Worst-Case Efficient Dynamic Geometric Independent Set

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Abstract
We consider the problem of maintaining an approximate maximum independent set of geometric objects under insertions and deletions. We present a data structure that maintains a constant-factor approximate maximum independent set for broad classes of fat objects in \(d\) dimensions, where \(d\) is assumed to be a constant, in sublinear worst-case update time. This gives the first results for dynamic independent set in a wide variety of geometric settings, such as disks, fat polygons, and their high-dimensional equivalents.

Our result is obtained via a two-level approach. First, we develop a dynamic data structure which stores all objects and provides an approximate independent set when queried, with output-sensitive running time. We show that via standard methods such a structure can be used to obtain a dynamic algorithm with amortized update time bounds. Then, to obtain worst-case update time algorithms, we develop a generic deamortization scheme that with each insertion/deletion keeps (i) the update time bounded and (ii) the number of changes in the independent set constant. We show that such a scheme is applicable to fat objects by showing an appropriate generalization of a separator theorem.

Interestingly, we show that our deamortization scheme is also necessary in order to obtain worst-case update bounds: If for a class of objects our scheme is not applicable, then no constant-factor approximation with sublinear worst-case update time is possible. We show that such a lower bound applies even for seemingly simple classes of geometric objects including axis-aligned rectangles in the plane.

2012 ACM Subject Classification Theory of computation → Approximation algorithms analysis;
Theory of computation → Data structures design and analysis

Keywords and phrases Maximum independent set, deamortization, approximation

Digital Object Identifier 10.4230/LIPIcs.ESA.2021.25

Related Version Full Version: https://arxiv.org/abs/2108.08050

Funding John Iacono: Supported by the Fonds de la Recherche Scientifique-FNRS under Grant no MISU F 6001 1.
Grigoris Koumoutsos: Supported by the Fonds de la Recherche Scientifique-FNRS under a “Scientific Collaborator” grant.

Acknowledgements We would like to thank Timothy Chan and Qizheng He for pointing out an error in the previous version of this paper.

1 Introduction

Dynamic algorithms for classic NP-hard optimization problems is a quite active research area and major progress has been achieved over the last years (see [1,9–11,27]). For such problems, typically improved performance can be achieved when their geometric versions are considered, i.e., when the input has a certain geometric structure. As a result, a very recent line of research considers dynamic algorithms for well-known algorithmic problems in the geometric setting [3,12,18,21,29]. In this work, we continue this investigation by considering
the geometric version of the Maximum Independent Set problem; some of our results improve upon the previous (very recent) work of Henzinger et al. [29] and Bhore et al. [12] and some others provide the first dynamic data structures for various geometric instances.

**Static Independent Set**

In the maximum independent set problem, we are given a graph \( G = (V, E) \) and we aim to produce a subset \( I \subseteq V \) of maximum cardinality, such that no two vertices in \( I \) are adjacent. This is one of the most well-studied algorithmic problems. It is well-known to be \( \text{NP} \)-complete and hard to approximate: no polynomial time algorithm can achieve an approximation factor \( n^{1-\epsilon} \), for any constant \( \epsilon > 0 \), unless \( \text{P=NP} \) [28,36].

**(Static) Geometric Independent Set**

In the geometric version of the maximum independent set problem, the graph \( G \) is the intersection graph of a set \( V \) of geometric objects: each vertex corresponds to an object, and there is an edge between two vertices if and only if the corresponding objects intersect.

Besides the theoretical interest, the study of independent sets of geometric objects such as axis-aligned squares, rectangles or disks has been motivated by applications in various areas such as VLSI design [30], map labeling [4,35] and data mining [8,31]. For most classes of geometric objects, the problem remains \( \text{NP} \)-hard. A notable exception is the case where all objects are intervals on the real line (the well-known interval scheduling problem), where the optimal solution can be computed in polynomial time using a folklore greedy algorithm [25]. However, even the simplest 2d-generalization to axis-aligned unit squares is \( \text{NP} \)-hard [24]. As a result, most of the related work has focused on developing PTASs for certain versions of geometric independent set. This has been achieved for various types of objects such as squares, hypercubes, fat objects and pseudodisks [15,16,23,30].

A substantially harder setting is the when the geometric objects are arbitrary (axis-aligned) rectangles in the plane: Despite the intense interest (see [2,20]), no PTAS is known. Until very recently the best known approximation factor was \( O(\log \log n) \) [13,14]; in 2021, a \( O(1) \)-approximation was claimed [33].

**Dynamic Geometric Independent Set**

In the dynamic version of geometric independent set, \( V \) is a class of geometric objects (for instance squares in the plane) and we maintain a set \( S \subseteq V \) of active objects. Objects of \( V \) may be inserted in \( S \) and deleted from \( S \) over time and the goal is to maintain a maximum independent set\(^1\) of \( S \), while keeping the time to implement the changes (the update time) sublinear on the size of the input.

**Previous Work**

Most previous work dates from 2020 onwards. The only exception is the work of Gavruskin et al. [26] who considered the very special case of intervals where no interval is fully contained in any other interval. The study of this area was revitalized by a paper of Henzinger, Neumann and Wiese in SoCG’20 [29]. They presented deterministic dynamic algorithms with approximation ratio \((1+\epsilon)\) for intervals and \((1+\epsilon)\cdot 2^d\) for \(d\)-dimensional hypercubes,

\(^1\) This problem should not be confused by the related, but very different, maximal independent set problem, where the goal is to maintain an inclusionwise maximal independent set subject to updates on the edges (and not the vertices). This problem has been studied in the dynamic setting, with a remarkable recent progress after a sequence of breakthrough results [5–7,19].
under the assumption that all objects are contained in \([0,N]^d\) and each of their edges has at least unit length. Their update time was polylogarithmic in both \(n\) and \(N\), but \(N\) could be unbounded in \(n\). Furthermore, they showed that no \((1 + \epsilon)\)-approximation scheme with sublinear update time is possible, unless the Exponential Time Hypothesis fails.

