

# Component Bound Branching in a Branch-and-Price Framework

Master Thesis in Computer Science  
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May 5, 2024

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## Abstract

This master thesis integrates the component bound branching rule, proposed by Vanderbeck et al. [1, 2], into the branch-price-and-cut solver GCG. This rule, similarly to Vanderbeck’s generic branching scheme [3], exclusively operates within the Dantzig-Wolfe reformulated problem, where branching decisions generally have no corresponding actions in the original formulation. The current GCG framework requires modifications for such branching rules, especially within the pricing loop, as seen in Vanderbeck’s method implementation. These rules also fail to utilize enhancements like dual value stabilization.

A significant contribution of this thesis is the enhancement of the GCG architecture to facilitate the seamless integration of new branching rules that operate solely on the reformulated problem. This allows these rules to benefit from current and future improvements in the branch-price-and-cut framework, including dual value stabilization, without necessitating alterations to the branching rule itself.

The thesis proposes an interface to manage constraints in the master problem that lack counterparts in the original formulation. These constraints require specific modifications to the pricing problems to ensure their validity in the master. The ‘generic mastercut’ interface, tightly integrated into the GCG solver, spans the pricing loop, column generation, and dual value stabilization. Enhancements to the existing branching rule interface complement this integration, enabling effective utilization of the generic mastercuts.

Finally, the component bound branching rule will be implemented using this new interface and evaluated on a set of benchmark instances. Its performance will be benchmarked against the existing Vanderbeck branching rule, offering a practical comparison of both approaches.



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# Chapter 1

## Introduction





# Chapter 2

## Preliminaries

In this preliminary chapter we will provide a brief rundown of theorems and algorithms on which the techniques described in later chapters, such as Column Generation in Section 3.1, are building upon. Understanding these concepts is essential to understanding the theory later presented. If, however, one is familiar with these, we invite the reader to skip ahead to Chapter 3.

### 2.1 Polyhedron Representation

**Definition 2.1.** Given  $k$  points  $\mathbf{x}_1, \dots, \mathbf{x}_k \in \mathbb{R}^n$ , any  $\mathbf{x} = \sum_{i=1}^k \alpha_i \mathbf{x}_i$  is a **conic combination** of the  $\mathbf{x}_i$ , iff  $\forall i \in \{1, \dots, k\}. \alpha_i \geq 0$ .

**Definition 2.2.** Given  $k$  points  $\mathbf{x}_1, \dots, \mathbf{x}_k \in \mathbb{R}^n$ , any  $\mathbf{x} = \sum_{i=1}^k \alpha_i \mathbf{x}_i$  is a **convex combination** of the  $\mathbf{x}_i$ , iff  $\sum_{i=1}^k \alpha_i = 1 \wedge \forall i \in \{1, \dots, k\}. \alpha_i \geq 0$ .

The set of all convex combinations of  $\mathbf{x}_1, \dots, \mathbf{x}_k$  is therefore defined as:

$$\text{conv}(\mathbf{x}_1, \dots, \mathbf{x}_k) := \left\{ \sum_{i=1}^k \alpha_i \mathbf{x}_i \mid \sum_{i=1}^k \alpha_i = 1 \wedge \forall i \in \{1, \dots, k\}. \alpha_i \geq 0 \right\}$$

**Corollary 2.1.** The intersection of two convex sets is convex.

**Definition 2.3.** Let  $\mathcal{P}$  be a convex set. A point  $\mathbf{p} \in \mathcal{P}$  is an **extreme point** of  $\mathcal{P}$  if there is no non-trivial convex combination of any two points in  $\mathcal{P}$  expressing  $\mathbf{p}$ , i.e.

$$\forall \mathbf{x}_1, \mathbf{x}_2 \in \mathcal{P}. \forall \alpha \in \mathbb{R}_+ \setminus \{0\}. \mathbf{x}_1 \neq \mathbf{x}_2 \implies \mathbf{p} \neq \alpha \mathbf{x}_1 + (1 - \alpha) \mathbf{x}_2$$

**Definition 2.4.** Let  $\mathcal{P}$  be a convex set. A vector  $\mathbf{r} \in \mathbb{R}_0^n \setminus \{0\}$  is a **ray** of  $\mathcal{P}$  iff  $\forall \mathbf{x} \in \mathcal{P}. \forall \beta \in \mathbb{R}_+. \mathbf{x} + \beta \mathbf{r} \in \mathcal{P}$ .

