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Online search for a hyperplane in high-dimensional Euclidean space

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A B S T R A C T

We consider the online search problem in which a server starting at the origin of a d-dimensional Euclidean space has to find an arbitrary hyperplane. The best-possible competitive ratio and the length of the shortest curve from which each point on the d-dimensional unit sphere can be seen are within a constant factor of each other. We show that this length is in Ω(√d)∩O(d 3/2).

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1. Introduction

In d-dimensional Euclidean space, given a set of objects \( T \subseteq \mathcal{P}(\mathbb{R}^d) \), the online search problem (for an object in \( T \)) asks for a curve (or search strategy) \( \zeta : \mathbb{R}_{\geq 0} \to \mathbb{R}^d \) with \( \zeta(0) = 0 \) that minimizes the competitive ratio [14]. We say that \( \zeta \) is c-competitive if there exists an \( \alpha \in \mathbb{R}_{\geq 0} \) such that

\[
\text{length}(\zeta \mid [0,t^\ast]) \leq c \cdot \text{dist}(0, T) + \alpha
\]

for all \( T \in \mathcal{T} \), where \( t^\ast = \inf\{t : \zeta(t) \in T\} \). The infimum over all such \( c \) is the competitive ratio of \( \zeta \). Problems of this type date back to Beck [4] and Bellman [6].

The arguably most basic and well-known such online search problem from this class is the version in which \( d = 1 \) and \( \mathcal{T} = \mathbb{R} \), also known as the cow-path problem, where the best-possible competitive ratio is 9 [5], achieved by visiting the points \((-2)^k, (-2)^{k+1}, \ldots\) sequentially. In fact, the class of all 9-competitive strategies has been investigated more closely [1]. Moreover, the competitive ratio can be improved to about 4.591 using randomization [5]. The problem has been generalized to more than two paths starting at the origin [13], searching various types of objects in the plane or lattice [3], and many more scenarios. For a (slightly outdated) survey, see the book by Gal [11].

Another very natural generalization is the case of general \( d \) and \( \mathcal{T} \) being equal to \( \mathcal{H}^{d-1} \), the set of all hyperplanes in \( \mathbb{R}^d \). We call this version the d-Dimensional Hyperplane Search Problem. When \( \mathcal{T} \) is a set of affine subspaces, this is arguably the most interesting case. Note that, if \( \mathcal{T} \) contains all affine subspaces of dimension \( d' \leq d - 2 \), any constant competitive ratio is ruled out, even when \( d \) is fixed. Surprisingly, in addition to the case of \( d = 1 \), results only seem to be known for \( d = 2 \) and for offline versions [9,2], leaving a gap in the online-algorithms literature. For \( d = 2 \), it is conjectured that a logarithmic
spiral that achieves a competitive ratio of about 13.811 is optimal [3,10]. The present paper addresses the afore-
mentioned gap by providing the first asymptotic results for \( d \to \infty \).

For the remainder of the paper, we will consider the essen-
tially equivalent but arguably cleaner Sphere Inspection
Problem: The goal is to find a \( d \)-dimensional minimum-
length closed curve, \( \gamma \), that inspects the unit sphere in \( \mathbb{R}^d \), i.e., \( \gamma \) sees every point \( p \) on the unit sphere \( S^{d-1} \). Here, we
say that an object \( O \subseteq \mathbb{R}^d \) sees a point \( p' \) on the
surface of the unit sphere if there is a point \( p \in O \) such that
the line segment \( pp' \) intersects the unit ball exclusively at
\( p' \). Note that the curve is not required to start in the origin
any more. Such a minimum-length curve exists for any di-


ection [12]. While this problem is trivial for \( d \in \{1,2\} \), it
has only been shown recently that the best-possible length
for \( d = 3 \) is \( 4\pi \) [12]. No results for higher dimensions are
known. Such visibility problems have also been considered
from an algorithmic point of view, e.g., [7,8].

