Knowledge Representation & Reasoning COMP9016

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Constraint Satisfaction Problems

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Outline

"In which we see how treating states as more than just little black boxes leads to the invention of a range of powerful new search methods and a deeper understanding of problem structure and complexity"

>> CSP examples

>> Backtracking search for CSPs

>> Problem structure and problem decomposition

>> Local search for CSPs

Constraint satisfaction problems (CSPs)

>> Standard search problem:

state is a "black box"—any old data structure that supports goal test, eval, successor

>> CSP:

state is defined by **variables** $\boldsymbol{X_i}$ with **values** from **domain** $\boldsymbol{D_i}$

goal test is a set of **constraints** specifying

allowable combinations of values for subsets of variables

Simple example of a **formal representation language**

Allows useful **general-purpose** algorithms with more power than standard search algorithms

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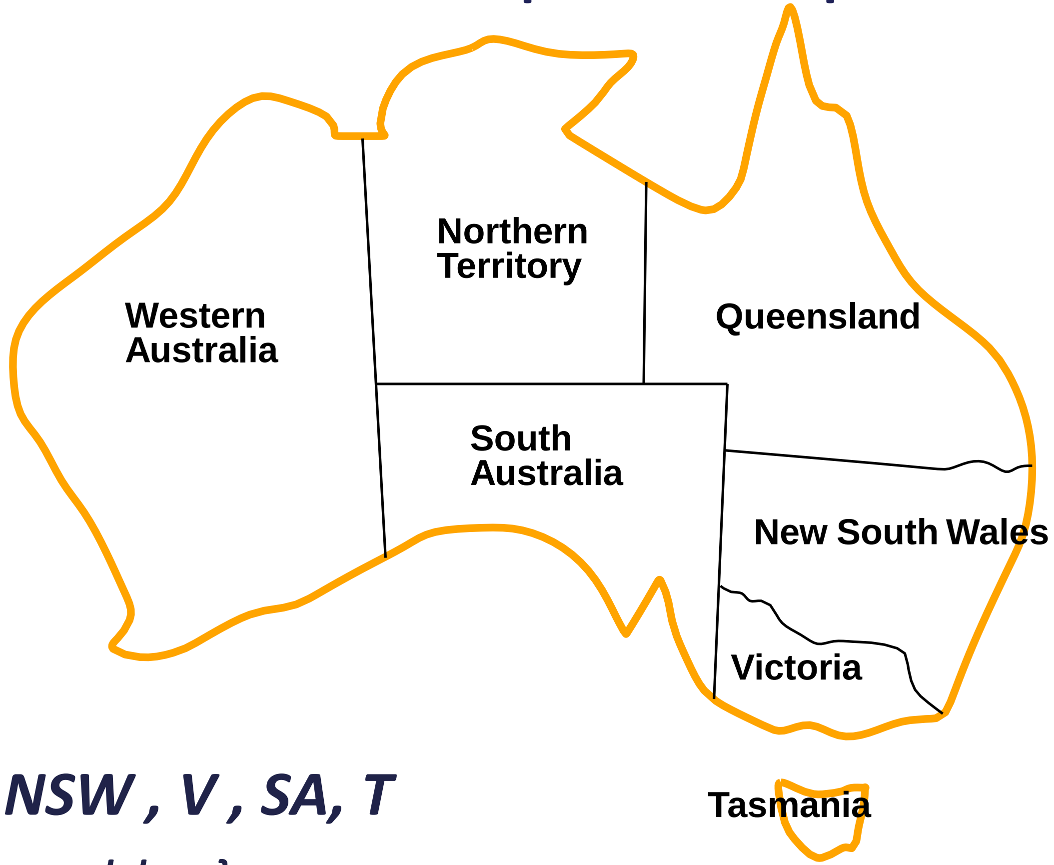
Example: Map-Coloring

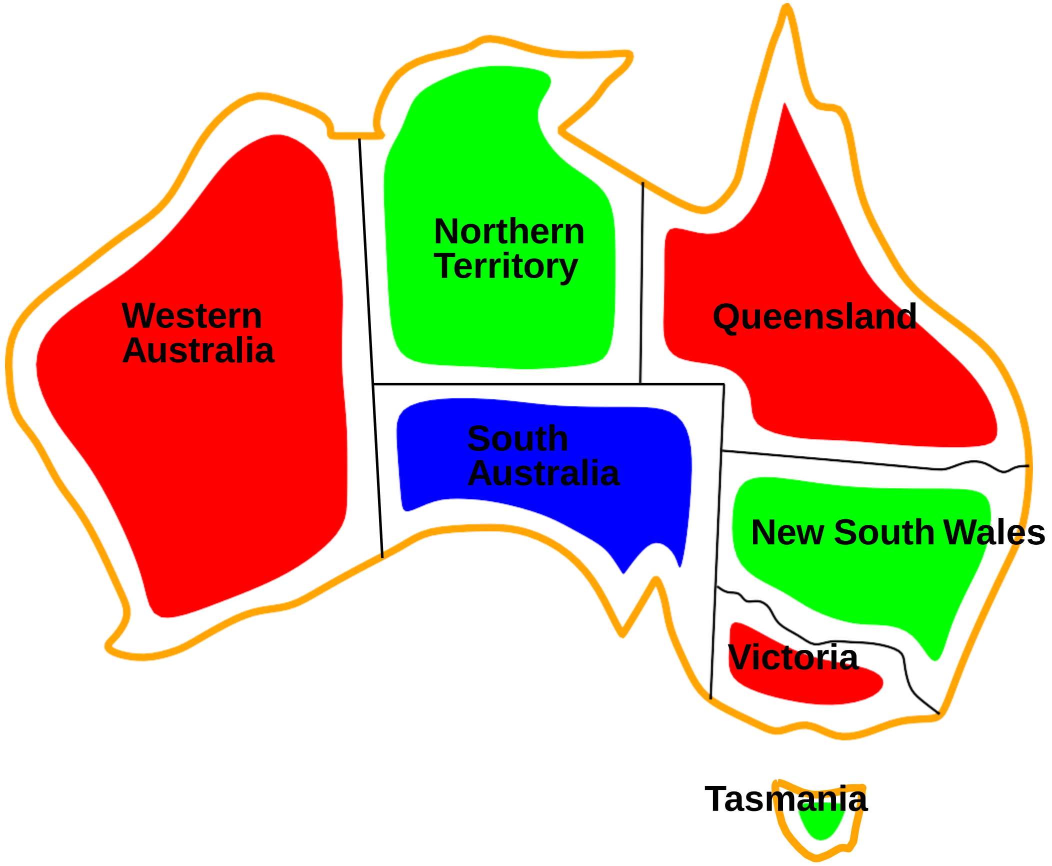


>> **Variables:** ***WA, NT , Q, NSW , V , SA, T***

>> **Domains:** ***D_i*** = *{red, green, blue}*

>> **Constraints**: adjacent regions must have different colors e.g., ***WA != NT*** (if the language allows this), or ***(WA, NT) ∈{(red, green), (red, blue), (green, red), (green, blue), . . .}***

Example: Map-Coloring contd.