Subsequently Bhore et al. \cite{bhore13} obtained the first results for dynamic geometric independent set without any assumption on the input. For intervals, they presented a dynamic \((1 + \epsilon)\)-approximation with logarithmic update time; this was recently simplified and improved by Compton et al. \cite{compton15}. For squares, \cite{bhore13} presented a randomized algorithm with expected approximation ratio roughly \(2^{12}\) (generalizing to roughly \(2^{2d+5}\) for \(d\)-dimensional hypercubes) with amortized update time \(O(\log^3 n)\) (generalizing to \(O(\log^{2d+1})\) for hypercubes).

Our Results

In this work we obtain the first dynamic algorithms for fat objects (formally defined in Section 2) in fixed dimension \(d\) with sublinear worst-case update time. The precise bounds on the approximation ratio and the update time depend on the fatness constant and the running time for worst-case range query structures for each family of objects. However, the results follow from a generic approach, applicable to all those classes of objects.

Theorem 1. There exists a deterministic data structure for maintaining a \(O(1)\)-approximate independent set of a collection of fat objects, with sublinear worst-case update time, that reports \(O(1)\) changes in the independent set per update. In particular, it achieves the following approximation ratios and worst-case update times, for any constant \(0 < \epsilon \leq 1/4\):

- \((4 + \epsilon)\)-approximation with \(O(n^{3/4})\) update time for axis-aligned squares in the plane.
- \((5 + \epsilon)\)-approximation with \(O(n^{3/4})\) update time for disks in the plane.\(^2\)
- \((2^d + \epsilon)\)-approximation with \(O(n^{1 - \frac{1}{d+1}})\) update time for \(d\)-dimensional hypercubes.
- \(O(1)\)-approximation with \(O(n^{1 - \frac{1}{d+1}})\) update time for fat objects which are unions of \(k\) (hyper)rectangles.
- \(O(1)\)-approximation with \(\tilde{O}(n^{1 - \frac{1}{m+1}})\) update time for fat simplices in \(d\) dimensions.
- \(O(1)\)-approximation with \(\tilde{O}(n^{1 - \frac{1}{m+1}})\) update time for fat objects which are unions of \(k\) simplices in \(d\) dimensions.
- \(O(1)\)-approximation with \(\tilde{O}(n^{1 - \frac{1}{m+1}})\) update time for balls in \(d\) dimensions.

This result gives the first dynamic algorithms with sublinear update time for all the aforementioned classes of objects, apart from \(d\)-dimensional hypercubes. Moreover, for hypercubes our result is the first with sublinear worst-case update time bounds without assumptions on the input; it also achieves the same approximation ratio as \cite{henzinger11}, which is the best known for any dynamic setting.

In fact, it seems hard to significantly improve our result on any aspect: First, for the approximation factor, as mentioned above, Henzinger, Neumann and Wiese \cite{henzinger11} proved that (under the Exponential Time Hypothesis) one cannot maintain a \((1 + \epsilon)\)-approximate maximum independent set of hypercubes in \(d \geq 2\) dimensions with update time \(n^{O((1/\epsilon)^{1-\delta})}\) for any \(\delta > 0\); therefore the only potential improvement in the approximation ratio is by small constant factors. Moreover, the update time we obtain is essentially the time required for detecting intersections between objects in a range query data structure. Fatness of the objects is a sensible condition for achieving such results: we prove that for (nonfat) rectangles, ellipses, or arbitrary polygons, no dynamic approximation in sublinear worst-case update time is possible. Finally, we emphasize the remarkable additional property that the number of changes reported per update is always constant.

\(^2\) Throughout this paper, \(\tilde{O}\) suppresses polylogarithmic factors.
To obtain the result of Theorem 1 we develop a generic method to obtain dynamic independent set algorithms and show how to apply it for fat objects. Our method uses a combination of several components. The first is a data structure which stores all objects, supports insertions and deletions in sublinear $f(n)$ time and, when queried, returns a $\beta$-approximate independent set with output-sensitive running time. The second main component is a generic transformation of such a data structure into a dynamic algorithm with approximation factor $\beta + \epsilon$ and amortized update time $O(f(n))$. This is done by periodically updating the solution using the data structure. Then, we apply a generic deamortization scheme, involving what we call a MIX function, a generic way to switch “smoothly” from one solution to another. We design such a MIX function for fat objects using geometric separators.

1 Overview

Notation

In what follows, $V$ is a class of geometric objects, such as squares in the plane, and we consider a finite set $S \subseteq V$. A subset of $S$ is a maximum independent set (MIS) of $S$ if all its objects are pairwise disjoint and it has maximum size over all sets with this property. We use $OPT$ to denote the size of a maximum independent set. We use $n$ to denote $|S|$, unless otherwise specified. We say that $I$ is a $\beta$-approximate MIS if its size is at least $\beta OPT$, for a constant $0 < \beta \leq 1$.