The span of rays  $\mathbf{r}_1, \dots, \mathbf{r}_k \in \mathbb{R}_+^n$  we denote as:

$$\text{rayspan}(\mathbf{r}_1, \dots, \mathbf{r}_k) := \bigcup_{i=1}^k \{ \omega \mathbf{r}_i \mid \omega \in \mathbb{R}_+ \}$$

**Definition 2.5.** A ray  $\mathbf{r}$  of  $\mathcal{P}$  is an **extreme ray** of  $\mathcal{P}$  if there is no non-trivial conic combination of any two rays in  $\mathcal{P}$  expressing  $\mathbf{r}$ , i.e.

$$\forall \mathbf{r}_1, \mathbf{r}_2 \in \mathcal{P}. \forall \alpha_1, \alpha_2, \beta \in \mathbb{R}_+ \setminus \{0\}. \mathbf{r}_1 \neq \beta \mathbf{r}_2 \implies \mathbf{r} \neq \alpha_1 \mathbf{r}_1 + \alpha_2 \mathbf{r}_2$$

**Definition 2.6.** A **hyperplane**  $\mathcal{H} \subset \mathbb{R}^n$  of a  $n$ -dimensional space is a subspace of dimension  $n - 1$ , and can therefore be described using a vector  $\mathbf{f} \in \mathbb{R}^n$  and a scalar  $f \in \mathbb{R}$  as  $\mathcal{H} = \{\mathbf{x} \mid \mathbf{f}^\top \mathbf{x} = f\}$ .

**Corollary 2.2.** Any hyperplane is a convex set.

*Proof.* Let  $\mathcal{H} = \{\mathbf{x} \mid \mathbf{f}^\top \mathbf{x} = f\}$  be a hyperplane. Let  $k \in \mathbb{N}$ ,  $\mathbf{x}_1, \dots, \mathbf{x}_k \in \mathcal{H}$ . For any  $\alpha_1, \dots, \alpha_k \in \mathbb{R}_+$  with  $\sum_{i=1}^k \alpha_i = 1$ :

$$\begin{aligned} \mathbf{f}^\top \left( \sum_{i=1}^k \alpha_i \mathbf{x}_i \right) &= \sum_{i=1}^k \alpha_i \mathbf{f}^\top \mathbf{x}_i \\ &= \sum_{i=1}^k \alpha_i \cdot f \\ &= f \cdot \sum_{i=1}^k \alpha_i \\ &= f \end{aligned}$$

Therefore, the convex combination  $\sum_{i=1}^k \alpha_i \mathbf{x}_i$  is in the hyperplane  $\mathcal{H}$ .  $\square$

**Definition 2.7.** A **halfspace** is the set above or below a hyperplane. A halfspace is open if the points on the hyperplane are excluded, otherwise closed.

**Corollary 2.3.** Any halfspace is a convex set.

*Proof.* Let  $\mathcal{H}^+ = \{\mathbf{x} \mid \mathbf{f}^\top \mathbf{x} > f\}$  be an open halfspace (analogous for  $\mathcal{H}^- = \{\mathbf{x} \mid \mathbf{f}^\top \mathbf{x} < f\}$ , and for the closed halfspaces). Let  $k \in \mathbb{N}$ ,  $\mathbf{x}_1, \dots, \mathbf{x}_k \in \mathcal{H}$ . For any  $\alpha_1, \dots, \alpha_k \in \mathbb{R}_+$  with  $\sum_{i=1}^k \alpha_i = 1$ :

$$\begin{aligned} \mathbf{f}^\top \left( \sum_{i=1}^k \alpha_i \mathbf{x}_i \right) &= \sum_{i=1}^k \alpha_i \mathbf{f}^\top \mathbf{x}_i \\ &> \sum_{i=1}^k \alpha_i \cdot f \\ &= f \cdot \sum_{i=1}^k \alpha_i \\ &= f \end{aligned}$$

Therefore, the convex combination  $\sum_{i=1}^k \alpha_i \mathbf{x}_i$  is in the halfspace  $\mathcal{H}$ .  $\square$

**Definition 2.8.** A **polyhedron**  $\mathcal{P} \subseteq \mathbb{R}^n$  is defined by the intersection of a set of closed halfspaces, i.e.  $\mathcal{P} := \{\mathbf{x} \in \mathbb{R}^n \mid \mathbf{Ax} \geq \mathbf{b}\}$ , with  $\mathbf{A} \in \mathbb{R}^{m \times n}$ ,  $\mathbf{b} \in \mathbb{R}^m$ .

