# FICO® Xpress Kalis Module for Mosel

13.4.3

REFERENCE MANUAL

FICO® Xpress Optimization

Artelys
solutions en optimisation

FICO®

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# Contents


1 Introduction 1
- 1.1 Contents of this manual . . . 1
- 1.2 Constraint programming overview . . . 1
- 1.3 What is Xpress Kalis for Mosel? . . . 2
- 1.4 Prerequisites . . . 3

I Paradigm 4

2 Decision variables 5

3 Constraints 7

4 Enumeration and search strategy 9

5 Scheduling 14
- 5.1 Tasks . . . 14
- 5.2 Resources . . . 16
- 5.3 Schedule . . . 17

6 Linear relaxations 21
- 6.1 Automatic relaxations . . . 21
- 6.2 User defined relaxations . . . 22
- 6.3 Usage of relaxations . . . 23
- 6.4 Branching with relaxation . . . 24
- 6.5 A simple hybrid example . . . 24

II Reference Manual 28

7 Constants 29
- KALIS_FORWARD_CHECKING . . . 32
- KALIS_GEN_ARC_CONSISTENCY . . . 32
- KALIS_SLIM_UNREACHED . . . 32
- KALIS_SLIM_BY_NODES . . . 32
- KALIS_SLIM_BY_SOLUTIONS . . . 33
- KALIS_SLIM_BY_DEPTH . . . 33
- KALIS_SLIM_BY_TIME . . . 33
- KALIS_SLIM_BY_BACKTRACKS . . . 33
- KALIS_TLIM_UNREACHED . . . 34

KALIS_TLIM_ABS_OPT . . . 34
KALIS_TLIM_REL_OPT . . . 34
KALIS_INPUT_ORDER . . . 34
KALIS_MAX_DEGREE . . . 35
KALIS_LARGEST_MIN . . . 35
KALIS_LARGEST_MAX . . . 35
KALIS_MAXREGRET_LB . . . 36
KALIS_MAXREGRET_UB . . . 36
KALIS_RANDOM_VARIABLE . . . 36
KALIS_SDOMDEG_RATIO . . . 36
KALIS_SMALLEST_DOMAIN . . . 37
KALIS_SMALLEST_MAX . . . 37
KALIS_SMALLEST_MIN . . . 37
KALIS_WIDEST_DOMAIN . . . 38
KALIS_MAX_TO_MIN . . . 38
KALIS_MIN_TO_MAX . . . 38
KALIS_MIDDLE_VALUE . . . 38
KALIS_NEAREST_VALUE . . . 39
KALIS_RANDOM_VALUE . . . 39
KALIS_RANDOM_SEED . . . 39
KALIS_COPYRIGHT . . . 39
KALIS_UNARY_RESOURCE . . . 40
KALIS_DISCRETE_RESOURCE . . . 40
KALIS_SMALLEST_ECT . . . 40
KALIS_SMALLEST_EST . . . 40
KALIS_SMALLEST_LCT . . . 41
KALIS_SMALLEST_LST . . . 41
KALIS_LARGEST_ECT . . . 41
KALIS_LARGEST_EST . . . 41
KALIS_LARGEST_LCT . . . 42
KALIS_LARGEST_LST . . . 42
KALIS_TASK_INPUT_ORDER . . . 42
KALIS_TASK_RANDOM_ORDER . . . 42
KALIS_DISJ_INPUT_ORDER . . . 43
KALIS_DISJ_PRIORITY_ORDER . . . 43
KALIS_TIMETABLING . . . 43
KALIS_TASK_INTERVALS . . . 43
KALIS_DISJUNCTIONS . . . 44
KALIS_EDGE_FINDING . . . 44
KALIS_INITIAL_SOLUTION . . . 44
KALIS_OPTIMAL_SOLUTION . . . 45
KALIS_RESET_PARAMS_ALL . . . 45
KALIS_RESET_VAR_BOUNDS . . . 46
KALIS_RESET_VAR_PRECISION . . . 46
KALIS_RESET_OPT_PARAMS . . . 46
KALIS_RESET_SEARCH_PARAMS . . . 47
KALIS_NB_SOLUTIONS . . . 47
KALIS_MAX_MIN_BOUND_CONSISTENCY . . . 47
KALIS_TASK_VARIABLES_DOMAIN_TYPE . . . 47
KALIS_TOPNODE_RELAX_SOLVER . . . 48
KALIS_TREENODE_RELAX_SOLVER . . . 48
KALIS_BILEVEL_RELAX_SOLVER . . . 48
KALIS_LINEAR_CONSTRAINTS . . . 48
KALIS_NON_LINEAR_CONSTRAINTS . . . 49
KALIS_LOGICAL_CONSTRAINTS . . . 49

KALIS_DISTANCE_CONSTRAINTS . . . 49
KALIS_ALL_CONSTRAINTS . . . 49
KALIS_MINIMIZE . . . 50
KALIS_MAXIMIZE . . . 50
KALIS_SOLVE_AS_LP . . . 50
KALIS_SOLVE_AS_MIP . . . 50
KALIS_RELAX_PRESOLVE . . . 50
KALIS_RELAX_RCOSTS_PROPAG . . . 51
KALIS_RELAX_RELOAD_BASIS . . . 51
KALIS_RELAX_MIP . . . 51
KALIS_RELAX_ALGORITHM . . . 51
KALIS_RELAX_OPT_TOL . . . 52
KALIS_RELAX_MIP_REL_STOP . . . 52
KALIS_RELAX_MIP_ABS_STOP . . . 52
KALIS_PRIMAL_SIMPLEX . . . 52
KALIS_DUAL_SIMPLEX . . . 53
KALIS_BARRIER . . . 53
KALIS_NETWORK_SIMPLEX . . . 53

**8 Parameters 54**

KALIS_DEFAULT_LB . . . 55
KALIS_DEFAULT_UB . . . 55
KALIS_AUTO_PROPAGATE . . . 55
KALIS_OPTIMIZE_WITH_RESTART . . . 55
KALIS_NODES . . . 56
KALIS_DEPTH . . . 56
KALIS_SEARCH_LIMIT . . . 56
KALIS_TOLERANCE_LIMIT . . . 56
KALIS_BACKTRACKS . . . 56
KALIS_COMPUTATION_TIME . . . 57
KALIS_MAX_NODES . . . 57
KALIS_MAX_SOLUTIONS . . . 57
KALIS_MAX_DEPTH . . . 57
KALIS_MAX_BACKTRACKS . . . 58
KALIS_MAX_COMPUTATION_TIME . . . 58
KALIS_MAX_NODES_BETWEEN_SOLUTIONS . . . 58
KALIS_OPT_ABS_TOLERANCE . . . 58
KALIS_OPT_REL_TOLERANCE . . . 59
KALIS_CHECK_SOLUTION . . . 59
KALIS_DEFAULT_CONTINUOUS_LB . . . 59
KALIS_DEFAULT_CONTINUOUS_UB . . . 59
KALIS_DEFAULT_PRECISION_VALUE . . . 60
KALIS_DEFAULT_PRECISION_RELATIVITY . . . 60
KALIS_DEFAULT_SCHEDULE_HORIZ_MIN . . . 60
KALIS_DEFAULT_SCHEDULE_HORIZ_MAX . . . 60
KALIS_DICHOTOMIC_OBJ_SEARCH . . . 60
KALIS_USE_3B_CONSISTENCY . . . 61
KALIS_VERBOSE_LEVEL . . . 61
KALIS_AUTO_RELAX . . . 61
KALIS_THREADS . . . 61
KALIS_NARY_OBJ_SEARCH . . . 62
KALIS_SCHEDULE_ENABLE_SHAVING . . . 62

**9 Subroutines 63**

9.1 Constraints . . . 63
cplinctr . . . 64
and . . . 66
or . . . 67
equiv . . . 68
implies . . . 70
dot . . . 71
cpnlinctr . . . 72
ln . . . 74
exp . . . 75
distance . . . 76
abs . . . 77
all_different . . . 78
cycle . . . 80
maximum, minimum . . . 85
occurrence . . . 87
element . . . 89
generic_binary_constraint . . . 91
generic_nary_constraint . . . 93
table_constraint . . . 96
distribute . . . 99
cumulative . . . 101
disjunctive . . . 103
producer_consumer . . . 105
9.2 Constraint parameters . . . 108
getarity . . . 109
getpriority . . . 110
setpriority . . . 111
gettag . . . 112
settag . . . 113
setfirstbranch . . . 114
getactivebranch . . . 115
9.3 Variables . . . 116
getlb . . . 117
getub . . . 118
getmiddle . . . 119
getsize . . . 120
getval . . . 121
is_fixed . . . 122
getdegree . . . 123
gettarget . . . 124
getrand . . . 125
getnext . . . 126
getprev . . . 127
contains . . . 128
is_equal . . . 129
is_same . . . 130
settarget . . . 131
setdomain . . . 132
setlb . . . 133
setub . . . 134
setval . . . 135
setprecision . . . 136
cp_show_var . . . 137
cp_show_var_constraints . . . 138