The problem we study is to maintain an approximate MIS set $I$ under a sequence of insertions and deletions in $S$, which we call generically an update, starting from an empty set. This can be expressed as implementing a single operation $\Delta = \text{Update}(u)$, where $u$ is the object to be inserted or deleted, and $\Delta$, the update set, is the set of objects that change in the approximate MIS $I$, presented as the symmetric difference from the previous set. In general we will use subscripts to express variables’ states after the indicated update, and unsubscripted versions for the current state. Using the operator $\oplus$ to denote the symmetric difference, we therefore have $S_i := \bigoplus_{j=1}^i \{u_j\}$ and $I_i := \bigoplus_{j=1}^i \Delta_j$. We say that $\text{Update}$ is a $\beta$-approximate MIS algorithm if $I_i$ is always a $\beta$-approximate MIS of $S_i$. We adopt the convention that the update set $\Delta_i$ is always returned explicitly and thus the running time of an update $u_i$ is at least the size of the returned update set, $|\Delta_i|$.

We begin with a simple yet crucial observation about MIS.

Fact 2. The size of a MIS can change by at most one with every update: $|OPT_i - OPT_{i-1}| \leq 1$.

Note that this fact does not hold for the weighted version of the MIS problem. Also note that this does not say that it is possible to have an update algorithm with an update set $\Delta_i$ with cardinality at most 1; this fact bounds how the size of a MIS can change after an update, and not the content. In fact, it is easy to produce examples where $|\Delta_i|$ must be 2, even for intervals (e.g. $u_1 = [1, 4], u_2 = [2, 3], u_3 = [1, 4]$). However, it does leave open the possibility to have an update operation returning constant-size update sets, which is something we will achieve for the classes of geometric objects we consider.

Note that while stating the main result in Theorem 1, we used the convention that the approximation ratio is $>1$. This is done mainly for aesthetical reasons, making the result easier to parse. From now on, we assume $\beta < 1$; it is easy to see that this is equivalent to a data structure achieving a $(1/\beta)$-approximation in the language of Theorem 1.
Overview

Our goal is thus to develop a general method for dynamic approximate MIS that has efficient worst-case running times and small update set sizes for various classes of geometric objects. We identify two ingredients that are needed:

- **β-dynamic independent set query structure (β-DISQS):** This an abstract data type for maintaining a set $S$ of $n$ objects, in which one can insert or delete an object in time $f(n)$, and obtain a $β$-approximate MIS of the current set $S$ in output-sensitive time $kf(n)$ if the set returned has size $k$.

- **MIX algorithm:** A MIX algorithm receives two independent sets $S_1$ and $S_2$ whose sizes sum to $n$ as input, and smoothly transitions from $S_1$ to $S_2$ by adding or removing one element at a time such that at all times the the intermediate sets are an independent sets of size at least $\min(|S_1|, |S_2|) - o(n)$. The running time of the MIX algorithm is said to be $\gamma(n)$ if the entire computation takes time $n\gamma(n)$.

The plan of the paper is as follows.

**Section 3: Amortized Update Time**

In this section, we prove that the first ingredient, the β-DISQS, is sufficient to obtain a $(\beta - \epsilon)$-approximate dynamic MIS algorithm with $O(f(n))$ amortized update time for any $\epsilon > 0$. This is presented as Theorem 4. We note that this is a bit of a “folklore” algorithm that essentially does nothing more than periodically querying the β-DISQS.

**Section 4: Worst-case Update time**

The second ingredient, MIX, is vital to deamortizing: In Section 4, we show that a DISQS and a MIX together are sufficient to produce a data structure which for any constant $\epsilon > 0$ maintains an approximate MIS of size at least $(\beta - \epsilon) \cdot \text{OPT} - o(\text{OPT})$, has a worst-case running time of $O(f(n) + \gamma(n) + \log n)$, and whose UPDATE operation returns a constant-sized update set; this is presented as Theorem 7. We also show in that the non-existence of a MIX function implies the impossibility of a approximate MIS data structure with sublinear update set size, hence sublinear worst-case running time, and that this impossibility holds for rectangles and other classes of nonfat objects (Theorem 8 and Lemma 9).

Given this generic scheme developed, to prove our main result, it remains to show that fat objects have a MIX function and a DISQS. This is the content of Sections 5 and 6.

**Section 5: Existence of a MIX function for fat objects**

We show in Lemma 13 that for fat objects in any constant dimension a MIX algorithm always exists with $\gamma(n) = O(\log n)$. This is achieved via geometric separators [34].

**Section 6: Existence of β-DISQS for fat objects**

Last, we show that obtaining a β-DISQS is possible for many types of fat objects using variants of standard range query data structures (kd-trees for orthogonal objects and partition trees for non-orthogonal objects such as disks, triangles or general polyhedra) with the running time $f(n)$ matching the query time of such structures. The result is based on a simple greedy algorithm for the MIS problem on fat objects [22,32], yielding an approximation factor $\beta$ that only depends on the fatness constant.
In this section we define formally the $\beta$-dynamic independent set query structure ($\beta$-DISQS) and show that its existence implies a dynamic independent set algorithm with approximation ratio $\beta - \epsilon$ and sublinear amortized update time.

**Definition 3.** A $\beta$-dynamic independent set query structure ($\beta$-DISQS) is a data structure that maintains a set $S$ whose size is denoted as $n$ and supports the following operations:

- **Update** $(u)$: Insert or remove $u$, so that $S$ becomes $S \oplus u$.
- **Query**: Returns a $\beta$-approximate MIS of $S$.

We say that the running time of a DISQS is $f(n)$ if Update takes time $f(n)$ and if Query returns a set of size $k$ in time $kf(n)$. We require $f(n)$ to be sublinear.

We now show that a $\beta$-DISQS is sufficient to give a approximate MIS data structure with an amortized running time, with a loss of only $\epsilon$ in the approximation factor for any $\epsilon > 0$. The intuition is simple, pass through the update operations to the DISQS and periodically replace the approximate MIS seen by the user by querying the DISQS. The only subtlety is to immediately remove any items from the approximate MIS that have been deleted in order to keep the approximate MIS valid. This simple transformation is likely folklore, but we work out the details in the full version of this paper for completeness.