By Corollaries 2.1 and 2.3, a polyhedron is also a convex set of points.

**Definition 2.9.** The **Minkowski sum** of two sets  $P, Q$  is defined by:

$$P \oplus Q := \{\mathbf{p} + \mathbf{q} \mid \mathbf{p} \in P \wedge \mathbf{q} \in Q\}$$

**Theorem 2.1** (Minkowski-Weyl). For  $\mathcal{P} \subseteq \mathbb{R}^n$  the following statements are equivalent:

1.  $\mathcal{P}$  is a polyhedron, i.e., there exists some finite matrix  $\mathbf{A} \in \mathbb{R}^{m \times n}$  and some vector  $\mathbf{b} \in \mathbb{R}^m$  such that  $P = \{\mathbf{x} \in \mathbb{R}^n \mid \mathbf{Ax} \leq \mathbf{b}\}$
2. There exist finitely many vectors  $\mathbf{v}_1, \dots, \mathbf{v}_s \in \mathbb{R}^n$  and finite vectors  $\mathbf{r}_1, \dots, \mathbf{r}_t \in \mathbb{R}_+^n$ , such that  $P = \text{conv}(\mathbf{v}_1, \dots, \mathbf{v}_s) \oplus \text{rayspan}(\mathbf{r}_1, \dots, \mathbf{r}_t)$

In simple terms, the Minkowski-Weyl theorem states that any polyhedron can always be defined in two ways: either by its faces, i.e. closed halfspaces, or by its vertices and rays. Because of their unique properties, for such representation of a polyhedron it is sufficient to select its the extreme points and extreme rays. Figure xyz. illustrates this TODO-til

The following theorem builds upon the Minkowski-Weyl theorem to describe a polyhedron, which is represented by its extreme points  $\{\mathbf{x}_p\}_{p \in P}$  and extreme rays  $\{\mathbf{x}_r\}_{r \in R}$ , using hyperplanes. Here, the sets  $P, R$  are used to index the extreme points and extreme rays, respectively.

**Theorem 2.2** (Nemhauser-Wolsey). Consider the polyhedron  $\mathcal{P} = \{\mathbf{x} \in \mathbb{R}^n \mid \mathbf{Qx} \geq \mathbf{b}\}$  with full row rank matrix  $\mathbf{Q} \in \mathbb{R}^{m \times n}$ , i.e.  $\text{rank}(\mathbf{Q}) = m \leq n \wedge \mathcal{P} \neq \emptyset$ . An equivalent description of  $\mathcal{P}$  using its extreme points  $\{\mathbf{x}_p\}_{p \in P}$  and extreme rays  $\{\mathbf{x}_r\}_{r \in R}$  is:

$$\mathcal{P} = \left\{ \mathbf{x} \in \mathbb{R}^n \left| \begin{array}{ll} \sum_{p \in P} \mathbf{x}_p \lambda_p + \sum_{r \in R} \mathbf{x}_r \lambda_r = \mathbf{x} \\ \sum_{p \in P} \lambda_p = 1 \\ \lambda_p \geq 0 \quad \forall p \in P \\ \lambda_r \geq 0 \quad \forall r \in R \end{array} \right. \right\} \quad (2.1)$$

In the Nemhauser-Wolsey theorem, the conditions of the Minkowski-Weyl theorem are clearly encoded: the second and third lines ensure that the convex set of the extreme points are considered in the first line (Definition 2.2), the last playing a part in the span of extreme rays (Definition 2.4), and the first line being the Minkowski sum of the convex hull of extreme rays and the span of extreme rays.