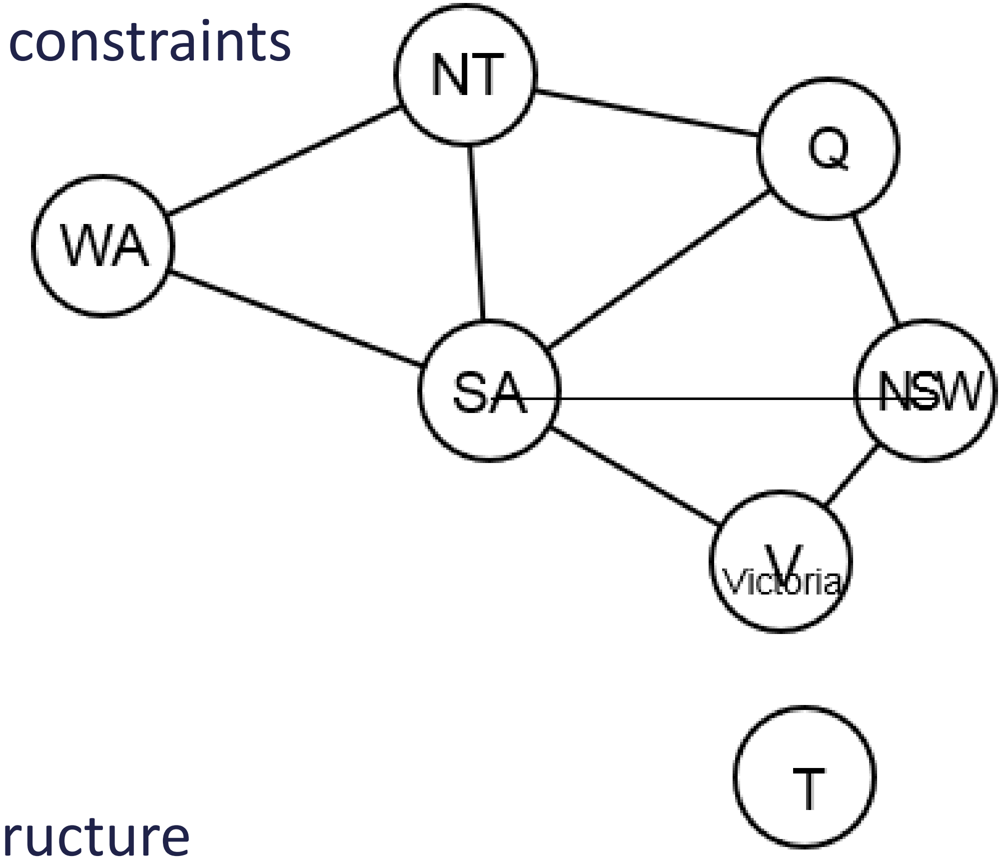
>> Solutions are assignments satisfying all constraints, e.g.,

{WA = red, NT = green, Q = red, NSW = green, V = red, SA = blue, T = green}

Constraint graph

>> **Binary CSP:** each constraint relates at most two variables

>> **Constraint graph:** nodes are variables, arcs show constraints



>> General-purpose CSP algorithms use the graph structure to speed up search. E.g., Tasmania is an independent subproblem!

Varieties of CSPs

\>> Discrete variables

finite domains; size $\boldsymbol{d} \Rightarrow \boldsymbol{O(d^n)}$ complete assignments

\> e.g., Boolean CSPs, incl. Boolean satisfiability (NP-complete) infinite domains (integers, strings, etc.)

\> e.g., job scheduling, variables are start/end days for each job

\> need a **constraint language**, e.g., $\boldsymbol{StartJob_1 + 5 \leq StartJob_3}$

\> **linear** constraints solvable, **nonlinear** undecidable

\>> Continuous variables

\> e.g., start/end times for Hubble Telescope observations

\> linear constraints solvable in poly time by LP methods

Varieties of constraints

>> **Unary** constraints involve a single variable,

e.g., ***SA != green***

>> ***Binary*** constraints involve pairs of variables,

e.g., ***SA != WA***

>> ***Higher-order*** constraints involve 3 or more variables,

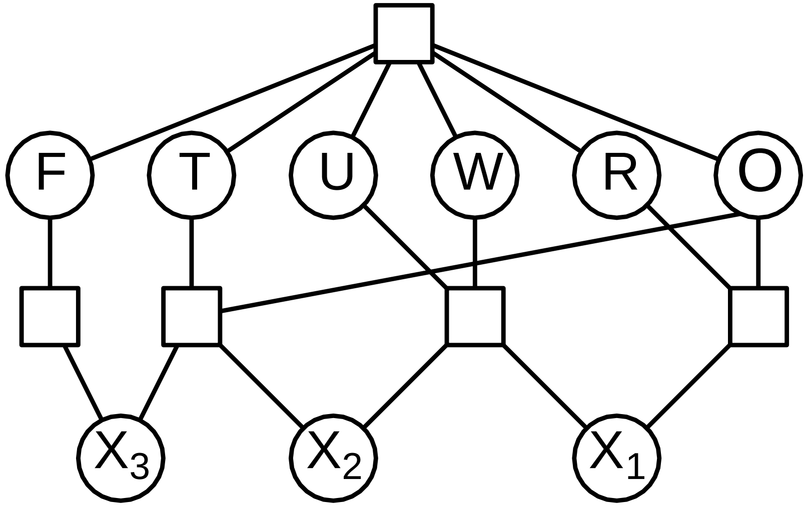
e.g., cryptarithmetic column constraints

>> **Preferences** (soft constraints), e.g., ***red*** is better than ***green*** often representable by a cost for each variable assignment

→ constrained optimization problems

Example: Cryptarithmetic

$$
\begin{array}{cccc}
 & T & W & O \\
+ & T & W & O \\
\hline
F & O & U & R
\end{array}
$$



>> Variables: ***F T U W R O X_1 X_2 X_3***

>> Domains: ***{0, 1, 2, 3, 4, 5, 6, 7, 8, 9}***

>> Constraints:

alldiff(F, T, U, W, R, O)

$O + O = R + 10 \cdot X_1$, etc.

Real-world CSPs

>> Assignment problems

e.g., who teaches what class

>> Timetabling problems

e.g., which class is offered when and where?

> Hardware configuration

> Spreadsheets

> Transportation scheduling

> Factory scheduling

> Floorplanning

Notice that many real-world problems involve real-valued variables

Standard search formulation (incremental)

>> Let's start with the straightforward, dumb approach, then fix it. States are defined by the values assigned so far

> **Initial state**: the empty assignment, ***{ }***

> **Successor function**: assign a value to an unassigned variable that does not conflict with current assignment $\Rightarrow$ fail if no legal assignments (not fixable!)

> **Goal test**: the current assignment is complete

1) This is the same for all CSPs!

2) Every solution appears at depth n with n variables

$\Rightarrow$ use depth-first search

3) Path is irrelevant, so can also use complete-state formulation

4) $b = (n - L)d$ at depth L, hence $n!d^n$ leaves!!!!

Backtracking search

>> Variable assignments are ***commutative***, i.e.,

[***WA = red*** then ***NT = green***] same as [***NT = green*** then ***WA = red***]