**Theorem 4.** Given a $\beta$-DISQS with sublinear running time $f(n)$ for an independent set problem and a $\epsilon > 0$ there is a fully dynamic data structure to maintain a $(1 - \epsilon)\beta$-approximate independent set that runs in $O\left(\frac{1}{\epsilon} f(n) + \log n\right)$ amortized time per operation.

## Deamortization

In this section we present our deamortization technique. In particular, we describe a procedure, which we call MIX, which if exists, is used to transform a $\beta$-DISQS into a deterministic dynamic algorithm for with worst-case update time guarantees and update set size bounds. We also show that if a MIX does not exist for an independent set problem, then no sublinear worst-case update time guarantees are possible.

**MIX function**

We now define our main ingredient for deamortization, which essentially says that we can smoothly switch from one solution to another, by adding or removing one item at a time:

**Definition 5 (MIX function).** Given two solution sets $A$ and $B$, let $\text{MIX}(A, B, i)$, for $i \in [0, |A| + |B|]$ be a set where:

- $\text{MIX}(A, B, i)$ is always a valid solution
- $\text{MIX}(A, B, 0) = A$
- $\text{MIX}(A, B, |A| + |B|) = B$
- $|\text{MIX}(A, B, i)| \geq \min(|A|, |B|) - \Gamma(|A| + |B|)$, for some $\Gamma(|A| + |B|) = o(|A| + |B|)$.
- $\text{MIX}(A, B, i)$ and $\text{MIX}(A, B, i + 1)$ differ by one item.

Given this purely combinatorial definition, we define a MIX algorithm as follows.

**Definition 6.** A MIX algorithm with running time $\gamma(n)$ is a data structure such that

1. It is initialized with $A$, $B$, $i = 0$ and it has a single operation ADVANCE which advances $i$ and reports the single element in the symmetric difference $\text{MIX}(A, B, i) \oplus \text{MIX}(A, B, i - 1)$.
2. The initialization plus $|A| + |B|$ calls to ADVANCE run in total time $(|A| + |B|)\gamma(|A| + |B|)$.
The rest of this section is organized as follows. In 4.1 we show that given a \(\beta\)-DISQS and a MIX function for an independent set problem, we can produce a dynamic algorithm with worst-case update time guarantees and approximation ratio arbitrarily close to \(\beta\). In 4.2, we show the necessity of MIX function; in other words, we show that if there does not exist a MIX function for an independent set problem, then no deterministic algorithms with worst-case update time guarantees exist.

### 4.1 Dynamic algorithm with worst-Case update time

We now present our main theorem. As we discuss next, the intuition expands upon that for Theorem 4, that in addition to periodically using the \(\beta\)-DISQS to get a new solution, the MIX slowly transitions between the two previous solutions reported by the \(\beta\)-DISQS. Our result is the following.

**Theorem 7.** Given a \(\beta\)-DISQS with running time \(f(n)\) for an independent set problem, a \(\gamma(n)\)-time MIX algorithm with nondecreasing \(\Gamma(n) = o(n)\), and an \(0 < \epsilon < 1/4\), there is a fully dynamic data structure to maintain an independent set of size at least \(\epsilon\) OPT - \(o(\text{OPT})\). The data structure runs in \(O(\epsilon, \beta)(f(n) + \gamma(n) + \log n)\) worst-case time per operation, where \(n\) is the current number of objects stored, and reports a \(O(1)\) number of changes in the independent set per update.

**High-level description**

We saw in the previous section how to obtain an amortized update time algorithm by splitting the update sequence into rounds and query the DISQS at the end of each round to recompute an approximate MIS. Let \(I_k^\ast\) be the independent set produced by the DISQS at the end of round \(k\). At a high-level, the main task is to deamortize the computation of \(I_k^\ast\): we can not afford computing it during one step. Instead, we compute \(I_k^\ast\) gradually during round \(k + 1\), making sure that the running time per step is bounded. \(I_k^\ast\) is eventually computed by the end of round \(k + 1\). At this point, we would like to have \(I_k^\ast\) (discarding elements deleted during round \(k + 1\)) as our output independent set; however this can not be done immediately, since \(I_k^\ast\) might be very different from \(I_{k-1}\). For that reason, the switch from \(I_{k-1}\) to \(I_k^\ast\) is done gradually using the MIX function during round \(k + 2\). After all, our algorithm uses \(I_k^\ast\) as its independent set at the end of round \(k + 2\).

It follows that the independent set reported to the user is a combination of DISQS queries 3 or 2 rounds in the past. We show that by appropriately choosing the lengths of the rounds depending on the sizes of the independent sets, this lag affects the approximation factor by an additive \(\epsilon\).

**Proof of Theorem 7.** We group the updates \(u_i\) into rounds, and use \(r_k\) to indicate that \(u_{r_k}\) is the last update of round \(k\). Let \(I_k^\ast\) be the independent set output by the \(\beta\)-DISQS (if queried) at time \(r_k\), i.e., at the end of 4th round. The length of the \(k\)th round, \(R_k = r_k - r_{k-1}\), is defined to be \(R_k := \max\{1, \lceil \epsilon \cdot |I_{k-2}| \rceil\}\) updates.