While the connection between hyperplane search and
sphere inspection seems to be folklore (e.g., [12]), we state
it formally and provide a short proof for completeness. Let
\( I \) be an interval, and for \( \beta \in \mathbb{R} \), a set \( T \subseteq \mathbb{R}^d \), and curve
\( \gamma : I \rightarrow \mathbb{R}^d \), we denote by \( \beta \cdot T \) the set \( \{ \beta \cdot x : x \in T \} \) and by \( \beta \cdot \gamma \) the curve \( I \rightarrow \mathbb{R}^d \), \( t \mapsto \beta \cdot \gamma(t) \).

**Proposition 1.** Let \( f : \mathbb{N} \rightarrow \mathbb{R}_{\geq 0} \). The following statements are equivalent:

(i) There exists a length-\( O(f(d)) \) closed curve in \( \mathbb{R}^d \) that
    inspects \( S^{d-1} \).

(ii) There exists an \( O(f(d)) \)-competitive strategy for the \( d \)-
    Dimensional Hyperplane Search Problem.

**Proof.** We first show that (i) implies (ii). Fix \( d \in \mathbb{N} \), let \( \gamma \)
be the length-\( \ell \) curve for the Sphere Inspection Problem
in \( \mathbb{R}^d \), and let \( y_0 \) be a point on \( \gamma \). We show that there
exists a \( (12\ell) \)-competitive strategy for the \( d \)-Dimensional
Hyperplane Search Problem where the additive constant \( \alpha \)

Since each \( H \in \mathcal{H}^{d-1} \) with \( \text{dist}(0,H) \leq \alpha/\varepsilon \), \( \gamma \) visits \( H \)
after traversing at most a length of \( c \cdot \text{dist}(0,H) + \alpha \). We
show that, for any \( \varepsilon > 0 \), there exists a, not necessarily
closed, length-\((c + \varepsilon)\) curve that inspects the sphere. This
then implies the existence of a length-\((2c + \varepsilon)\) closed curve
that inspects the sphere. We define

\[ \zeta := \frac{\varepsilon}{\alpha} \cdot \gamma|_{[0,1]} \]

where \( t^* := \sup_{H \in \mathcal{H}^{d-1} \text{dist}(0,H) \leq \alpha/\varepsilon} \min \{ t : \gamma(t) \in H \} \).

Note that the minimum exists because \( H \) is closed. Since
for each \( H \in \mathcal{H}^{d-1} \) with \( \text{dist}(0,H) \leq \alpha/\varepsilon \), \( \gamma \) visits \( H \)
after traversing at most a length of \( c \cdot \alpha/\varepsilon + \alpha \), the length
of \( \gamma|_{[0,t^*]} \) is at most \( c \cdot \alpha/\varepsilon + \alpha \), so the length of \( \zeta \) is at
most \( c + \varepsilon \).

It remains to be shown that \( \zeta \) indeed sees every point
\( p \in S^{d-1} \). Let \( H \) be the hyperplane tangent to the unit
sphere at \( p \). Further let \( \tau := \min \{ t : \gamma(t) \in \alpha/\varepsilon \cdot H \} \).

Both \( \varepsilon < \alpha/\varepsilon \). Further, by definition of \( \zeta \), we
have \( \zeta(0) \in \alpha/\varepsilon \cdot H \). Hence we have \( \tau < \zeta^{-1}(0) \in \alpha/\varepsilon \cdot H \). Hence
we have \( \zeta(t) \in H \), implying that \( \zeta(t) \) sees \( p \).

In Section 2, we give an auxiliary lemma. In Sections 3
and 4 we will use that lemma and show the following
two theorems.

**Theorem 1.** Any curve in \( \mathbb{R}^d \) that inspects \( S^{d-1} \) has length at
least \( 2d \).

**Theorem 2.** There exists a closed curve \( \gamma \) in \( \mathbb{R}^d \) of length
\( (2d)^{1/2} \) that inspects \( S^{d-1} \).

2. An auxiliary lemma

The following lemma simplifies thinking about the
Sphere Inspection Problem.

**Lemma 3.** Let \( P \subset \mathbb{R}^d \) be the convex hull of some point set \( V \).
Then, the following two statements are equivalent.

(i) We have \( S^{d-1} \subset P \).

