

Project Part II: MIP Callbacks and TSP as a Service

Ross Anderson and Iain Dunning

Massachusetts Institute of Technology

Operations Research Center

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Outline

Introduction

MIP Callbacks

TSP

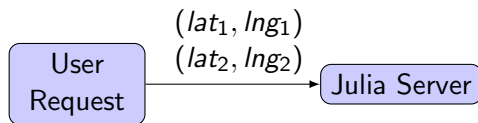
TSPaaS

Deployment

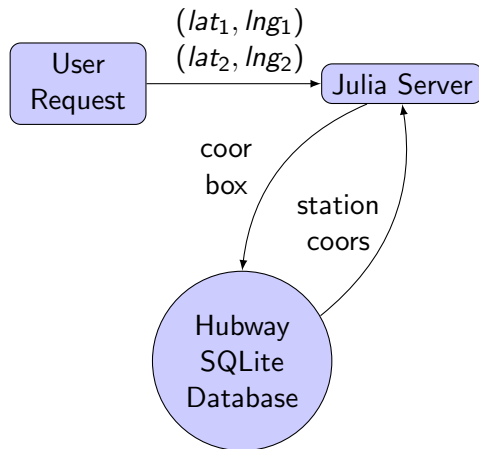
Project: TSP as a Service

User
Request

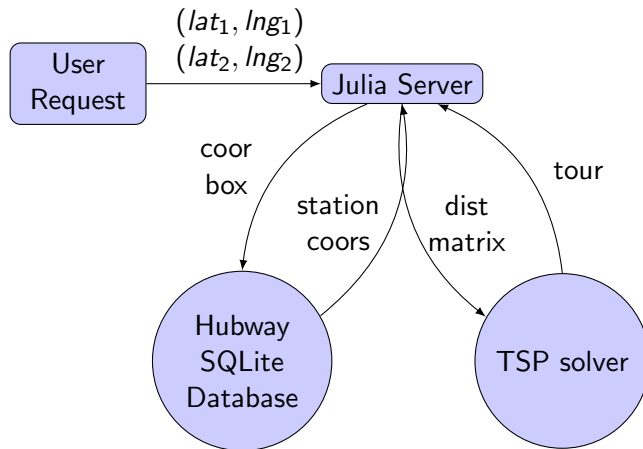
Project: TSP as a Service



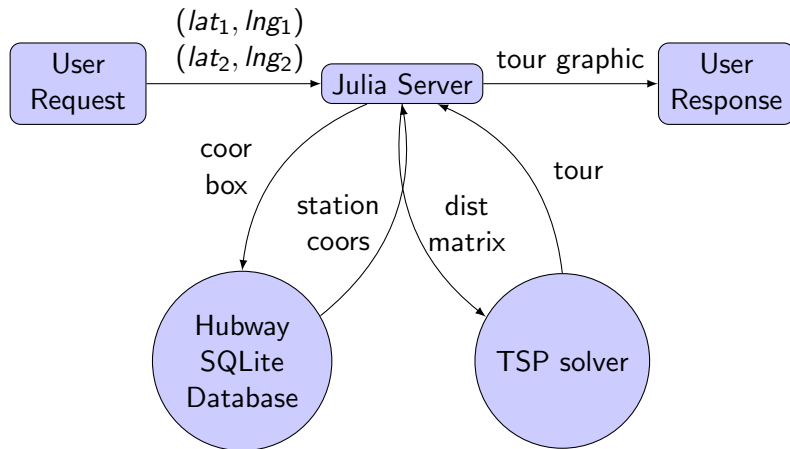
Project: TSP as a Service



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Last Time

- ▶ The internet

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- ▶ **Stations Service:** (*lat, lng*) for all hubway stations in a box

Today

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- ▶ **Convert Stations Service to TSP Service**

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- ▶ TSP
- ▶ **Convert Stations Service to TSP Service**
- ▶ Deploying MIP solvers in the real world

What is a MIP Callback?

Callbacks interrupt the MIP solver to run custom code.

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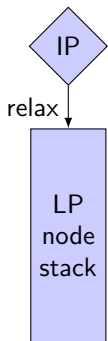
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- ▶ Add constraints to the problem
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- ▶ Control branching & node selection
- ▶ Log **anything** about solver progress for offline analysis

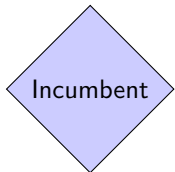
How does a MIP solver work anyway?