For convenience, we define the following functions for any \(0 < \epsilon < 1/4\):

\[
\begin{align*}
g(\epsilon) &= \frac{1 + \sqrt{1 - 4\epsilon}}{2} \\
h(\epsilon) &= \frac{3 - \sqrt{1 - 4\epsilon}}{2} \\
\phi(\epsilon) &= \frac{16h^2(\epsilon)}{\epsilon \cdot \beta \cdot g^3(\epsilon)}
\end{align*}
\]

Note that \(g(\epsilon) = 1 - \epsilon - O(\epsilon^2)\) and \(h(\epsilon) = 1 + \epsilon + O(\epsilon^2)\). Note also that \(g(\epsilon) \in (1/2, 1)\) and in particular \(g(\epsilon) \to 1\) as \(\epsilon \to 0\). Similarly, \(h(\epsilon) \in (1, 3/2)\) and \(h(\epsilon) \to 1\) as \(\epsilon \to 0\).
Our Data Structures and Operations

Our overall structure contains a $\beta$-DISQS and a MIX algorithm. We also maintain the current active set of objects $S_i$ and our approximate independent set $I_i$ explicitly in a binary search tree; we refer to simply as $S$ and $I$, each stored according to some total order on the objects\footnote{Instead of a tree one could use a hash table, which would remove the additive logarithmic term from the update time, at the expense of randomization. However this will not improve our overall result, since functions $\gamma(n)$ and $f(n)$ are at least logarithmic in our application (see sections 5,6); therefore the logarithm can be absorbed while keeping the result deterministic.}. We maintain the invariant that at the beginning of round $k$, the DISQS stores the set of objects $S_{r_{k-1}}$. Also, our structure stores $I_{k-3}$ and $I_{k-2}$.

To execute update operations in round $k$, the following are performed:

Running MIX slowly: During round $k$ we use MIX to transition from $I_{k-3}$ to $I_{k-2}$. This is done by initializing MIX with $I_{k-3}$ and $I_{k-2}$ and repeatedly running the ADVANCE operation. After each update, we continue running MIX where we left off and continue until either $\phi(\epsilon) \cdot \gamma \left( |I_{k-3}| + |I_{k-2}| \right)$ time has passed or if $\phi(\epsilon)$ calls to ADVANCE have been performed.

Operation archiving: All updates are placed into a queue $Q$ as they arrive. This will ensure that the DISQS will take into account all updates of previous rounds. Moreover, if an update $u_i$ deletes an element $v$ of $S$, we wish to report it as being deleted. To do so we set a variable $\Delta^{\text{DEL}} = \{v\}$, and otherwise $\Delta^{\text{DEL}} = \emptyset$.

Interaction with the DISQS: During round $k$, we want to use the DISQS in order to compute the set $I_{k-1}$. To do that, we first perform to the DISQS all updates of round $k - 1$ one by one and remove them from $Q$. This way, DISQS stores the set $S_{r_{k-1}}$. Then, we perform a query to the DISQS, to get $I_{k-1}$. In each update of the round $\left(1 + \frac{2h(n)}{\sqrt{n}}\right) f(n)$ time is spent on executing these operations.

Maintaining $S$: We store $S$ in a binary search tree based on some total ordering of the objects. For each update $u_i$, we search for $u_i$ in $S$ and remove it if it is there, and add it if it is not, to maintain $S = S_i = S_{i-1} \oplus \{u_i\}$.

Output: After each update, we report the symmetric difference $\Delta$ between previous and current independent set to the user. Let $\Delta^{\text{MIX}}$ be the union of the items returned by the ADVANCE operation of the MIX algorithm during the execution of update $u_i$. We combine $\Delta^{\text{MIX}}$ and $\Delta^{\text{DEL}}$, and before returning, we remove any items that would result in the insertion into $I_i$ of items that are not in $S$.

Roadmap

We need to argue about (i) correctness, (ii) running time, (iii) approximation ratio and (iv) feasibility of our algorithm, i.e., that during each round the computation of MIX and DISQS have finished before the round ends. Due to space limitations, we provide a brief sketch here and defer the formal proofs to the full version.

Correctness

It is easy to see that the algorithm described above always outputs an independent set to the user: During current round $t$, the user always sees $\text{MIX}(I_{t-3}, I_{t-2}, j)$ for some $j$, with perhaps some items that have been deleted in round $t - 1$ or the current round removed. MIX is by definition an independent set at every step as in any subset of it, so the user always sees an independent set.
Bound on update set size

The update set returned is a subset of $\Delta_i^{MIX} \cup \Delta_i^{DEL}$, as insertions of $\Delta_i^{MIX}$ might be removed if the items are no longer in $S$. The size of $\Delta_i^{MIX}$ is at most $\phi(\epsilon)$ by construction; the set $\Delta_i^{DEL}$ contains at most one element. Therefore,

$$
\Delta \leq \phi(\epsilon) + 1 = \frac{16k^2(\epsilon)}{\epsilon \cdot \beta \cdot g^3(\epsilon)} + 1 \leq \frac{16}{\epsilon \cdot \beta} \cdot \frac{(3/2)^2}{(1/2)^3} + 1 = O\left(\frac{1}{\epsilon \cdot \beta}\right) = O_{\epsilon,\beta}(1) \quad (1)
$$

Running time

The formal proof is located in the full version. Briefly, MIX takes time $\phi(\epsilon) \cdot \gamma \left(|\bar{I}_{k-3}| + |\bar{I}_{k-2}|\right)$. It is easy to show that $|\bar{I}_{k-3}| + |\bar{I}_{k-2}| \leq \frac{2OPT}{g(\epsilon)} \leq 16n$. Using that $\gamma$ is sublinear, we get that $\phi(\epsilon) \cdot \gamma \left(|\bar{I}_{k-3}| + |\bar{I}_{k-2}|\right) = O_{\epsilon}(\gamma(n))$. DISQS works for time $(1 + \frac{2h(n)}{\epsilon \cdot \beta})/f(n) = O_{\epsilon,\beta}(f(n))$. Last, operations for checking if update elements are still in $S$ require time $O(|\Delta_i^{MIX} \cup \Delta_i^{DEL}| \cdot \log n) = O_{\epsilon,\beta}(\log n)$, due to (1).

