

Slack-based Heuristics for JSSP

Heuristics in choco

Variable ordering

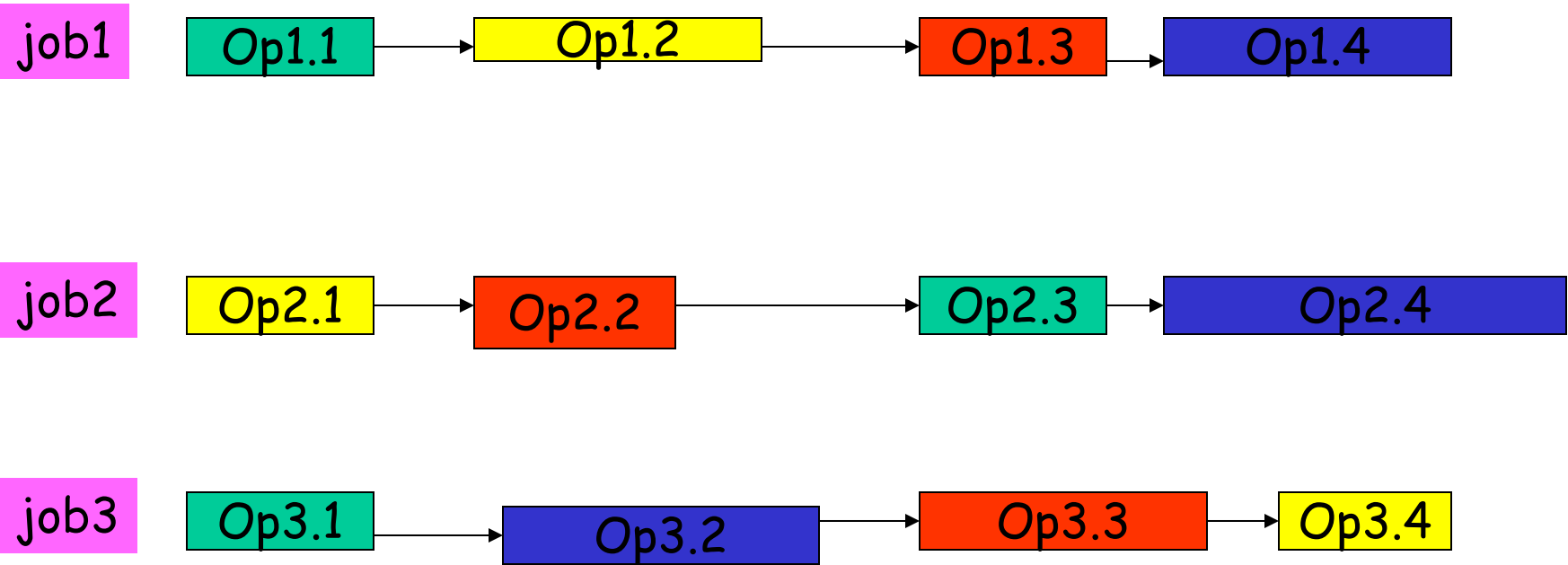
Value ordering

jssp refresh

We have

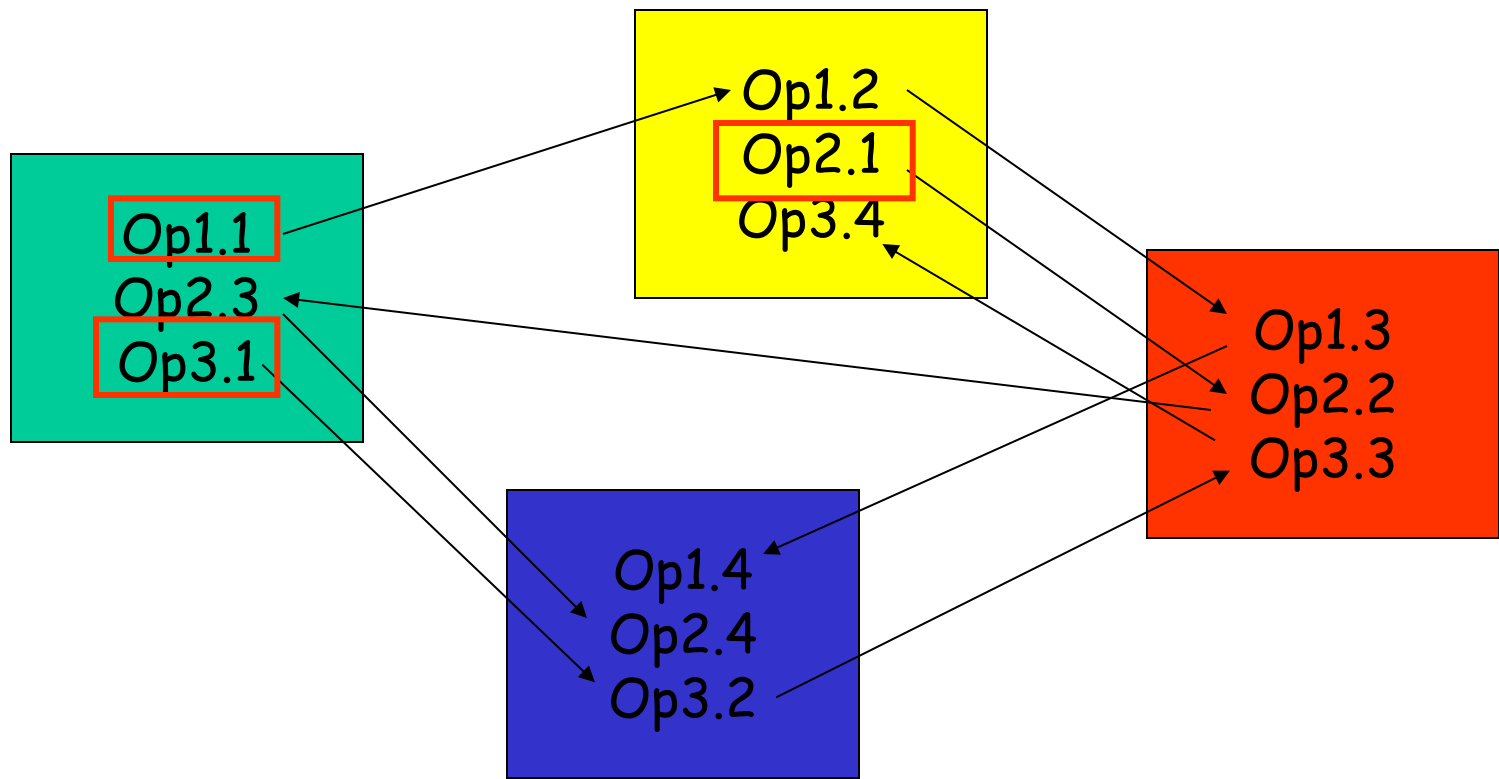
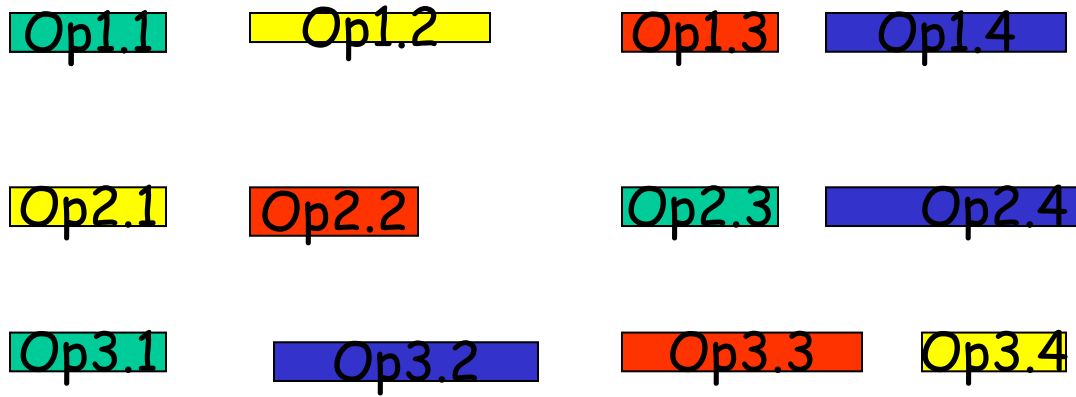
- a set of resources
- a set of jobs
 - a job is a sequence of operations/activities
- sequence the activities on the resources

An example: 3 x 4



- We have 4 resources: green, yellow, red and blue
- a job is a sequence of operations (precedence constraints)
- each operation is executed on a resource (resource constraints)
- each resource can do one operation at a time
- the duration of an operation is the length of its box
- we have a due date, giving time windows for operations (time constraints)

An example: 3 x 4



Assign a start time to each operation such that

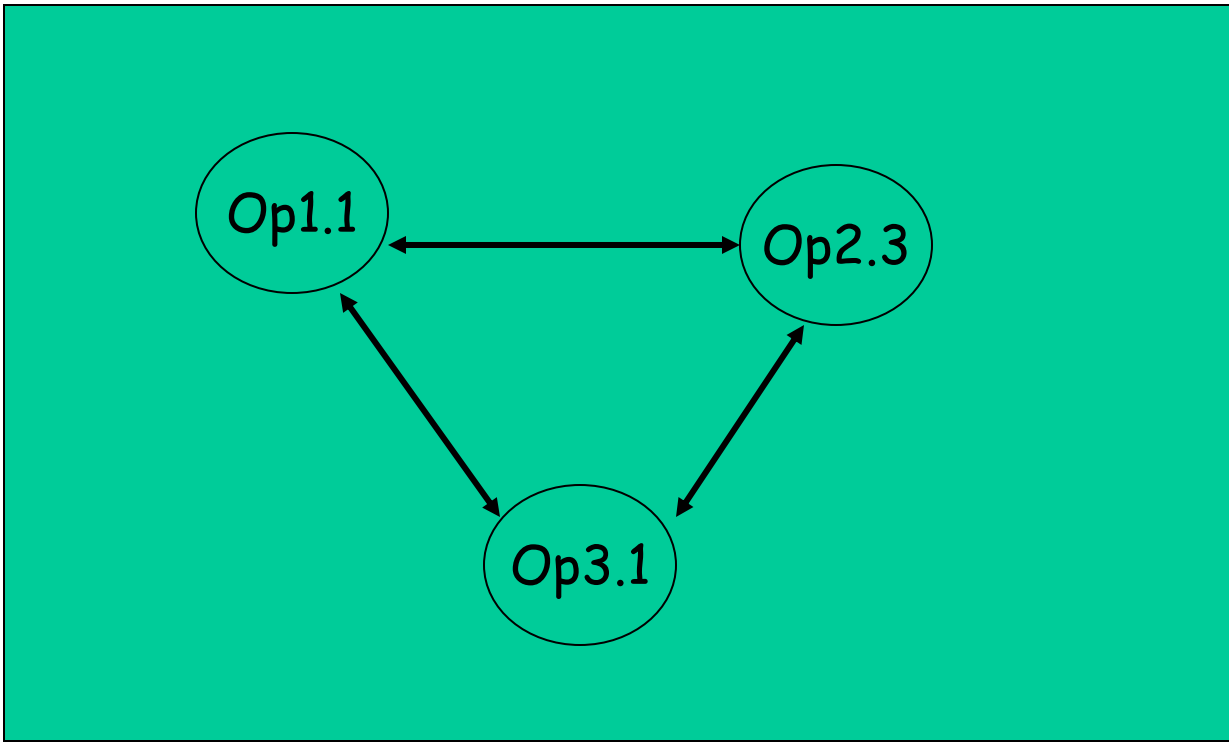
- (a) no two operations are in process on the same machine at the same time and
- (b) time constraints are respected

An example: 3 x 4

Op1.1 Op1.2 Op1.3 Op1.4

Op2.1 Op2.2 Op2.3 Op2.4

Op3.1 Op3.2 Op3.3 Op3.4



On the "green" resource, put a *direction* on the arrows

A disjunctive graph

An example: 3 x 4

Op1.1 Op1.2 Op1.3 Op1.4

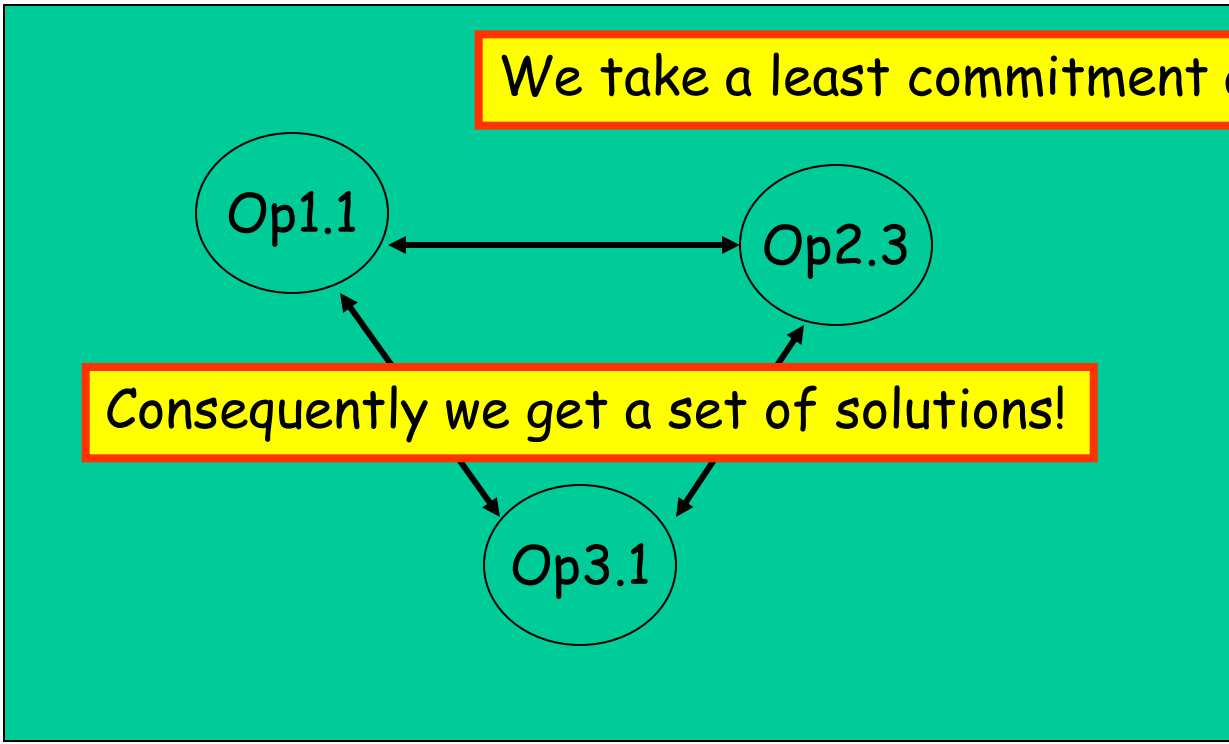
Op2.1 Op2.2 Op2.3 Op2.4

We do not bind operations to start times

Op3.1 Op3.2 Op3.3 Op3.4

We take a least commitment approach

Consequently we get a set of solutions!



