

Operations Reserach 2 Final Thesis

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1 Introduction

In this thesis we will go over the implementation of the main heuristics involving the famous TSP problem. The entire implementation is done using the C programming language and the CPLEX optimization LP optimization framework.

1.1 The Traveling Salesman Problem

The Traveling Salesman Problem is among the most disussed and researched problems in the field of Operations Research.

Mathematical Formulation The TSP can be formulated as an optimization problem as follows:

$$\min \sum_{i=1}^n \sum_{j=1}^n c_{ij} x_{ij} \quad (1)$$

subject to:

$$\sum_{i=1}^n x_{ij} = 1 \quad \forall j \in \{1, \dots, n\} \quad (2)$$

$$\sum_{j=1}^n x_{ij} = 1 \quad \forall i \in \{1, \dots, n\} \quad (3)$$

$$u_i - u_j + nx_{ij} \leq n - 1 \quad \forall i \in \{2, \dots, n\}, j \in \{2, \dots, n\} \quad (4)$$

$$x_{ij} \in \{0, 1\} \quad \forall i, j \in \{1, \dots, n\} \quad (5)$$

$$u_i \in \text{text} \quad \forall i \in \{1, \dots, n\} \quad (6)$$

2 TSP data structure

Throught the implementation of the Metaheuristics and Mathheuristics, we will be using the following data structures:

- instance : A structure that holds the TSP instance data. This is implemented as a C data structure in which we hold all the metadata relevant to the loaded TSP instance.
- solution : A structure that holds the TSP solution data. Normally this is represented as a simple integer array in which we map for every nodex index its successor in the tour. This type of solution representation suits both the indirected and directed graph cases.

The code for the data structures implementation can be found in the appendixx section.

The cost functio used is the euclidean distance between two nodes in the graph. The code for the implementation can be found in the appendix section ??.

3 TSP Heuristics

3.1 Greedy Randomized Adaptive Search (GRASP)

The GRASP method is basically a greedy randomized adaptive search procedure. It consists of two main phases: construction and local search. In the construction phase, a feasible solution is built, one element at a time, in a greedy randomized fashion. In the local search phase, the neighborhood of the constructed solution is explored until a local minimum is found.

Construction Phase In the construction phase, the solution is built iteratively. At each iteration, a candidate list is created, containing the best elements to be added to the solution. One of these elements is chosen randomly, according to a probability distribution, and added to the solution.

Local Search Phase In the local search phase, the algorithm explores the neighborhood of the constructed solution to find a local minimum. This is done by iteratively replacing the current solution with a better solution from its neighborhood, until no better solution can be found.

Algorithm The GRASP algorithm can be summarized as follows:

1. **Initialization:** Set the best solution found to null.
2. **Construction:** Build a feasible solution using the greedy randomized approach.
3. **Local Search:** Improve the constructed solution using local search.
4. **Update:** If the improved solution is better than the best solution found, update the best solution.
5. **Termination:** Repeat steps 2-4 until a stopping criterion is met (e.g., a maximum number of iterations).

Implementation The GRASP algorithm is implemented as follows:

1. **Initialization:**
 - The function starts by recording the start time for performance measurement.
 - It logs the start of the GRASP process and details about the instance, including the number of nodes and their coordinates.
2. **Setup:**
 - The function initializes the current node index to the starting node (which is passed as an argument) and sets the remaining nodes count to the total number of nodes.
 - It allocates memory for the solution and remaining nodes arrays.
 - The solution array is initialized with -1 to indicate that no nodes have been visited yet.
 - The remaining nodes array is initialized with all node indices.
3. **Main Loop:**
 - The function iterates over all nodes to construct the solution.
 - For each node, it finds the nearest unvisited node using the `euclidean_nearest_node` function.
 - If no nearest node is found (i.e., all nodes are visited), it connects the current node back to the starting node to complete the tour.
 - Otherwise, it updates the solution with the nearest node and logs the current node index and nearest node found.
 - The current node index is updated to the nearest node for the next iteration.
4. **Finalization:**

- After constructing the solution, the function records the end time and calculates the elapsed time.
- It logs the total time taken and the cost of the solution.
- Finally, it frees the allocated memory for the remaining nodes array.

The code of the implementation can be found in the appendix section [A.1](#).