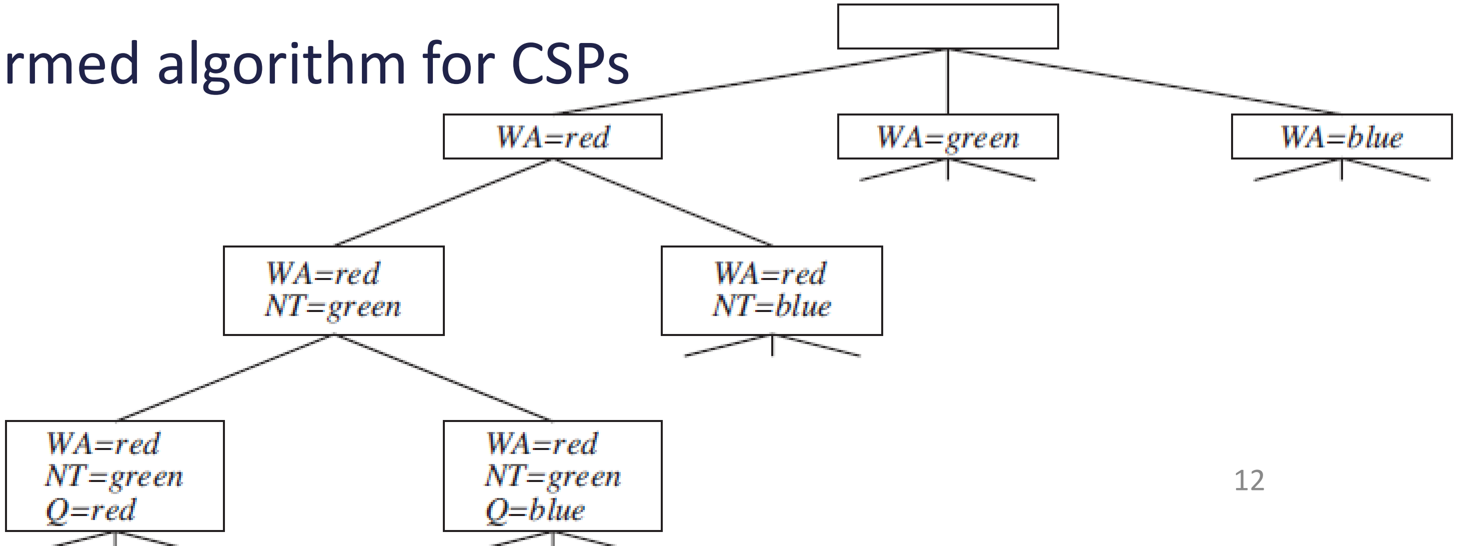
>> Only need to consider assignments to a single variable at each node

$\Rightarrow$ ***b = d*** and there are d^n leaves

>> Depth-first search for CSPs with single-variable assignments is called backtracking search

>> Backtracking search is the basic uninformed algorithm for CSPs

>> Can solve ***n***-queens for $n \approx 25$

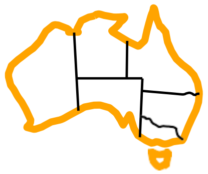


Backtracking search

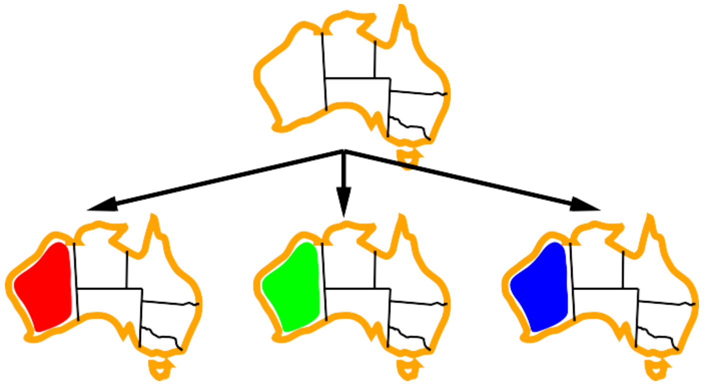
```
function Backtracking-Search(csp) returns solution/failure
    return Recursive-Backtracking({}, csp)

function Recursive-Backtracking(assignment, csp) returns soln/failure
    if assignment is complete then return assignment
    var ← Select-Unassigned-Variable(Variables[csp], assignment, csp)
    for each value in Order-Domain-Values(var, assignment, csp) do
        if value is consistent with assignment given Constraints[csp] then
            add {var = value} to assignment
            result ← Recursive-Backtracking(assignment, csp)
            if result /= failure then return result
            remove {var = value} from assignment
    return failure
```

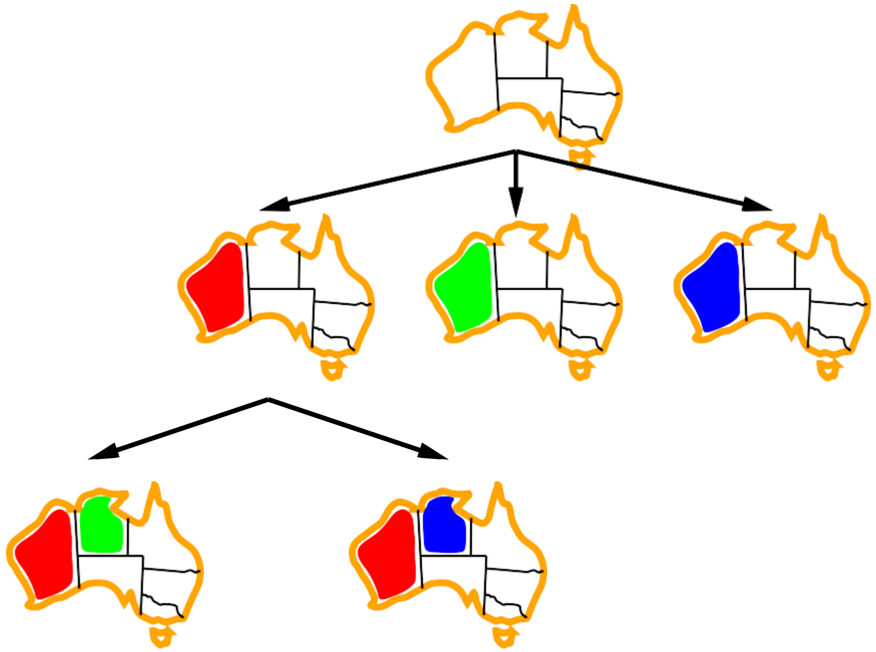
Backtracking example



Backtracking example



Backtracking example



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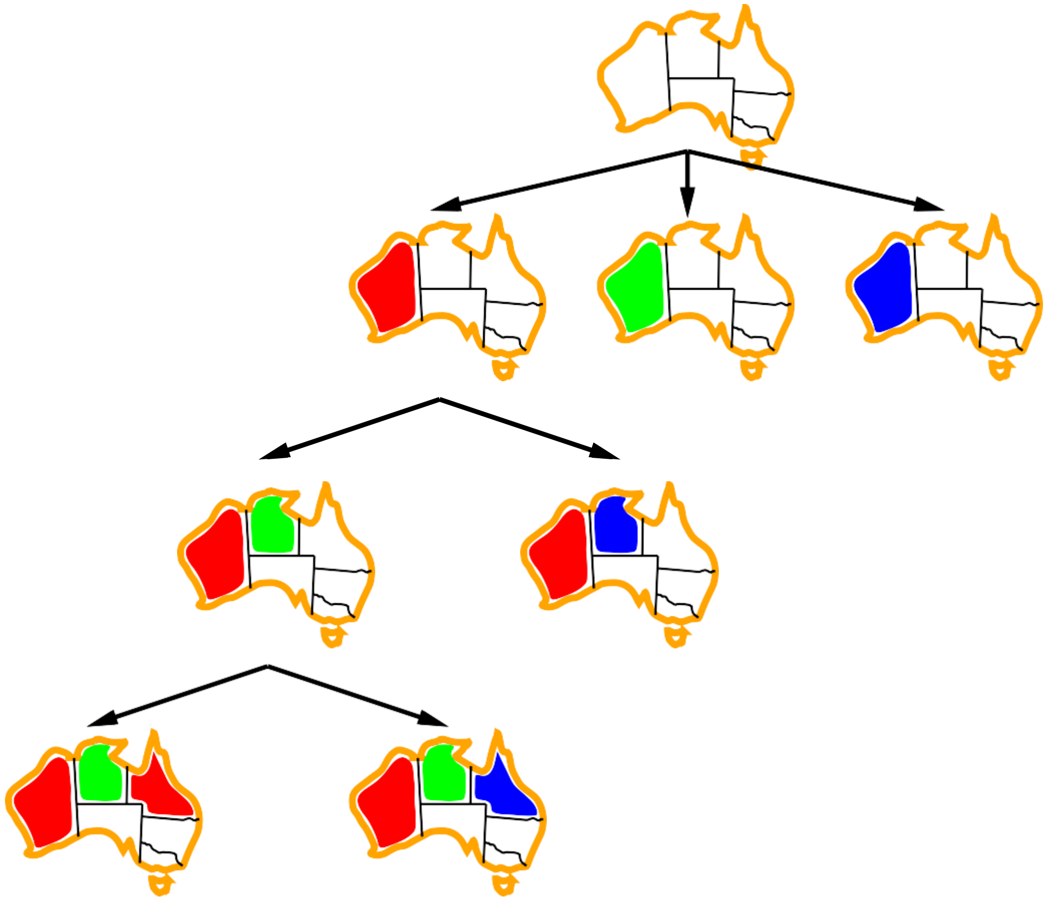