9.4 Problem . . . 139
cp_post . . . 140
cp_propagate . . . 141
cp_find_next_sol . . . 142
cp_reset_search . . . 143
cp_maximise . . . 144
cp_maximize . . . 145
cp_minimise . . . 146
cp_minimize . . . 147
getsol . . . 148
cp_show_prob . . . 149
cp_show_sol . . . 150
cp_show_best_sol . . . 151
getname . . . 152
setname . . . 153
getindex . . . 154
cp_shave . . . 155
cp_infeas_analysis . . . 156
cp_save_state . . . 157
cp_restore_state . . . 158
path_order . . . 159
cp_local_optimize . . . 160
set_sol_as_target . . . 161
cp_reset_params . . . 162
set_reversible_attributes . . . 163
setval . . . 164
getval . . . 165
setelt . . . 166
getelt . . . 167
getsize . . . 168
9.5 Search . . . 169
assign_var . . . 170
assign_and_forbid . . . 173
settle_disjunction . . . 174
probe_assign_var . . . 176
probe_settle_disjunction . . . 177
split_domain . . . 179
task_serialize . . . 181
cp_set_branching . . . 186
cp_show_stats . . . 187
cp_print_stats . . . 188
cp_get_nb_solutions . . . 189
cp_get_computation_time . . . 190
cp_get_number_of_nodes . . . 191
cp_get_depth . . . 192
cp_get_backtracks . . . 193
cp_get_total_computation_time . . . 194
cp_get_total_number_of_nodes . . . 195
cp_get_total_depth . . . 196
cp_get_total_backtracks . . . 197
bs_group . . . 198
group_serializer . . . 199
gettag . . . 202
9.6 Callbacks . . . 203
cp_set_solution_callback . . . 204

cp_set_node_callback . . . 207
cp_set_branch_callback . . . 208
9.7 Scheduling . . . 209
is_fixed . . . 211
set_task_attributes . . . 212
setduration . . . 213
set_start_based_duration . . . 214
get_start_based_duration . . . 215
set_duration_with_idle_times . . . 216
update_duration_with_idle_times . . . 218
addpredecessors . . . 222
setpredecessors . . . 223
addsuccessors . . . 224
setsuccessors . . . 225
cp_show_schedule . . . 226
getstart . . . 227
getend . . . 228
getduration . . . 229
getconsumption . . . 230
getrequirement . . . 232
getproduction . . . 233
getprovision . . . 234
is_consuming . . . 235
is_requiring . . . 236
is_producing . . . 237
is_providing . . . 238
cp_schedule . . . 239
getmakespan . . . 240
consumes . . . 241
requires . . . 244
produces . . . 245
provides . . . 246
set_resource_attributes . . . 247
setcapacity . . . 248
setmaxavailability . . . 250
setminusage . . . 251
getcapacity . . . 252
setsetuptime . . . 253
getsetuptime . . . 254
is_fixed . . . 255
cp_set_schedule_strategy . . . 256
cp_get_default_schedule_strategy . . . 257
resusage . . . 258
get_earliest_start_possible . . . 261
getassignment . . . 262
has_assignment . . . 264
setidletimes . . . 265
is_idletime . . . 266
cp_close_schedule . . . 267
9.8 Linear relaxations . . . 268
KALIS_LARGEST_REDUCED_COST . . . 269
KALIS_NEAREST_RELAXED_VALUE . . . 270
cp_get_linrelax . . . 271
get_linrelax_solver . . . 272
fix_to_relaxed . . . 273

set_verbose_level . . . 274
cp_show_relax . . . 275
cp_add_linrelax_solver . . . 276
cp_remove_linrelax_solver . . . 277
cp_clear_linrelax_solver . . . 278
generate_cuts . . . 279
lp_optimize . . . 280
set_linrelax_solver_attribute . . . 281
get_indicator . . . 282
get_linrelax . . . 283
export_prob . . . 284
get_reduced_cost . . . 285
get_relaxed_value . . . 286
set_integer . . . 287

Appendix 288

A Contacting FICO 288

FICO Customer Support . . . 288
Documentation . . . 288
FICO Learning . . . 289
Sales and maintenance . . . 289
About FICO . . . 289

Bibliography 290

Index 291

CHAPTER 1

# Introduction

## 1.1 Contents of this manual

This reference manual documents version 13.4.3 of Xpress Kalis.

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## 1.2 Constraint programming overview

Constraint programming (CP) is a software technology becoming more widespread thanks to many successes whith effective solving of large, real-life, particularly combinatorial, problems. It provides a powerful technique for different problems such as scheduling, timetabling, resource allocation, or network configuration.

Research results from different fields (operations research, artificial intelligence, discrete mathematics, graph theory) are all involved in the core of Constraint Programming packages. Constraint Programming allows for representing many problems in a way which is very close to a natural language description, thanks to semantic constraints. Benefits are important: fast prototyping, compact code, easy modification, and good performance. It allows for specifying powerful decision support systems.

In order to have a quick overview of this technique, here are the basic elements required for a problem description:

A *constraint satisfaction problem* (CSP) is defined by:

- A set of decision variables $V = \{x_1, ..., x_n\}$
- For each variable, a set (or a range) of possible values called its *domain*
- A set of constraints on these variables.

The *arity* of a constraint corresponds to the number of variables that it involves. For discrete variables, domain values do not have to be consecutive (for example {1, 4, 6, 8}). For continuous variables, the domain is modelled as an interval.

An interesting notion is the *constraint graph*:

A CSP can be represented by a non-oriented graph where the edges symbolize the links between constraints and variables. The Figure 1.1 shows an example of a constraint graph for the following CSP:

Variables: $x, y, z$
Constraints: $x \neq y, y \neq z, z \neq x$

A *solution* to a CSP is an assignment of a value (belonging to its domain) to every variable, satisfying all the constraints.

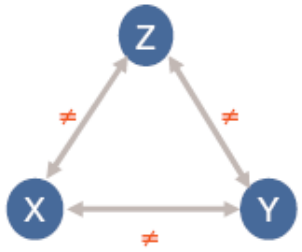



**Figure 1.1**: Constraint graph corresponding to the CSP

In CP, constraints are used actively to deduce infeasible values and delete them from the domains of variables. This mechanism is called *constraint propagation*. It represents the core of Constraint Programming systems. Each constraint computes impossible values for its variables and informs other constraints. This process continues as long as new deductions are made.

Constraint propagation is associated with *tree search techniques* in order to find solutions or prove optimality. Each node and each decision will induce constraint propagation automatically. Many specific and efficient algorithms will be used in this propagation, but do not need to be known by the end-user. This allows persons who are familiar with problem modeling to quickly use such techniques for optimization or generation of solutions.

Solutions of a discrete CSP can be found by a systematic search on the set of possible assignments of values to variables. Other interval techniques are applied for continuous variables.

One may wish to find:

- just *one* feasible solution, without any choice preference
- *all* the solutions
- an *optimal* solution (or at least a nearly optimal solution) that optimizes a certain objective function defined on a subset of the variables of the problem

Solution search methods can be classified in two categories:

- Search methods that explore the space of the partial assignments
- Search methods that explore the space of complete assignments, generally in a stochastic way

The main reason for representing a problem as a CSP is that the formulation of the problem as a CSP is close to the original one in that: variables of the CSP directly correspond to the problem entities and the constraints can be expressed in a natural way without any translation to a set of linear inequalities as in the Mathematical Programming framework. This formulation is thus clearer, solutions are easier to represent, and search heuristics more direct.

## 1.3 What is Xpress Kalis for Mosel?

The *Xpress Kalis Module for Mosel* provides access to the FICO® Xpress Kalis Constraint Programming solver by Artelys from the Mosel language. The software is provided in the form of a Mosel module, *kalis*. Xpress Mosel must be installed in order to be able to use the *kalis* module. The graphical environment Xpress Workbench can be used to work with Xpress Kalis Mosel models. The module *kalis* extends the Mosel language with functionality for defining and solving Constraint Programming (CP) problems.

## 1.4 Prerequisites

This manual assumes some familiarity with the Mosel syntax. The reader is refered to the 'Mosel User Guide' for an introduction to working with Mosel. The 'Mosel Language Reference Manual' contains the complete documentation of the Mosel language. The 'Getting Started' manual explains how to work with Mosel models in Xpress Workbench.

# I. Paradigm

CHAPTER 2

# Decision variables

Decision variables are represented in the Xpress Kalis Mosel module by the types `cpvar` and `cpfloatvar`. They correspond respectively to finite domain variables taking their values in a given interval, or set of integers, called a domain and to continuous domain variables represented by real valued intervals. Conceptually the variables can be represented in the following way:

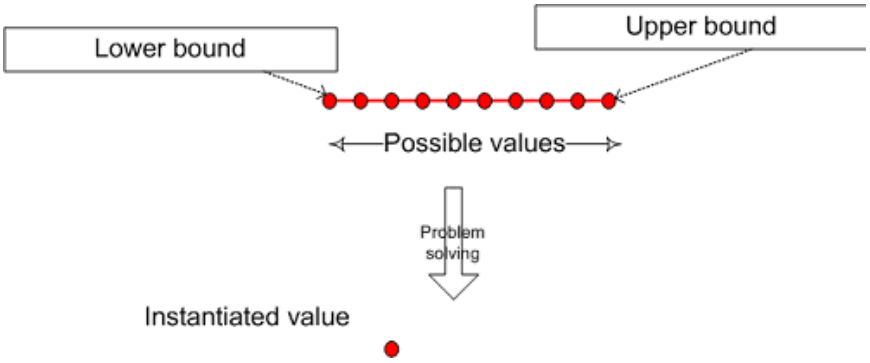



**Figure 2.1**: Conceptual representation of finite domain variables

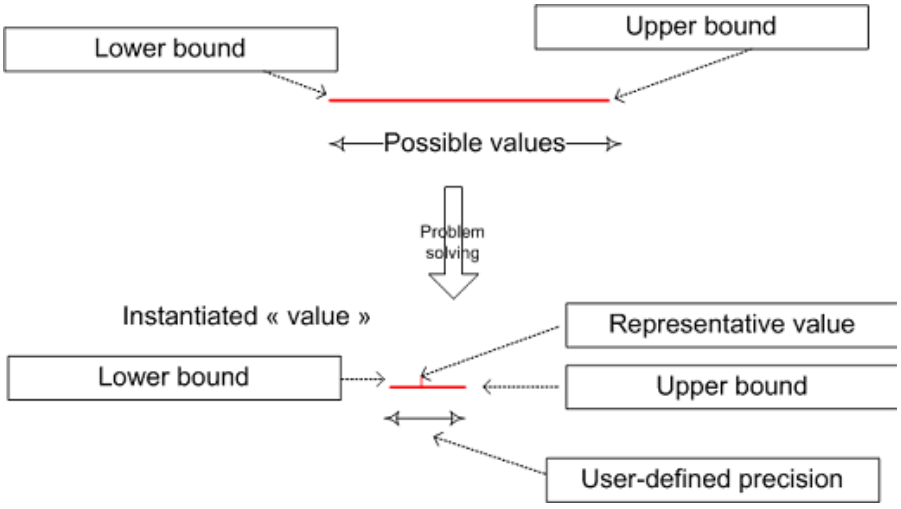



**Figure 2.2**: Conceptual representation of continuous variables

Decision variables are declared by using the standard Mosel syntax. For instance, the following code extract shows how to create a finite domain variable `my_cpvar`, a static array of cpvar `cpvar_array`, and a dynamic array of cpfloatvar `dyn_cpfloatvar_array`:

```
declarations
   my_cpvar           : cpvar
   cpvar_array        : array(1..10) of cpvar
   dyn_cpfloatvar_array : array(range) of cpfloatvar
end-declarations
```

Note that entries of dynamic arrays of domain variables (arrays declared as `dynamic` at their creation or arrays for which some or all of the index sets are not known at the declaration like `dyn_cpfloatvar_array` in the example above) must be created explicitly using the Mosel procedure `create`:

```
declarations
  dyn_cpfloatvar_array : array(range) of cpfloatvar
end-declarations
forall(i in 3..30) create(dyn_cpvar_array(i))
```

After its declaration, the second step in the creation of a domain variable consists of defining its domain with the procedure `setdomain`.