On the "green" resource, put a *direction* on the arrows

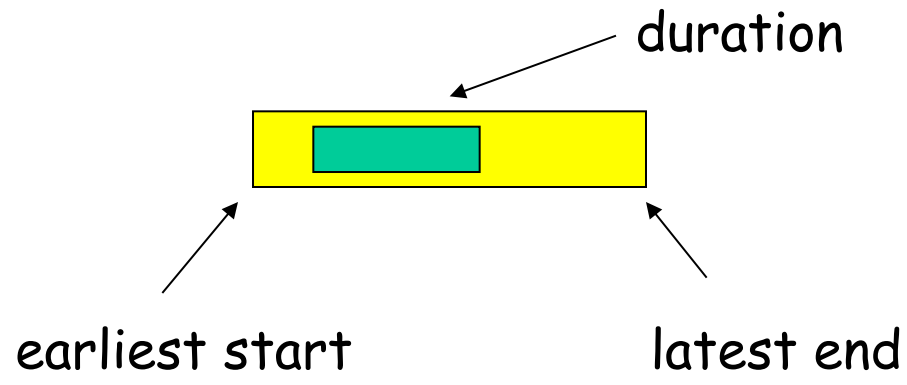
A disjunctive graph

```
Constraint before(Operation op2){  
    return model.arithm(op2.start, ">=", start, "+", duration);  
}
```

op1.before(op2)

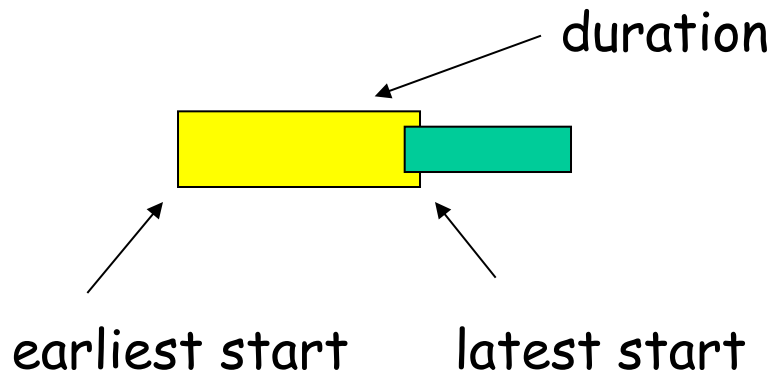
Picture of an operation

op1.before(op2)



Picture of an operation

op1.before(op2)



Constrained integer variable represents start time

Picture of an operation

op1.before(op2)



op1



op2

$$\text{op1.before(op2)} \longrightarrow \text{op1.start()} + \text{op1.duration()} \leq \text{op2.start()}$$

Picture of an operation

op1.before(op2)



op1

propagate

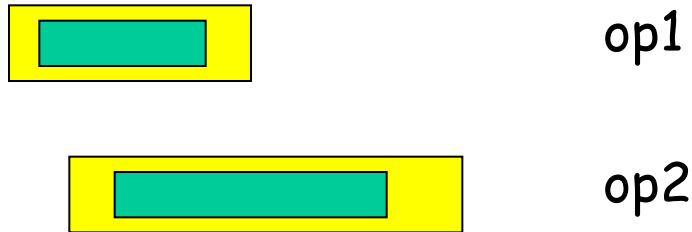


op2

$$\text{op1.before(op2)} \longrightarrow \text{op1.start()} + \text{op1.duration()} \leq \text{op2.start()}$$

Picture of an operation

op1.before(op2)



op1 and op2 cannot be in process at same time

→ op1.before(op2) **OR** op2.before(op1)

Not easy to propagate until
decision made (disjunction broken)

Picture of an operation

op1.before(op2)



op1



op2

Use a 0/1 decision variable $d[i][j]$ as follows

$d[i][j] = 0 \rightarrow \text{op}[i].\text{before}(\text{op}[j])$

$d[i][j] = 1 \rightarrow \text{op}[j].\text{before}(\text{op}[i])$

heuristics

JUST ONE EXAMPLE



Stephen F. Smith

Research Professor, Robotics
Director, [Intelligent Coordination and Logistics Laboratory](#)

[The Robotics Institute](#)
[Carnegie Mellon University](#)
5000 Forbes Avenue, Pittsburgh, PA 15213

Email: sfs@cs.cmu.edu, Phone: (412) 268-8811, Fax: (412) 268-5569
Office: 1502E Newell & Simon Hall

[HOME](#) [INFORMATION](#) [PERSONNEL](#) [PROJECTS](#) [PUBLICATIONS](#) [CONTACT](#)[HOME](#)

INTELLIGENT COORDINATION & LOGISTICS LABORATORY

Stephen F. Smith, Director



Problems of large-scale coordination and logistics are ubiquitous, and better solutions are becoming increasingly critical in many domains. In manufacturing, trends toward industrial globalization and constrained market focus on high value-adding products, together with new coordination concepts such as electronic marketplaces, require organizations to become more agile. Military command and control infrastructure is faced with shrinking budgets and personnel, even though current geopolitical realities demand improved capability for rapid crisis-action mission planning and deployment. The rising cost of health care places a premium on more efficient methods for administration and delivery.

smith-cheng-slack-aaai93.pdf (SECURED) - Adobe Reader

File Edit View Document Tools Window Help

1 / 6 97% Find

From: AAAI-93 Proceedings. Copyright © 1993, AAAI (www.aaai.org). All rights reserved.

Slack-Based Heuristics For Constraint Satisfaction Scheduling *

Stephen F. Smith
The Robotics Institute
Carnegie Mellon University
Pittsburgh, PA 15213
sfs@isl1.ri.cmu.edu

Cheng-Chung Cheng
The Robotics Institute
Carnegie Mellon University
Pittsburgh, PA 15213
ccen@isl1.ri.cmu.edu

Abstract

In this paper, we define and empirically evaluate new heuristics for solving the job shop scheduling problem with non-relaxable time windows. The hypothesis underlying our approach is that by approaching the problem as one of establishing sequencing constraints between pairs of operations requiring the same resource (as opposed to a problem of assigning start times to each operation) and by exploiting previously developed analysis techniques for limiting search through the space of possible sequencing decisions, simple, localized look-ahead techniques can yield problem solving performance comparable to currently dominating techniques that rely on more sophisticated analysis of resource contention. We define a series of attention focusing heuristics based on simple analysis of the temporal flexibility associated with different sequencing decisions, and a similarly motivated heuristic for determining how to reserve

exclusive use of a designated machine for the duration of its processing (i.e. machines have unit processing capacity). Each job has an associated ready time and a deadline, and its production must be accomplished within this interval. The problem can be extended in various ways - to include selection among designated resource alternatives for each operation, to associate multiple resource requirements (e.g. machine, operator) with operations, etc. In any case, the objective is to determine a schedule for production that satisfies all temporal and resource capacity constraints.

The job shop scheduling with non-relaxable time windows problem is known to be NP-Complete (Garey & Johnson 1979). Accordingly, the development of effective heuristic procedures for solving this constraint satisfaction problem (CSP) has been the subject of considerable previous research. This work, with few exceptions, has sought to exploit the special structure of the problem, in particular the structure of resource capacity constraints, to enhance consistency enforce-

straints. The solutions generated in this way typically represent a set of feasible schedules (i.e., the sets of operation start times that remain consistent with posted sequencing constraints), as opposed to a single assignment of operation start times. In (Erschler et al. 1976, 1980) the structure of resource capacity constraints is exploited to define dominance conditions for pruning the set of feasible sequencing alternatives at each stage of the search. More recently, (Muscuttola 1993) has demonstrated the utility of global resource capacity analysis techniques (similar in spirit to the approach in (Sadeh 1991)) as a focusing mechanism within this alternative search space; in this case sequencing constraints are repeatedly posted between sets of conflicting operations until resource capacity analysis indicates no further possibility of resource contention.

Like (Muscuttola 1993), we believe that the inherent flexibility gained by providing sets of feasible solutions offers considerable pragmatic value over typically over-constrained fixed times solutions. The principal claim of this paper, however, is that this second formulation of the problem also provides a more convenient search space in which to operate. When the problem is cast as a search for orderings between pairs of operations vying for the same resource, we argue that it is possible to obtain the look-ahead benefits of global resource capacity analysis through the use of simpler, local analysis of the sequencing possibilities associated with unordered operation pairs. We define a series of variable ordering heuristics based on measures of temporal slack which, when integrated with the search space pruning techniques developed in (Erschler et al. 1976), are shown to yield comparable problem solving performance to contention-based heuristics at a fraction of the compu-

- **resource capacity constraints** - for any two operations i and j requiring the same resource, $st_i + p_i \leq st_j \vee st_j + p_j \leq st_i$
- **ready times and deadlines** - for each operation i of job \mathcal{J} , $r_{\mathcal{J}} \leq st_i$ and $st_i + p_i \leq d_{\mathcal{J}}$, where $r_{\mathcal{J}}$ and $d_{\mathcal{J}}$ are the ready time and deadline respectively associated with job \mathcal{J} .

While this problem representation provides a direct basis for problem solving search (and in fact has been taken as the starting point of most previous research), the problem can be alternatively formulated as one of establishing sequencing constraints between pairs of operations contending for the same resource over time. In this case, we define a decision variable $ordering_{i,j}$ for each pair of operations i and j that require the same resource, which can take on either of two values: $i \rightarrow j$ (implying the constraint $st_i + p_i \leq st_j$) and $j \rightarrow i$ (implying $st_j + p_j \leq st_i$). A solution then is a consistent assignment of values to all ordering variables. There are several potential advantages to this formulation. The advantage emphasized in this paper is that the simpler structure of the search space enables more straightforward accounting of resource capacity constraints and the use of simpler, localized analysis of current solution structure as a basis for variable and value ordering.

Our problem solving framework assumes a backtrack search procedure in which the solution is incrementally extended through the repeated selection and binding of an as yet unconstrained $ordering_{i,j}$ variable (referred to as the posting of a new precedence relation). Whenever a new precedence relation is posted, constraint propagation is performed to ensure continued temporal consistency and maintain current bound

straints. The solutions generated in this way typically represent a set of feasible schedules (i.e., the sets of operation start times that remain consistent with posted sequencing constraints), as opposed to a single assignment of operation start times. In (Erschler et al. 1976, 1980) the structure of resource capacity constraints is exploited to define dominance conditions for pruning the set of feasible sequencing alternatives at each stage of the search. More recently, (Muscuttola 1993) has demonstrated the utility of global resource capacity analysis techniques (similar in spirit to the approach in (Sadeh 1991)) as a focusing mechanism within this alternative search space; in this case sequencing constraints are repeatedly posted between sets of conflicting operations until resource capacity analysis indicates no further possibility of resource contention.

Like (Muscuttola 1993), we believe that the inherent flexibility gained by providing sets of feasible solutions offers considerable pragmatic value over typically over-constrained fixed times solutions. The principal claim of this paper, however, is that this second formulation of the problem also provides a more convenient search space in which to operate. When the problem is cast as a search for orderings between pairs of operations vying for the same resource, we argue that it is possible to obtain the look-ahead benefits of global resource capacity analysis through the use of simpler, local analysis of the sequencing possibilities associated with unordered operation pairs. We define a series of variable ordering heuristics based on measures of temporal slack which, when integrated with the search space pruning techniques developed in (Erschler et al. 1976), are shown to yield comparable problem solving performance to contention-based heuristics at a fraction of the computational cost.

- **resource capacity constraints** - for any two operations i and j requiring the same resource, $st_i + p_i \leq st_j \vee st_j + p_j \leq st_i$
- **ready times and deadlines** - for each operation i of job \mathcal{J} , $r_{\mathcal{J}} \leq st_i$ and $st_i + p_i \leq d_{\mathcal{J}}$, where $r_{\mathcal{J}}$ and $d_{\mathcal{J}}$ are the ready time and deadline respectively associated with job \mathcal{J} .

While this problem representation provides a direct basis for problem solving search (and in fact has been taken as the starting point of most previous research), the problem can be alternatively formulated as one of establishing sequencing constraints between pairs of operations contending for the same resource over time.

In this case, we define a decision variable $ordering_{i,j}$ for each pair of operations i and j that require the same resource, which can take on either of two values: $i \rightarrow j$ (implying the constraint $st_i + p_i \leq st_j$) and $j \rightarrow i$ (implying $st_j + p_j \leq st_i$). A solution then is a consistent assignment of values to all ordering variables. There are several potential advantages to this formulation. The advantage emphasized in this paper is that the simpler structure of the search space enables more straightforward accounting of resource capacity constraints and the use of simpler, localized analysis of current solution structure as a basis for variable and value ordering.

Our problem solving framework assumes a backtrack search procedure in which the solution is incrementally extended through the repeated selection and binding of an as yet unconstrained $ordering_{i,j}$ variable (referred to as the posting of a new precedence relation). Whenever a new precedence relation is posted, constraint propagation is performed to ensure continued temporal consistency and maintain current bound values.

of the problem also provides a more convenient search space in which to operate. When the problem is cast as a search for orderings between pairs of operations vying for the same resource, we argue that it is possible to obtain the look-ahead benefits of global resource capacity analysis through the use of simpler, local analysis of the sequencing possibilities associated with unordered operation pairs. We define a series of variable ordering heuristics based on measures of temporal slack which, when integrated with the search space pruning techniques developed in (Erschler et al. 1976), are shown to yield comparable problem solving performance to contention-based heuristics at a fraction of the computational cost.

The remainder of the paper is organized as follows. In Section 2, we specify the problem as a CSP search for operation pair orderings, and review dominance conditions that enable search space pruning relative to this model. In Sections 3 through 5, we propose a series of variable ordering heuristics and present comparative results on a previously studied suite of 60 test problems. Finally, in Section 6, we outline current work in applying the approach to schedule optimization.

Problem Representation and Search Framework

In more precise terms, a solution to the basic job shop scheduling CSP requires a consistent assignment of values to start time variables st_i for each operation i , under the following constraints:

- **sequencing restrictions** - for every precedence relation $i \rightarrow j$ specified between operations i and j in the process plan of a given job \mathcal{J} , $st_i + p_i \leq st_j$, where p_i is the processing time required by operation i of job \mathcal{J} .

formulation. The advantage emphasized in this paper is that the simpler structure of the search space enables more straightforward accounting of resource capacity constraints and the use of simpler, localized analysis of current solution structure as a basis for variable and value ordering.

Our problem solving framework assumes a backtrack search procedure in which the solution is incrementally extended through the repeated selection and binding of an as yet unconstrained $ordering_{i,j}$ variable (referred to as the posting of a new precedence relation). Whenever a new precedence relation is posted, constraint propagation is performed to ensure continued temporal consistency and maintain current bounds on the earliest start time and latest finish time of each operation.¹ If the decision $i \rightarrow j$ is taken, for example, then est_j (the earliest start time of j) and lft_i (the latest finish time of i) are updated by

$$est_j = \max\{est_j, est_i + p_i\}, \text{ and} \quad (1)$$

$$lft_i = \min\{lft_i, lft_j - p_j\}, \quad (2)$$

and these new values are then propagated forward or backward respectively through all pre-specified and posted temporal precedence relations. If during this process, $est_k + p_k$ becomes greater than lft_k for any operation k then an inconsistent set of assignments has been detected.