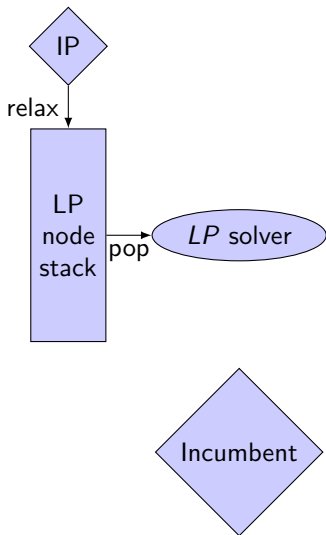
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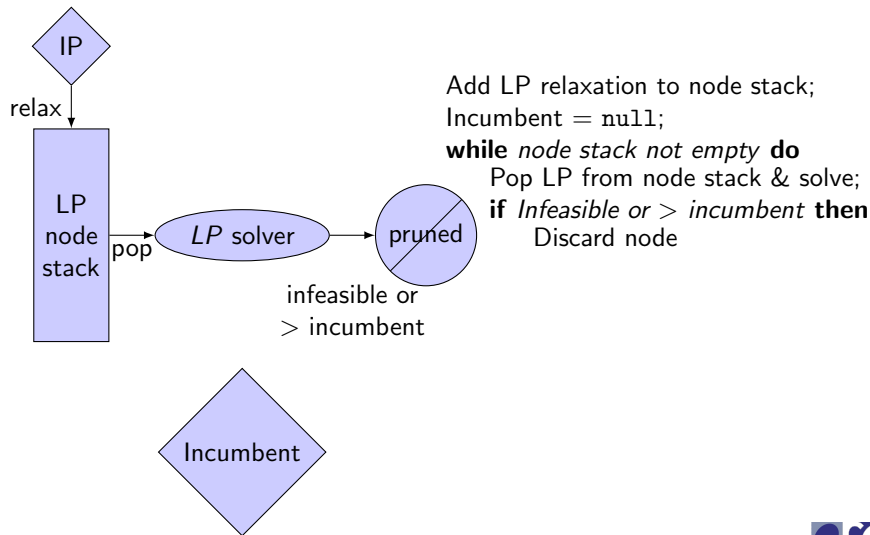


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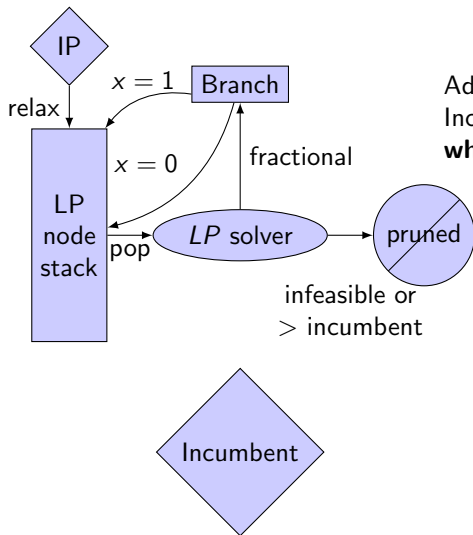


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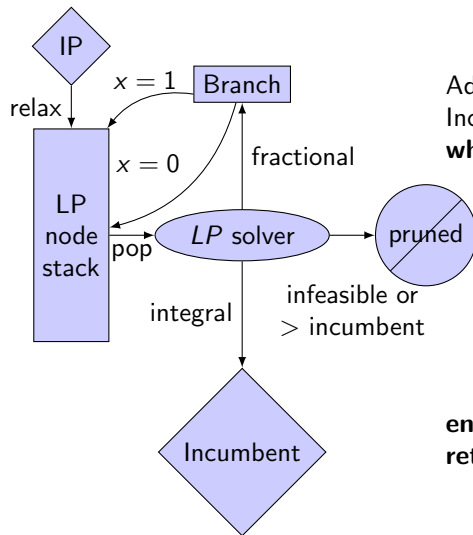
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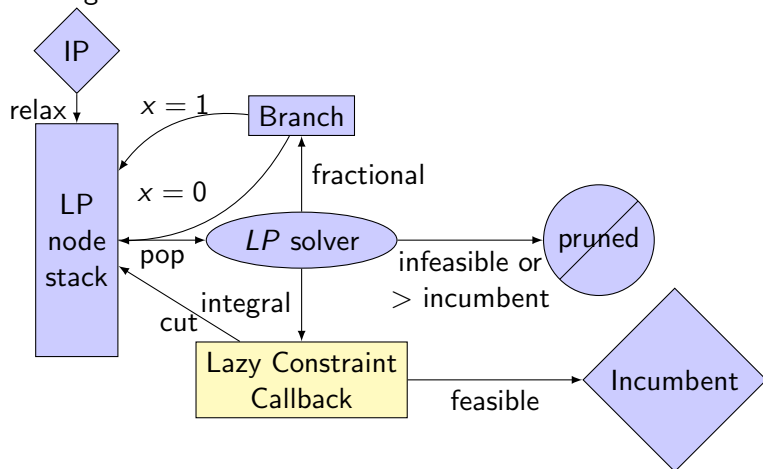