Domain variables are also used in the definition of constraints and search strategy.

*kalis* defines a set of functions for accessing and modifying `cpvar` and `cpfloatvar` states:

| | | |
|---|---|---|
| `contains` | Tests if a value is in the domain of a variable | p. 128 |
| `cp_show_var` | Shows the current domain of the variable | p. 137 |
| `getdegree` | Returns the degree of a variable | p. 123 |
| `getlb` | Returns the current lower bound of a variable | p. 117 |
| `getmiddle` | Returns the middle value of a variable | p. 119 |
| `getnext` | Gets the next value in the domain of a finite domain variable | p. 126 |
| `getprev` | Gets the previous value in the domain of a finite domain variable | p. 127 |
| `getrand` | Returns a random value belonging to the domain of a variable | p. 125 |
| `getsize` | Returns the cardinality of the variable domain | p. 120 |
| `gettarget` | Returns the target value of a variable | p. 124 |
| `getub` | Returns the current upper bound of a variable | p. 118 |
| `getval` | Returns the instantiation value of a variable | p. 121 |
| `is_equal` | Tests if two variable domains are equal | p. 129 |
| `is_fixed` | Tests if the variable passed in argument is instantiated | p. 122 |
| `is_same` | Tests if two decision variables represent the same variable | p. 130 |
| `setdomain` | Sets the domain of a variable | p. 132 |
| `setlb` | Sets the lower bound of a variable | p. 133 |
| `setprecision` | Sets the precision relativity and value of a continuous variable | p. 136 |
| `settarget` | Sets the target value of a variable | p. 131 |
| `setub` | Sets the upper bound of a variable | p. 134 |
| `setval` | Instantiate the value of a variable | p. 135 |

CHAPTER 3

# Constraints

Constraints represent logical restrictions on the values that decision variables can simultaneously take and that must be satisfied. There are various types of constraints that can be stated within Xpress Kalis:

- Linear constraint (equation, inequality, disequality), *e.g.*: $x \neq y$, $x = y$, $x \leqslant y$ *etc.*
- Non-linear constraint (equation, inequality), *e.g.*: $x = y/z$, $x * y + 2 * \ln(z) = \exp(w)$, $x^2 + y^2 \leqslant z^2$ *etc.*
- Symbolic constraint, *e.g.*: $\mathrm{all\text{-}different}(x, y, z)$ meaning $(x \neq y) \wedge (x \neq z) \wedge (x \neq z)$
- Logical relation, *e.g.*: $x \neq y \Rightarrow z = 3$
- User-defined constraints such as $\mathrm{generic_binary_constraint}(x, y)$

All constraints are represented by the type `cpctr`.


| | | |
|---|---|---|
| `abs` | Absolute value constraint | p. 77 |
| `all_different` | All different constraint | p. 78 |
| `and` | Conjunction composite constraint | p. 66 |
| `cplinctr` | Linear constraints | p. 64 |
| `cpnlinctr` | Non-linear constraints | p. 72 |
| `cumulative` | Cumulative constraint | p. 101 |
| `cycle` | Cycle constraint | p. 80 |
| `disjunctive` | Disjunctive constraint | p. 103 |
| `distance` | Distance constraint | p. 76 |
| `distribute` | Distribute constraint with fixed bounds | p. 99 |
| `element` | Element constraint | p. 89 |
| `equiv` | Equivalence composite constraint | p. 68 |
| `exp` | Exponential of a non-linear expression | p. 75 |
| `generic_binary_constraint` | Generic Binary constraint | p. 91 |
| `generic_nary_constraint` | Generic nary constraint | p. 93 |
| `implies` | Implication composite constraint | p. 70 |
| `ln` | Natural logarithm of a non-linear expression | p. 74 |

| | | |
|---|---|---|
| `maximum, minimum` | Maximum/minimum constraint | p. 85 |
| `occurrence` | Occurrence constraint | p. 87 |
| `or` | Disjunction composite constraint | p. 67 |
| `producer_consumer` | Producer Consumer constraint | p. 105 |
| `table_constraint` | Generic nary table constraint | p. 96 |

CHAPTER 4

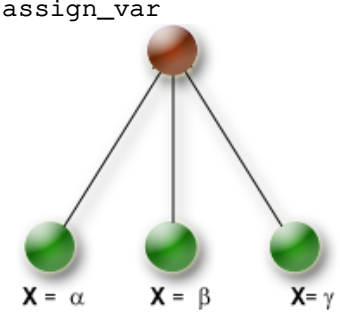
# Enumeration and search strategy

Since the combination of constraint solving and propagation mechanism is usually not sufficient to reduce all variable domains to a single value, an enumeration needs to be added to the problem definition to find feasible solutions or to prove that no such solution exists.

The search process is made by a branch and bound algorithm with depth-first exploration of the search tree. At each node, a propagation phase is triggered in order to detect possible inconsistencies and reduce the search space. If this phase detects an inconsistency, the algorithm backtracks and removes the effects of the previous decisions. If no inconsistency is detected, a branching process is applied recursively to the child nodes until a solution is found or until all the search space has been explored.

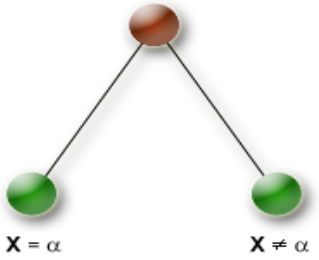
The way the branching is done is defined by branching schemes (type cpbranching). Six *branching schemes* are predefined in Xpress Kalis:

1. `assign_var`



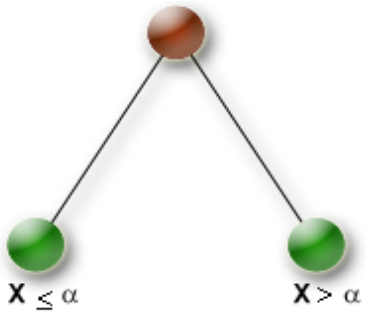

This branching scheme may be considered as the standard enumeration scheme in finite domain Constraint Programming. For a given branching variable it enumerates all values currently in its domain. A branch is formed by assigning a value to the branching variable, resulting in a variable number of branches per node (determined by the variable's domain size). Since this strategy tends to create a very wide search tree it is used preferably with small domains or if variable and value selection strategies are known that quickly lead to (good) feasible solutions.

2. `assign_and_forbid`



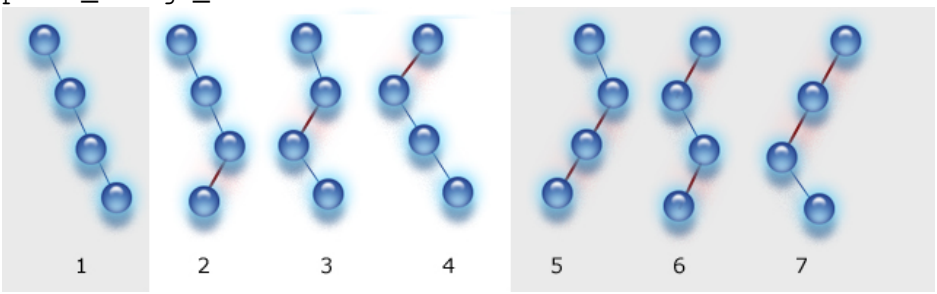

This branching scheme creates a binary search tree by creating two branches for a given branching variable. The first branch is formed by assigning a value to the branching variable, and the second branch, by forbidding this value for this variable.

3. `split_domain`



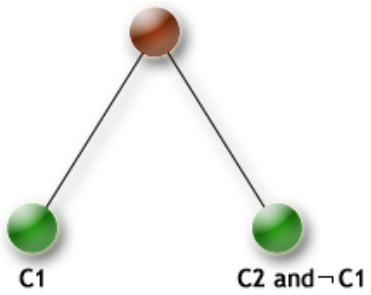

The split_domain strategy creates a binary search tree by splitting the domain of the branching variable into two intervals (all values less than or equal to the branching value in the first and all values greater than the branching value in the second). This strategy is the only possible choice for continuous variables and it is also applicable for finite domain variables. For the latter this strategy may be helpful if the initial domain sizes are relatively large. The strategy can be configured by choosing which branch to explore first and whether to stop applying it when domain sizes are reduced to less than a certain limit.