As indicated at the outset, our approach to directing the search integrates a procedure previously developed by Erschler *et al.*, referred to as *Constraint-based Analysis (CBA)*, which exploits dominance conditions to prune the space of possible ordering assignments. To summarize their basic idea, assume that est_i and lft_i

¹Since we are assuming in this paper that operation processing times are fixed, we could equivalently reason in terms of earliest and latest start times.

different cases:

1. If $lft_i - est_j < p_i + p_j \leq lft_j - est_i$ then i must be scheduled before j in any feasible extension of the current ordering decisions. (case 1)
2. If $lft_j - est_i < p_i + p_j \leq lft_i - est_j$ then j must be scheduled before i in any feasible extension of the current ordering decisions. (case 2)
3. If $p_i + p_j > lft_j - est_i$ and $p_i + p_j > lft_i - est_j$ then there is no feasible schedule. (case 3)
4. If $p_i + p_j \leq lft_j - est_i$ and $p_i + p_j \leq lft_i - est_j$ then either sequencing decision is still possible. (case 4)

These dominance conditions of course provide only necessary conditions for determining a set of feasible schedules, and thus interleaved application of CBA and temporal constraint propagation yields an underspecified search procedure. What is needed to generate solutions are heuristics for resolving the undecided states specified in case 4. In this regard, previous use of CBA has emphasized fuzzy integration of sets of different scheduling rules. In (Bensana & Dubois 1988), a voting procedure based on fuzzy set theory and approximate reasoning was developed and used in conjunction with a set of fuzzy scheduling rules. In (Kerr & Walker 1989), fuzzy arithmetic together with fuzzy scheduling rules was utilized instead. Our goal, alternatively, is to investigate the effectiveness of CBA in conjunction with simple look-ahead analysis of current ordering flexibility. This leads to the search procedure that is graphically depicted in Figure 1, which we will refer to as precedence constraint posting (PCP). In the following sections, we define and evaluate a specific set of variable and value ordering heuristics.

Exploiting Estimates of Sequencing Flexibility

Initially, in situations where CBA leaves the search

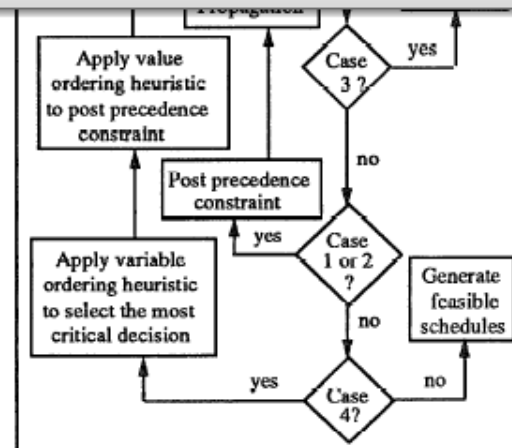


Figure 1: PCP Search Procedure

we define two measures, corresponding to the two possible decisions that might be taken. For a given pair of currently unordered operations (i, j) contending for the same resource, we define the “temporal slack remaining after sequencing i before j ” as

$$slack(i \rightarrow j) = lft_j - est_i - (p_i + p_j), \quad (3)$$

and similarly the “temporal slack remaining after sequencing j before i ” as

$$slack(j \rightarrow i) = lft_i - est_j - (p_i + p_j). \quad (4)$$

Figure 2 provides a graphic illustration of $slack(i \rightarrow j)$ and $slack(j \rightarrow i)$. Note that in either case the remaining slack is shared by both i and j . Thus, the larger the temporal slack, the greater the chance that subsequent ordering decisions involving i and j can be feasibly imposed.

Given these measures of temporal slack, we now have a basis for identifying the most constrained or “most critical” decision and for specifying an initial variable ordering heuristic. We define the ordering decision

different cases:

1. If $lft_i - est_j < p_i + p_j \leq lft_j - est_i$ then i must be scheduled before j in any feasible extension of the current ordering decisions. (case 1)
2. If $lft_j - est_i < p_i + p_j \leq lft_i - est_j$ then j must be scheduled before i in any feasible extension of the current ordering decisions. (case 2)
3. If $p_i + p_j > lft_j - est_i$ and $p_i + p_j > lft_i - est_j$ then there is no feasible schedule. (case 3)
4. If $p_i + p_j \leq lft_j - est_i$ and $p_i + p_j \leq lft_i - est_j$ then either sequencing decision is still possible. (case 4)

These dominance conditions of course provide only necessary conditions for determining a set of feasible schedules, and thus interleaved application of CBA and temporal constraint propagation yields an underspecified search procedure. What is needed to generate solutions are heuristics for resolving the undecided states specified in case 4. In this regard, previous use of CBA has emphasized fuzzy integration of sets of different scheduling rules. In (Bensana & Dubois 1988), a voting procedure based on fuzzy set theory and approximate reasoning was developed and used in conjunction with a set of fuzzy scheduling rules. In (Kerr & Walker 1989), fuzzy arithmetic together with fuzzy scheduling rules was utilized instead. Our goal, alternatively, is to investigate the effectiveness of CBA in conjunction with simple look-ahead analysis of current ordering flexibility. This leads to the search procedure that is graphically depicted in Figure 1, which we will refer to as precedence constraint posting (PCP). In the following sections, we define and evaluate a specific set of variable and value ordering heuristics.

Exploiting Estimates of Sequencing Flexibility

Initially, in situations where CBA leaves the search

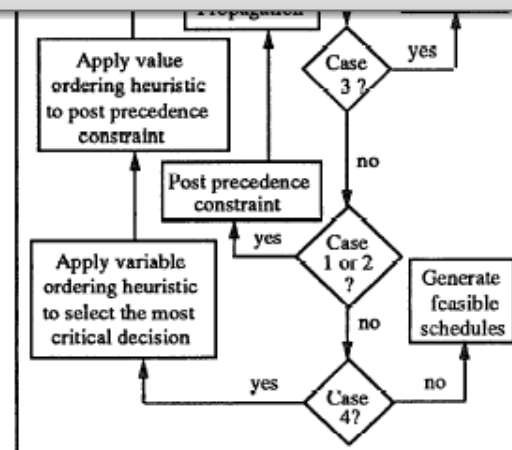


Figure 1: PCP Search Procedure

we define two measures, corresponding to the two possible decisions that might be taken. For a given pair of currently unordered operations (i, j) contending for the same resource, we define the “temporal slack remaining after sequencing i before j ” as

$$slack(i \rightarrow j) = lft_j - est_i - (p_i + p_j), \quad (3)$$

and similarly the “temporal slack remaining after sequencing j before i ” as

$$slack(j \rightarrow i) = lft_i - est_j - (p_i + p_j). \quad (4)$$

Figure 2 provides a graphic illustration of $slack(i \rightarrow j)$ and $slack(j \rightarrow i)$. Note that in either case the remaining slack is shared by both i and j . Thus, the larger the temporal slack, the greater the chance that subsequent ordering decisions involving i and j can be feasibly imposed.

Given these measures of temporal slack, we now have a basis for identifying the most constrained or “most critical” decision and for specifying an initial variable ordering heuristic. We define the ordering decision

scheduling rules was utilized instead. Our goal, alternatively, is to investigate the effectiveness of CBA in conjunction with simple look-ahead analysis of current ordering flexibility. This leads to the search procedure that is graphically depicted in Figure 1, which we will refer to as precedence constraint posting (PCP). In the following sections, we define and evaluate a specific set of variable and value ordering heuristics.

Exploiting Estimates of Sequencing Flexibility

Intuitively, in situations where CBA leaves the search in a state with several unresolved ordering assignments (i.e., for each unordered operation pair, both ordering decisions are still feasible), we would like to focus attention on the ordering decision that is currently most constrained. Since the posting of any sequence constraint is likely to further constrain other ordering decisions that remain to be made, delaying the currently most constrained decision increases the chances of arriving at an infeasible problem solving state.

Implementation of such a variable ordering strategy requires a means of estimating the current flexibility associated with a given unresolved ordering decision. One simple indicator of flexibility is the amount of temporal slack that is retained by a given operation pair if a decision to sequence them is taken. To this end,

sequencing j before i as

$$\text{slack}(j \rightarrow i) = \text{lft}_i - \text{est}_j - (p_i + p_j). \quad (4)$$

Figure 2 provides a graphic illustration of $\text{slack}(i \rightarrow j)$ and $\text{slack}(j \rightarrow i)$. Note that in either case the remaining slack is shared by both i and j . Thus, the larger the temporal slack, the greater the chance that subsequent ordering decisions involving i and j can be feasibly imposed.

Given these measures of temporal slack, we now have a basis for identifying the most constrained or “most critical” decision and for specifying an initial variable ordering heuristic. We define the ordering decision with the **overall minimum slack**, to be the decision $\text{ordering}_{i,j}$ for which

$$\min\{\text{slack}(i \rightarrow j), \text{slack}(j \rightarrow i)\} = \min_{(u,v)}\{\min\{\text{slack}(u \rightarrow v), \text{slack}(v \rightarrow u)\}\}$$

for all unassigned $\text{ordering}_{u,v}$. Using this notion of criticality, we define a variable ordering heuristic that selects this decision at each unresolved state of the search.

With respect to the decision of which sequencing constraint to post (i.e., value assignment), we intuitively prefer the decision that leaves the search with the most degrees of freedom. Thus we post the sequencing constraint that retains the largest amount of temporal slack.

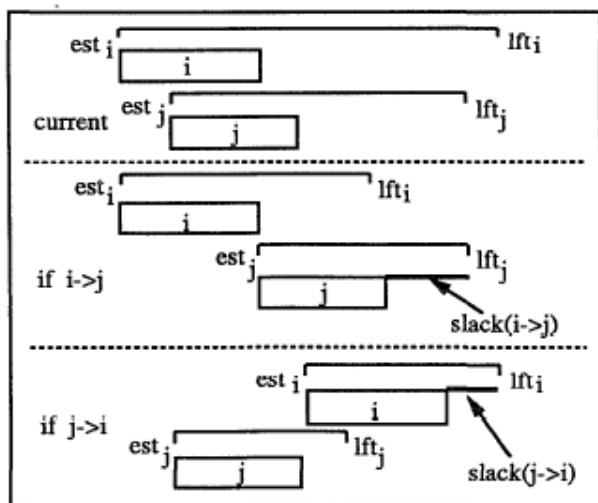


Figure 2: Slack($i \rightarrow j$) and Slack($j \rightarrow i$)

Summarizing then, our initial configuration of variable and value ordering heuristics is defined as follows:

- I. **Min-Slack** variable ordering: Select the sequencing decision with the overall minimum temporal slack. Suppose this decision is $ordering_{i,j}$.
- II. **Max-Slack** value ordering: choose the sequencing constraint $i \rightarrow j$ if $slack(i \rightarrow j) > slack(j \rightarrow i)$; otherwise choose $j \rightarrow i$.

A Computational Study

In this section we evaluate the performance of the above heuristics in conjunction with the PCP search

tion). Both ORR/FSS and CPS have reported very strong results on the set of scheduling problems used in this study.

As an additional point of comparison, we also include results obtained with three priority dispatch rules from the field of Operations Research: EDD, COVERT, and ATC (Vepsalainen & Morton 1987). These heuristics are frequently used and have been determined to work very well in job shop scheduling circumstances where expected job tardiness is low (as would likely be the case if a feasible solution exists).

The set of problems used in this study come from the dissertation of Sadeh (Sadeh 1991). The problem set consists of 60 randomly generated scheduling problems. Each problem contains 10 jobs and 5 resources. Each job has 5 operations. In all problems, deadlines were generated randomly within a specified range. A controlling parameter was used to generate problems in three different deadline ranges: wide (w), median (m), and tight (t). A second parameter was used to generate problems with both 1 and 2 “bottleneck” resources. Combining these two parameters, 6 different categories of scheduling problems were defined, and 10 problems were generated for each category. The problem categories were carefully defined to cover a variety of manufacturing scheduling circumstances. While each problem has at least one feasible solution, they range in difficulty from easy to hard.

The results obtained on these problems, along with those previously reported, are given in Table 1 (where problem difficulty increases from top to bottom). The number of problems solved by each approach by problem category are indicated. In the case of ORR/FSS

Incorporating Additional Search Bias

While **Min-Slack** performed quite well over the tested problem set, it does not in fact utilize all of the information provided by the temporal slack data. In particular, it relies exclusively on the smaller slack value in determining the criticality of an ordering decision $ordering_{i,j}$, and ignores any information that might be provided by the larger one.

The most common problem created by disregarding this additional value appears in a form of tie-breaking. Consider the following example. Suppose that we have two unsequenced operation pairs, one with associated temporal slack values of (20, 3), and the other with values of (4, 3). **Min-Slack** does not distinguish between the criticality of these two ordering decisions, since the minimum value in both cases is 3. In the event that the overall minimum slack over all candidate decisions is also 3, then **Min-Slack** will choose randomly. But, in this case sequencing the second operation pair is certainly more critical since the flexibility that will be left after the decision is made will be considerably less than the flexibility that will remain if the first unsequenced operation pair is instead chosen and sequenced.

Given this insight, we define a second variable ordering heuristic, which operates exactly as **Min-Slack** except in situations where more than one pending decision $ordering_{i,j}$ is identified as a decision with overall minimum temporal slack. In these situations, ties are broken by selecting the decision with the minimum larger temporal slack value. Applying the PCP procedure with this extended heuristic to the same suite of 60 problems yielded 57 solved problems. Although this

²All computation times were obtained on a Decstation 5000. Both ORR/FSS and CPS are Lisp-based systems; our procedure is implemented in C.

ues increases and decrease criticality as the slack values become more dissimilar might provide more effective search guidance.

Let us define a measure of similarity in the range [0, 1] such that for slack value pairs with identical values, the similarity value is 1 and as the distance between large and small slack values increases, the similarity value approaches 0. More precisely, we estimate the similarity between two slack values by the following ratio expression:

$$S = \frac{\min\{\text{slack}(i \rightarrow j), \text{slack}(j \rightarrow i)\}}{\max\{\text{slack}(i \rightarrow j), \text{slack}(j \rightarrow i)\}} \quad (5)$$

Given the definition of S and the direction of bias desired, we now define a new criticality metric, referred to as biased temporal slack, as follows:

$$Bslack(i \rightarrow j) = \frac{\text{slack}(i \rightarrow j)}{f(S)}, \quad (6)$$

where f is a monotonically increasing function.

