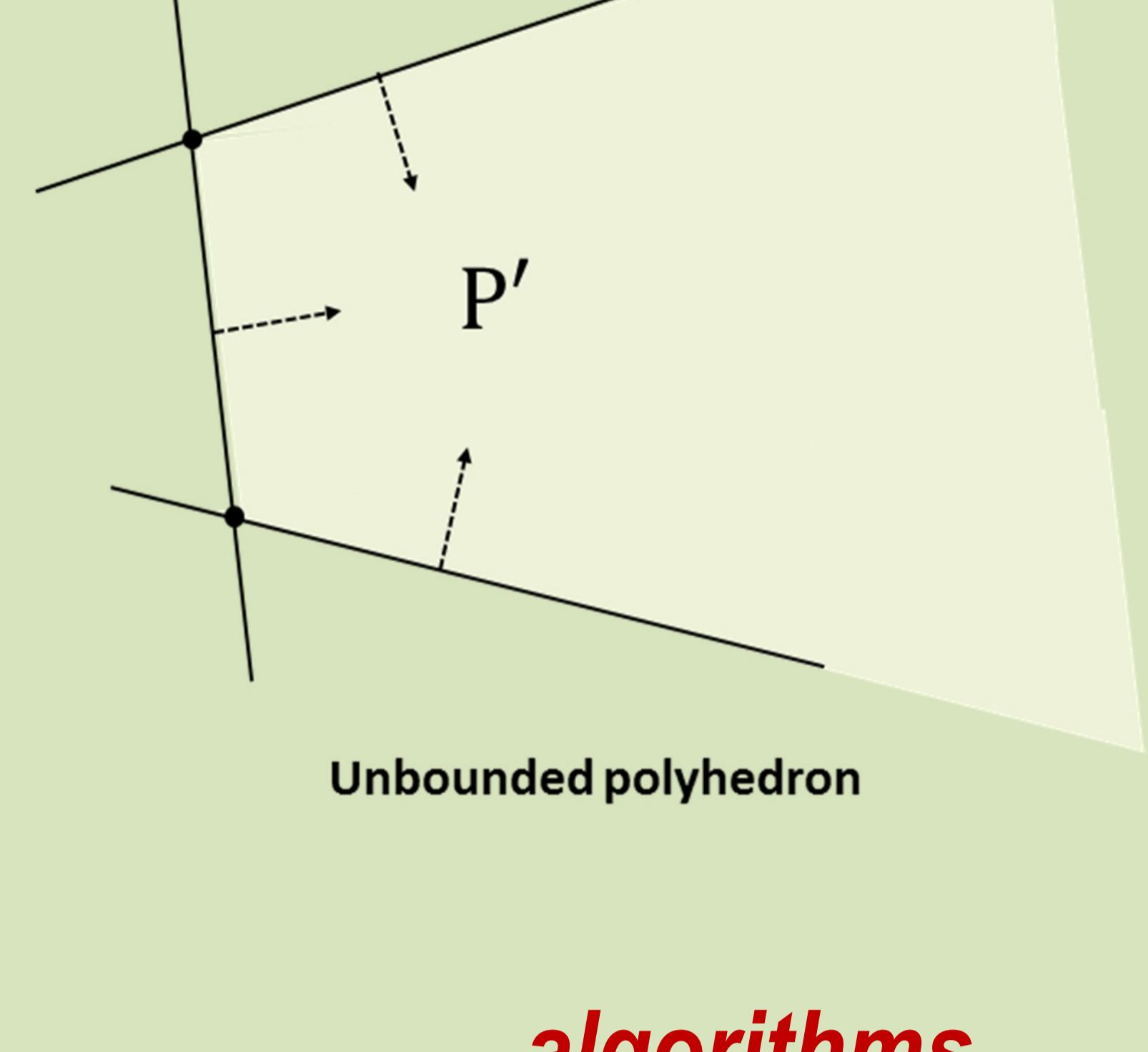