4. `probe_assign_var`



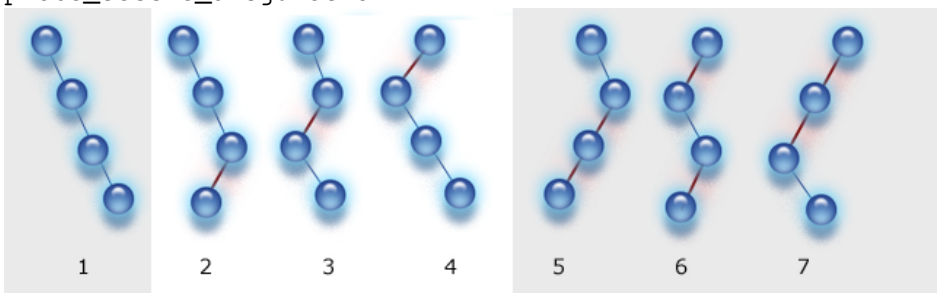

The probe_assign_var strategy is directly derived from the assign_var strategy which means that the branches created are the same. The difference lies in the completeness and the order in which branches are explored. Some of the possible branches are skipped by limiting the total number of times that the heuristic (first branch created) may fail and the branching process is stopped when this counter exceeds a specified value. The picture below shows the order in which the branches are explored when the domains of all variables are reduced to two values. This strategy can be useful to apply local search to an already known solution (combined with the KALIS_NEAREST_VALUE value selection heuristic) or to explore the neighborhood of a heuristic solution to find quickly a first solution and avoid the thrashing behavior of the chronological backtracking algorithm used during the resolution process.

5. `settle_disjunction`




The settle_disjunction strategy creates a binary search tree by branching on the two possibilities defined by a disjunction. Recall that a disjunction can be written as `c1 or c2` where c1 and c2 are two constraints, the settle_disjunction strategy will create a branch for each constraint stating that it must hold. The strategy can be configured by choosing the first branch of the disjunction that will be explored during the search process.

6. `probe_settle_disjunction`




The probe_assign_var strategy is directly derived from the settle_disjunction strategy which means that the branches created by this strategy are the same. The difference lies in the completeness and the order in which branches are explored. Some of the possible branches are skipped by limiting the total number of times that the heuristic (first branch created) may fail and the branching process is stopped when this counter exceeds a specified value. The picture below shows the order in which the branches are explored when the domains of all variables are reduced to two values. This strategy can be useful to apply local search to a disjunctive scheduling problem for which a solution is already known (combined with the setfirstbranch and getactivebranch methods).

These predefined branching schemes are used in conjunction with variable (resp. disjunction) and value selection heuristics that fully define the way how the search tree will be explored.

Xpress Kalis predefines several *variable selection heuristics*:

- `KALIS_SMALLEST_DOMAIN`
- `KALIS_MAX_DEGREE`
- `KALIS_SDOMDEG_RATIO`
- `KALIS_SMALLEST_MAX`
- `KALIS_SMALLEST_MIN`
- `KALIS_LARGEST_MAX`
- `KALIS_LARGEST_MIN`
- `KALIS_MAXREGRET_UB`

- KALIS_MAXREGRET_LB
- KALIS_INPUT_ORDER
- KALIS_WIDEST_DOMAIN (continuous variables)

... *value selection heuristics*:

- KALIS_MAX_TO_MIN
- KALIS_MIN_TO_MAX
- KALIS_MIDDLE_VALUE
- KALIS_RANDOM_VALUE

... and *disjunction selection heuristics*:

- KALIS_DISJ_INPUT_ORDER
- KALIS_DISJ_PRIORITY_ORDER

Xpress Kalis offers several possibilities to define the search strategy:

- Use the predefined strategy provided by Xpress Kalis.
- Build custom search strategies based on combinations of predefined branching schemes, variable and value selection heuristics.
- Define custom heuristics for variable and value selection.
- Add an optimization function (cost or objective function) for an enumeration and thus search for a feasible solution with the best (minimum or maximum) cost (optimal solution). We refer to this case as *optimization*, although, in practical applications one is typically only interested in good solutions that are found quickly, without necessarily spending time in proving that, indeed, the best solution is found.

The following example shows a specific problem and branching strategy with the corresponding search tree:

```
declarations
   x        : cpvar
   y        : cpvar
   strategy : array(1..2) of cpbranching
end-declarations
1 <= x; x <= 3
1 <= y; y <= 3
strategy(1) := split_domain(KALIS_SMALLEST_DOMAIN, KALIS_MIN_TO_MAX, {x})
strategy(2) := assign_var(KALIS_SMALLEST_DOMAIN, KALIS_MIN_TO_MAX, {y})
cp_set_branching(strategy)
```

| | | |
|---|---|---|
| assign_and_forbid | assign_and_forbid branching scheme | p. 173 |
| assign_var | assign_var branching scheme | p. 170 |
| bs_group | Create a group of branching schemes | p. 198 |
| cp_set_branching | Sets the strategy to use during the search for a solution | p. 186 |

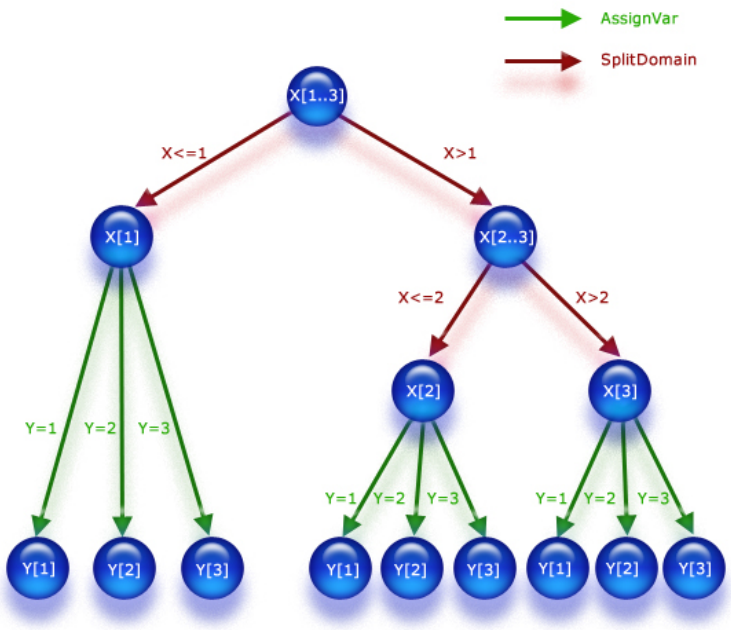



**Figure 4.1**: Example of search tree

| | | |
|---|---|---|
| `cp_show_stats` | Shows some statistics about the search | p. 187 |
| `gettag` | Gets the tag of a constraint | p. 112 |
| `group_serializer` | Creates a branching scheme Group Serializer | p. 199 |
| `probe_assign_var` | probe_assign_var branching scheme | p. 176 |
| `probe_settle_disjunction` | probe_settle_disjunction branching scheme | p. 177 |
| `settle_disjunction` | settle_disjunction branching scheme | p. 174 |
| `split_domain` | split_domain branching scheme | p. 179 |
| `task_serialize` | task_serialize branching scheme | p. 181 |

CHAPTER 5

# Scheduling

Scheduling plays an important role in manufacturing and engineering where it can have a major impact on the productivity of a process. The goal of scheduling is to optimize the production process by telling which operation to do, when, with which staff, and using which equipment.

Let's take the example of constructing a house. This task can be broken down into a set of smaller tasks:

- Grading and preparation of the site
- Foundations
- Framing
- Installation of windows and doors
- Roofing
- Siding
- Electricity
- Plumbing
- Underlayment
- Painting
- etc...

All these tasks must be carried out in a certain order: for example, laying the foundations cannot be done before the excavation and grading of the site. Moreover, certain tasks require specific resources (you need a plumber to do plumbing, a concrete mixer to do the carpentry *etc.*).

Tasks and resources are represented in *kalis* by the special purpose types `cpresource` and `cptask`.

## 5.1 Tasks

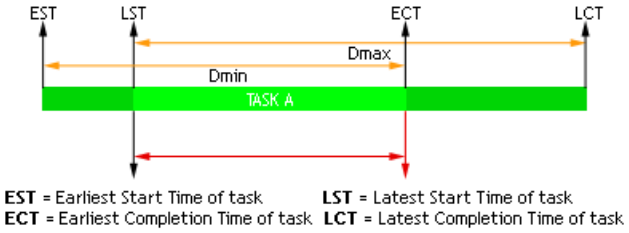
A `cptask` is represented by three decision variables of type `cpvar`:

- $\mathrm{start}$ representing the starting time of the task
- $\mathrm{end}$ representing the ending time of the task
- $\mathrm{duration}$ representing the duration of the task

These three structural variables are linked by Xpress Kalis with the following constraint: $\mathrm{start} + \mathrm{duration} = \mathrm{end}$.

- The starting time variable represents two specific parameters of the task:
  - the *Earliest Start Time* (EST, represented by the lower bound of the 'start' variable) and its *Latest Start Time* (LST, represented by the upper bound of the 'start' variable).
- The end variable represents two specific parameters of the task:
  - the *Earliest Completion Time* (ECT, represented by the lower bound of the 'end' variable) and its *Latest Completion Time* (LCT, represented by the upper bound of the 'end' variable).
- The duration variable represents two specific parameters of the task:
  - the *minimum task duration* (Dmin, represented by the lower bound of the 'duration' variable) and the *maximum task duration* (Dmax, represented by the upper bound of the 'duration' variable).

The picture below illustrates this:




In the case of tasks using resources, another variable is instantiated : the *resource assignment* binary variable. It is defined for a couple (task, resource) and takes the value 1 if the task uses the specific resource, otherwise it has value 0.

Task attributes can be assigned or retrieved with the following methods:

- `getstart`
- `getend`
- `getduration`
- `setduration`
- `has_assignment`
- `getassignment`
- `get_earliest_start_possible`
- `getname`
- `setname`
- `is_fixed`
- `addpredecessors`
- `setpredecessors`
- `addsuccessors`
- `setsuccessors`
- `setsetuptime`

# 5.2 Resources

A resource can be of two different types:

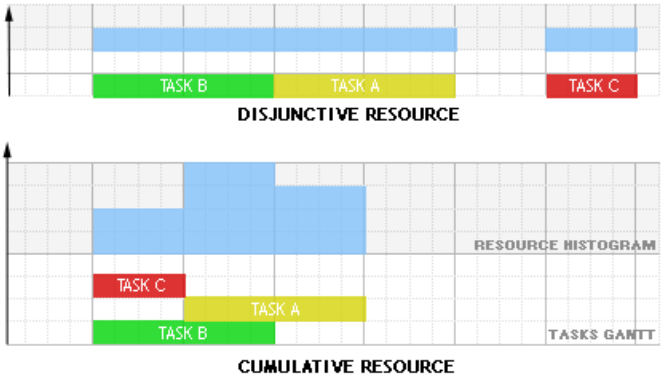
- *Disjunctive* when the resource can process only one task at a time (KALIS_UNARY_RESOURCE).
- *Cumulative* when the resource can process several tasks at the same time (KALIS_DISCRETE_RESOURCE).