With little intuition as to the appropriate level of bias to exert on the criticality calculation, but assuming that the level of bias should not be too great, we use $\sqrt[n]{S}$, $n \geq 2$, to define a set of alternatives, yielding

$$Bslack(i \rightarrow j) = \frac{\text{slack}(i \rightarrow j)}{\sqrt[n]{S}}. \quad (7)$$

By empirical reasoning, we also define a composite form of the metric with two different parameters, n_1 and n_2 , as

$$Bslack(i \rightarrow j) = \frac{\text{slack}(i \rightarrow j)}{\sqrt[n_1]{S}} + \frac{\text{slack}(i \rightarrow j)}{\sqrt[n_2]{S}}. \quad (8)$$

Table 2 presents results obtained using overall minimum **Bslack** as a variable ordering criterion for different values of n in Eqn. (7) and n_1 and n_2 in Eqn. (8)

```

//
// Slack-Based Heuristics for Constraint Satisfaction Scheduling
// Stephen F. Smith and Cheng-Chung Cheng
// Proceedings AAAI-93
//

```

```

import org.chocosolver.solver.variables.IntVar;
import org.chocosolver.solver.search.strategy.selectors.variables.VariableSelector;

```

```

public class MinSlackHeuristic implements VariableSelector<IntVar> {

```

```

    @Override

```

```

    public IntVar getVariable(IntVar[] vars){

```

```

        int minSlack = Integer.MAX_VALUE;

```

```

        IntVar minSlackVar = null;

```

```

        for (IntVar v : vars)

```

```

            if (!v.isInstantiated()){

```

```

                int slack = slack((Decision) v);

```

```

                if (slack < minSlack){minSlackVar = v; minSlack = slack;}

```

```

            }

```

```

        return minSlackVar;

```

```

    }

```

```

//
// select the uninstantiated variable with minimum maximum slack
//

```

```

private int slack(IntVar op_i,int d_i,IntVar op_j,int d_j){
    return op_j.getUB() - Math.max(op_i.getLB() + d_i,op_j.getLB());
}

```

```

//

```

```

// slack if op_i before op_j

```

```

// i.e. slack(op_i -> op_j) in S&C AAAI-93 parlance

```

```

//

```

```

// NOTE: we consider earliest and latest start times whereas S&C

```

```

// consider earliest start and latest finish, but our calculations

```

```

// are exactly the same

```

```

//

```

```

private int slack(Decision v){

```

```

    return Math.max(slack(v.op_i.start,v.op_i.duration,v.op_j.start,v.op_j.duration),
                    slack(v.op_j.start,v.op_j.duration,v.op_i.start,v.op_i.duration));
}

```

```

//

```

```

// get slack of ith decision variable, to be the largest slack

```

```

// from either slack(op1 -> op2) or slack(op2 -> op1)

```

```

// This differs from Smith & Cheng as they select the smaller of the two,

```

```

// i.e. replace Math.max with Math.min

```

```

//

```

```

}

```

```
// Slack-Based Heuristics for Constraint Satisfaction Scheduling
// Stephen F. Smith and Cheng-Chung Cheng
// Proceedings AAI-93
//
import org.chocosolver.solver.variables.IntVar;
import org.chocosolver.solver.search.strategy.selectors.values.IntValueSelector;

public class MaxSlackValue implements IntValueSelector {

    @Override
    public int selectValue(IntVar v){
        Decision dec = (Decision) v;
        int slack_0 = slack(dec.op_i.start,dec.op_i.duration,dec.op_j.start,dec.op_j.duration);
        int slack_1 = slack(dec.op_j.start,dec.op_j.duration,dec.op_i.start,dec.op_i.duration);
        if (slack_0 > slack_1) return 0; else return 1;
    }
    //
    // decision = 0 -> op_i before op_j
    // decision = 1 -> op_j before op_i
    //
    private int slack(IntVar op_i,int d_i,IntVar op_j,int d_j){
        return op_j.getUB() - Math.max(op_i.getLB() + d_i,op_j.getLB());
    }
    //
    // slack if op_i before op_j
    // i.e. slack(op_i -> op_j) in S&C AAI-93 parlance
    //
    // NOTE: we consider earliest and latest start times whereas S&C
    // consider earliest start and latest finish, but our calculations
    // are exactly the same
    //
}
```

```
public class Optimize {
```

```
    public static void main(String[] args) throws ContradictionException, FileNotFoundException, IOException {
        JSSP jssp          = new JSSP(args[0],9999);
        String valueHeuristic = args[1];
        int timeLimit      = Integer.parseInt(args[2]);
        Model model        = jssp.getModel();
        Solver solver       = model.getSolver();
        Decision[] decisions = jssp.getDecisions();
        IntVar makeSpan    = jssp.getMakeSpan();
        int lwb            = 0;
        int upb            = 9999;

        solver.limitTime(timeLimit*1000);

        if (valueHeuristic.equals("maxslack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new MaxSlackValue()));
        else if (valueHeuristic.equals("fuzzyMaxSlack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new FuzzyMaxSlackValue(0.5)));
        else if (valueHeuristic.equals("minslack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new MinSlackValue()));
        else if (valueHeuristic.equals("fuzzyMinSlack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new FuzzyMinSlackValue(0.5)));
        else if (valueHeuristic.equals("random"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new FuzzyMaxSlackValue(-1.0)));
        else solver.setSearch(Search.inputOrderLBSearch(jssp.getDecisions()));
        //
        // attach a variable & value ordering heuristic to solver
        //

        model.setObjective(Model.MINIMIZE,makeSpan);
        while (solver.solve()){
            lwb = makeSpan.getLB();
            upb = makeSpan.getUB();
        }
        System.out.println("makespan: ["+ lwb +", "+ upb +"]");
        System.out.println("nodes: "+ solver.getMeasures().getNodeCount() +
                           " cpu: "+ solver.getMeasures().getTimeCount());
    }
}
```


Anyway, will the variable ordering heuristic make a difference on it's own? Admittedly the heuristic is rather expensive to run so will it reduce search effort to the point that it reduces run time (the bottom line)

Do some experiments

```

public class Restart {
    public static void main(String[] args) throws ContradictionException, FileNotFoundException, IOException {
        JSSP jssp          = new JSSP(args[0],9999);
        String valueHeuristic = args[1];
        int timeLimit      = Integer.parseInt(args[2]);
        Model model        = jssp.model;
        Solver solver      = model.getSolver();
        Decision[] decisions = jssp.getDecisions();
        IntVar makeSpan    = jssp.getMakeSpan();
        int lwb            = 0;
        int upb            = 9999;

        solver.limitTime(timeLimit*1000);

        if (valueHeuristic.equals("maxslack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new MaxSlackValue()));
        else if (valueHeuristic.equals("fuzzyMaxSlack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new FuzzyMaxSlackValue(0.5)));
        else if (valueHeuristic.equals("minslack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new MinSlackValue()));
        else if (valueHeuristic.equals("fuzzyMinSlack"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new FuzzyMinSlackValue(0.5)));
        else if (valueHeuristic.equals("random"))
            solver.setSearch(new IntStrategy(jssp.getDecisions(),
                                             new MinSlackHeuristic(),
                                             new FuzzyMaxSlackValue(-1.0)));
        else solver.setSearch(Search.inputOrderLBSearch(jssp.getDecisions()));
        //
        // attach a variable & value ordering heuristic to solver
        //

        solver.setLubyRestart(2,new NodeCounter(model,Long.MAX_VALUE),Integer.MAX_VALUE);
        model.setObjective(Model.MINIMIZE,makeSpan);
        while (solver.solve()){
            lwb = makeSpan.getLB();
            upb = makeSpan.getUB();
            //System.out.println(lwb + " " + upb + " " + solver.getMeasures().getNodeCount());
        }
        System.out.println("makespan: ["+ lwb +", "+ upb +"]");
        System.out.println("nodes: " + solver.getMeasures().getNodeCount() +
                           " cpu: " + solver.getMeasures().getTimeCount());
    }
}

```

Luby Restart

restarts, small amounts of randomness, nogood recording, watched literals

Mail

Calendar

Contacts

Deleted Items

Drafts [365]

Inbox (127)

Junk E-mail [2]

Sent Items

[Click to view all folders](#)

- EPSRC
- KA
- MSc
- Machrihanish (5)**
- abarth
- advisees (12)**
- ex01 (1)**
- expenses
- fata (1)**
- miniZinc (2)**

[Manage Folders...](#)

Reply Reply All Forward X Junk Close

[FATA] Seminar reminder - 20th February - Ciaran McCreesh - Subgraph Isomorphism in Practice

fata [fata-bounces@mr1.dcs.gla.ac.uk] on behalf of Jessica Ryan [2338839R@student.gla.ac.uk]

Sent: Monday, February 19, 2018 12:09 PM
To: fata@mr1.dcs.gla.ac.uk [fata@dcs.gla.ac.uk]
Attachments: ATT00001.txt (201 B)

A reminder of this week's FATA seminar and post-seminar coffee in the common room.

Date/Time: 20th Feb, 13:00-14:00
Location: SAWB 422
Speaker: Ciaran McCreesh, University of Glasgow

Title: Subgraph Isomorphism in Practice.

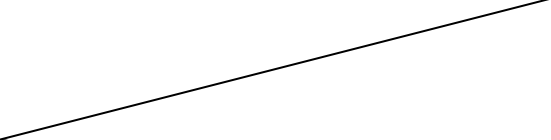
Abstract:
The subgraph isomorphism problem is to find a little "pattern" graph inside a larger "target" graph. Despite being NP-complete, practical algorithms can often solve instances with graphs involving many thousands of vertices. I'll give an overview of the state of the art in subgraph isomorphism solving, with a particular focus on search strategies. I'll then explain some recent work we've carried out on moving away from simple backtracking search and on introducing small amounts of randomness. This can be hugely beneficial for satisfiable instances, and thanks to the "two watched literals" scheme (which is the awesomest data structure in all of computer science), we can even make this change without affecting performance on unsatisfiable instances. Finally, I'll talk about how we verify empirically that these techniques actually give an improvement, since they have no effect on worst-case theoretical complexity.



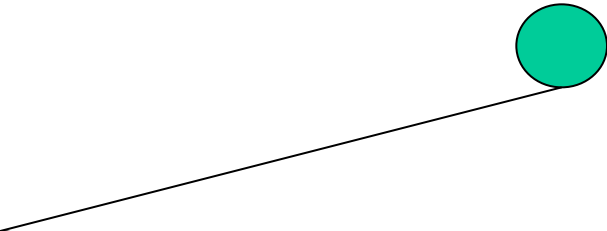
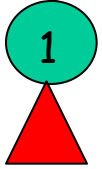