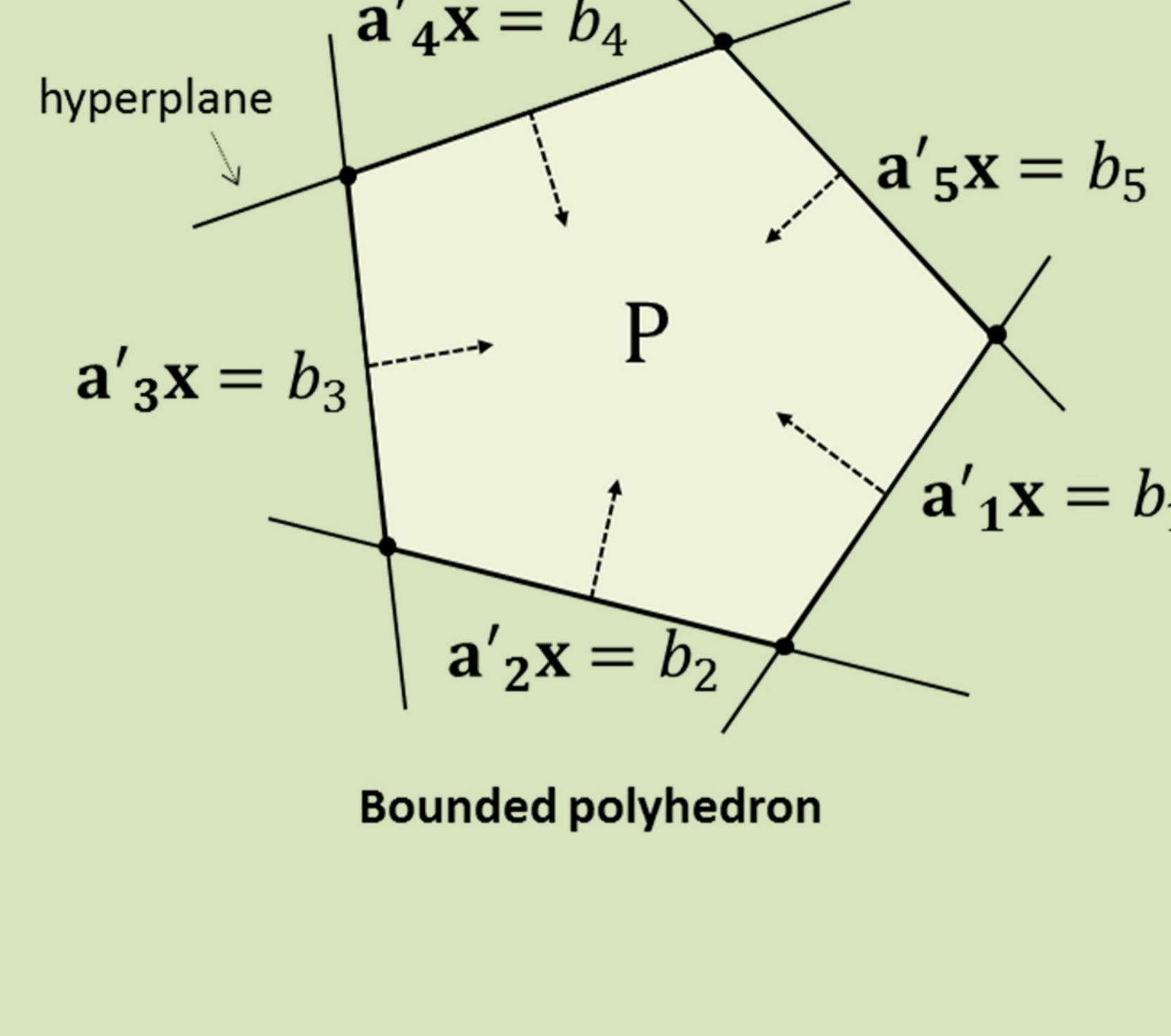
network optimization