Improving backtracking efficiency

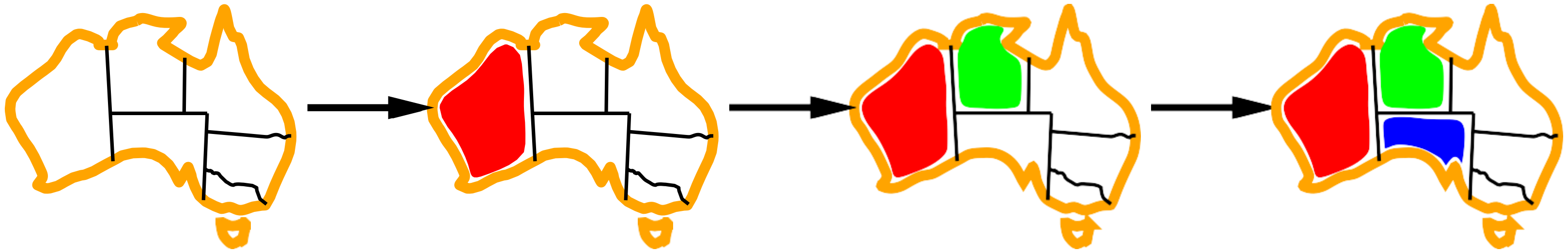
>> **General-purpose** methods can give huge gains in speed:

1) Which variable should be assigned next?
2) In what order should its values be tried?
3) Can we detect inevitable failure early?
4) Can we take advantage of problem structure?

Minimum remaining values

>> Minimum remaining values (MRV):

choose the variable with the fewest legal values

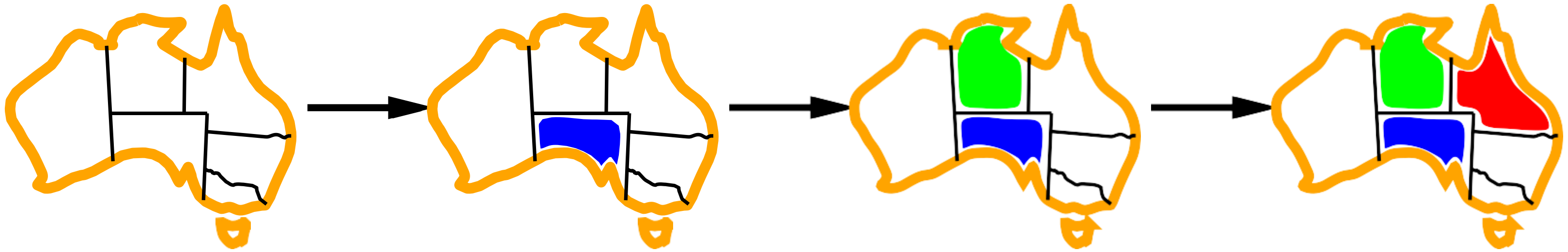


Degree heuristic

\>> Tie-breaker among MRV variables

\>>Degree heuristic:

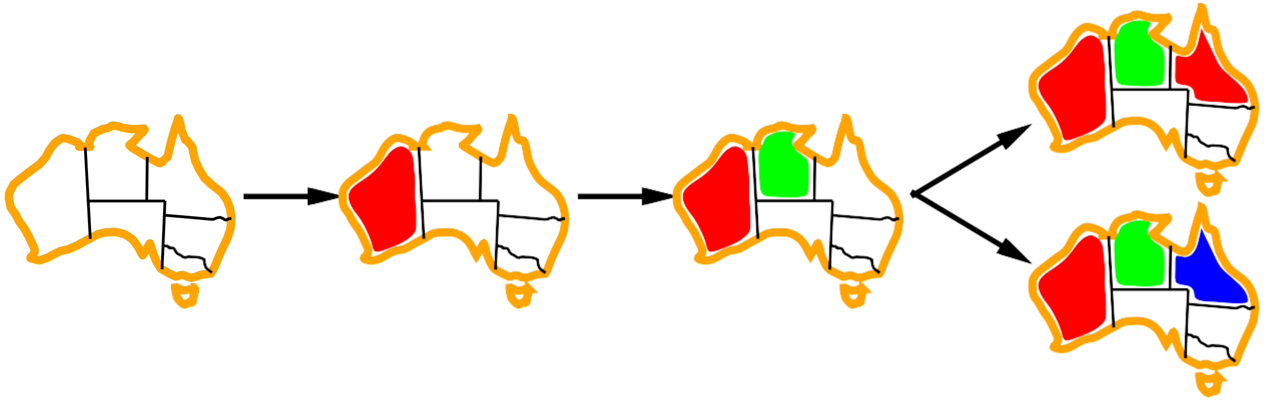
choose the variable with the most constraints on remaining variables



Least constraining value

>> Given a variable, choose the least constraining value:

the one that rules out the fewest values in the remaining variables



Allows 1 value for SA

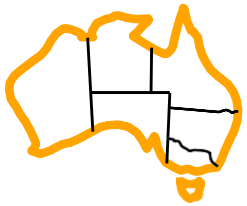
Allows 0 value for SA

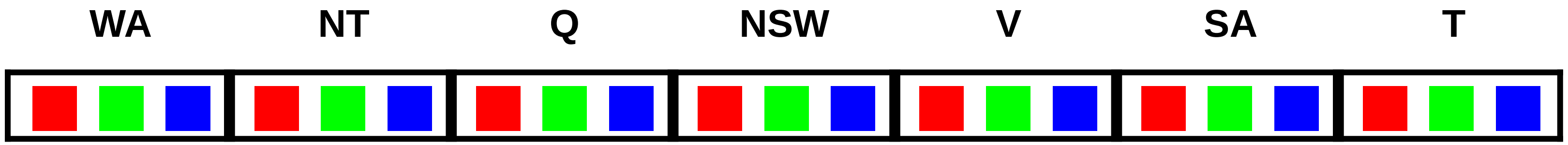
>> Combining these heuristics makes 1000 queens feasible

Forward checking

>> Idea: Keep track of remaining legal values for unassigned variables

Terminate search when any variable has no legal values





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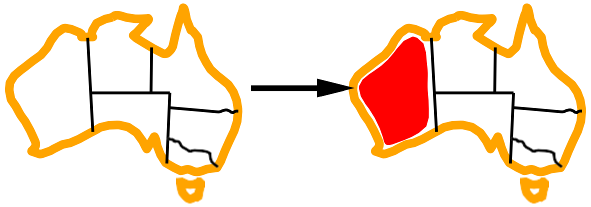