A

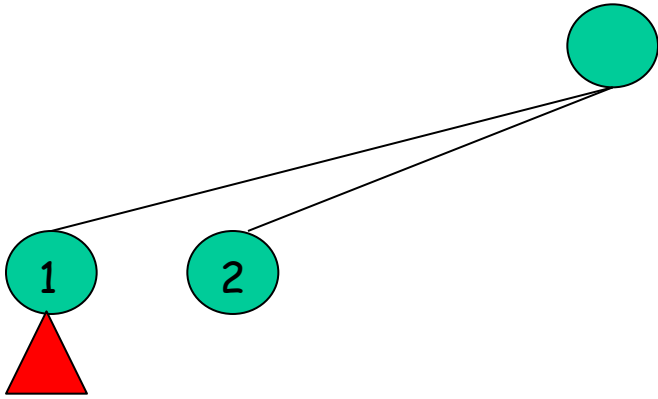
A



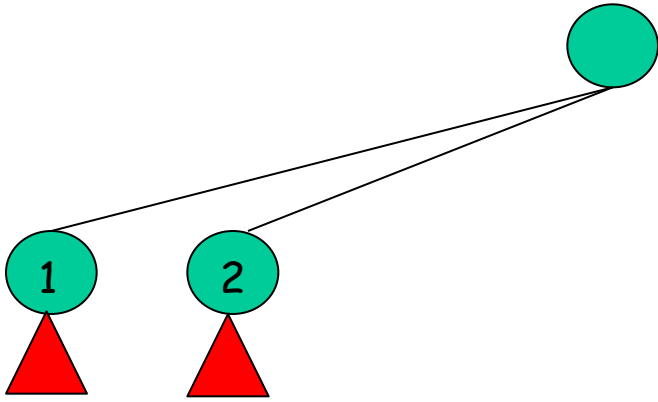
A



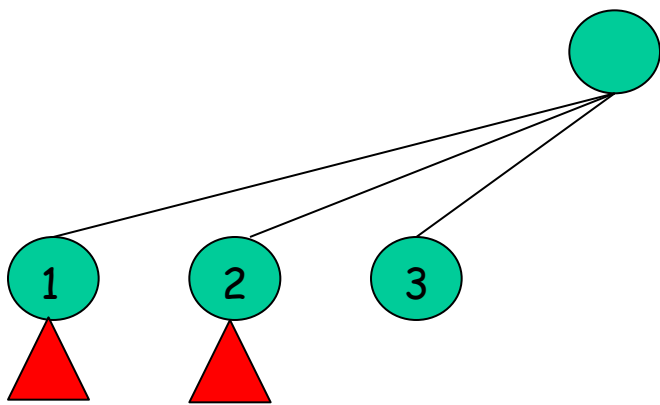
A



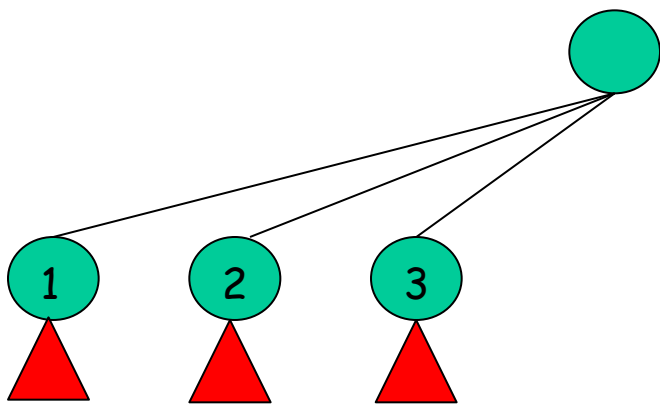
A



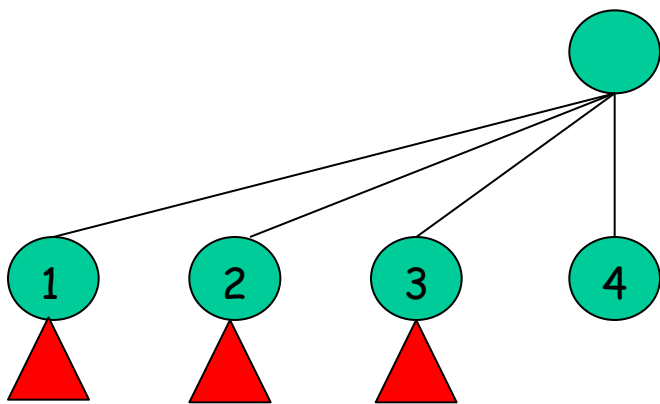
A



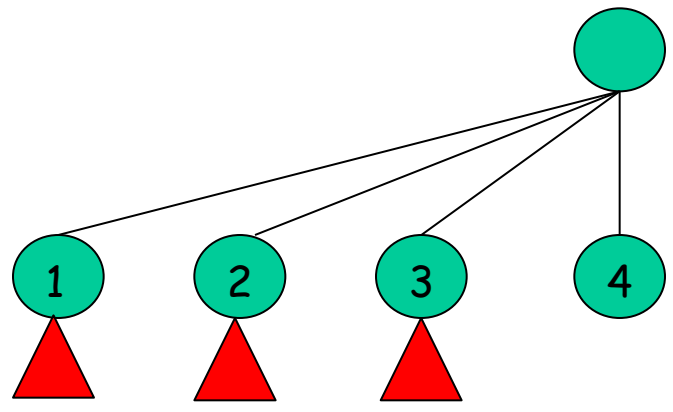
A



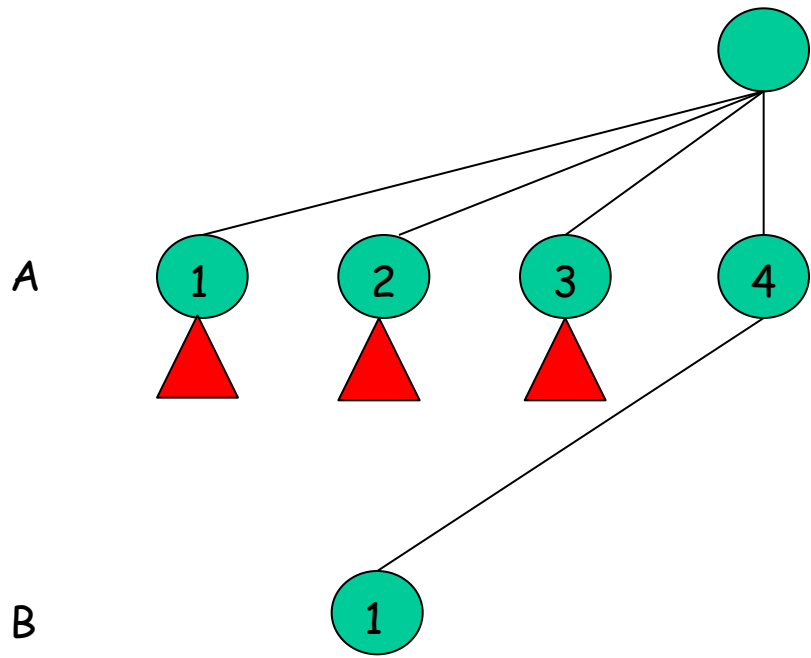
A

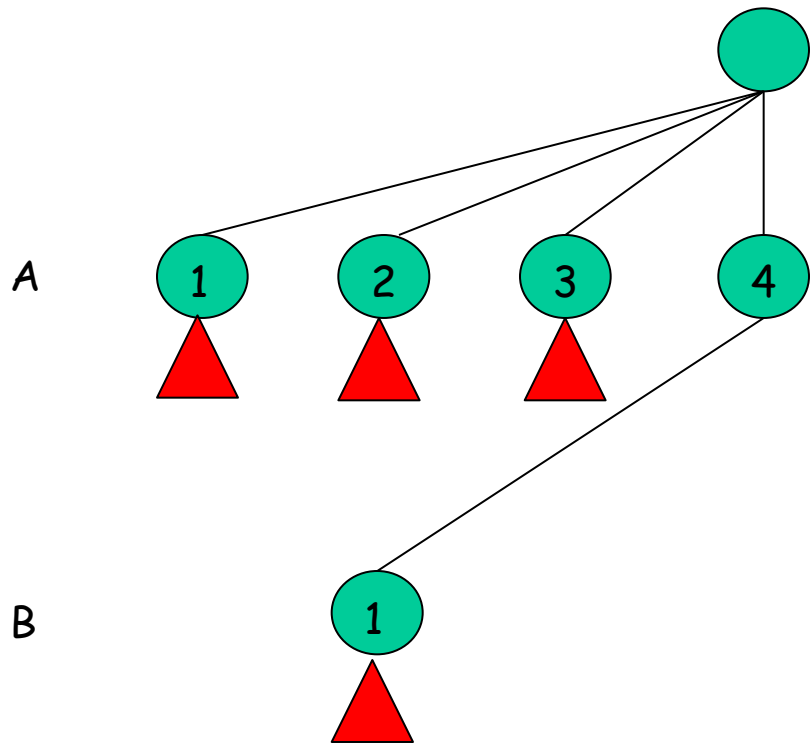


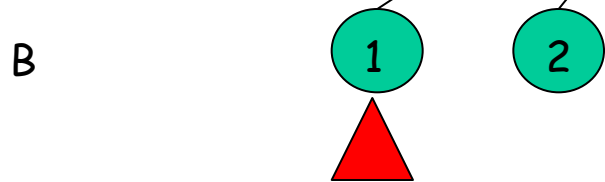
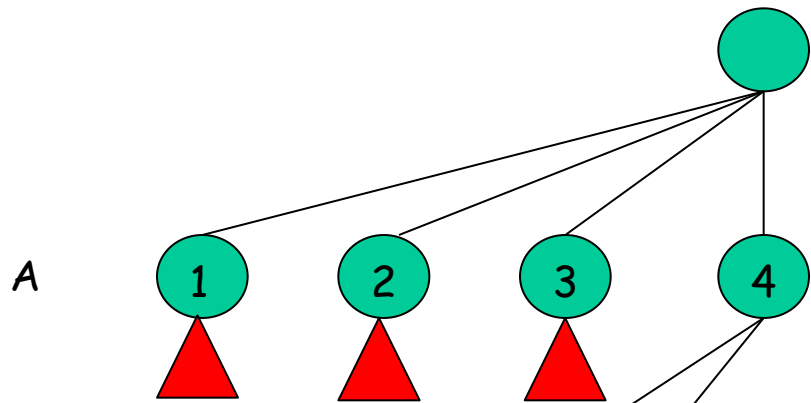
A

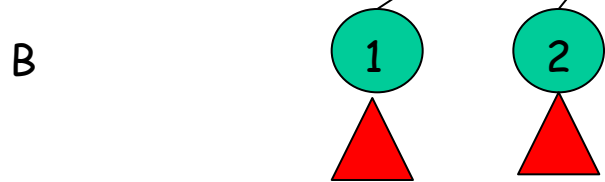
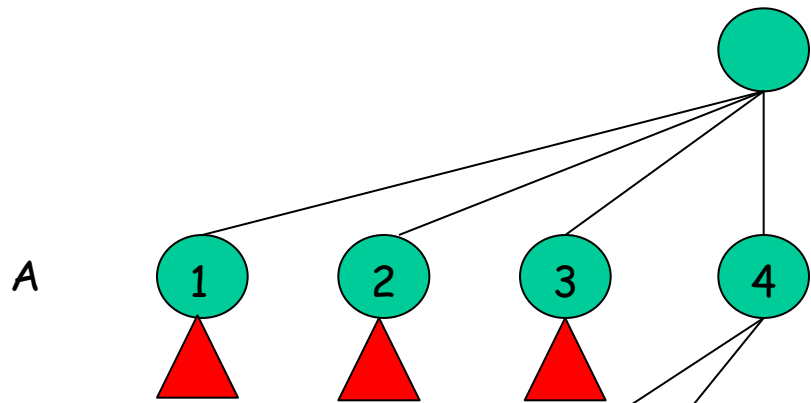


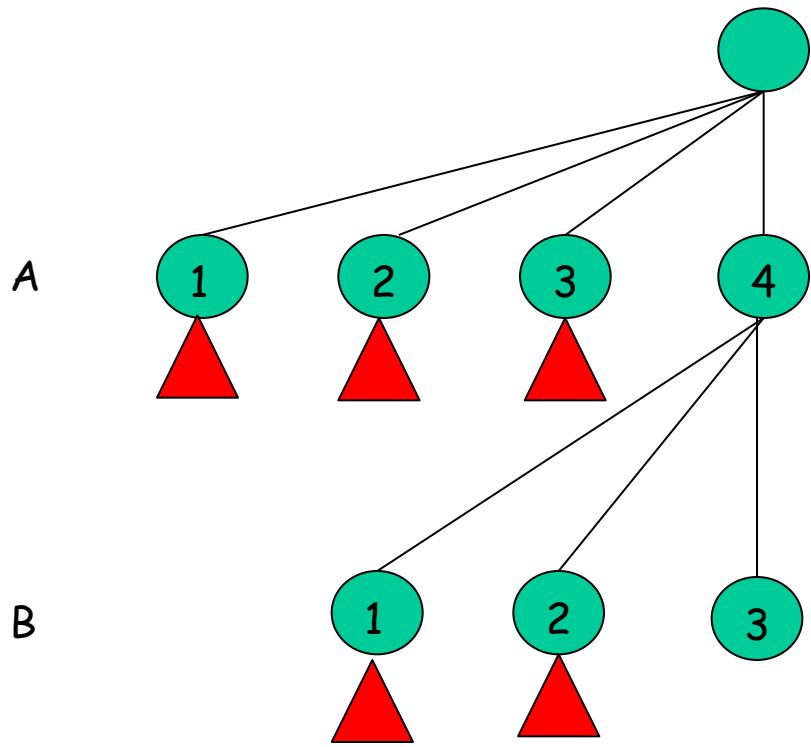
B

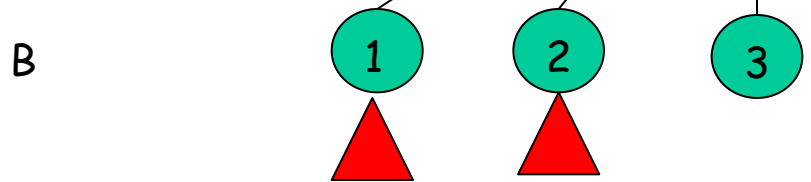
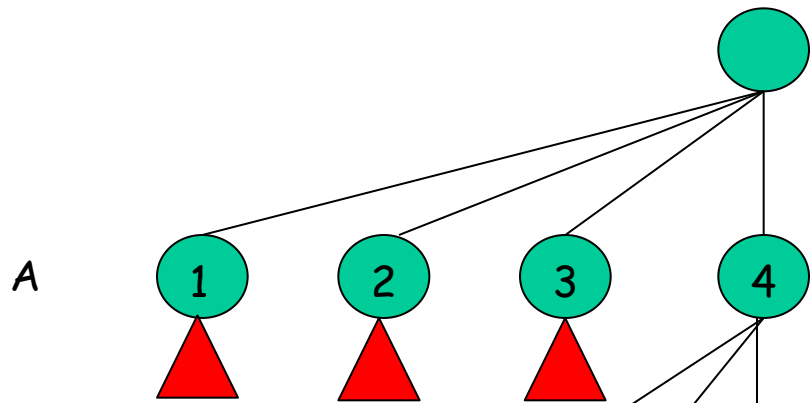