courses and instructors

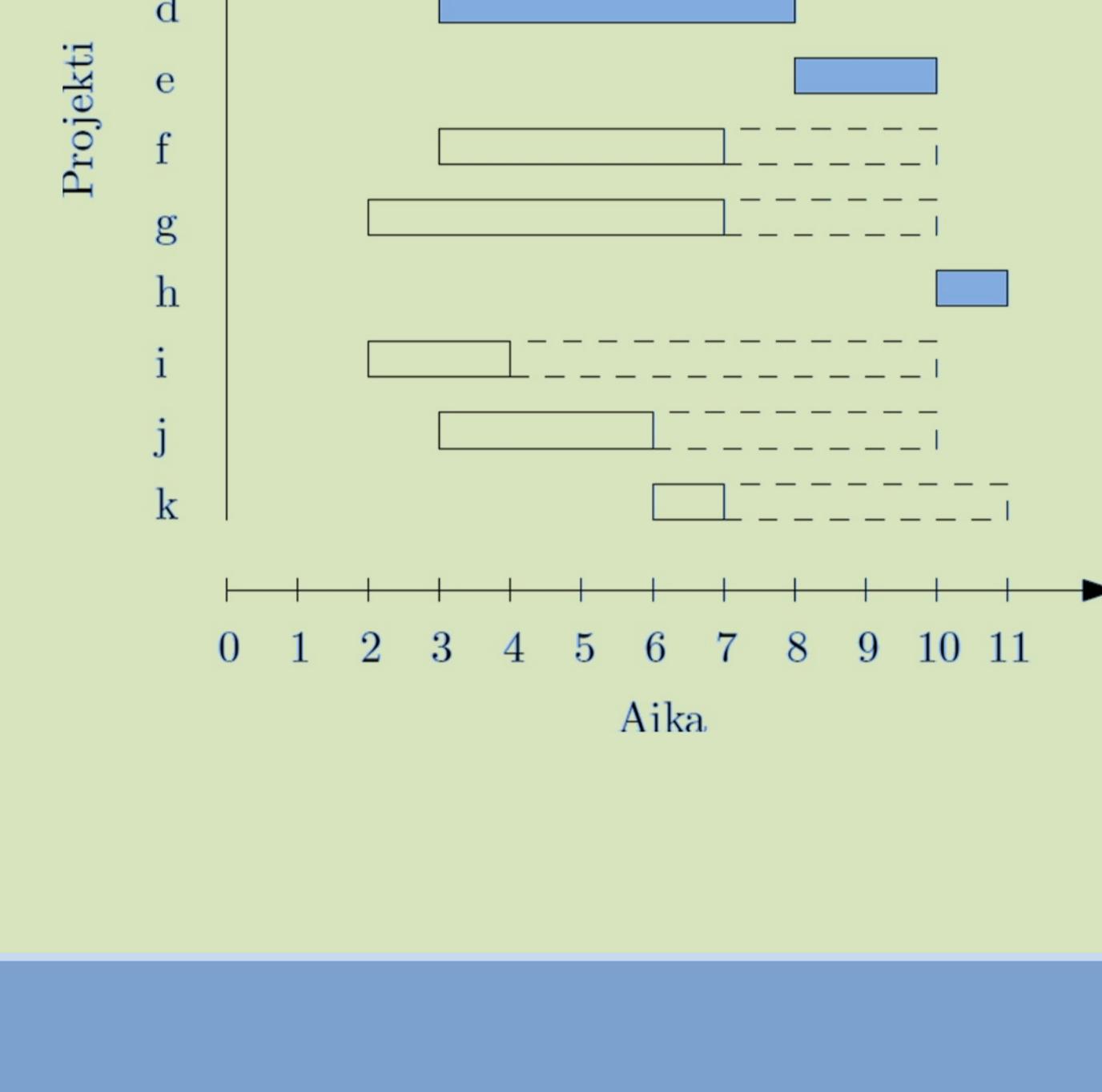
Optimoinnin Perusteet: MS-C2105, Prof. Harri Ehtamo
 Linear Programming: Mat-2.3139, Prof. Enrico Bartolini
 Nonlinear Programming: Mat-2.3140, PhD Matteo Brunelli
 Dynaaminen optimointi : Mat-2.3148, TkD Kimmo Berg
 Integer Programming: Mat-2.4148, Prof. Enrico Bartolini
 Optimoinnin Matemaattinen Teoria: Mat-2.4144, Prof. Harri Ehtamo
 Multiple Criteria Optimization: Mat-2.4153, PhD. Matteo Brunelli
 Peliteoria: Mat-2.3152, Prof. Harri Ehtamo