Approximation ratio and feasibility

The proofs of approximation ratio and feasibility are simple but technical, and deferred to the full version. At a high level, the main idea is that the size of each round is carefully chosen such that, combined with Fact 2, the approximation factor $\beta$ of the DISQS worsens just by an additive $\epsilon$ term due to the delayed updates and allows the DISQS and MIX operation to complete during the round.

4.2 Necessity of the MIX function

 résultant MIX, their independent set is at least $|B|$ inserts and delete $\delta$ reports
|I| \leq \phi(\epsilon) \cdot \gamma(3/2)^2 \cdot (1/2)^3 + 1 = O\left(\frac{1}{\epsilon \cdot \beta}\right) = O_{\epsilon,\beta}(1)

Suppose for any $n$, there are independent sets $A$ and $B$ of size $n$ such that there is no MIX function with $\Gamma(n) \leq (1 - \beta)n$ for all $A' \subseteq A$ and $B' \subseteq B$, where $|A'|, |B'| \geq \beta n$. Then there is no $(\beta + \epsilon)$-approximate dynamic MIS algorithm that reports at most $o(n)$ changes in the independent set per update, for any $\epsilon > 0$.

Proof. Let $\delta(n) = o(n)$ and suppose there is a $(\beta - \epsilon)$-approximate MIS algorithm that reports $\delta(n)$ changes per update in the worst case. Insert $A$ in to the data structure. Then insert $B$ and delete $A$. This is $|A| + |B|$ update operations. At all times the independent set is at least $(\beta - \epsilon)n$, and there are at most $\delta(n)$ changes per update operation. We could transform this into a MIX function by taking the at most $\delta(n)$ changes from update and report each change one at a time, first deletes and then inserts; thus at each step of the resultant MIX, their independent set is at least $(\beta + \epsilon)n - \delta(n)$ which is at least $\beta n$ for sufficiently large $n$.

We can apply this to the case of rectangles in the plane, where we show that with a non-trivial worst-case performance of $o(n)$ changes in the independent set per operation, it is impossible to have a $\beta$-approximate MIS for any $\beta > 0$.

Lemma 9. There is no MIX function for rectangles with $\Gamma(n) < n$. Thus from Theorem 8, for any $\beta > 0$, there is no $\beta$-approximate dynamic MIS algorithm that reports at most $o(n)$ changes in the independent set per update.

Proof. This is equivalent to saying that there are sets of rectangles $A$ and $B$ such that for any MIX function, there is an $i$ such that $\text{MIX}(A, B, i) = \emptyset$. Consider sets of rectangles $A$ and $B$, each of size $n$, in the form of a grid such that $A$ are horizontally thin and disjoint, $B$
are vertically thin and disjoint, and every rectangle of $A$ intersects all rectangles of $B$. In a MIX function, starting from $A$, one can not add a single element from $B$ until all elements of $A$ have been removed.

This construction works for any class of objects for such a generalized “hashtag” construction is possible, which includes any class of shapes which are connected and where for any rectangle, there is a shape in the class that has that rectangle as its minimum orthogonal bounding rectangle. This includes natural classes of shapes without fatness constraints, such as triangles, ellipses, polygons, etc.

5 A MIX algorithm for fat objects

Fat objects

There are many possible definitions of fat objects in Euclidean space, we use the following one from [15]. Define the center and size of an object to be the center and side length of one of its minimal enclosing hypercube.

Definition 10. A collection $S$ of (connected) objects is $f$-fat, for a constant $f$, if for any size-$r$ box $R$, there are $f$ points such that every object that intersects $R$ and has size at least $r$ contains one of the chosen points.

This implies that any box can only intersect $f$ disjoint objects of size larger than the box. Throughout the whole section, $f$ and the dimension $d$ are considered to be constant.

We will develop and use a variant of the rectangle separator theorem of Smith and Wormald [34]. We first state the classic version, and then prove the variant we need. Our proofs are straightforward adaptations of those in [34].

Lemma 11 (Smith and Wormald [34]). For any set $S$ of disjoint squares objects in the plane, there is a separating rectangle $R$ that such if we partition $S$ into $S_{IN}$, $S_{OUT}$ and $S_{ON}$ based on whether each object lies entirely inside $R$, entirely outside $R$, or intersects $R$, $S_{IN} \leq \frac{2}{3} |S|$, $S_{OUT} \leq \frac{2}{3} |S|$ and $S_{ON} = O(\sqrt{|S|})$.

What we need differs from this in that we have two sets of fat objects, in each set the objects are disjoint but intersection is allowed between the two sets, and we want to have the separator intersect with an order-square-root number of objects in each set. However we require the separator to be balanced with respect to the first set only; it is not possible to require balance with respect to both sets. We state the separator theorem here, the proof is in the full version.