## 2.2 Primal Simplex Algorithm

Have the following linear program in standard form:

$$\begin{aligned} \min \quad & \mathbf{c}^\top \mathbf{x} \\ \text{s. t.} \quad & \mathbf{Ax} = \mathbf{b} \quad [\pi] \\ & \mathbf{x} \geq \mathbf{0} \end{aligned} \tag{2.2}$$

The primal simplex algorithm finds an optimal solution by moving from one extreme point of the polyhedron to the next, therefore always remaining feasible. A central part of this algorithm is the sufficient optimality condition. For a basic solution  $\mathbf{X} = [\mathbf{x}_B, \mathbf{x}_N]$  at a given extreme point to be optimal, the reduced costs  $\bar{c}_j := c_j - \pi^\top \mathbf{a}_j$  for  $j \in N$  must be non-negative.

This sufficient optimality condition gives rise to the **pricing problem**, which either verifies the optimality of the current basic solution, and otherwise determines the non-basic variable  $x_l$ ,  $l \in N$  with the least reduced cost ( $\bar{c}_l < 0$ ) to be swapped into the basis next, according to Dantzig's rule (TODO cite). Formally, this can be written as:

$$l \in \arg \min_{j \in N} c_j - \pi^\top \mathbf{a}_j \tag{2.3}$$

Solving the pricing problem thus plays an integral role in the primal simplex algorithm:

---

**Algorithm 2.1:** Primal simplex algorithm with Dantzig's rule

---

**Input:** LP in standard form (2.2); Basic and non-basic index-sets  $B, N$

**Output:** Optimal Solution  $(\mathbf{x}, z)$

---

```

1 loop
2    $\pi^\top \leftarrow \mathbf{c}_B^\top \mathbf{A}_B^{-1}; \bar{\mathbf{b}} \leftarrow \mathbf{A}_B^{-1} \mathbf{b};$ 
3    $\bar{c}_j \leftarrow c_j - \pi^\top \mathbf{a}_j; \quad \forall j \in N$ 
4    $l \leftarrow \arg \min_{j \in N} \bar{c}_j; \bar{c}(\pi) \leftarrow \bar{c}_l;$ 
5   if  $\bar{c}(\pi) \geq 0$  then
6     return  $([\bar{\mathbf{b}}, \mathbf{0}], \mathbf{c}_B^\top \mathbf{x}_B)$  by optimality
7   end
8    $\bar{\mathbf{a}}_l \leftarrow \mathbf{A}_B^{-1} \mathbf{a}_l;$ 
9   if  $\bar{\mathbf{a}}_l \leq \mathbf{0}$  then
10    return None by unboundedness
11  end
12   $s \leftarrow \arg \min_{i \in \{1, \dots, m\}} \frac{\bar{b}_i}{\bar{a}_{il}}; x_l \leftarrow \frac{\bar{b}_s}{\bar{a}_{sl}}; B \leftarrow B \cup \{l\} \subseteq \{s\}; N \leftarrow N \cup \{s\} \subseteq \{l\};$ 

```

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# Chapter 3

## Column Generation and Branch-and-Price

3.1 Column Generation

3.2 Dantzig-Wolfe Reformulation

3.3 Dantzig-Wolfe Reformulation for Mixed Integer Programs

3.4 Branch-and-Price

3.5 Branch-Price-and-Cut

3.6 Dual Value Stabilization



# Chapter 4

## SCIP Optimization Suite

### 4.1 SCIP

### 4.2 GCG





# Chapter 5

## Component Bound Branching

### 5.1 Overview of the branching scheme

### 5.2 Separation Procedure

### 5.3 Parameterizations

*Which block to separate in? Which components to branch on?*



# Chapter 6

## Master Constraints without corresponding Original Problem Constraints

- 6.1 Definition of the Generic Mastercuts
- 6.2 Application of the Generic Mastercuts
- 6.3 Dual Value Stabilization for Generic Mastercuts
- 6.4 Mastervariable Synchronization across the entire B&B-Tree
  - 6.4.1 Problem Statement
  - 6.4.2 Current Approach used by the Implementation of Vanderbeck's Generic Branching
  - 6.4.3 History Tracking Approach
  - 6.4.4 History Tracking using Unrolled Linked Lists Approach



# Chapter 7

## Implementation

### 7.1 Generic Mastercuts

### 7.2 Mastervariable Synchronization

### 7.3 Component Bound Branching



# Chapter 8

## Evaluation





# Chapter 9

## Conclusion



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