Linear programming

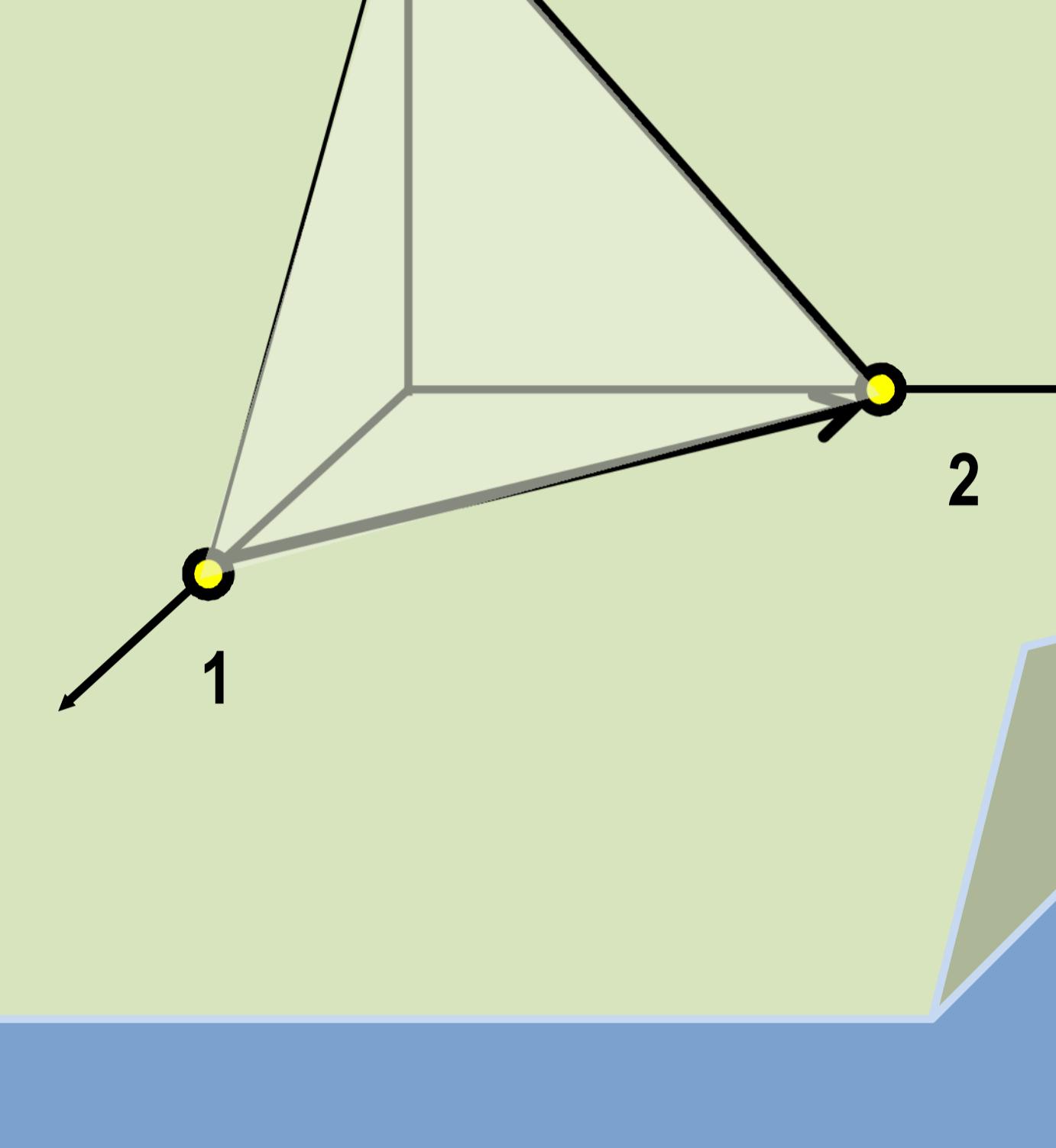
modeling and theory



applications



algorithms



Dynamic optimization

optimal macroeconomical stabilization

$$x(k+1) = Ax(k) + B_1 u(k) + B_2 v(k)$$

$$u(k) \triangleq r(k+1) - r(k)$$

$$v(k) \triangleq D(k+1) - D(k)$$

we can express the losses (4) and (5) over a planning horizon of N time stages by

$$J_s = \frac{1}{2} \sum_{k=0}^{N-1} [x^T(k) Q_s x(k) + R_{11} u^2(k) + R_{22} v^2(k)] \quad (8)$$

$$J_D = \frac{1}{2} \sum_{k=0}^{N-1} [x^T(k) Q_D x(k) + R_{11} u^2(k) + R_{22} v^2(k)] \quad (9)$$