Lemma 12. Let $S_1$ and $S_2$ be two sets of disjoint $f$-fat objects in $d$-dimensions. Let $n = |S_1| + |S_2|$. We can compute a hypercube $s$ and sets $S_{IN}^1, S_{IN}^2, S_{OUT}^1, S_{OUT}^2$ with the following properties in time $O(d \cdot n) = O(n)$:

- The hypercube $s$ intersects $O(n^{1-\frac{1}{d}})$ objects of $S_1 \cup S_2$.
- $S_{IN}^1 \subseteq S_1, S_{IN}^2 \subseteq S_2, S_{OUT}^1 \subseteq S_1, S_{OUT}^2 \subseteq S_2$
- All objects in $S_{IN}^1$ and $S_{IN}^2$ lie entirely inside $s$
- All objects in $S_{OUT}^1$ and $S_{OUT}^2$ lie entirely outside $s$
- $|S_{IN}^1| \leq \frac{2^{d-1}}{\pi^d} |S_1|$
- $|S_{OUT}^1| \leq \frac{2^{d-1}}{\pi^d} |S_1|$
Lemma 13. Fat objects in constant dimension $d$ have a MIX algorithm with running time $\gamma(n) = O(\log n)$: Given independent sets of fat objects $S_1$ and $S_2$, there is a MIX from $S_1$ to $S_2$ whose size is always at least $\min(|S_1|, |S_2|) - \Gamma(|S_1| + |S_2|)$, with $\Gamma(n) = O(n^{1-\frac{2}{d}} \log n) = o(n)$. The total running time of initializing the algorithm with $S_1$ and $S_2$ and performing all steps of MIX is $O((|S_1| + |S_2|) \cdot \log(|S_1| + |S_2|))$.

Proof. We compute the separator $s$ from Lemma 12. Let $S_1^{IN}$, $S_1^{OUT}$, $S_2^{IN}$, $S_2^{OUT}$, $S_1^s$, $S_2^s$ denote partition of $S_1$ and $S_2$ into parts that are completely inside the separator, completely outside, and those that intersect the separator, respectively.

Main Idea. The main idea is the following: First, we will remove all objects of $S_1^s$. Then the remaining objects of $S_1$ would be either completely inside $s$ or completely outside $S$. We will use recursively the MIX function in both sides to switch from $S_1^{IN}$ to $S_2^{IN}$ and from $S_1^{OUT}$ to $S_2^{OUT}$ respectively. At the end we will add $S_2^s$.

Applying the recursion carefully. Recall that our goal is twofold: First, minimize the running time of MIX, second, make sure that at each step the size of the current set is at large as possible. Formally, minimize both $\gamma(n)$ and $\Gamma(n)$, which should be definitely sublinear, and as small as possible. Note that towards the second goal, i.e., keeping the set size as high as possible at all times, the sets used to apply the first recursive call of MIX matter: should we start from switching from $S_1^{IN}$ to $S_2^{IN}$ or from $S_1^{OUT}$ to $S_2^{OUT}$? We want to make the choice that leads to the largest independent set at the intermediate step when only one of the two recursive calls has been applied.

We denote $a$ and $b$ the sides of separator (IN and OUT) so that $|S_1^a| + |S_2^b| \leq |S_1^s| + |S_2^s|$ holds. As $\min(w + x, y + z) \leq \max(w + z, x + y)$:

$$|S_1^a| + |S_2^b| = \max(|S_1^a| + |S_2^b|, |S_1^s| + |S_2^s|) \geq \min(|S_1^s| + |S_1^s|, |S_2^s| + |S_2^s|). \tag{2}$$

This way, at the intermediate step when we have mixed only one side, the set size will not be smaller than the beginning or the end of the mix operation.

Formal Description. The MIX function then proceeds as follows:

1. Start with $S_1$.
2. Remove the elements of $S_1^s$, one at a time, to give $S_1^a \cup S_1^b$.
3. Recursively MIX $S_1^a$ to $S_2^s$.
4. Now we have $S_2^s \cup S_1^b$.
5. Recursively MIX $S_1^b$ to $S_2^s$. At the end of this process we will have $S_2^s \cup S_2^b$.
6. Add the elements of $S_2^b$, one at a time.
7. We finish with $S_2^s \cup S_2^a \cup S_2^b = S_2$.

The base case is when one of the two sets is empty, and the MIX proceeds in the obvious way by deleting all elements of $S_1$ if $S_2$ is empty, or inserting all elements of $S_2$ if $S_1$ is empty. In such a case the lemma holds trivially as $\min(|S_1|, |S_2|)$ is zero.

We need to argue that at all times this process generates a set that is an independent set of the claimed size.

Always an independent set. In steps 1-2 we always have a subset of $S_1$, which is an independent set, the same holds in steps 6-7 with respect to $S_2$. In step 4, $S_2^s \cup S_1^b$ is independent as each of the sets are independent and all of the objects on each set are entirely on opposite sides of the separating rectangle $s$. Steps 3 and 5 hold by induction, and that the part we are recursively MIXing and the part that is unchanged are entirely on opposite sides of the separating rectangle.
Worst-Case Efficient Dynamic Geometric Independent Set

**Size bound.** Let $\text{MIX}_{\text{min}}(S_1, S_2, n)$ be the smallest size of the independent set during the running of the MIX function from $S_1$ to $S_2$, and where $n$ is an upper bound on $|S_1| + |S_2|$. Then we can directly express $\text{MIX}_{\text{min}}$ as a recurrence, taking the minimum of each step of the algorithm:

$$\text{MIX}_{\text{min}}(S_1, S_2, n) = \min(|S_1|, |S_1^0| + |S_2^0|, \text{MIX}_{\text{min}}(|S_1^0|, |S_2^0|, n) + |S_1^0|, |S_2^0| + |S_1^0|),$$

where $S_1^0$ and $S_2^0$ are disjoint subsets of $S_1$ and $S_2$. We will prove that

$$\text{MIX}(S_1, S_2, n) \geq \min(|S_1|, |S_2|) - (\log \frac{1}{1 - \epsilon}) |S_1| \cdot n^{1 - \frac{c}{d}}$$

which implies the claim of this lemma. The details of this inductive proof are given in the full version. It follows exactly the intuition that (i) the only loss in the MIX function is the separators at each level of the recursion, (ii) there are logarithmic levels of the recursion and (iii) the size of the separators in each level are $O(n^{1-1/d})$. Some care must be taken, since the separators are only balanced for one of the two sets.