(ii) The set \( V \) sees every point \( p \in S^{d-1} \).

**Proof.** We start by showing that (i) implies (ii). Let \( H \)
be the hyperplane that is tangent to the unit sphere at
\( p \). If \( H \) contains a point \( v \in V \), then the lemma directly
follows since the line segment \( vH \) lies completely within
\( H \) and therefore does not intersect the unit sphere other
than at $p$. So assume that there is no point $v \in V$ that is contained in $H$. Then, and since $P$ contains one point of the hyperplane $(p \in S^{d-1}$, which is contained in $P$ by (i)), there must exist two points $v_1, v_2 \in V$ which are separated by $H$. Without loss of generality, let $v_1$ be the point in the halfspace defined by $H$ whose interior is disjoint from $S^{d-1}$. Then the line segment $v_1p$ is completely contained in that halfspace, and since the interior of the halfspace is disjoint from $S^{d-1}$, $v_1$ can see $p$.

Now we show that (ii) implies (i). Towards a contradiction, assume that there exists $p^* \in S^{d-1}$ with $p^* \notin P$. Then consider a hyperplane $H$ that separates $p^*$ from $P$, and let $n$ be a unit normal vector of $H$ pointing away from $P$. Consider the hyperplane $H'$ that is tangent to $S^{d-1}$ at $n$. Clearly, both $P$ and $S^{d-1} \setminus \{n\}$ are contained in one open halfspace defined by $H'$. Note that no point in this halfspace can see $n$. Therefore, no $v \in V$ can see $n$; a contradiction. □

3. Lower bound

The goal of this section is to prove Theorem 1. Towards this, let $γ$ be a curve in $\mathbb{R}^d$ that inspects the unit sphere. We cut $γ$ into a minimum number of contiguous portions of length at most $δ$ for some fixed $δ < 2$. Let $ξ_1, \ldots, ξ_n$ be the resulting tour portions, where $n = \lceil|γ|/δ\rceil$. Choose a portion $ξ$, and let $x$ be its midpoint. Clearly $ξ$ is contained in the ball $B$ that has center $x$ and radius $δ/2$. Further define $C$ to be the cone that is the intersection of all halfspaces that contain both $B$ and $S^{d-1}$ and whose defining hyperplanes are tangent to both $B$ and $S^{d-1}$. Note that the set of points on the sphere that can be seen by the curve $ξ$ can also be seen from the apex of $C$, as visualized by Fig. 1. This holds since the radius of $B$ is $δ/2 < 1$. Note that a single point $p \in \mathbb{R}^d$ can see some subset of an open hemisphere $H$ of the unit sphere. Let $H_1, \ldots, H_n$ denote a set of open hemispheres such that $H_i$ covers the portion of the sphere seen by $ξ_i$. Since $γ$ inspects the sphere, we have that $(H_i)_{i=1}^n$ covers the sphere.

We need the following lemma.

Lemma 4. The minimum number of open hemispheres that cover $S^{d-1}$ is $d + 1$.

Proof. To show that $d + 1$ points are sufficient, choose a simplex containing the sphere. Now consider the set of open hemispheres whose poles are collinear with the origin and a vertex of that simplex. Indeed, since the simplex contains the sphere, by Lemma 3, the set of vertices of the simplex sees every point $p \in S^{d-1}$. Since each point sees only a subset of the corresponding open hemisphere, the upper bound follows.

For the lower bound, we can use induction on $d$. Clearly the circle $S^1$ needs at least three open half-circles to be covered. For $S^{d-1}$, we have that the boundary of the first hemisphere $H_1$ is $S^{d-2}$, and each hemisphere $H_i$ can cover at most an open hemisphere of $∂H_1$. So by induction at least $d(−d−2) = d$ hemispheres are needed to cover $∂H_1$, and thus we have that at least $d + 1$ hemispheres are needed to cover $S^{d-1}$. □

By Lemma 4 we have that $n \geq d + 1$, implying $\lceil|γ|/δ\rceil \geq d + 1$ and therefore $|\text{length}(γ)/δ| \geq d + 1$. With $δ = 2 - ε$, we have that $\text{length}(γ) \geq (2 - ε) \cdot d$ for all $ε > 0$, and thus $|\text{length}(γ)| \geq 2d$.

