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Nonlinear Programming 2nd Edition Solutions Manual Dimitri P. Bertsekas Massachusetts Institute of Technology Athena Scientific, Belmont, Massachusetts 1. NOTE This solutions manual is continuously updated and improved. Portions of the manual, involving

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1.2. Linear Programming: A Graphical Perspective in R2 13 The feasible region is shown in Figure 1.4. The LP has alternative optimal solutions that fall on the segment connecting $x = \begin{pmatrix} 3 \\ 1 \end{pmatrix}$ # to $x = \begin{pmatrix} 6 \\ 0 \end{pmatrix}$ #. Each such solution has an objective value of $z = 12$, and the parametric representation of the segment is given by $x = \begin{pmatrix} 3t+6(1-t) \\ t+0(1-t) \end{pmatrix}$ # = $\begin{pmatrix} 6-3t \\ t \end{pmatrix}$ #, where $0 \leq t \leq 1$. $x_1 \ x_2$

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