Traditional examples of disjunctive resources are Jobshop scheduling problems. Cumulative resources are used for the Resource-Constrained Project Scheduling Problem (RCPSP)

Note that a disjunctive resource is semantically equivalent to a cumulative resource with maximal capacity one and unit resource usage for each task using this resource but this equivalence does not hold in terms of constraint propagation.

When defining a resource with Xpress Kalis its initial capacity is specified. For a disjunctive resource the capacity value is always equal to one. The structural capacity of a resource does not vary over time but a maximal temporal capacity can be imposed at any point of time with the procedure `setcapacity`.

The following graphic shows an example with three tasks A, B and C executing on a disjunctive resource and on a cumulative resource with resource usage 3 for task A, 1 for task B, and 1 for task C.




Tasks require, provide, consume and produce resources:

- A task `requires` a resource if some amount of the resource capacity must be made available for the execution of the activity. The capacity is renewable, this means the required capacity becomes available again after the end of the task.
- A task `provides` a resource if some amount of the resource capacity is made available through the execution of the task. The capacity is renewable, that is, the provided capacity is available only during the execution of the task.
- A task `consumes` a resource if some amount of the resource capacity must be made available for the execution of the task and the capacity is non-renewable, that is, the consumed capacity is no longer available at the end of the task.
- A task `produces` a resource if some amount of the resource capacity is made available through the execution of the task and the capacity is non-renewable, that is, the produced capacity is definitively available after the start of the task.

Task productions, requirements, provisions and productions can be accessed with the following methods:

- consumes
- requires
- provides
- produces
- getconsumption
- getrequirement
- getprovision
- getproduction
- is_consuming
- is_requiring
- is_providing
- is_producing

Resources and tasks are declared by using the standard Mosel syntax. For instance, the following code extract shows how to create a task my_cptask, a static array of resources cpresource_array, and a dynamic array of cptask dyn_cptask_array:

```
declarations
   my_cptask       : cptask
   cpresource_array: array(1..10) of cpresource
   dyn_cptask_array: array(range) of cptask
end-declarations
```

Note that entries of dynamic arrays of tasks or resources (arrays declared as dynamic at their creation or arrays for which some or all of the index sets are not known at the declaration like dyn_cptask_array in the example above) must be created explicitly using the Mosel procedure create:

```
declarations
   dyn_cptask_array: array(range) of cptask
end-declarations
forall(i in 3..30) create (dyn_cptask_array(i))
```

After its declaration, the second step in the creation of a task or resource consists of defining somes attributes with the procedures set_task_attributes and set_resource_attributes.

# 5.3 Schedule

Tasks and resources form a *schedule*. The cp_schedule method allows to optimize a schedule with respect to any objective variable and implements advanced scheduling techniques specialized in makespan minimization. The creation of the schedule makespan can be automated by calling the getmakespan method that ensures automatically its computation.

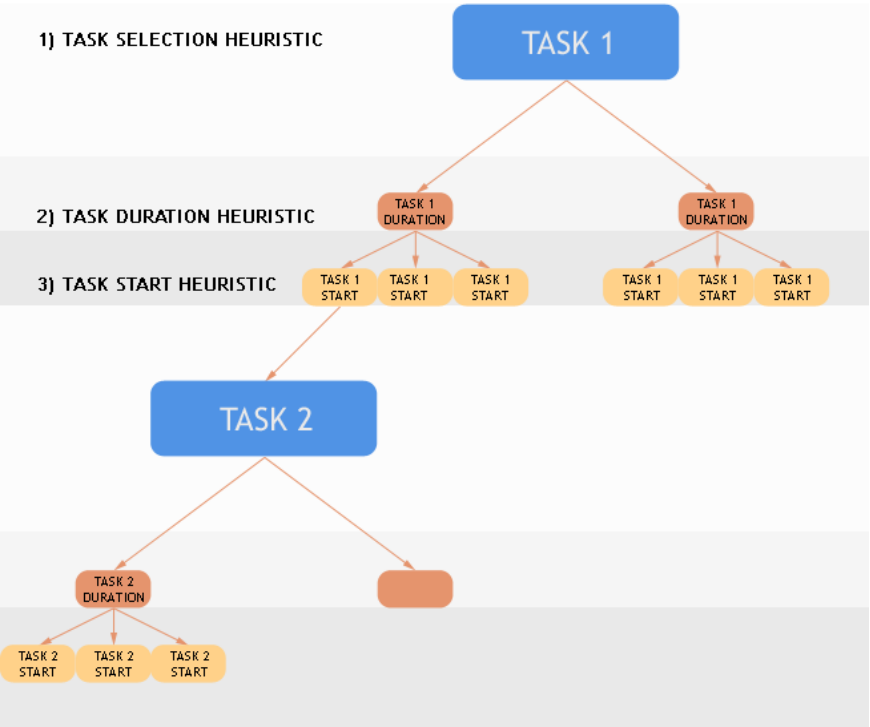
A custom scheduling optimization strategy can be specified by using the task_serialize branching scheme to select the task to be scheduled and value choice heuristics for its start and duration variables.

The task selection method can be any user Mosel method or it may be configured with the predefined strategies of Xpress Kalis:

- KALIS_SMALLEST_ECT

- KALIS_SMALLEST_EST
- KALIS_SMALLEST_LCT
- KALIS_SMALLEST_LST
- KALIS_LARGEST_ECT
- KALIS_LARGEST_EST
- KALIS_LARGEST_LCT
- KALIS_LARGEST_LST

The picture below illustrates the definition of a task-based branching strategy:




*kalis* defines a set of functions for accessing and modifying `cptask` and `cpresource` states:

| | | |
|---|---|---|
| `addpredecessors` | Adds a set of predecessors for a task | p. 222 |
| `addsuccessors` | Adds a set of tasks as successors of a task | p. 224 |
| `consumes` | Sets the minimal and maximal amount of resource consumed by a task for a particular resource | p. 241 |
| `cp_close_schedule` | Close the schedule. | p. 267 |
| `cp_get_default_schedule_strategy` | Gets the default schedule search strategy of cp_schedule | p. 257 |
| `cp_schedule` | Optimizes the schedule with respect to an objective variable. | p. 239 |
| `cp_set_schedule_strategy` | Sets the schedule search strategy for cp_schedule | p. 256 |

| | | |
|---|---|---|
| `cp_show_schedule` | Shows a textual representation of the current schedule | p. 226 |
| `get_earliest_start_possible` | Gets the earliest time at which the task can start on the given resource. | p. 261 |
| `getassignment` | Gets the cpvar representing the assignment of a task for a particular resource. | p. 262 |
| `getcapacity` | Get the maximal capacity of a resource for a specific time period. | p. 252 |
| `getconsumption` | Gets the cpvar representing the consumption of a task for a particular resource | p. 230 |
| `getduration` | Gets the cpvar representing a task duration | p. 229 |
| `getend` | Gets the cpvar representing a task completion time | p. 228 |
| `getmakespan` | Gets the cpvar representing the makespan of the schedule. | p. 240 |
| `getproduction` | Gets the cpvar representing the production of a task for a particular resource | p. 233 |
| `getprovision` | Gets the cpvar representing the provision of a task for a particular resource | p. 234 |
| `getrequirement` | Gets the cpvar representing the requirement of a task for a particular resource | p. 232 |
| `getsetuptime` | Gets the sequence dependent setup times between two tasks | p. 254 |
| `getstart` | Gets the cpvar representing a task start time | p. 227 |
| `has_assignment` | Tests whether an assignment decision variable for a task and a particular resource exists. | p. 264 |
| `is_consuming` | Tests whether a task consumes a specific resource | p. 235 |
| `is_fixed` | Tests if the variable passed in argument is instantiated | p. 122 |
| `is_idletime` | Tests if a timestep is an idle timestep for a resource. | p. 266 |
| `is_producing` | Tests whether a task produces a specific resource | p. 237 |
| `is_providing` | Tests whether a task provides a specific resource | p. 238 |
| `is_requiring` | Tests whether a task requires a specific resource | p. 236 |
| `produces` | Sets the minimal and maximal amount of resource produced by a task for a particular resource | p. 245 |
| `provides` | Sets the minimal and maximal amount of resource provided by a task for a particular resource. | p. 246 |
| `requires` | Sets the minimal and maximal amount of resource required by a task for a particular resource | p. 244 |
| `resusage` | Creates a resource usage | p. 258 |
| `set_resource_attributes` | Sets some attributes for a resource | p. 247 |
| `set_task_attributes` | Sets some attributes for a task | p. 212 |
| `setcapacity` | Sets the maximal capacity of a resource between two time bounds. | p. 248 |
| `setduration` | Sets the duration of a task | p. 213 |

| | | |
|---|---|---|
| `setidletimes` | Specifies the set of timesteps where a resource is idle. | p. 265 |
| `setmaxavailability` | Sets the maximal capacity of a resource between two time bounds. | p. 250 |
| `setminusage` | Sets the minimum usage of a resource between two time bounds. | p. 251 |
| `setpredecessors` | Sets the tasks that must precede a task | p. 223 |
| `setsetuptime` | Sets sequence dependent setup times between two tasks | p. 253 |
| `setsuccessors` | Sets the set of tasks that must succeed a task | p. 225 |

CHAPTER 6

# Linear relaxations

Some parts of an optimization problem may be best expressed and solved in the declarative (solver-independent) manner of Mathematical Programming (MP). Other parts benefit from constraint propagation and search directions provided by a CP solver. So why not trying to get the best of both worlds by combining the MP and CP approaches?

Xpress Kalis allows you to benefit from CP and MIP hybridization in a clean and easy way by means of linear relaxations of the CP model. Xpress Kalis can build automatically several linear (or mixed integer linear) relaxations of the CP problem and use Xpress Optimizer to solve them.