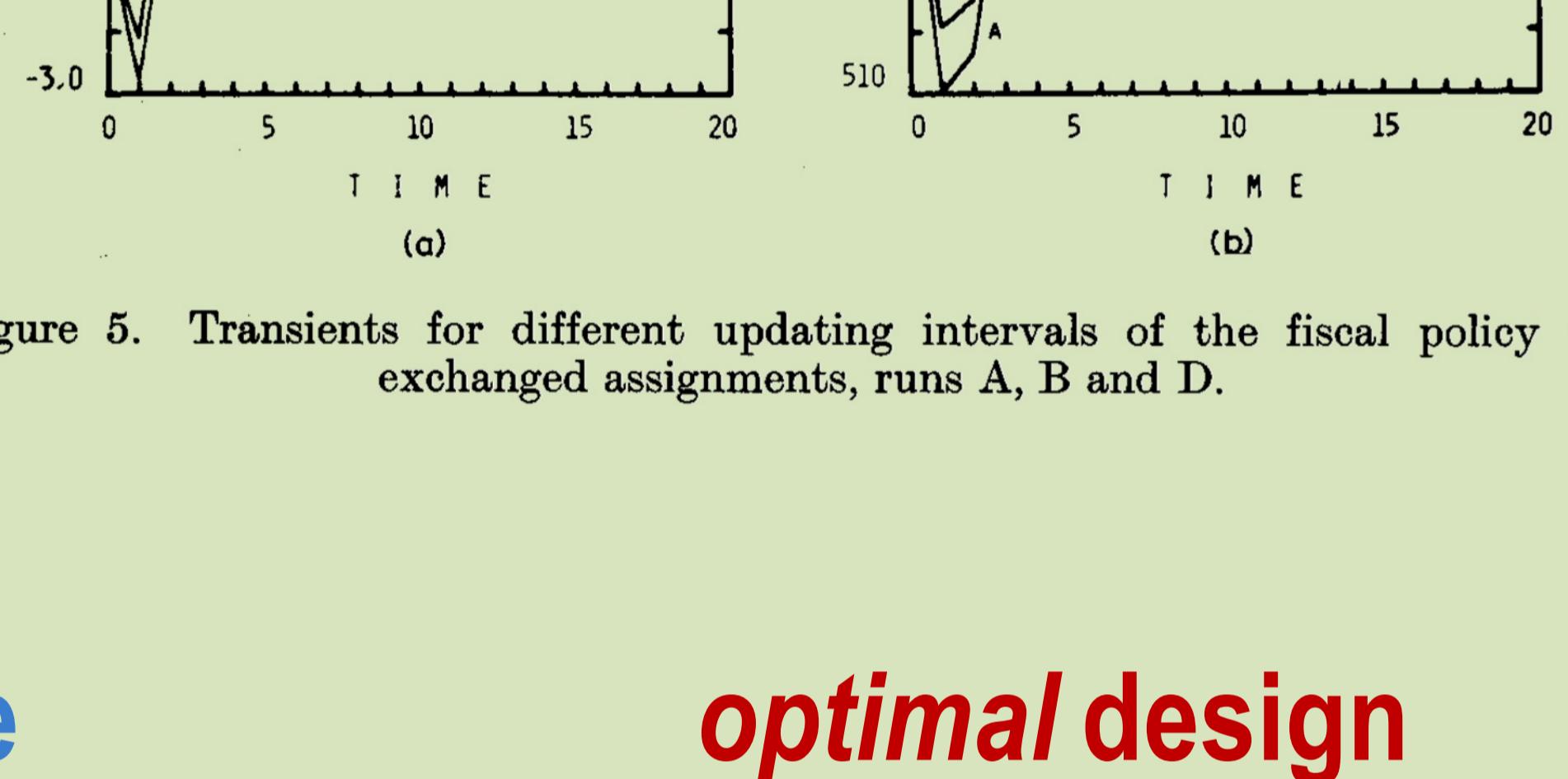


Figure 5. Transients for different updating intervals of the fiscal policy with exchanged assignments, runs A, B and D.