3.2 Extra Mileage

In the extra mileage heuristic, we try to build a valid tsp solution starting an edge of the graph and we try and build a tour by selecting the adjacent edge with the minimum cost.

Algorithm The extra mileage algorithm can be summarized as follows:

1. **Initialization:** Initialize the starting edge.
2. **Construction:** Build a feasible solution by iteratively selecting the edge with the minimum cost.
3. **Update:** If the improved solution is better than the best solution found, update the best solution.
4. **Termination:** Repeat steps 2-3 until a stopping criterion is met (e.g., a maximum number of iterations).

Implementation The extra mileage algorithm is implemented as follows:

1. **Initialization:**
 - The function starts by recording the start time for performance measurement.
 - It logs the start of the Extra Mileage process and details about the instance, including the number of nodes and their coordinates.
2. **Setup:**
 - The function initializes the solution with the most distant pair of nodes using the `euclidean_most_distant_pair` function.
 - It marks these nodes as covered and updates the solution to reflect this initial pair.
3. **Main Loop:**
 - While there are uncovered nodes:
 - For each covered node, it finds the nearest uncovered node that results in the smallest increase in the total tour length.
 - It updates the solution to include this node and marks it as covered.
4. **Finalization:**
 - Once all nodes are covered, the function calculates the total cost of the solution.
 - It records the end time and calculates the elapsed time.
 - It logs the total time taken and the cost of the solution.

the code for the implementation can be found in the appendix section [A.2](#).

3.3 Tabu Search

4 TSP with CPLEX

4.1 Bender's subtour elimination method

4.2 Patching Heuristic

4.3 CPLEX Callback implementation

References

A Metaheuristics

A.1 GRASP

```
1 void tsp_grasp(instance* inst, int starting_node) {
2     clock_t start_time = clock();
3     log_message(LOG_LEVEL_INFO, "Solving TSP with GRASP\n");
4     log_message(LOG_LEVEL_INFO, "Instance details: nnodes = %d\n", inst->nnodes);
5     for (int i = 0; i < inst->nnodes; i++) {
6         log_message(LOG_LEVEL_INFO, "Node %d: (%f, %f)\n", i, inst->xcoord[i],
inst->ycoord[i]);
7     }
8     log_message(LOG_LEVEL_INFO, "Starting GRASP with starting node %d\n",
starting_node);
9
10    int current_node_index = starting_node;
11    int remaining_nodes_count = inst->nnodes;
12    solution nearest_node;
13    int* remaining_nodes = (int*)malloc(inst->nnodes * sizeof(int));
14
15    inst->solution = (int*)malloc(inst->nnodes * sizeof(int));
16    inst->best_cost_value = 0;
17
18    // Initialize solution
19    for (int i = 0; i < inst->nnodes; i++) {
20        inst->solution[i] = -1;
21        remaining_nodes[i] = i;
22    }
23
24    remaining_nodes[current_node_index] = remaining_nodes[--remaining_nodes_count
];
25
26    for (int i = 0; i < inst->nnodes; i++) {
27        log_message(LOG_LEVEL_INFO, "Current node index: %d\n", current_node_index
);
28        nearest_node = euclidean_nearest_node(inst, current_node_index,
remaining_nodes, &remaining_nodes_count);
29
30        if (nearest_node.node == -1) {
31            inst->solution[current_node_index] = starting_node;
32            inst->best_cost_value += euclidean_distance(inst->xcoord[
current_node_index],
33                                                         inst->ycoord[
current_node_index],
34                                                         inst->xcoord[starting_node
],
35                                                         inst->ycoord[starting_node
], false);
36            continue;
37        }
38        inst->solution[current_node_index] = nearest_node.node;
39        inst->best_cost_value += nearest_node.cost;
40        current_node_index = nearest_node.node;
41    }
42
43    clock_t end_time = clock();
44    double elapsed_time = ((double) (end_time - start_time)) / CLOCKS_PER_SEC;
45    inst->elapsed_time = elapsed_time;
46    log_message(LOG_LEVEL_INFO, "GRASP solution time: %f seconds\n", elapsed_time)
;
47    log_message(LOG_LEVEL_INFO, "GRASP solution cost: %f\n", inst->best_cost_value
);
48
49    free(remaining_nodes);
50 }
```