This process can be fully configured ranging from a complete user definition of the relaxation and choice of when to launch the relaxation to a fully automatic relaxation.

Xpress Kalis uses a double modeling approach by exchanging automatically and in bidirectional way, informations such as objective bounds, infeasibility, optimal relaxed solutions and reduced costs between the cp solver and the linear relaxations solver(s) during the search for a solution.

**Note:** the linear relaxation functionality of Xpress Kalis can only be used if Xpress Optimizer is installed and licensed.

## 6.1 Automatic relaxations

The following constraints can be relaxed automatically with Xpress Kalis :

- Linear constraints
- all-different
- occurrence
- distribute
- Min/Max
- absolute value
- distance
- element
- cycle
- logical (implies, or ,and ,equiv)

To obtain an automatic relaxation of the whole problem, Xpress Kalis takes the intersection of the relaxations of the constraints of the constraint programming model. Such a relaxation is obtained by a simple call to the function `cp_get_linrelax`

Note that this method is parameterized with an integer parameter since Xpress Kalis offers several relaxations for each constraint. In the present case, 0 means an LP oriented relaxation and 1 means a MIP oriented relaxation.

## 6.2 User defined relaxations

Xpress Kalis allows the user to define his own relaxation for the problem and provides several operators, functions and methods for this purpose:

- Overloaded operators for the specification of linear inequalities in a linear relaxation.
- The method `get_linrelax(ctr: cpctr)` returns the automatic relaxation for a constraint.
- The `set_integer` method turns variables in the relaxation into discrete variables (by default all relaxation variables are considered as continuous).
- Variables can be defined either in both, CP model and relaxation, or only in the CP model, or only in the relaxation (auxiliary variables).

Auxiliary variables (of the type `cpauxvar`) are additional variables that are used only in the definition of the relaxation and not in the formulation of the CP problem. For example, they can be used to linearize non-linear constraints or to express choices in the relaxation.

The CP model will not see these variables (no propagation and no branching) except for one particular kind of auxilliary variables called *indicators*. These indicator variables are 0-1 integer variables that are linked to `cpvar` variables. There is one indicator variable per value in the domain of a `cpvar`, and the indicator takes the value 1 if and only if this `cpvar` is instantiated to the value associated with the indicator variable. Bounds on indicator variables are automatically propagated by Xpress Kalis and reduced costs provided by the relaxation are retro-propagated to the CP variables by the means of reduced costs fixing (a kind of propagation reasoning on optimality).

Indicator variables are created and retrieved by a call to the `get_indicator` function.

The following examples show some expressions that can be used in the definition of custom relaxations:

```
 declarations
  myrelax: cplinrelax               ! A linear relaxation
  a1,a2  : cpauxvar                 ! Auxiliary variables for relaxation
  taux   : array(1..4) of cpauxvar  ! Array of auxiliary variables

  x1,x2,x3: cpvar                   ! Finite domain variables
  z       : cpfloatvar              ! CP variable with continuous domain
  CAlld   : cpctr                   ! A CP constraint
 end-declarations

! Define an 'alldifferent' constraint
 CAlld := all_different({x1,x2,x3})

! Build an automatic 'LP' oriented linear relaxation
 myrelax1 := cp_get_linrelax(0)

! Setting bounds on the auxiliary variables
 setdomain(a2,0,1)
 setdomain(a1,0.56,18.67)

! Adding linear inequalities to the relaxation
 myrelax += 3*a1      <= 3
 myrelax += a1+a2     >= 3.1
 myrelax += 2*a1-4*a2  = 3
 myrelax += a1-x1      <= 3.4
 myrelax += a1+4*a2-z <= 3
```

```
 myrelax += get_linrelax(CAlld,0)
 myrelax +=
   get_indicator(x1,1) + get_indicator(x2,1) + get_indicator(x3,1) <= 1
 myrelax += sum(i in 1..4) taux(i) = 4

! Set integrality condition for variables in the relaxation
 set_integer(myrelax,a2,true)
 set_integer(myrelax,x1,true)

! Output the resulting relaxation to the screen
 cp_show_relax(myrelax)
```

# 6.3 Usage of relaxations

Xpress Kalis can create several distinct relaxations of a CP problem and solve them.

The optimal solution of these relaxations provides bounds for the CP branch-and-bound process and prunes the search tree with reduced costs propagation (optimality reasoning).

To solve a linear relaxation, Xpress Kalis uses relaxation solvers (of the type `cplinrelaxsolver`) that define for the relaxation:

- An objective variable for the relaxation
- An optimization sense (either `KALIS_MINIMIZE` or `KALIS_MAXIMIZE`)
- A configuration defining when and what to do with the relaxation.
- A flag indicating whether to solve the relaxation as a pure LP problem or as a MIP.(either `KALIS_SOLVE_AS_LP` or `KALIS_SOLVE_AS_MIP`

Several predefined configurations are implemented within Xpress Kalis:

- `KALIS_TOPNODE_RELAX_SOLVER`: This configuration solves the relaxation only at the top node and provides bounds for the objective variable.
- `KALIS_TREENODE_RELAX_SOLVER`: This configuration solves the relaxation at each node of the search tree. It provides bounds for the objective variable and performs reduced costs propagation.
- `KALIS_BILEVEL_RELAX_SOLVER`: This configuration solves the relaxation whenever all the variables (by default all the discrete variables such as `cpvar`) of a user defined set are instantiated. After solving of the relaxation, all the other variables are instantiated to their optimal value in the relaxation. The principal use of the bi-level configuration is to decompose the CP model simply and automatically into a main problem and a subproblem.

The user can also take full control over the relaxation solver by the means of callbacks.

A relaxation solver is obtained by specifying three callbacks functions:

- must_relax: This function with no argument and returning a Boolean must return true whenever the users wants to solve the relaxation
- before_relax: This procedure with no argument is called just before the relaxation is performed
- after_relax(status: integer): This procedure with one argument is called after the relaxation has been solved. The status parameter indicates whether the relaxation is optimal (0) or infeasible (1). This callback can be used, for example, to instantiate some variables to their values in the optimal solution of the relaxation.

In addition to the user-configurable relaxations, Xpress Kalis provides a fully automated mode for using linear relaxations, enabled by the control parameter `KALIS_AUTO_RELAX`.

## 6.4 Branching with relaxation

Xpress Kalis defines predefined branching schemes and value and variable selection heuristics based on the optimal solution of a relaxation:

- `KALIS_LARGEST_REDUCED_COST` variable selection heuristic selects the variable with the largest reduced cost in the optimal solution of the relaxation used by the specified relaxation solver.
- `KALIS_NEAREST_RELAXED_VALUE` value selection heuristic selects the value in the domain of the variable that is the nearest (in L1) to the value of this variable in the optimal solution of the relaxation used by the specified relaxation solver.

Moreover, the `fix_to_relaxed` method can be called during the tree search process to instantiate all the continuous variables to their values in the optimal solution of a relaxation.

This can be useful with some specific problem structures and in combination with the `KALIS_BILEVEL_RELAX_SOLVER` configuration for the relaxation solver to obtain an automatic logical benders decomposition of the solving process.

## 6.5 A simple hybrid example

Consider the following knapsack problem with an additional non linear constraint: all-different

$$\begin{aligned} \text{minimize} \quad & 5 \cdot x_1 + 8 \cdot x_2 + 4 \cdot x_3 \\ s.t. \quad & 3 \cdot x_1 + 5 \cdot x_2 + 2 \cdot x_3 \geqslant 30 \\ & \text{all-different}(x_1, x_2, x_3) \\ & x_j \in \{1, 3, 8, 12\} \text{ for } j = 1, 2, 3 \end{aligned}$$

A pure and straightforward CP approach for formulating and solving this problem is shown below:

```
model "Knapsack with side constraints"
 uses "kalis"

 declarations
  x1,x2,x3: cpvar                   ! Decision variables
  cost: cpvar                       ! The objective to minimize
 end-declarations

! Enable output printing
 setparam("kalis_verbose_level", 1)

! Setting name of variables for pretty printing
 setname(x1,"x1"); setname(x2,"x2"); setname(x3,"x3")
 setname(cost,"cost")

! Set initial domains for variables
 setdomain(x1, {1,3,8,12})
 setdomain(x2, {1,3,8,12})
 setdomain(x3, {1,3,8,12})

! Knapsack constraint
 3*x1 + 5*x2 + 2*x3 >= 30

! Additional global constraint
 all_different({x1,x2,x3})
```

```
! Objective function
 cost = 5*x1 + 8*x2 + 4*x3

! Initial propagation
 if not cp_propagate: exit(1)

! Display bounds on objective after constraint propagation
 writeln("Constraint propagation objective ", cost)

! Solve the problem
 if cp_minimize(cost):
   cp_show_sol                    ! Output optimal solution to screen

end-model
```

This model formulation can be augmented by the definition of a linear relaxation.

We start by getting an automatic relaxation of the problem by a call to the function `cp_get_linrelax`. The resulting relaxation can be displayed (printed to the standard output) with a call to the procedure `cp_show_relax`.

From the linear relaxation a linear relaxation *solver* is built with a call to the `get_linrelax_solver` method. Note that the `KALIS_TOPNODE_RELAX_SOLVER` argument passed to the method indicates that we just want to solve the linear relaxation at the top node of the CP search tree.

Having obtained the linear relaxation solver, we need to add it to the search process by a call to `cp_add_linrelax_solver`. Of course, Xpress Kalis is not limited to one relaxation so several solvers can be defined and added to the search process.

The model definition is completed by specifying a 'MIP style' branching scheme that branches first on the variables with largest reduced cost and tests first the values nearest to the optimal solution of the relaxation. The invocation ot the search and solution display remain the same as in the CP model.