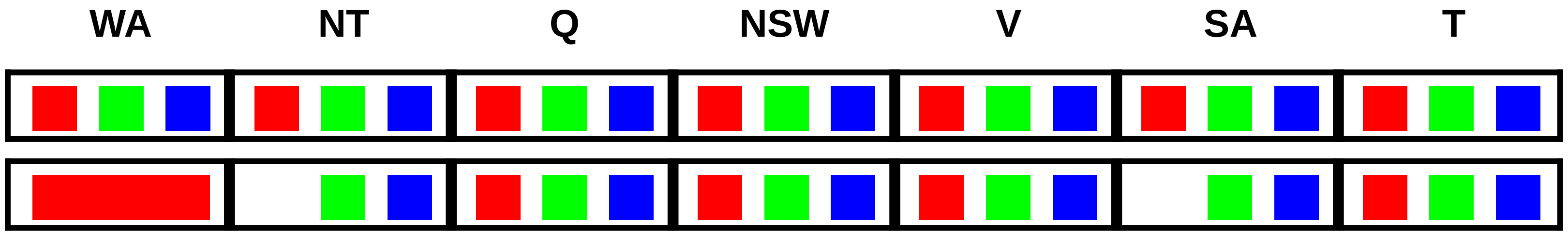

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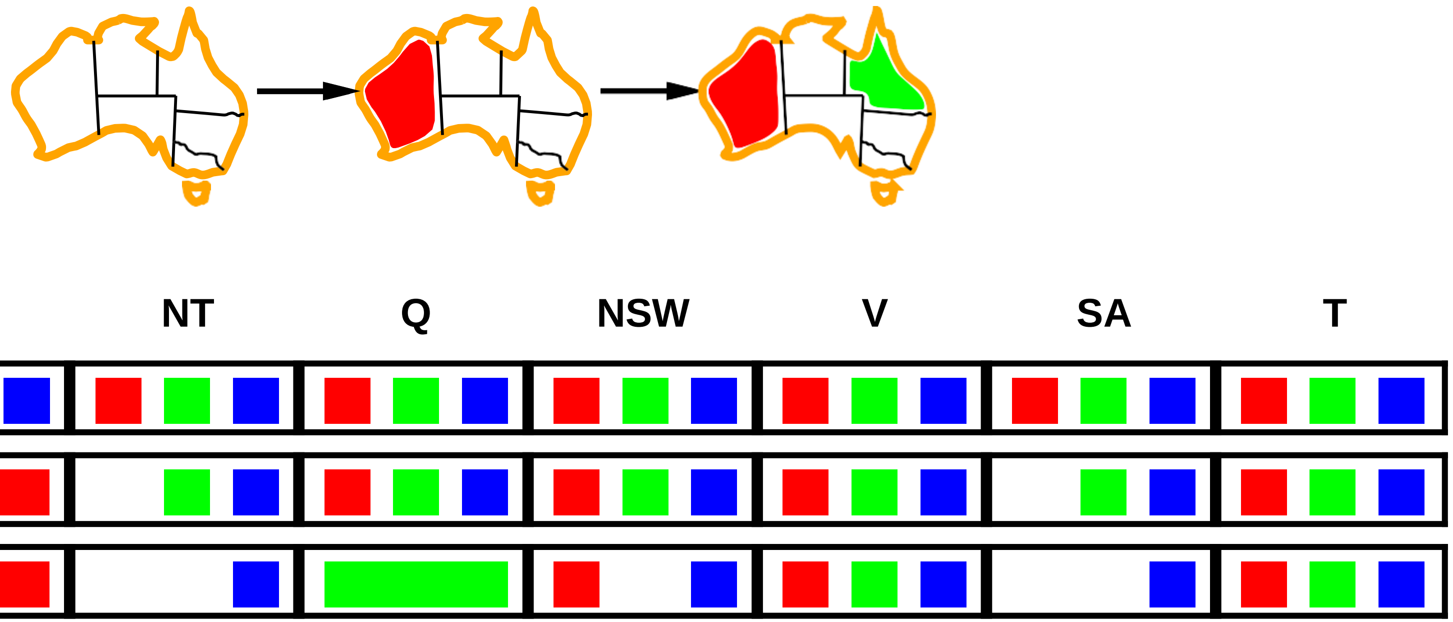

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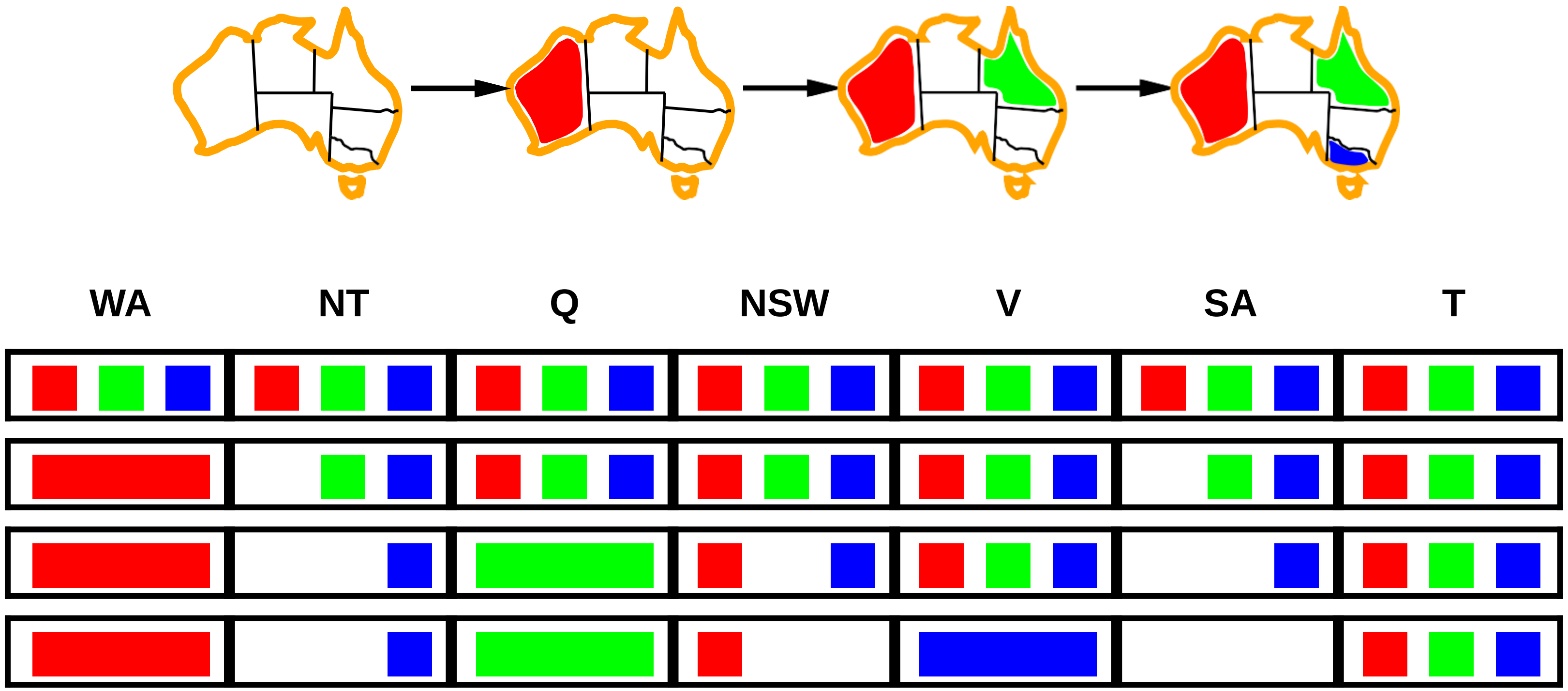
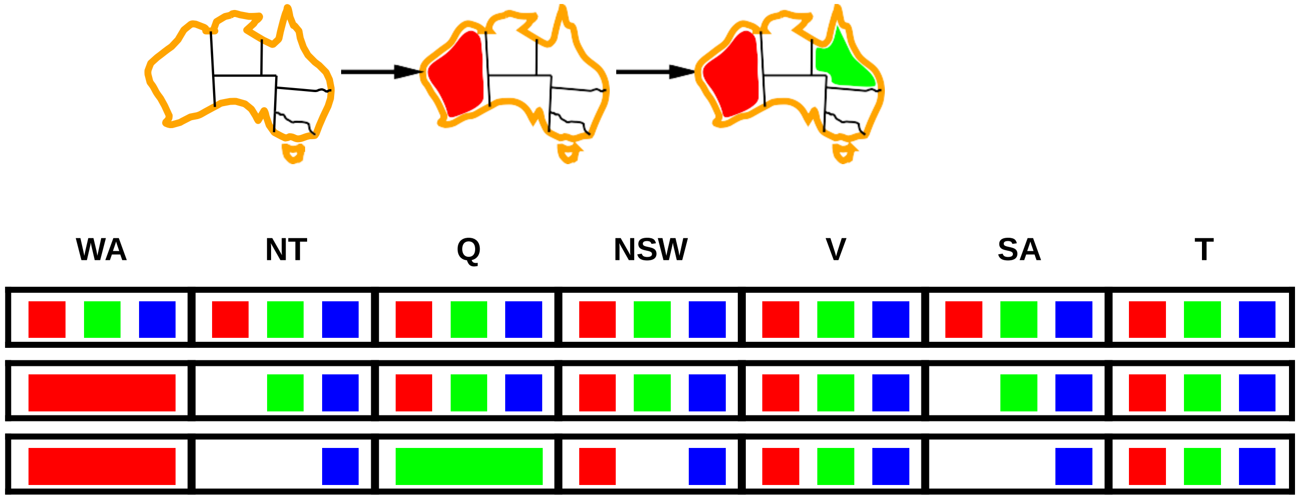