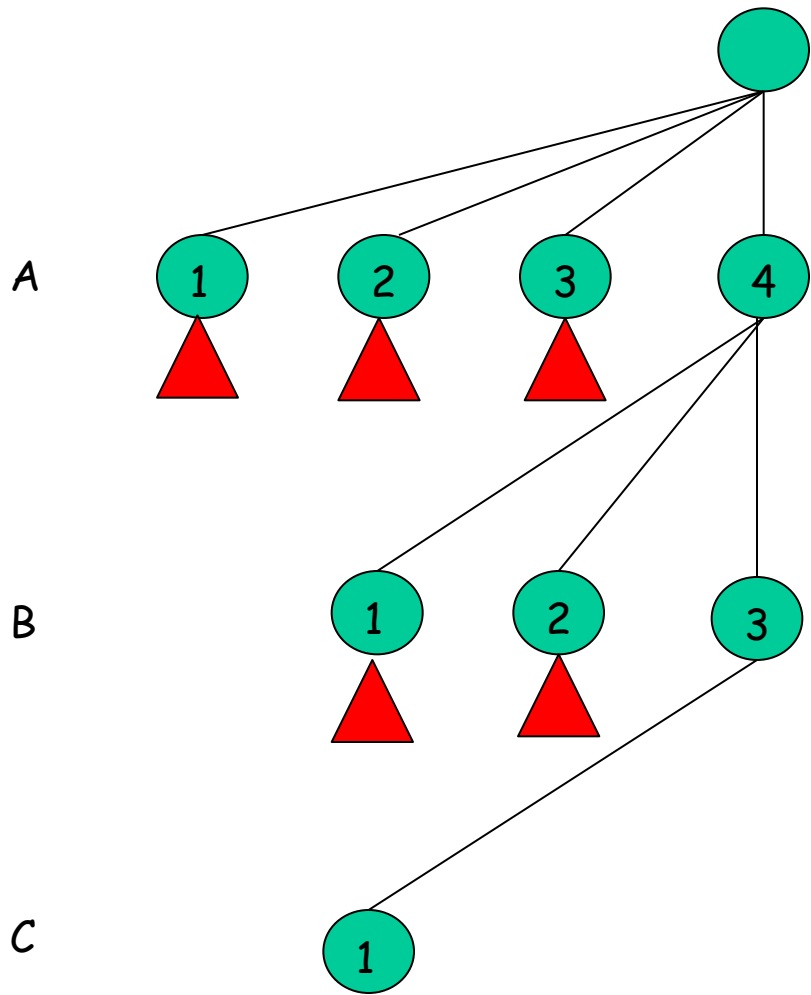


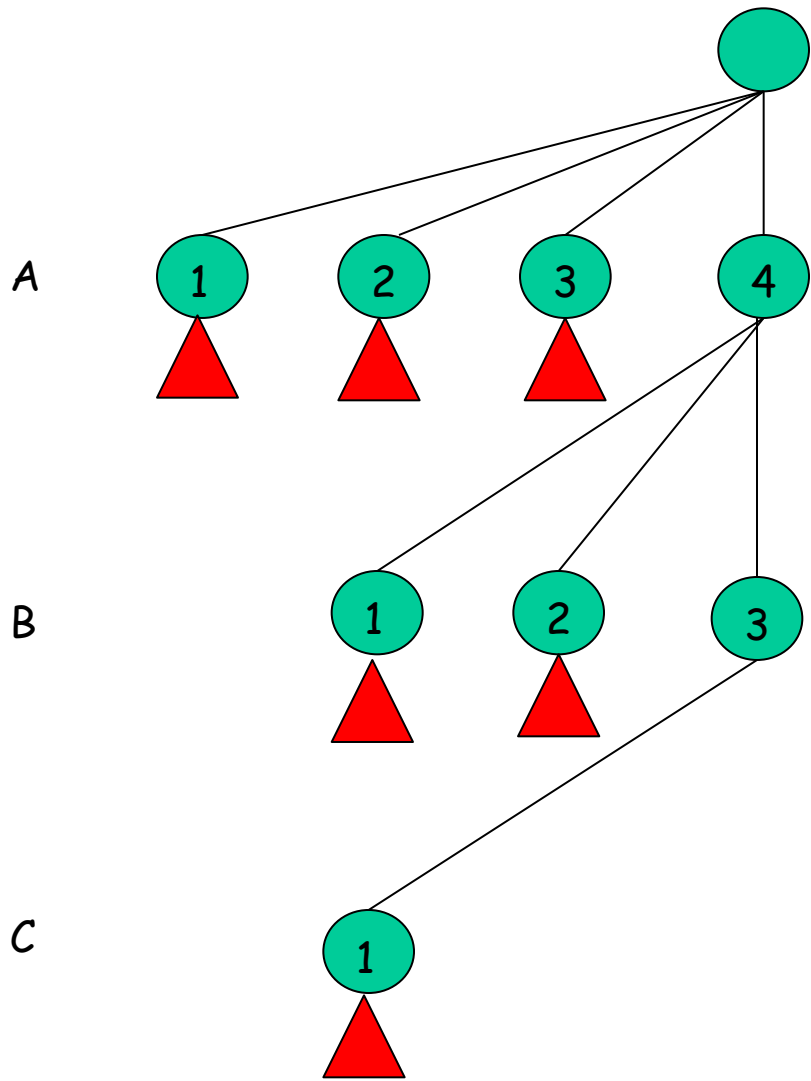


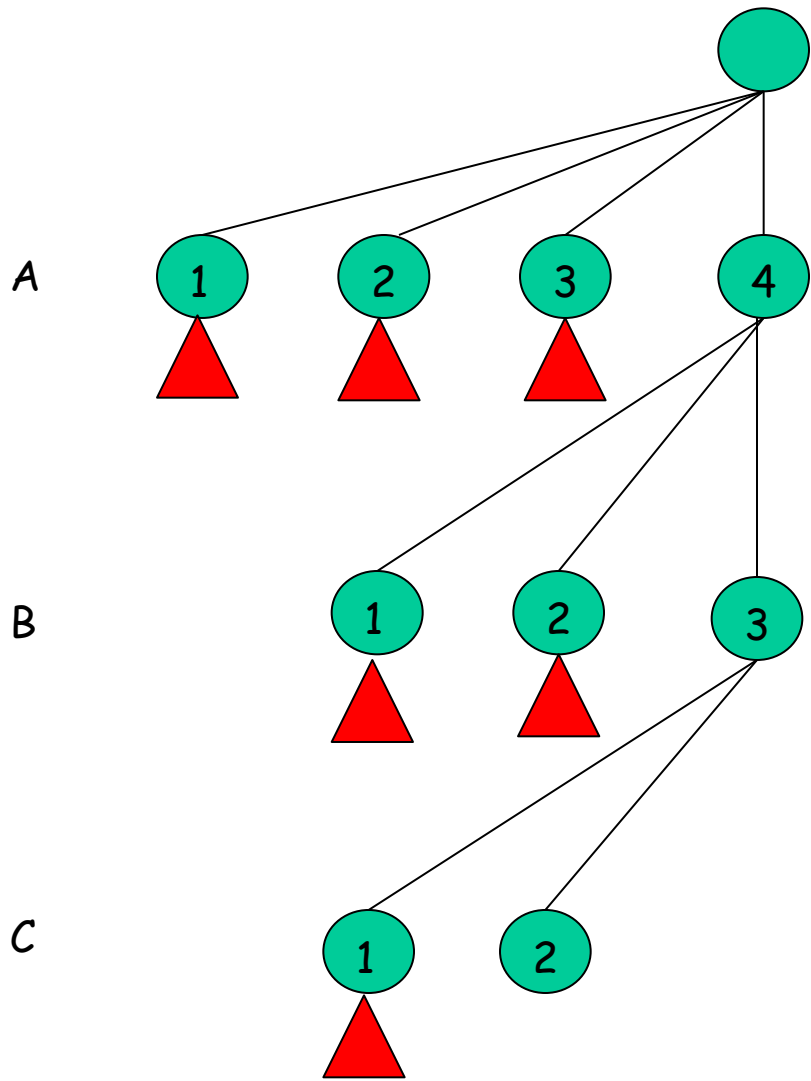


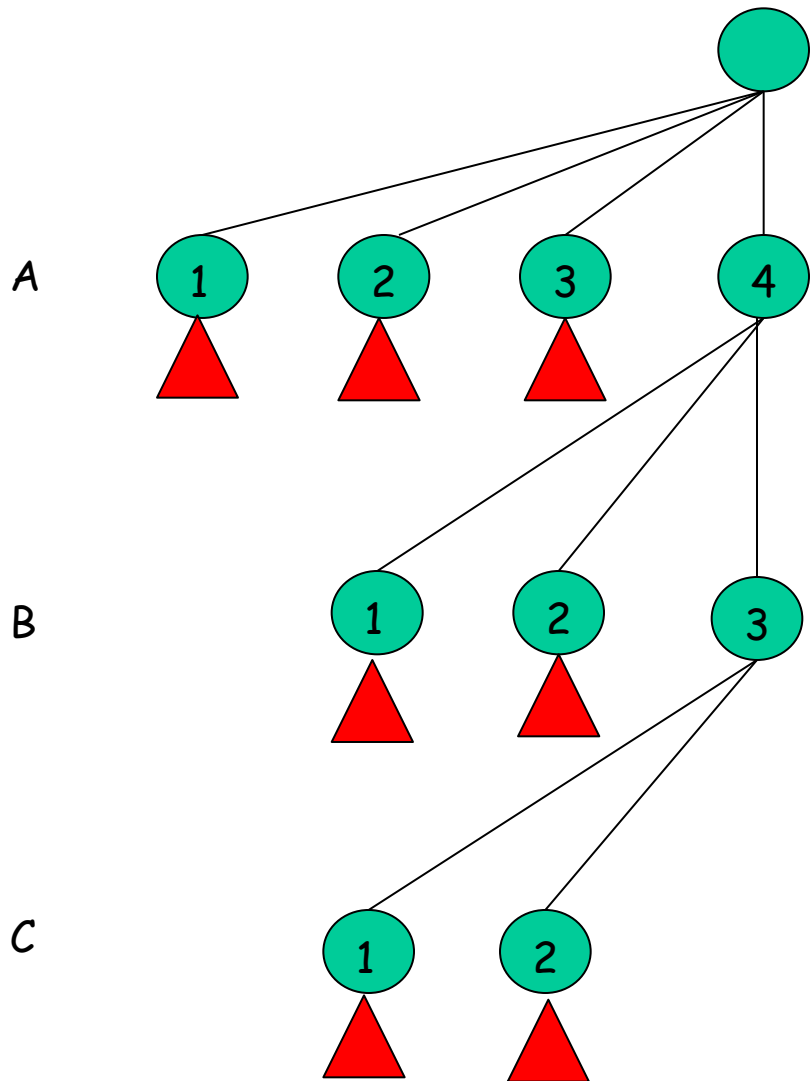


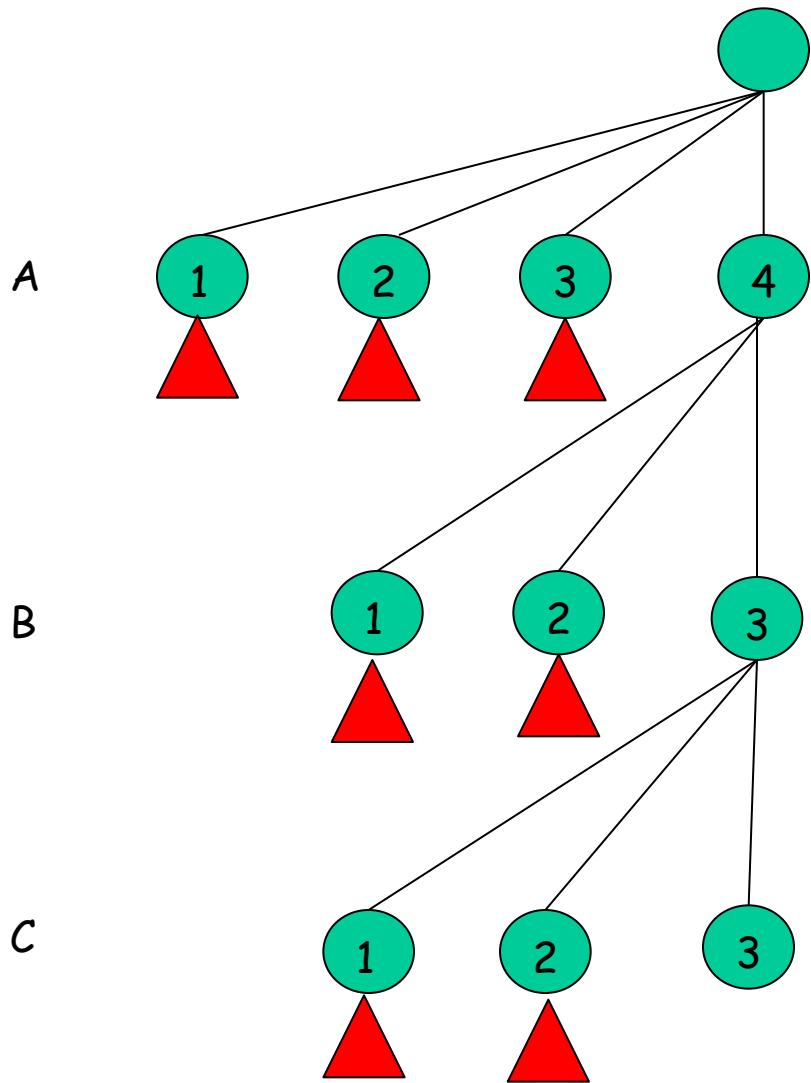


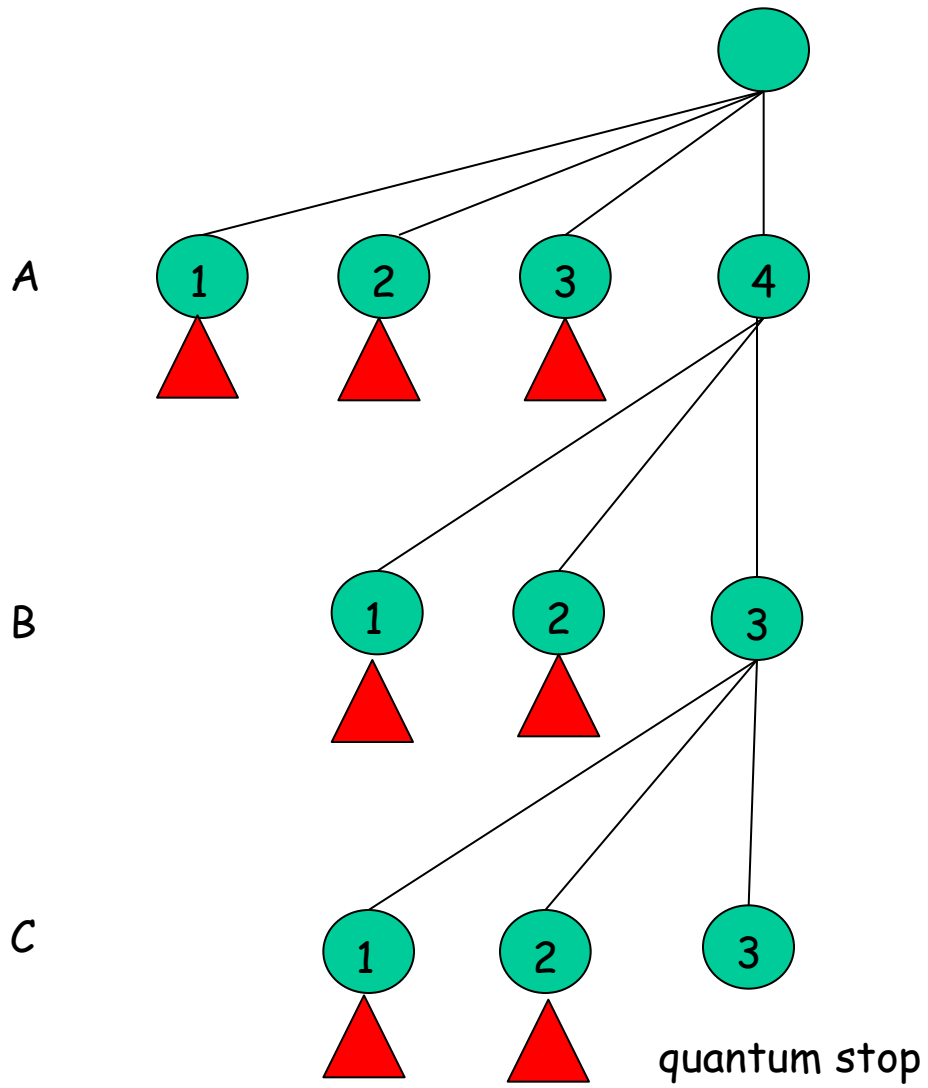


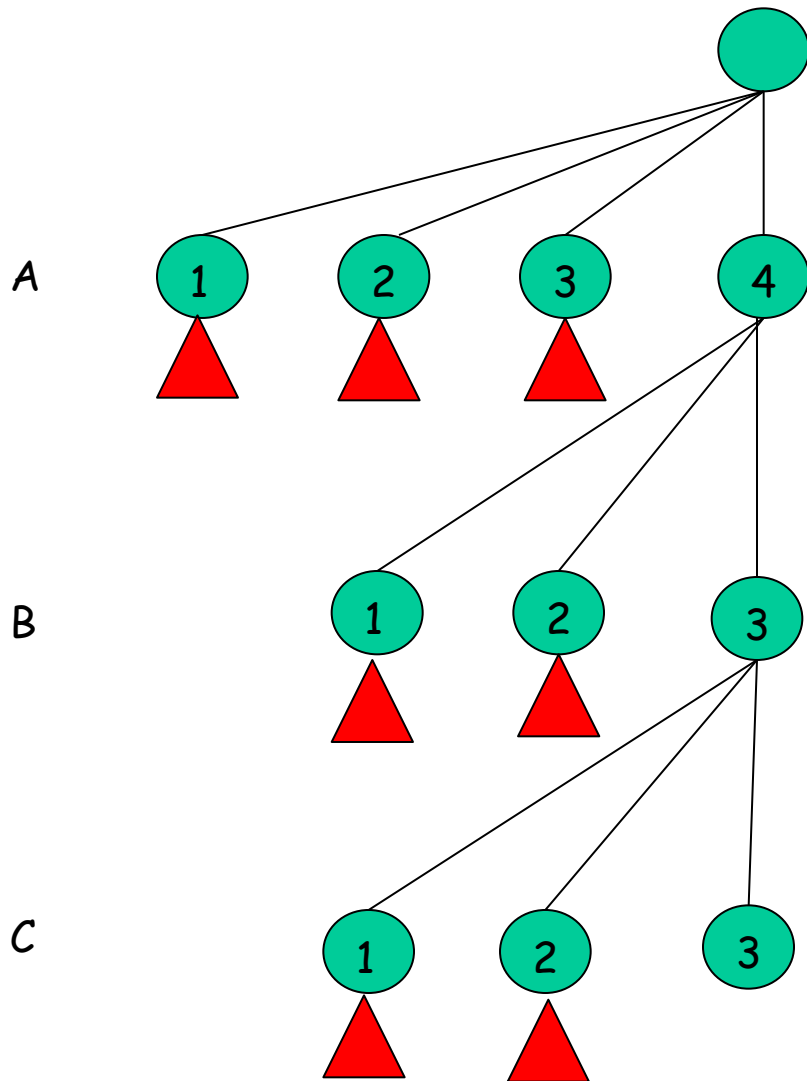




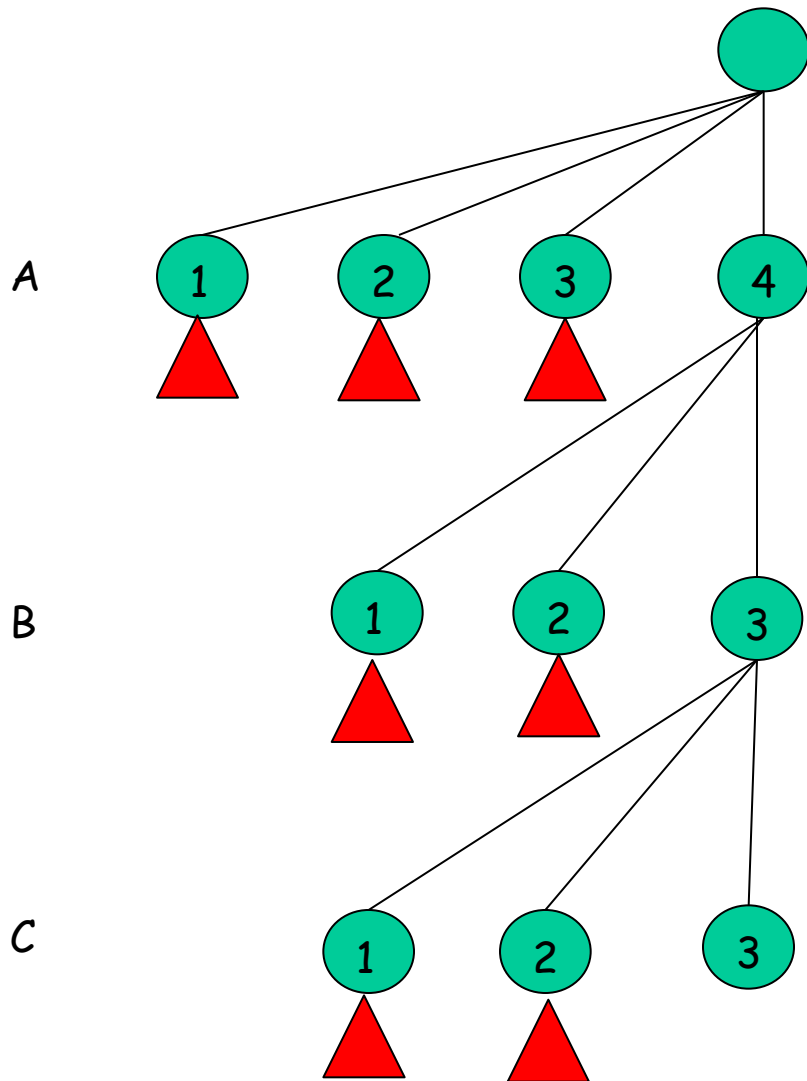




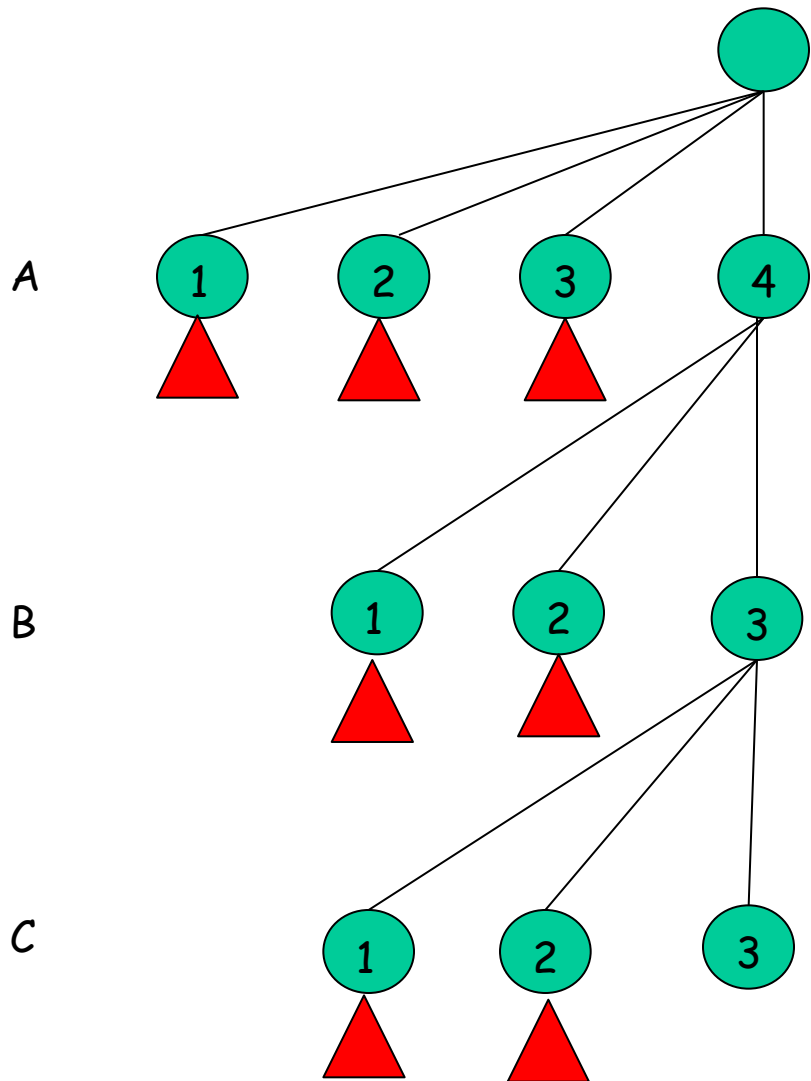




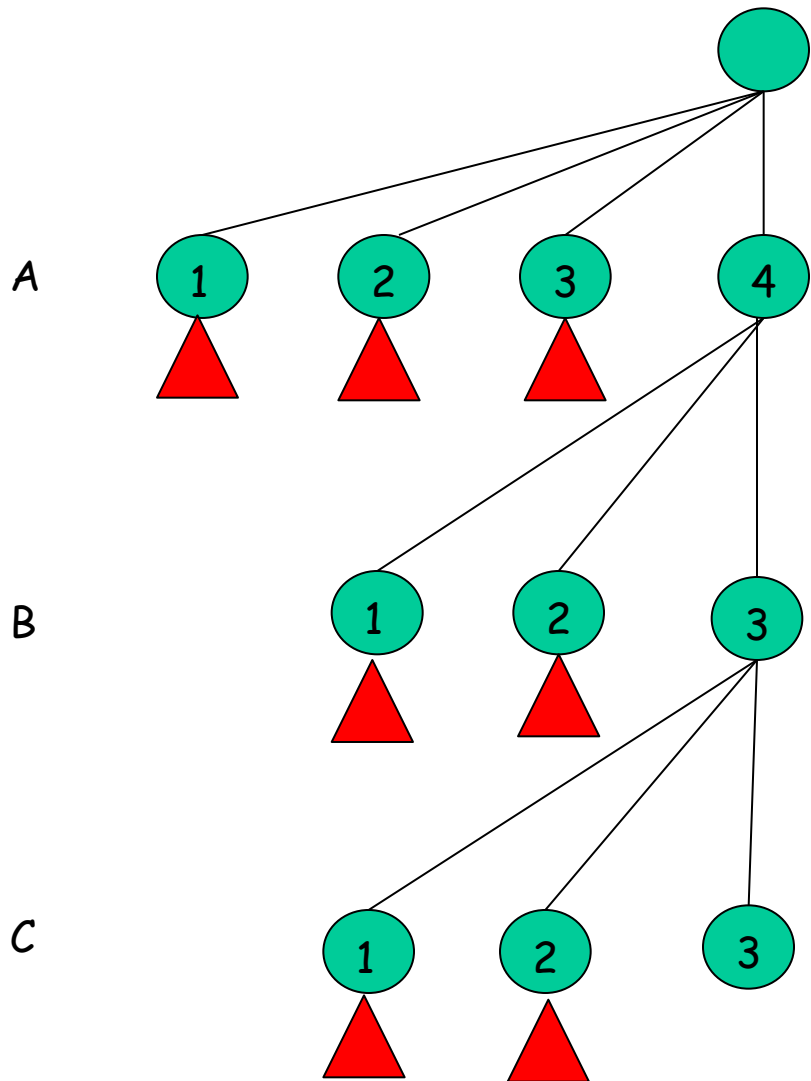
nogood({A/1}).post



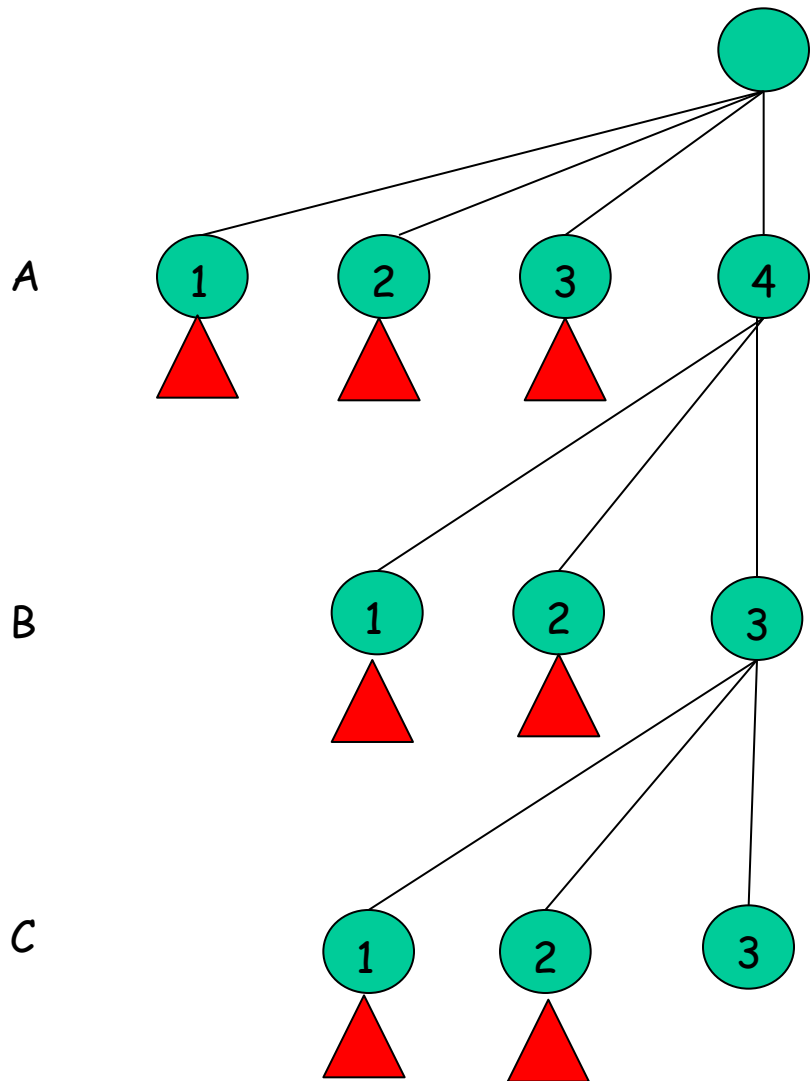
nogood({A/2}).post



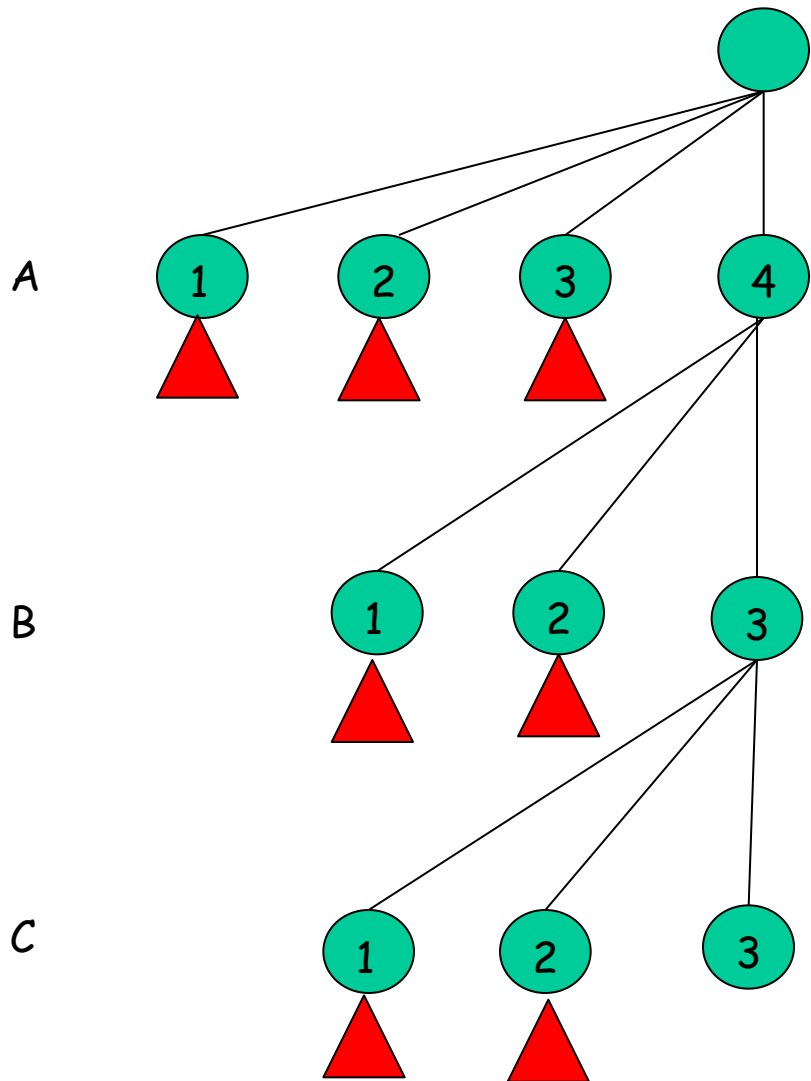
`nogood({A/3}).post`



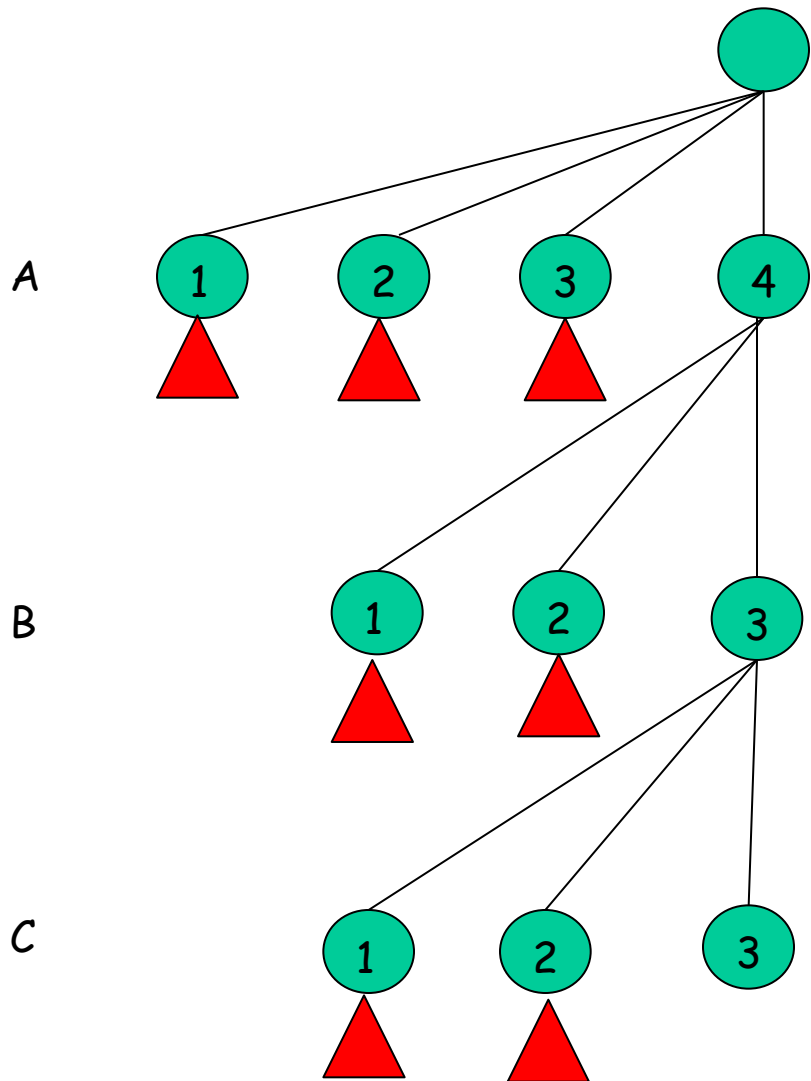
nogood({A/4,B/1}).post



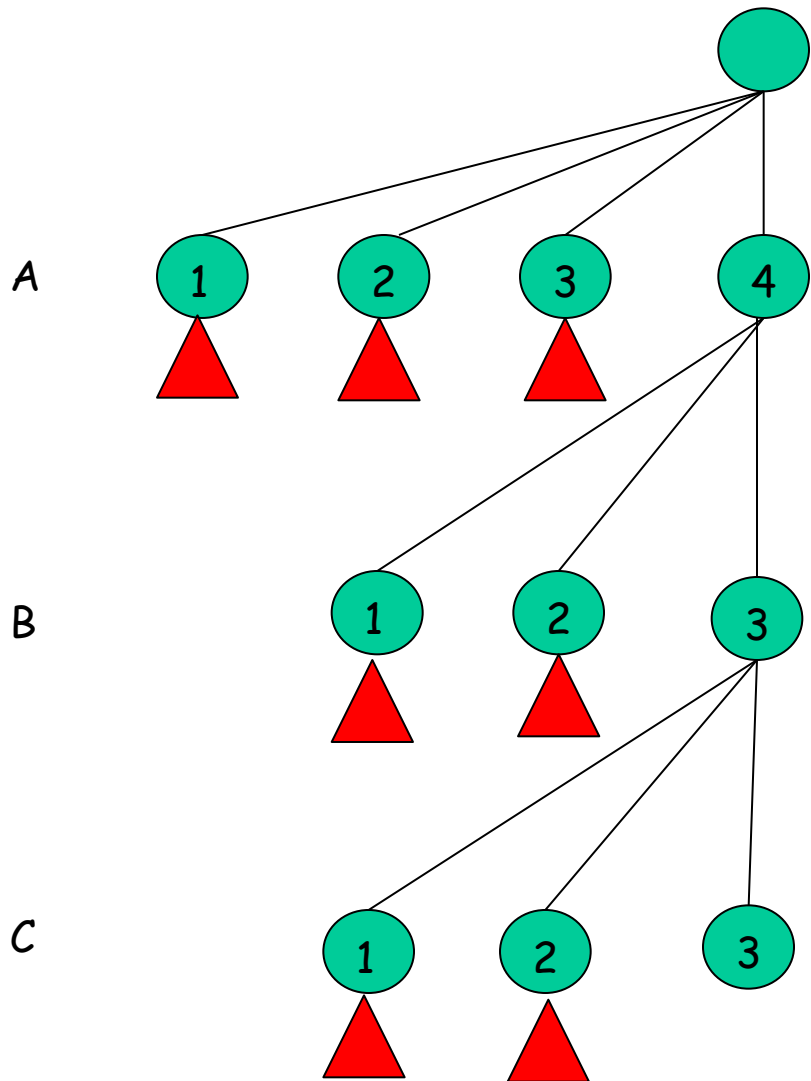
`nogood({A/4,B/2}).post`



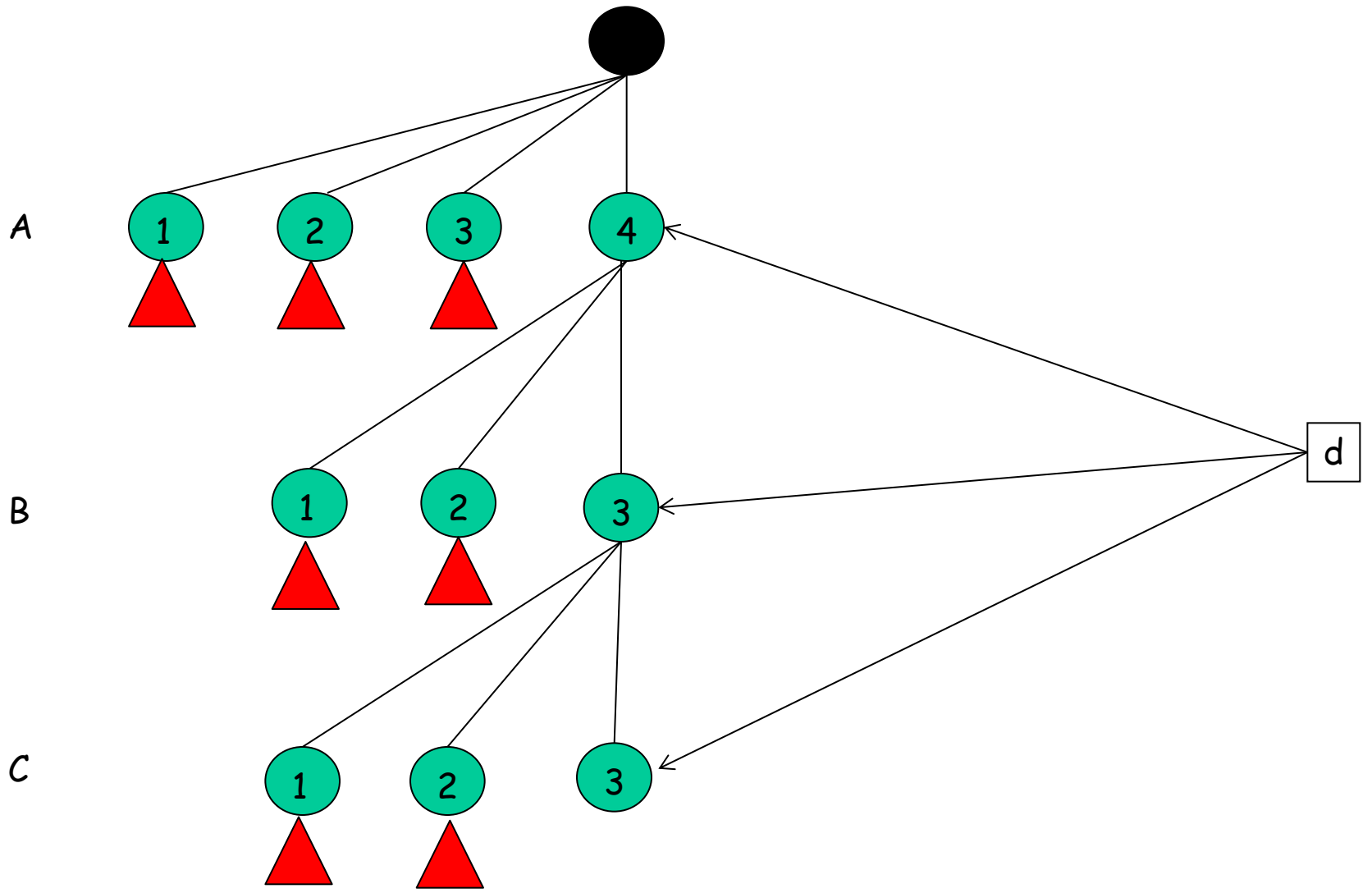
nogood({A/4,B/3,C/1}).post

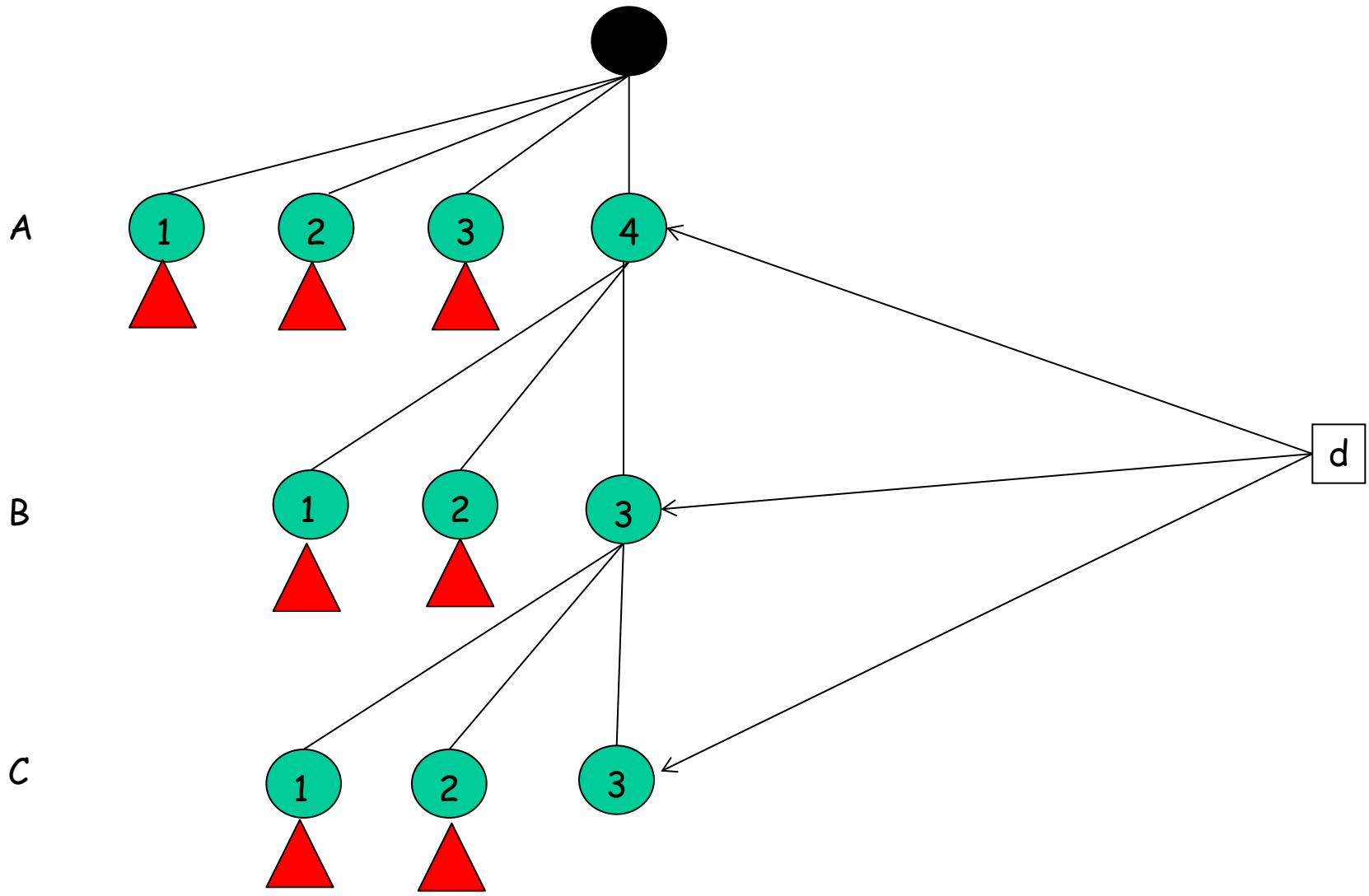


nogood({A/4,B/3,C/2}).post



More generally





forall s in siblings(d) nogood(ancestors(d) U {s}).post

Now maintain nogoods using "watched literals"

- The CLP Procedure
 - Overview: CLP Procedure
 - Introductory Examples: CLP Procedure
 - Syntax: CLP Procedure
 - Details: CLP Procedure