This is the full hybrid model:

```
model "Knapsack with side constraints"
 uses "kalis"

 declarations
  x1,x2,x3: cpvar                  ! Decision variables
  cost: cpvar                      ! The objective to minimize
 end-declarations

! Enable output printing
 setparam("kalis_verbose_level", 1)

! Setting name of variables for pretty printing
 setname(x1,"x1"); setname(x2,"x2"); setname(x3,"x3")
 setname(cost,"cost")

! Set initial domains for variables
 setdomain(x1, {1,3,8,12})
 setdomain(x2, {1,3,8,12})
 setdomain(x3, {1,3,8,12})

! Knapsack constraint
 3*x1 + 5*x2 + 2*x3 >= 30

! Additional global constraint
 all_different({x1,x2,x3})

! Objective function
 cost = 5*x1 + 8*x2 + 4*x3

! Initial propagation
 if not cp_propagate: exit(1)
```

```
! Display bounds on objective after constraint propagation
 writeln("Constraint propagation objective ", cost)


 declarations
  myrelaxall: cplinrelax
 end-declarations

! Build an automatic 'LP' oriented linear relaxation
 myrelaxall:= cp_get_linrelax(0)

! Output the relaxation to the screen
 cp_show_relax(myrelaxall)

 mysolver:= get_linrelax_solver(myrelaxall, cost, KALIS_MINIMIZE,
                KALIS_SOLVE_AS_MIP, KALIS_TOPNODE_RELAX_SOLVER)

! Define the linear relaxation
 cp_add_linrelax_solver(mysolver)

! Define a 'MIP' style branching scheme using the solution of the
! optimal relaxation
 br1 := KALIS_LARGEST_REDUCED_COST(mysolver)
 br2 := KALIS_NEAREST_RELAXED_VALUE(mysolver)
 cp_set_branching(assign_var(br1, br2))

! Solve the problem
 if cp_minimize(cost):
   cp_show_sol                  ! Output optimal solution to screen

end-model
```

You will find below the list of relaxation related functions and procedures defined by the *kalis* module:

| | | |
|---|---|---|
| `cp_add_linrelax_solver` | Add a linear relaxation solver to the linear relaxation solver list | p. 276 |
| `cp_clear_linrelax_solver` | Clear the linear relaxation solver list | p. 278 |
| `cp_get_linrelax` | Returns an automatic relaxation of the cp problem | p. 271 |
| `cp_remove_linrelax_solver` | Remove a linear relaxation solver from the linear relaxation solver list | p. 277 |
| `cp_show_relax` | Pretty printing of a linear relaxation | p. 275 |
| `export_prob` | Export the linear relaxation in LP format | p. 284 |
| `fix_to_relaxed` | Fix the continuous variables to their optimal value in the relaxation solver passed in argument | p. 273 |
| `generate_cuts` | Generate and add cuts to the relaxation passed in parameters | p. 279 |
| `get_indicator` | Get an indicator variable for a given variable and a value. | p. 282 |
| `get_linrelax` | Get the linear relaxation for a constraint | p. 283 |
| `get_linrelax_solver` | Returns a linear relaxation solver from a linear relaxation, an objective variables and some configuration parameters | p. 272 |
| `get_reduced_cost` | Get a reduced cost value from a linear relaxation solver | p. 285 |
| `get_relaxed_value` | Returns the optimal relaxed value for a variable in a relaxation | p. 286 |
| `KALIS_LARGEST_REDUCED_COST` | Get a largest reduced cost variable selector from a linear relaxation solver | p. 269 |

| | | |
|---|---|---|
| KALIS_NEAREST_RELAXED_VALUE | Get a nearest relaxed value selector from a linear relaxation solver | p. 270 |
| lp_optimize | Launch LP/MIP solver without CP branching. | p. 280 |
| set_integer | Set integrality flag for a variable in a linear relaxation | p. 287 |
| set_linrelax_solver_attribute | Parameter setting for a linear relaxation solver. | p. 281 |
| set_verbose_level | Set the verbose level for a specific linear relaxation solver | p. 274 |

# II. Reference Manual

Chapter 7

# Constants


KALIS_ALL_CONSTRAINTS Set of all the constraints p. 49

KALIS_BARRIER Set the solution algorithm for the relaxation to barrier p. 53

KALIS_BILEVEL_RELAX_SOLVER Bilevel node relaxation solver configuration p. 48

KALIS_COPYRIGHT Xpress Kalis copyright information p. 39

KALIS_DISCRETE_RESOURCE Discrete resource p. 40

KALIS_DISJ_INPUT_ORDER Input order disjunction selection heuristic p. 43

KALIS_DISJ_PRIORITY_ORDER Input order disjunction selection heuristic p. 43

KALIS_DISJUNCTIONS Disjunctions propagation type for unary resource constraints p. 44

KALIS_DISTANCE_CONSTRAINTS Set of the distance constraints p. 49

KALIS_DUAL_SIMPLEX Set the solution algorithm for the relaxation to dual simplex p. 53

KALIS_EDGE_FINDING Tasks Interval + Edge finding propagation type for discrete resource constraints p. 44

KALIS_FORWARD_CHECKING Forward checking propagation type for the all_different constraint p. 32

KALIS_GEN_ARC_CONSISTENCY Generalized arc consistency propagation type for the all_different constraint p. 32

KALIS_INITIAL_SOLUTION Schedule search strategy choice: heuristic solution p. 44

KALIS_INPUT_ORDER Input Order variable selection heuristic p. 34

KALIS_LARGEST_ECT Largest Earliest Completion time task selection heuristic p. 41

KALIS_LARGEST_EST Largest Earliest Start time task selection heuristic p. 41

KALIS_LARGEST_LCT Largest Latest Completion time task selection heuristic p. 42

KALIS_LARGEST_LST Largest Latest Start time task selection heuristic p. 42

KALIS_LARGEST_MAX Largest maximum variable selection heuristic p. 35

KALIS_LARGEST_MIN Largest minimum variable selection heuristic p. 35

KALIS_LINEAR_CONSTRAINTS Set of linear constraints p. 48

KALIS_LOGICAL_CONSTRAINTS Set of logical constraints p. 49

KALIS_MAX_DEGREE Maximum constraint graph degree variable selection heuristic p. 35

KALIS_MAX_MIN_BOUND_CONSISTENCY Propagation level for maximum and minimum constraints p. 47

KALIS_MAX_TO_MIN Maximum to minimum value selection heuristic p. 38

KALIS_MAXIMIZE Maximize objective in linear relaxation p. 50

KALIS_MAXREGRET_LB Maximum regret on the lower bound variable selection heuristic p. 36

KALIS_MAXREGRET_UB Maximum regret on the upper bound variable selection heuristic p. 36

KALIS_MIDDLE_VALUE Middle value selection heuristic p. 38

KALIS_MIN_TO_MAX Minimum to maximum value selection heuristic p. 38

KALIS_MINIMIZE Minimize objective in linear relaxation p. 50

KALIS_NB_SOLUTIONS Number of solutions already found for the problem p. 47

KALIS_NEAREST_VALUE Nearest to target value selection heuristic p. 39

KALIS_NETWORK_SIMPLEX Set the solution algorithm for the relaxation to network simplex p. 53

KALIS_NON_LINEAR_CONSTRAINTS Set of non linear constraints p. 49

KALIS_OPTIMAL_SOLUTION Schedule search strategy choice: improving bound and prove optimality p. 45

KALIS_PRIMAL_SIMPLEX Set the solution algorithm for the relaxation to primal simplex p. 52

KALIS_RANDOM_SEED Seed of the random generator p. 39

KALIS_RANDOM_VALUE Random value selection heuristic p. 39

KALIS_RANDOM_VARIABLE Random variable selection heuristic p. 36

KALIS_RELAX_ALGORITHM Set the solution algorithm for the relaxation p. 51

KALIS_RELAX_MIP Set MIP search flag for the linear relaxation p. 51

KALIS_RELAX_MIP_ABS_STOP Set the MIP absolute tolerance to optimality for the resolution of the linear relaxation solver p. 52

KALIS_RELAX_MIP_REL_STOP Set the MIP relative tolerance to optimality for the resolution of the linear relaxation solver p. 52

KALIS_RELAX_OPT_TOL Set the optimality tolerance for the resolution of the linear relaxation solver p. 52

KALIS_RELAX_PRESOLVE Use presolve for relaxation p. 50

KALIS_RELAX_RCOSTS_PROPAG Use reduced costs for propagation p. 51

KALIS_RELAX_RELOAD_BASIS Use reload basis for relaxation p. 51

KALIS_RESET_OPT_PARAMS Group parameter choice for strategy optimisation p. 46

KALIS_RESET_PARAMS_ALL Group parameter choice for all parameters p. 45

KALIS_RESET_SEARCH_PARAMS Group parameter choice for strategy properties p. 47

KALIS_RESET_VAR_BOUNDS Group parameter choice for variable bounds p. 46

KALIS_RESET_VAR_PRECISION Group parameter choice for variable precisions p. 46

KALIS_SDOMDEG_RATIO Smallest domain size to degree ratio variable selection heuristic. p. 36

KALIS_SLIM_BY_BACKTRACKS Type of limitation on the search tree p. 33

KALIS_SLIM_BY_DEPTH Type of limitation on the search tree p. 33

KALIS_SLIM_BY_NODES Type of limitation on the search tree p. 32

KALIS_SLIM_BY_SOLUTIONS Type of limitation on the search tree p. 33

KALIS_SLIM_BY_TIME Type of limitation on the search tree p. 33

KALIS_SLIM_UNREACHED Type of limitation on the search tree p. 32

KALIS_SMALLEST_DOMAIN Smallest domain variable selection heuristic (finite domain and continuous variables) p. 37

KALIS_SMALLEST_ECT Smallest Earliest Completion time task selection heuristic p. 40

KALIS_SMALLEST_EST Smallest Earliest Start time task selection heuristic p. 40

KALIS_SMALLEST_LCT Smallest Latest Completion time task selection heuristic p. 41

KALIS_SMALLEST_LST Smallest Latest Start time task selection heuristic p. 41

KALIS_SMALLEST_MAX Smallest maximum variable selection heuristic p. 37

KALIS_SMALLEST_MIN Smallest minimum variable selection heuristic p. 37

KALIS_SOLVE_AS_LP Use LP relaxation p. 50

KALIS_SOLVE_AS_MIP Use MIP relaxation p. 50

KALIS_TASK_INPUT_ORDER Input order task selection heuristic p. 42

KALIS_TASK_INTERVALS Task intervals propagation type for resource constraints p. 43