Constraint propagation

>> Forward checking propagates information from assigned to unassigned variables, but doesn't provide early detection for all failures:



>> **NT** and **SA** cannot both be blue!

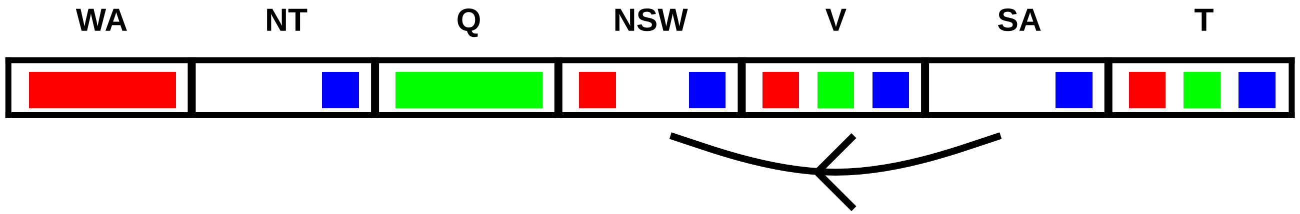
>> **Constraint propagation** repeatedly enforces constraints locally

Arc consistency

>> Simplest form of propagation makes each arc **consistent**

X* → *Y is consistent iff

for **every** value **x** of **X** there is **some** allowed **y**



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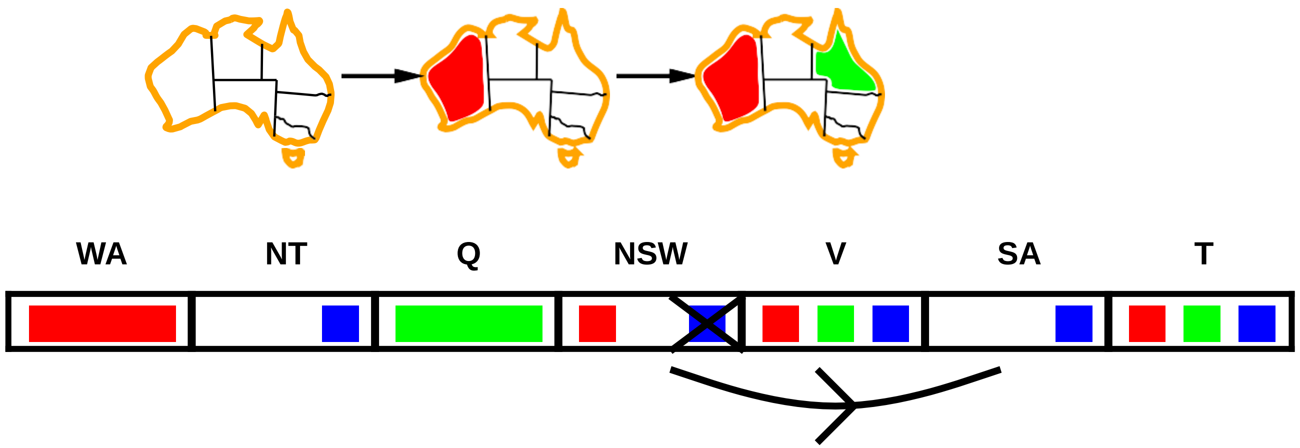

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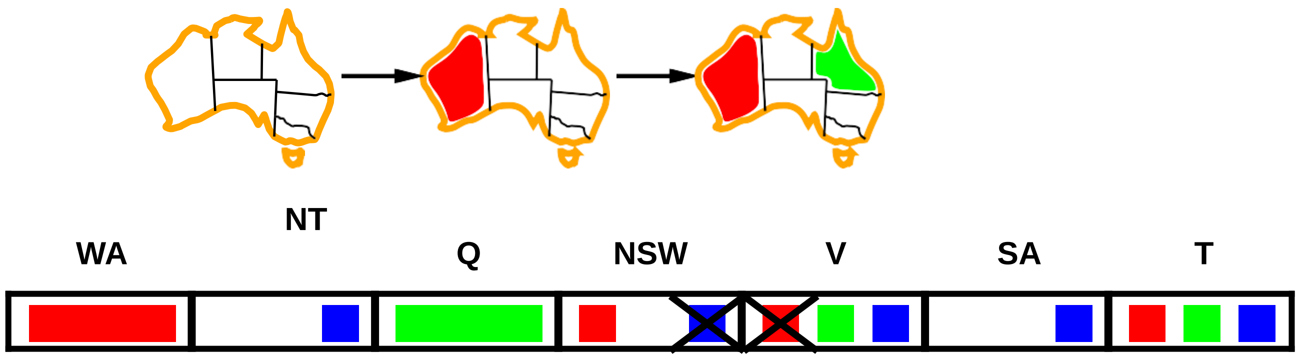

If ***X*** loses a value, neighbors of ***X*** need to be rechecked

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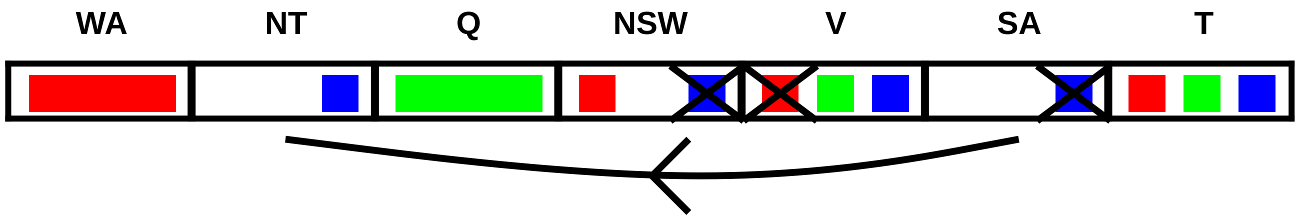