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while node stack not empty do
  Pop LP from node stack & solve;
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  else if Fractional then
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  else
    Set incumbent to solution
  end
end
return incumbent
```

The Lazy Constraint Callback

Add the “lazy” constraints only once they have been violated by an integer solution.



When to make a family of constraints lazy

Good idea when:

- ▶ Family of constraints is large
(e.g. n^3 , 2^n , $|\mathbb{R}|$)
- ▶ Integer solutions quickly
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- ▶ Most constraints not
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Problems:

- ▶ Hard to find an integer solution
- ▶ Best bound improves slowly if many lazy constraints needed

Lazy Constraints in Julia

Simple Lazy IP:

Julia Solution:

$$\max \quad x_1 + 2x_2$$

$$\text{lazy:} \quad x_1 + x_2 \leq 1$$

$$x_1, x_2 \in \{0, 1\}$$

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Julia Solution:

```
m = Model(solver=GurobiSolver(LazyConstraints=1))
@defVar(m,x[1:2],Bin)
@setObjective(m,Max, x[1] + 2*x[2])
function lazy(cb)
    xVal = getValue(x)
    if xVal[1] + xVal[2] > 1 + 1e-4
        @addLazyConstraint(cb, x[1] + x[2] <= 1)
    end
end
setlazycallback(m,lazy)
solve(m)
```

Exercise: the feasible circle

Input: radius r , direction $\mathbf{c} = (c_1, c_2)$

Goal: maximize $\mathbf{c} \cdot \mathbf{x}$ on integer inside radius r circle.

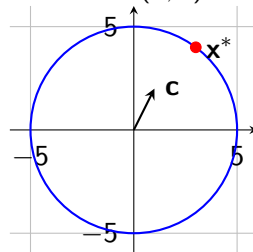
Exercise: the feasible circle

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Goal: maximize $\mathbf{c} \cdot \mathbf{x}$ on integer inside radius r circle.

$r = 5$, $\mathbf{c} = (2, 1)$

$$\begin{array}{ll}\max & \mathbf{c}\mathbf{x} \\ \text{subject to:} & \|\mathbf{x}\|_2 \leq r \\ & \mathbf{x} \in \mathbb{Z}_2\end{array}$$



$\mathbf{x}^* = (3, 4)$

Solving the feasible circle with Lazy Constraint Callbacks

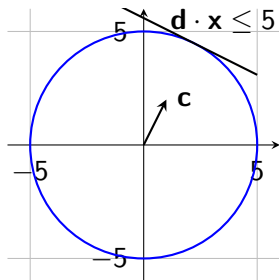
Lazy Formulation:

$$\begin{array}{ll}\max & \mathbf{c} \cdot \mathbf{x} \\ \text{s.t.} & -r \leq x_i \leq r \quad i = 1, 2 \\ \text{lazy:} & \mathbf{d} \cdot \mathbf{x} \leq r \quad \forall \|\mathbf{d}\|_2 = 1 \\ & \mathbf{x} \in \mathbb{Z}_2\end{array}$$

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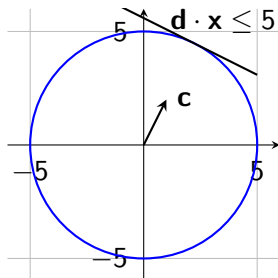
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Implementing Lazy Constraints:

- Uncountably many!



Solving the feasible circle with Lazy Constraint Callbacks