**Running time.** The running time is given by the recursion:

$$T(S_1, S_2) = \begin{cases} |S_1| & \text{if } S_2 = \emptyset \\ |S_2| & \text{if } S_1 = \emptyset \\ T(S_1^0, S_2^0) + T(S_1^0, S_2^0) + O(|S_1| + |S_2|) & \text{otherwise} \end{cases}$$

where the additive term in the last case is dominated by the time needed to compute the separator (Lemma 12) which is $O(d \cdot (|S_1| + |S_2|)) = O(|S_1| + |S_2|)$, since $d$ is assumed to be constant.

Recall $|S_1^0|, |S_2^0| \leq \frac{d}{d+1} \cdot |S_1|$, $S_1^0$ and $S_2^0$ are disjoint subsets of $S_1$, and $S_1^0$ and $S_2^0$ are disjoint subsets of $S_2$. Hence the recursion depth is logarithmic in $|S_1|$ and each item from $S_1$ and $S_2$ is passed to at most one of the recursive terms.

Thus the running time is $O((|S_1| + |S_2|) \log |S_1|)$. As the running time is defined to be $(|S_1| + |S_2|) \cdot \gamma(|S_1| + |S_2|)$, we have $\gamma(|S_1| + |S_2|) \leq \log(|S_1| + |S_2|)$.

**Remark.** We note the effect of the running time of the separator algorithm (Lemma 12) on the running time of the MIX algorithm: If the running time was $O(n^c)$ for some constant $c$, then the additive term in the recursion would have increase to $O((|S_1| + |S_2|)^c)$, leading to $\gamma(n) = n^{c - 1} \cdot \log n$; such a running time would be sublinear only for $c < 2$; here, by achieving $c = 1$, we get the fastest possible running time which implies the polylogarithmic running time for MIX for fat objects.

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**6 DISQS for fat objects**

In this section, we define DISQS for various classes of geometric objects. First observe that for intervals, a 1-DISQS with running time $O(\log n)$ follows from the classic greedy algorithm [25]. By storing the intervals in an augmented binary search tree, one can insert and delete intervals as well as answer queries of the form “What is the interval entirely to the right of $x$ with the leftmost right endpoint?” As intervals are fat, this implies a $(1 - \epsilon)$ approximate MIS algorithm with running time $O(\frac{1}{\epsilon} \log n)$. This in not new, in the past year a complicated structure via local exchanges appeared in [12] and soon after a much simpler method [21] using a local rebuilding was obtained; we obtain this as part of our more general scheme for fat objects.
We now focus on developing DISQS for fat objects. This involves two ideas. First, we use a simple greedy offline algorithm that computes an constant-approximate MIS for fat objects. Then we combine this algorithm with a range searching data structure to implement the greedy choice.

A greedy offline approximation algorithm

Given a collection of fat objects, we consider the independent set obtained by sorting them by size, from the smallest to the largest, and adding them greedily to the independent set, provided they do not intersect anything added previously. We refer to this algorithm as the greedy algorithm. It was considered in particular by Chan and Har-Peled [17], but was known in special cases before [22]. From the definition of \( f \)-fat objects, every successive object returned by the algorithm can intersect at most \( f \) disjoint objects that are larger. Hence this simple algorithm yields a constant-factor approximation algorithm for fat objects.

**Lemma 14.** For \( f \)-fat objects in dimension \( d \), the greedy algorithm returns an \( 1/f \)-approximate MIS.

We need to implement this greedy method as the query of a DISQS; that is, it should support insertion and deletion of objects, and the running time of the greedy algorithm must be output-sensitive. This can be done with a slight variation of classic range intersection query structures, where we can insert and delete objects, mark or unmark objects that intersect a given query, and return the largest unmarked object. Thus each item returned by the greedy algorithm is reported after a constant number of range intersection query operations.

The DISQS data structures thus have running times that match those of the underlying range intersection query structures when the query ranges are from the same family of objects as the objects stored: \( O(n^{1-\frac{1}{d}}) \) for hyperrectangles, using kd-trees, \( \tilde{O}(n^{1-\frac{1}{d}}) \) for disks and \( \tilde{O}(n^{1-\frac{1}{d(d+1)}}) \) for simplices, using partition trees; see the full version for more details.

Summary

The range intersection queries (details in the full version) combined with the greedy algorithm (Lemma 14) gives a DISQS whose running time depends on the range intersection queries, and whose approximation radio is the inverse of the fatness constant. From Lemma 13 fat objects have a MIX algorithm. Given the MIX, DISQS, and constant \( \epsilon > 0 \), Theorem 7 yields a dynamic MIS structure, with worst-case update time depending on the range intersection queries, approximation ratio within \( \epsilon \) of that from the fatness, and with only a constant-size update set per operation. Putting all these pieces together yields Theorem 1.

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Revision Notice

This is a revised version of the eponymous paper appeared in the proceedings of ESA 2021 (LIPIcs, volume 204, https://www.dagstuhl.de/dagpub/978-3-95977-204-4, published in September, 2021), in which it was erroneously claimed that the update time for squares, hypercubes and unions of $k$ fat hyperrectangles is polylogarithmic. This claim is withdrawn and replaced by the polynomial update time presented in this version. Reaching polylogarithmic worst-case update time bounds for these objects would require new ideas, distinct from those given in Section 6.

Dagstuhl Publishing – October 15, 2021.