>> If ***X*** loses a value, neighbors of ***X*** need to be rechecked

>> Arc consistency detects failure earlier than forward checking

>> Can be run as a preprocessor or after each assignment

Arc consistency algorithm

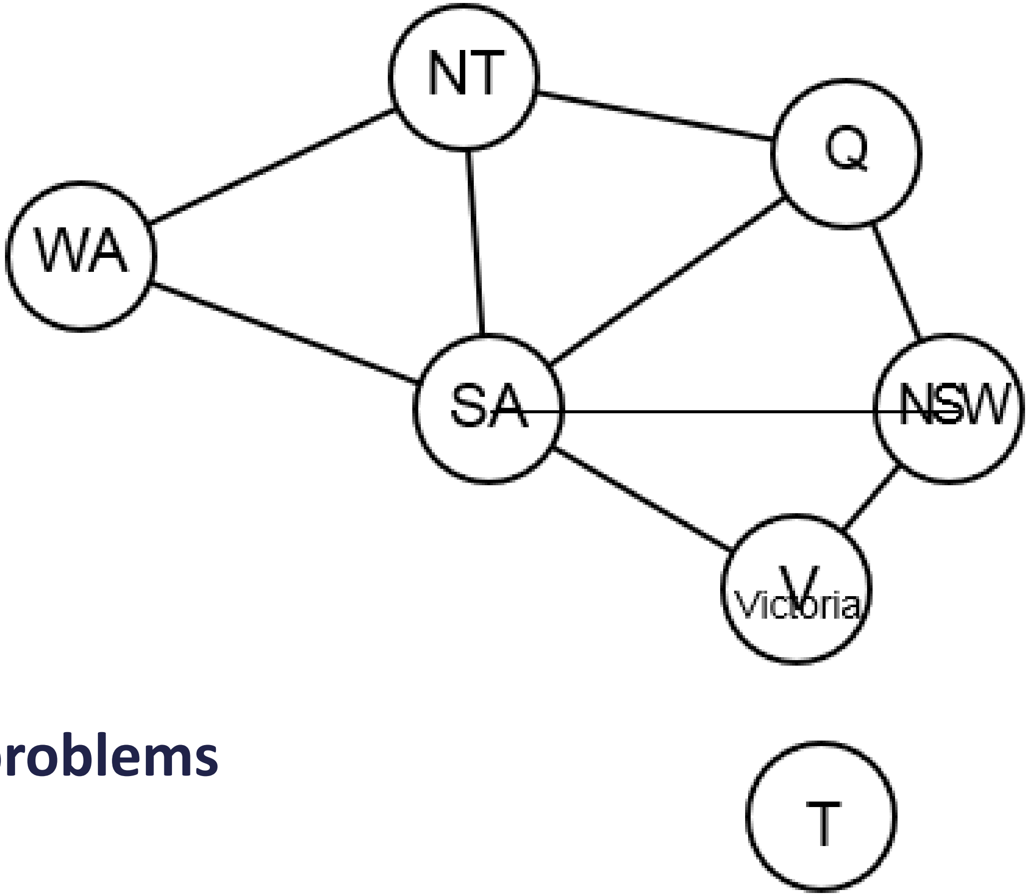
```
function AC-3( csp) returns the CSP, possibly with reduced domains
   inputs: csp, a binary CSP with variables {X1, X2, . . . , Xn}
   local variables: queue, a queue of arcs, initially all the arcs in csp

   while queue is not empty do
      (Xi, Xj) ← Remove-First(queue)
      if Remove-Inconsistent-Values(Xi, Xj )then
         for each Xk in Neighbors[Xi] do
            add (Xk, Xi) to queue
```

```
function Remove-Inconsistent-Values( Xi, Xj) returns true iff succeeds
   removed ← false
   for each x in Domain[Xi] do
      if no value y in Domain[Xj] allows (x,y) to satisfy the constraint Xi ↔ Xj
         then delete x from Domain[Xi]; removed ← true
   return removed
```

>> ***$O(n^2d^3)$***, can be reduced to ***$O(n^2d^2)$*** (but detecting **all** is NP-hard)

Problem structure



>> Tasmania and mainland are **independent subproblems**

>> Identifiable as **connected components** of constraint graph

Problem structure contd.

>> Suppose each subproblem has ***c*** variables out of ***n*** total

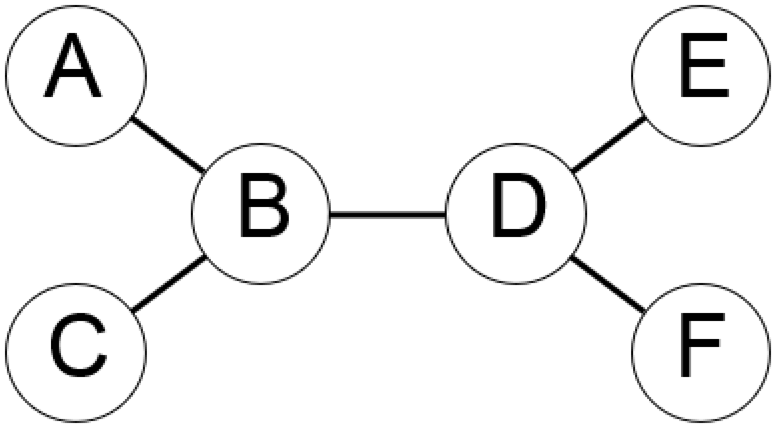
Worst-case solution cost is $n/c \cdot d^c$, linear in ***n***

E.g., $n = 80, d = 2, c = 20$

2^{80} = 4 billion years at 10 million nodes/sec

$4 \cdot 2^{20}$ = 0.4 seconds at 10 million nodes/sec

Tree-structured CSPs



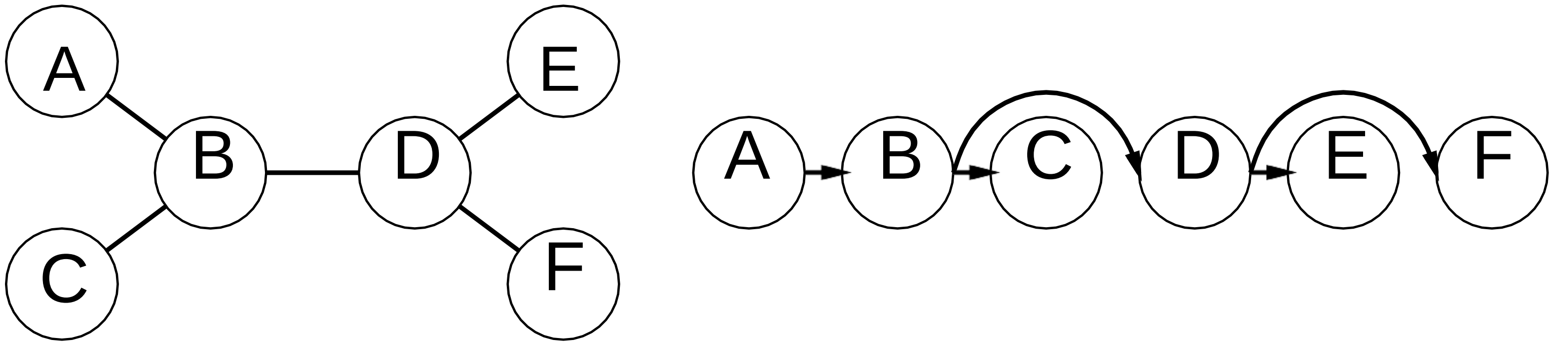
>> Theorem: if the constraint graph has no loops, the CSP can be solved in **$O(n\ d^2)$** time

Compare to general CSPs, where worst-case time is **$O(d^n)$**

This property also applies to logical and probabilistic reasoning: an important example of the relation between syntactic restrictions and the complexity of reasoning.