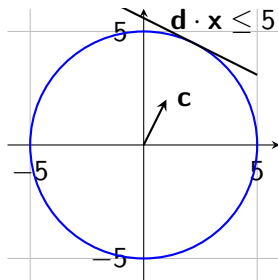
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- ▶ If $\|\mathbf{x}\|_2 > r$, take $\mathbf{d} = \frac{1}{\|\mathbf{x}\|_2} \mathbf{x}$, as

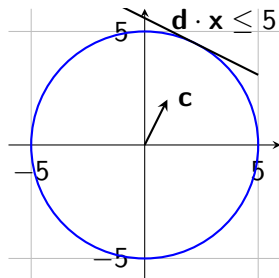
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Solving the feasible circle with Lazy Constraint Callbacks

Lazy Formulation:

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$$\mathbf{d} \cdot \mathbf{x} = \frac{1}{\|\mathbf{x}\|_2} \mathbf{x} \cdot \mathbf{x} = \|\mathbf{x}\|_2 > r$$

- ▶ Psuedo code:
if $\|\mathbf{x}\|_2 > r$ then
 $\mathbf{d} = \frac{1}{\|\mathbf{x}\|_2} \mathbf{x}$;
 add lazy constraint $\mathbf{d} \cdot \mathbf{x} \leq r$;
end

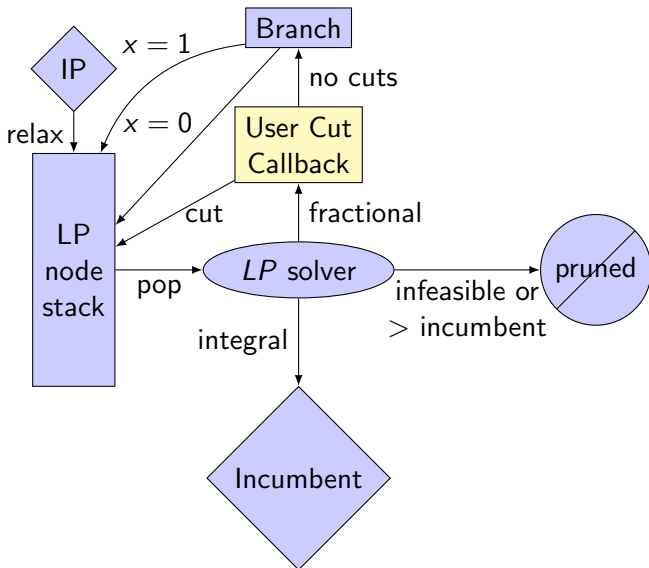
Lazy constraints vs. Lazy constraint callbacks

Some solvers support lazy constraints without callbacks. However, they have the following limitations:

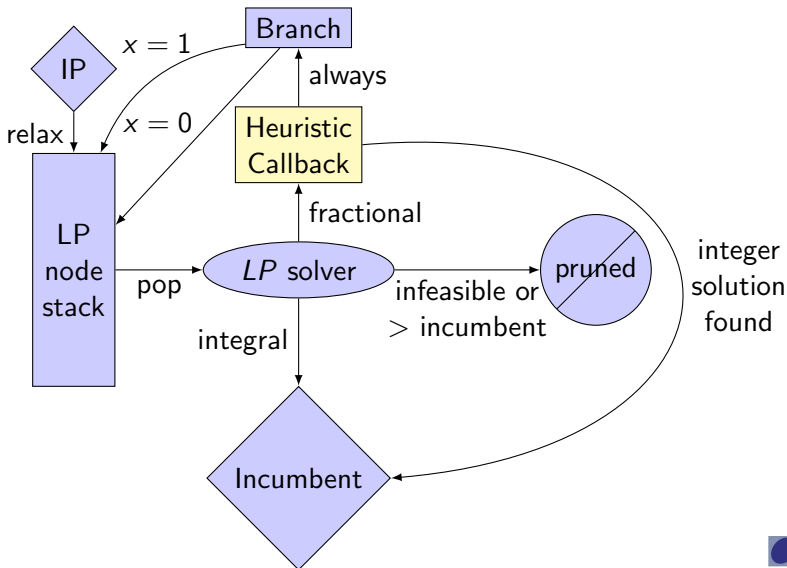
- ▶ All constraints must be generated at start
- ▶ Each constraint is checked manually against integer solutions.

Wouldn't work for the “feasible circle.”

User Cut Callback



Heuristic Callback



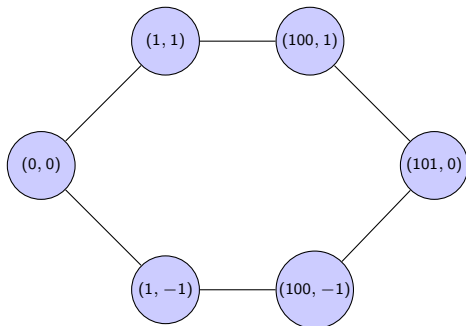
Other callbacks

- ▶ **Incumbent Callback:** optionally reject solutions, improvement heuristics
- ▶ **Branching Callback:** select variable/constraint to branch on
- ▶ **Node Selection Callback:** select node from node stack

The Traveling Salesman Problem

The TSP:

- ▶ n cities
- ▶ c_{ij} cost between cities
 - ▶ (Euclidean distance)
- ▶ Visit each city once
- ▶ Minimize total cost



Optimal tour, geometric c_{ij} .

IP for TSP

- ▶ Graph $G = (V, E)$
- ▶ $\delta(v)$ = edges incident to v
- ▶ For $S \subset V$, $\delta(S)$ = edges with **one** endpoint in S

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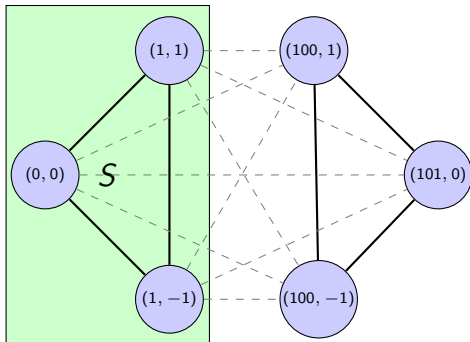
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$$\begin{aligned} \min \quad & \sum_{e \in E} c_e x_e \\ \text{s.t.} \quad & \sum_{e \in \delta(v)} x_e = 2 \quad \forall v \in V \\ & \sum_{e \in \delta(S)} x_e \geq 2 \quad \forall S \subset V, \\ & \quad \quad \quad S \neq \emptyset, V \\ & x_e \in \{0, 1\} \end{aligned}$$

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A violated cutset constraint

Exercise: Solving TSP in Julia w/o cutset constraints

Input: a symmetric 2d matrix c_{ij} with $c_{ii} = 0$

Output: the optimal cost, and an array with the city indices in order

Step 1: Ignore the cutset constraints, make sure it works.