A.2 Extra Mileage

```
1 void tsp_extra_mileage(instance* inst, pair starting_pair)
2 {
3     clock_t start_time = clock();
4     log_message(LOG_LEVEL_INFO, "Solving TSP with Extra Mileage\n");
5     log_message(LOG_LEVEL_INFO, "Instance details: nnodes = %d\n", inst->nnodes);
6     for (int i = 0; i < inst->nnodes; i++) {
7         log_message(LOG_LEVEL_INFO, "Node %d: (%f, %f)\n", i, inst->xcoord[i], inst->
8         ycoord[i]);
9     }
10
11     heuristic_state state;
12     pair current_pair = starting_pair;
13
14     initialize_instance(inst, &state);
15
16     inst->solution[current_pair.node1] = current_pair.node2;
17     inst->solution[current_pair.node2] = current_pair.node1;
18     state.covered_nodes[state.covered_nodes_count++] = current_pair.node1;
19     state.covered_nodes[state.covered_nodes_count++] = current_pair.node2;
20     state.uncovered_nodes[current_pair.node1] = state.uncovered_nodes[--state.
21     uncovered_nodes_count];
22     state.uncovered_nodes[current_pair.node2] = state.uncovered_nodes[--state.
23     uncovered_nodes_count];
24
25     while (state.covered_nodes_count < inst->nnodes)
26     {
27         log_message(LOG_LEVEL_INFO, "Covered nodes count: %d\n", state.
28         covered_nodes_count);
29         solution best_node;
30         for (int i = 0; i < state.covered_nodes_count; i++)
31         {
32             log_message(LOG_LEVEL_INFO, "Current node index: %d\n", i);
33             int current_node = state.covered_nodes[i];
34             int current_node_opposite = inst->solution[current_node];
35             double min_distance_delta = INFINITY;
36             best_node.node = -1;
37             best_node.node_index = -1;
38             for (int j = 0; j < state.uncovered_nodes_count; j++)
39             {
40                 double distance1 = euclidean_distance(inst->xcoord[current_node],
41                 inst->ycoord[current_node],
42                 inst->xcoord[state.
43                 uncovered_nodes[j]],
44                 inst->ycoord[state.
45                 uncovered_nodes[j]], false);
46                 double distance2 = euclidean_distance(inst->xcoord[state.
47                 uncovered_nodes[j]],
48                 inst->ycoord[state.
49                 uncovered_nodes[j]],
50                 inst->xcoord[
51                 current_node_opposite],
52                 inst->ycoord[
53                 current_node_opposite], false);
54                 double existing_pair_distance = euclidean_distance(inst->xcoord[
55                 current_node],
56                 inst->ycoord[
57                 current_node],
58                 inst->xcoord[
59                 current_node_opposite],
60                 inst->ycoord[
61                 current_node_opposite], false);
62                 double distance_delta = distance1 + distance2 - existing_pair_distance
63                 ;
64                 if (distance_delta < min_distance_delta)
65                 {
66                     min_distance_delta = distance_delta;
67                     best_node.node = state.uncovered_nodes[j];
68                 }
69             }
70         }
71     }
72 }
```

```

55         best_node.node_index = j;
56         best_node.cost = distance_delta;
57     }
58 }
59 if (best_node.node > -1)
60 {
61     log_message(LOG_LEVEL_INFO, "Best node found: %d\n", best_node.node);
62     inst->solution[current_node] = best_node.node;
63     inst->solution[best_node.node] = current_node_opposite;
64     state.covered_nodes[state.covered_nodes_count++] = best_node.node;
65     state.uncovered_nodes[best_node.node_index] = state.uncovered_nodes[--
state.uncovered_nodes_count];
66 }
67 }
68 }
69
70 inst->best_cost_value = compute_solution_cost(inst, inst->solution);
71 clock_t end_time = clock();
72 double elapsed_time = ((double) (end_time - start_time)) / CLOCKS_PER_SEC;
73 inst->elapsed_time = elapsed_time;
74 log_message(LOG_LEVEL_INFO, "Extra Mileage solution time: %f seconds\n",
elapsed_time);
75 log_message(LOG_LEVEL_INFO, "Extra Mileage solution cost: %f\n", inst->
best_cost_value);
76 }

```