4. Upper bound

In this section we prove Theorem 2. Let $C^d$ be the $d$-dimensional cross-polytope, i.e., the polytope $\{x \in \mathbb{R}^d : \|x\|_1 \leq 1\}$. Define $C^d := \sqrt{d} \cdot C^d = \{x \in \mathbb{R}^d : \|x\|_1 \leq \sqrt{d}\}$, as shown in Fig. 2. We claim that the vertices of $C^d$ inspect the unit sphere.

Lemma 5. For any point $p \in S^{d-1}$, there exists a vertex $v$ of $C^d$ that sees $p$.

Proof. We prove that $C^d$ contains the unit sphere; then Lemma 3 shows the claim. In other words we prove that for any point $x \in S^{d-1}$, i.e., $\|x\|_2 = 1$, it also holds that $\|x\|_1 \leq \sqrt{d}$. Indeed, by the Cauchy-Schwartz inequality we have that $\|x\|_1 \leq \sqrt{d} \cdot \|x\|_2$ for any $x \in \mathbb{R}^d$ which in turn can be upper bounded by $\sqrt{d}$ for any $x \in \mathbb{R}^d$ with $\|x\|_2 \leq 1$. □
Let $G(\tilde{C}^d)$ be the graph of polytope $\tilde{C}^d$. Note that $G(\tilde{C}^d)$ is the so-called cocktail party graph which can be obtained by removing a perfect matching from a complete graph on $2d$ vertices (indeed, in $\tilde{C}^d$ any vertex $v$ has an edge to any other vertex except $-v$). We note that Ore’s Theorem [15] implies that $G(\tilde{C}^d)$ is Hamiltonian, but we provide a short proof for this paper to be self-contained.

Lemma 6. The graph $G(\tilde{C}^d)$ is Hamiltonian.

Proof. The proof is by induction on $d$. The statement clearly holds for $\mathbb{R}^2$ where the cross polytope is a square, and $G(\tilde{C}^2)$ itself is a Hamiltonian cycle that we denote by $c^2$. Consider a Hamiltonian cycle $c^{d-1}$ for $G(\tilde{C}^{d-1})$. Note that $G(\tilde{C}^d)$ can be constructed by $G(\tilde{C}^{d-1})$ and adding two nodes, $v^*$ and $-v^*$ that are connected to each of the nodes of $G(\tilde{C}^{d-1})$. To construct a cycle $c^d$ of $G(\tilde{C}^d)$, take any two distinct edges $\{v_1, v_2\}$ and $\{v_3, v_4\}$ contained in $c^{d-1}$ and replace them with the edges $\{v_1, v^*, v_2\}$ and $\{v_3, -v^*, v_4\}$, respectively. The resulting tour is connected, visits all nodes of $G(\tilde{C}^d)$ exactly once and the used edges are contained in the edge set of $G(\tilde{C}^d)$, thus ensuring the feasibility of $c^d$. □

By Lemma 5 it directly follows that any closed curve that visits all vertices of $\tilde{C}^d$ inspects the unit sphere, and therefore so does the closed curve $\gamma$ corresponding to the Hamiltonian cycle $c^d$ in the skeleton of $\tilde{C}^d$. To complete the proof of Theorem 2, note that each edge of $\tilde{C}^d$ has a length of $\sqrt{2}d$ and that $\gamma$ traverses $2d$ such edges.

5. Conclusion

In this paper, we narrowed down the optimal competitive ratio for the $d$-Dimensional Hyperplane Search Problem to $\Omega(d) \cap O(d^{3/2})$. The obvious open problem is closing this gap.

Declaration of competing interest

The authors declare that they have no known competing financial interests or personal relationships that could have appeared to influence the work reported in this paper.

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The graph $G(P)$ of a polytope $P$ is a graph with a node for each vertex of $P$ and an edge connecting those nodes if $P$ has an edge between the corresponding vertices. The graph of $P$ is also referred to as its 1-skeleton.