optimal maintenance planning



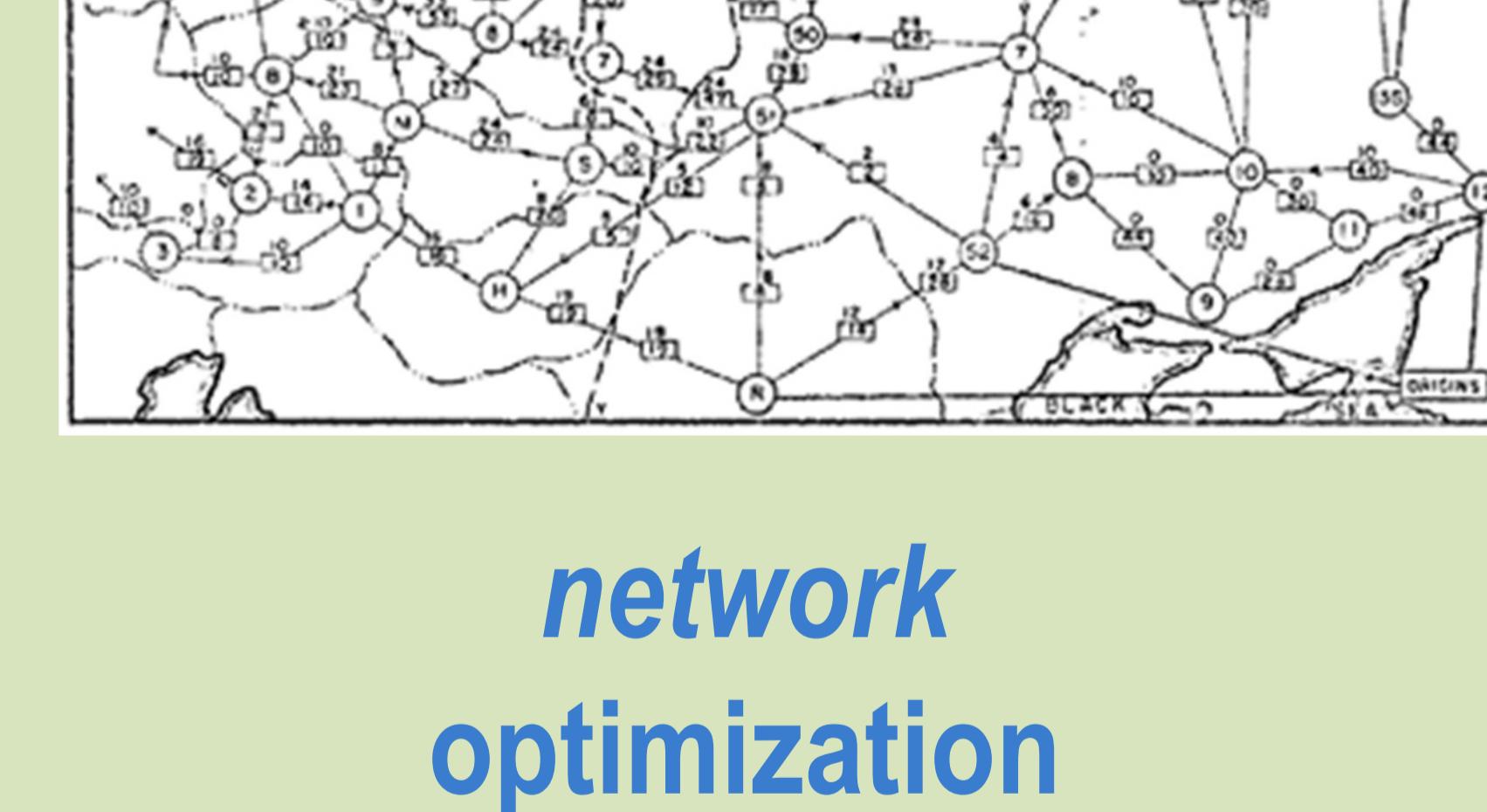
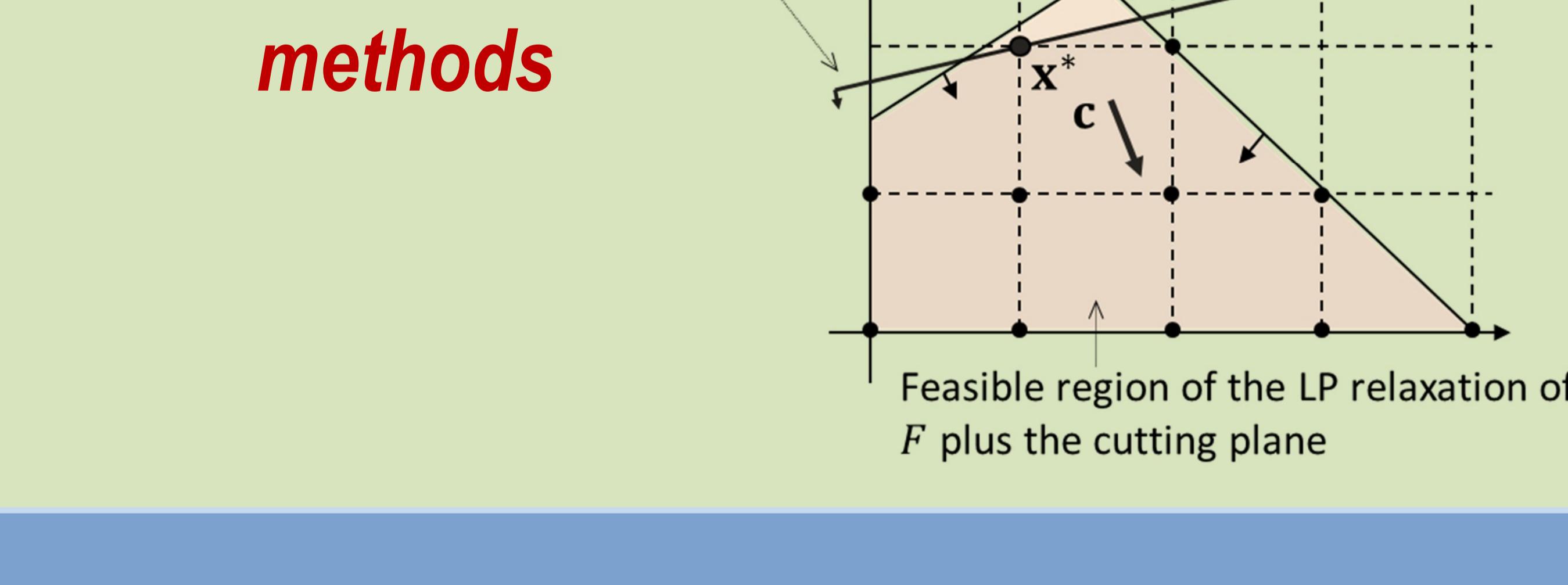
optimal design