Algorithm for tree-structured CSPs

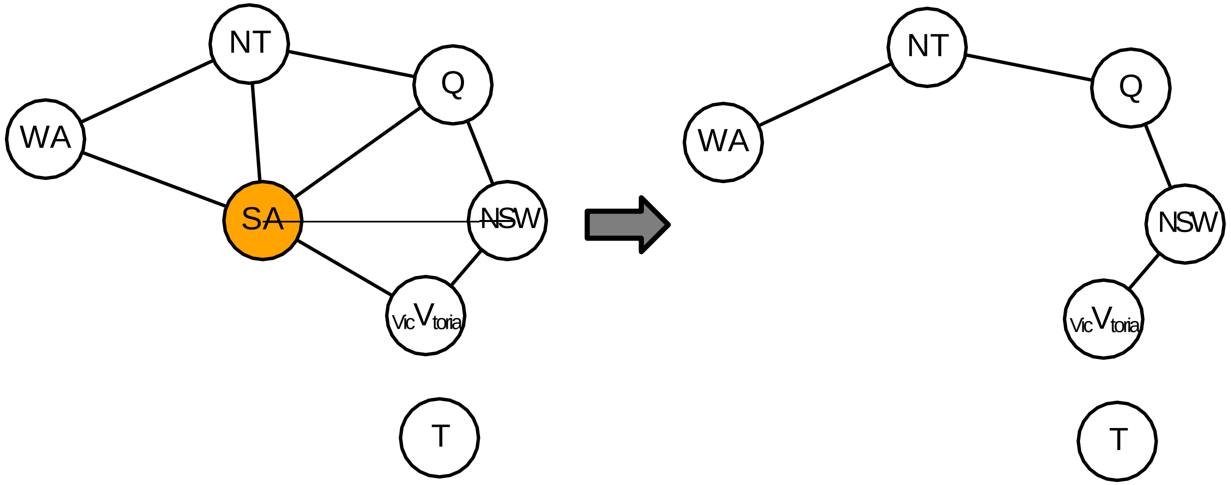
1) Choose a variable as root, order variables from root to leaves such that every node's parent precedes it in the ordering



2) For j from n down to 2, apply *RemoveInconsistent*($\boldsymbol{Parent(X_j)}, \boldsymbol{X_j}$)
3) For j from 1 to n, assign $\boldsymbol{X_j}$ consistently with $\boldsymbol{Parent(X_j)}$

Nearly tree-structured CSPs

>> **Conditioning**: instantiate a variable, prune its neighbors' domains



>> **Cutset conditioning**: instantiate (in all ways) a set of variables such that the remaining constraint graph is a tree

Cutset size **c** ⇒ runtime $\mathbf{O(d^c \cdot (n - c)d^2)}$, very fast for small **c**

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Iterative algorithms for CSPs

>> Hill-climbing, simulated annealing typically work with "complete" states, i.e., all variables assigned

>> To apply to CSPs:

allow states with unsatisfied constraints operators **reassign** variable values

>> Variable selection: randomly select any conflicted variable

>> Value selection by **min-conflicts** heuristic:

choose value that violates the fewest constraints

i.e., hillclimb with ***h(n)*** = total number of violated constraints

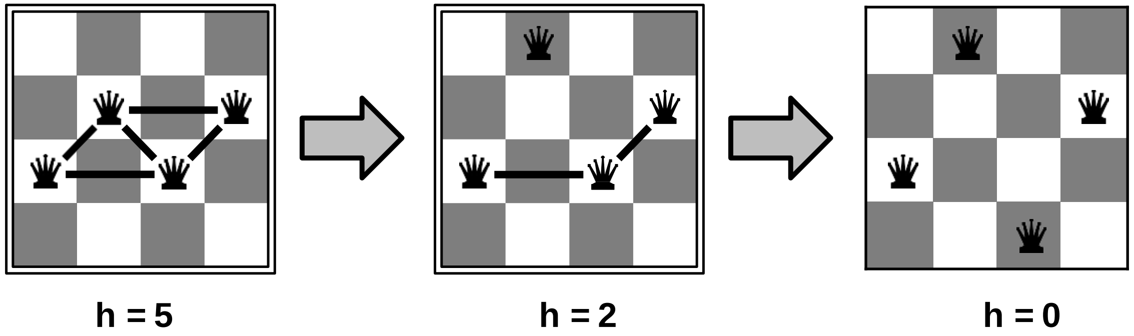
Example: 4-Queens

States: 4 queens in 4 columns (**4^4 = 256** states)

Operators: move queen in column

Goal test: no attacks

Evaluation: h(n) = number of attacks

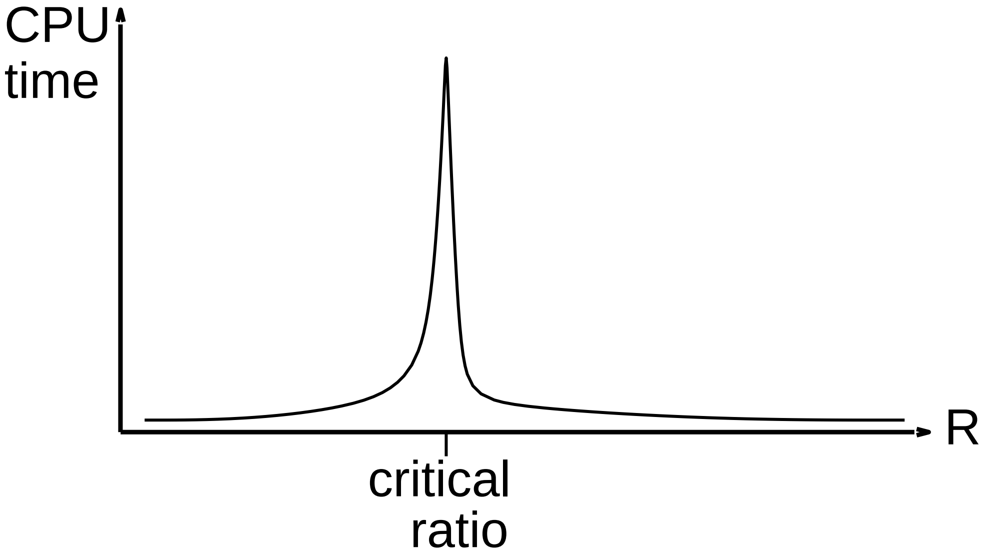


Performance of min-conflicts

>> Given random initial state, can solve **n**-queens in almost constant time for arbitrary **n** with high probability (e.g., n = 10,000,000)

>> The same appears to be true for any randomly-generated CSP ***except*** in a narrow range of the ratio

$$R = \frac{\text{number of constraints}}{\text{number of variables}}$$



Summary

- CSPs are a special kind of problem:
  - states defined by values of a fixed set of variables
  - goal test defined by constraints on variable values
- Backtracking = depth-first search with one variable assigned per node Variable ordering and value selection heuristics help significantly Forward checking prevents assignments that guarantee later failure Constraint propagation (e.g., arc consistency) does additional work
- to constrain values and detect inconsistencies
- The CSP representation allows analysis of problem structure Tree-structured CSPs can be solved in linear time
- Iterative min-conflicts is usually effective in practice

References

[1] Russell, S. and Norvig, P., 2002. Artificial intelligence: a modern approach CSPs, Chapter 6.

[2] – Lecture slides prepared by Russell, S.