 - Modes of Operation
 - Constraint Data Set
 - Solution Data Set
 - Activity Data Set
 - Schedule Data Set
 - Edge Finding
 - Macro Variable ORCLP
 - Examples: CLP Procedure
 - References

Edge Finding

Edge-finding (EF) techniques are effective propagation techniques for resource capacity constraints that reason about the processing order of a set of activities requiring a given resource or set of resources. Some of the typical ordering relationships that EF techniques can determine are whether an activity can, cannot, or must execute before (or after) a set of activities requiring the same resource or set of resources. This in turn determines new time bounds on the start and finish times. Carlier and Pinson (1989) were responsible for some of the earliest work in this area that resulted in solving MT10, a 10×10 job shop problem that had remained unsolved for over 20 years (Muth and Thompson; 1963). Since then, there have been several variations and extensions of this work (Carlier and Pinson; 1990; Applegate and Cook; 1991; Nuijten; 1994; Baptiste and Le Pape; 1996).

The edge-finding consistency routines are invoked by specifying the EDGEFINDER= or EDGE= option in the SCHEDULE statement. Specifying EDGEFINDER=FIRST computes an upper bound on the activity finish time by detecting whether a given activity must be processed first from a set of activities requiring the same resource or set of resources. Specifying EDGEFINDER=LAST computes a lower bound on the activity start time by detecting whether a given activity must be processed last from a set of activities requiring the same resource or set of resources. Specifying EDGEFINDER=BOTH is equivalent to specifying both EDGEFINDER=FIRST and EDGEFINDER=LAST.

An extension of the edge-finding consistency routines is in determining whether an activity **cannot** be the first to be processed or whether an activity **cannot** be the last to be processed from a given set of activities requiring the same resource (set of resources). The NOTFIRST= or NF= option in the SCHEDULE statement determines whether an activity is "not first." In similar fashion, the NOTLAST= or NL= option in the SCHEDULE statement determines whether an activity is "not last."

Note: This procedure is [experimental](#).