Integer optimization

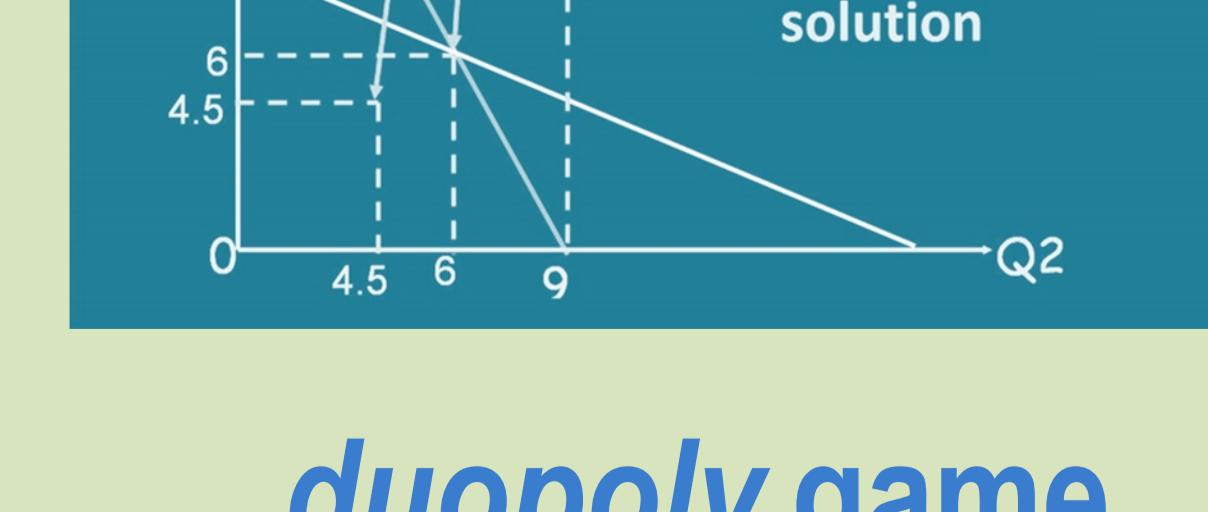
applications

combinatorial optimization



network optimization

Game theory



duopoly game

Opera	F-ball
4, 1	0, 0
0, 0	1, 4

battle of the sexes game