- ▶ Create variables x_{ij} for $i = 1, \dots, n, j = 1, \dots, n$
- ▶ Add constraints

$$x_{ii} = 0$$

$$x_{ij} = x_{ji}$$

- ▶ Add degree = 2 constraints & objective
- ▶ Use `extractCycle` to get the optimal tour when you are done

Exercise: Check your work

- ▶ 3 cities (in `testTspSolver.jl`)
- ▶ 6 cities with subtours (in `testTspSolver.jl`)
- ▶ Try `plotTour`

Exercise: Add cutset constraints with lazy constraints

Don't check each of $2^V - 2$ cutsets! Use *separation*!

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- ▶ Check your work on 6 cities
- ▶ Try a larger instance from TSPLIB (in `tsplib.jl`)

Aside: the TSP and separation

The *separation problem* for a polyhedron P :

- ▶ Given \mathbf{x} show $\mathbf{x} \in P$, or find a violated constraint

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For lazy constraints, we assumed in addition that \mathbf{x} was integer, a *much easier* problem!

Use the separation problem for *user cut callbacks*.

For TSP, the separation by n Max-Flow Min-Cut computations.

Challenge: use Julia (make n LPs in each callback)!

Aside: more callbacks for TSP

Easy **heuristic** callback:

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Incumbent callback + heuristic callback + two-opt:

- ▶ Use incumbent callback to grab integer solutions
- ▶ Run two-opt
- ▶ If solution improves, add with heuristic callback

Software-as-a-Service (SaaS)

Sending a solver is hard

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- ▶ Compiling
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Bring problem to the solver!

TSP-as-a-Service

Code is ready. Lets try it!

- ▶ Navigate to `cd winstonWorks`
- ▶ Run `julia tsp_service_winston.jl`
- ▶ Wait for terminal output Listening on 8000...
- ▶ Go to

`http://localhost:8000/stationservice/42.3/42.4/-71.2/-71.0`

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It worked! Now lets look at `tsp_service_winston.jl`

Considerations for deploying MIPs

- ▶ Real time or offline MIP solving
- ▶ Number of simultaneous users
- ▶ Solver licenses
- ▶ Reliability/maximum solve time

Deployment Options

Option		Pros	Cons
Personal computer	Easy		Spilled coffee Two concurrent users Blackouts International lag Data Safety
Rent a box	Pretty Easy		Two concurrent users International lag Data safety
Cloud (Amazon/Google)	Scale up for many users Data safety Low latency Monitoring/uptime		Set up time Learn a system Can be \$\$
Gurobi a la cart (Amazon) (<i>Solver only</i>)	Pay for what you use Scale up for many users		Can be \$\$ No callbacks