KALIS_TASK_RANDOM_ORDER Random order task selection heuristic p. 42

KALIS_TASK_VARIABLES_DOMAIN_TYPE Control if task variables are using bound domains or dense domains p. 47

KALIS_TIMETABLING Timetabling propagation type for resource constraints p. 43

KALIS_TLIM_ABS_OPT Limitation on the optimization through absolute tolerance p. 34

KALIS_TLIM_REL_OPT Limitation on the optimization through relative tolerance p. 34

KALIS_TLIM_UNREACHED No limitation on the optimization due to tolerance limits p. 34

KALIS_TOPNODE_RELAX_SOLVER Top node relaxation solver configuration p. 48

KALIS_TREENODE_RELAX_SOLVER Tree node relaxation solver configuration p. 48

KALIS_UNARY_RESOURCE Unary resource p. 40

KALIS_WIDEST_DOMAIN Widest domain variable selection heuristic (continuous variables) p. 38

## KALIS_FORWARD_CHECKING

**Description** Forward checking propagation type for the all_different constraint

**Type** Integer, read only

**Values** 0

**Notes** This constant is passed to the `all_different` constraint to specify the kind of propagation used to filter it. When KALIS_FORWARD_CHECKING is used, the filtering algorithm achieves a very simple, and fast, filtering. Although less powerful than the generalized algorithm (KALIS_GEN_ARC_CONSISTENCY) that may lead to a stronger pruning, the speed of the KALIS_FORWARD_CHECKING filtering allows the search process to explore more nodes in the same amount of time which makes the algorithm competitive for simple problems.

**See also** `all_different` `KALIS_GEN_ARC_CONSISTENCY`

## KALIS_GEN_ARC_CONSISTENCY

**Description** Generalized arc consistency propagation type for the all_different constraint

**Type** Integer, read only

**Values** 3

**Notes** This constant is passed to the `all_different` constraint to specify the kind of propagation used to filter it. When KALIS_GEN_ARC_CONSISTENCY is used, the filtering algorithm achieves generalized arc-consistency (cf. [R94]). Although this algorithm may filter more values than the KALIS_FORWARD_CHECKING algorithm, this additional pruning comes at the price of a computational overhead at each node that is not necessary for simple problems.

**See also** `all_different` `KALIS_FORWARD_CHECKING`

## KALIS_SLIM_UNREACHED

**Description** Type of limitation on the search tree

**Type** Integer, read only

**Values** 0

**Notes** This constant represents the value of the parameter `KALIS_SEARCH_LIMIT` when no limitation of the search process has occurred.

**See also** `KALIS_SLIM_BY_NODES` `KALIS_SLIM_BY_SOLUTIONS` `KALIS_SLIM_BY_DEPTH` `KALIS_SLIM_BY_TIME` `KALIS_SLIM_BY_BACKTRACKS`

## KALIS_SLIM_BY_NODES

**Description** Type of limitation on the search tree

**Type** Integer, read only

**Values** 1

**Notes** This constant represents the value of the parameter `KALIS_SEARCH_LIMIT` when the maximum number of nodes allowed for the search process has been reached.

**See also** KALIS_SLIM_BY_NODES KALIS_SLIM_BY_SOLUTIONS KALIS_SLIM_BY_DEPTH KALIS_SLIM_BY_TIME KALIS_SLIM_BY_BACKTRACKS

## KALIS_SLIM_BY_SOLUTIONS

**Description** Type of limitation on the search tree

**Type** Integer, read only

**Values** 2

**Notes** This constant represents the value of the parameter KALIS_SEARCH_LIMIT when the maximum number of solutions to be found during the search process has been reached.

**See also** KALIS_SLIM_BY_NODES KALIS_SLIM_BY_SOLUTIONS KALIS_SLIM_BY_DEPTH KALIS_SLIM_BY_TIME KALIS_SLIM_BY_BACKTRACKS

## KALIS_SLIM_BY_DEPTH

**Description** Type of limitation on the search tree

**Type** Integer, read only

**Values** 3

**Notes** This constant represents the value of the parameter KALIS_SEARCH_LIMIT when the maximum depth of the search tree has been reached.

**See also** KALIS_SLIM_BY_NODES KALIS_SLIM_BY_SOLUTIONS KALIS_SLIM_BY_DEPTH KALIS_SLIM_BY_TIME KALIS_SLIM_BY_BACKTRACKS

## KALIS_SLIM_BY_TIME

**Description** Type of limitation on the search tree

**Type** Integer, read only

**Values** 4

**Notes** This constant represents the value of the parameter KALIS_SEARCH_LIMIT when the maximum computation time allowed to the search process has been reached.

**See also** KALIS_SLIM_BY_NODES KALIS_SLIM_BY_SOLUTIONS KALIS_SLIM_BY_DEPTH KALIS_SLIM_BY_TIME KALIS_SLIM_BY_BACKTRACKS

## KALIS_SLIM_BY_BACKTRACKS

**Description** Type of limitation on the search tree

**Type** Integer, read only

**Values** 5

**Notes** This constant represents the value of the parameter KALIS_SEARCH_LIMIT when the maximum number of backtracks was reached during the search process and the search process was interrupted.

**See also** KALIS_SLIM_BY_NODES KALIS_SLIM_BY_SOLUTIONS KALIS_SLIM_BY_DEPTH KALIS_SLIM_BY_TIME KALIS_SLIM_BY_BACKTRACKS

## KALIS_TLIM_UNREACHED

**Description** No limitation on the optimization due to tolerance limits

**Type** Integer, read only

**Values** `0`

**Notes** This constant represents the value of the parameter `KALIS_TOLERANCE_LIMIT` when no limitation of the optimization process has occurred.

**See also** `KALIS_TLIM_UNREACHED` `KALIS_TLIM_ABS_OPT` `KALIS_TLIM_REL_OPT`

## KALIS_TLIM_ABS_OPT

**Description** Limitation on the optimization through absolute tolerance

**Type** Integer, read only

**Values** `1`

**Notes** This constant represents the value of the parameter `KALIS_TOLERANCE_LIMIT` when the search process has been interrupted due to an absolute tolerance limit.

**See also** `KALIS_TLIM_UNREACHED` `KALIS_TLIM_ABS_OPT` `KALIS_TLIM_REL_OPT`

## KALIS_TLIM_REL_OPT

**Description** Limitation on the optimization through relative tolerance

**Type** Integer, read only

**Values** `2`

**Notes** This constant represents the value of the parameter `KALIS_TOLERANCE_LIMIT` when the search process has been interrupted due to a relative tolerance limit

**See also** `KALIS_TLIM_UNREACHED` `KALIS_TLIM_ABS_OPT`

## KALIS_INPUT_ORDER

**Description** Input Order variable selection heuristic

**Type** String, read only

**Values** `*a`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The input order heuristic selects non-instantiated variables with the smallest index for indexed containers and in the order of iteration for ordered containers such as lists and arrays.

**See also** `KALIS_MAX_DEGREE` `KALIS_LARGEST_MIN` `KALIS_LARGEST_MAX` `KALIS_MAXREGRET_LB` `KALIS_MAXREGRET_UB` `KALIS_RANDOM_VARIABLE` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_MAX_DEGREE

**Description** Maximum constraint graph degree variable selection heuristic

**Type** String, read only

**Values** `*b`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The max degree heuristic selects non-instantiated variables with the largest degree in the constraint graph (*i.e.*, that are involved in the maximum number of different constraints).

**See also** `KALIS_INPUT_ORDER` `KALIS_LARGEST_MIN` `KALIS_LARGEST_MAX` `KALIS_MAXREGRET_LB` `KALIS_MAXREGRET_UB` `KALIS_RANDOM_VARIABLE` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_LARGEST_MIN

**Description** Largest minimum variable selection heuristic

**Type** String, read only

**Values** `*c`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The largest min heuristic selects non-instantiated variables with the largest lower bound.

**See also** `KALIS_INPUT_ORDER` `KALIS_MAX_DEGREE` `KALIS_LARGEST_MAX` `KALIS_MAXREGRET_LB` `KALIS_MAXREGRET_UB` `KALIS_RANDOM_VARIABLE` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_LARGEST_MAX

**Description** Largest maximum variable selection heuristic

**Type** String, read only

**Values** `*d`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The largest maximum heuristic selects non-instantiated variables with the largest upper bound.

**See also** `KALIS_INPUT_ORDER` `KALIS_MAX_DEGREE` `KALIS_LARGEST_MIN` `KALIS_MAXREGRET_LB` `KALIS_MAXREGRET_UB` `KALIS_RANDOM_VARIABLE` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_MAXREGRET_LB

**Description** Maximum regret on the lower bound variable selection heuristic

**Type** String, read only

**Values** `*e`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. This variable selection will select the variable maximizing the distance between its lower bound and its second-smallest value.

**See also** `KALIS_INPUT_ORDER` `KALIS_MAX_DEGREE` `KALIS_LARGEST_MIN` `KALIS_LARGEST_MAX` `KALIS_MAXREGRET_UB` `KALIS_RANDOM_VARIABLE` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_MAXREGRET_UB

**Description** Maximum regret on the upper bound variable selection heuristic

**Type** String, read only

**Values** `*f`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. This variable selection will select the variable maximizing the distance between its upper bound and the second-largest value.

**See also** `KALIS_INPUT_ORDER` `KALIS_MAX_DEGREE` `KALIS_LARGEST_MIN` `KALIS_LARGEST_MAX` `KALIS_MAXREGRET_LB` `KALIS_RANDOM_VARIABLE` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_RANDOM_VARIABLE

**Description** Random variable selection heuristic

**Type** String, read only

**Values** `*g`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The random variable heuristic selects non-instantiated variables in a random order.

**See also** `KALIS_INPUT_ORDER` `KALIS_MAX_DEGREE` `KALIS_LARGEST_MIN` `KALIS_LARGEST_MAX` `KALIS_MAXREGRET_LB` `KALIS_MAXREGRET_UB` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_SDOMDEG_RATIO

**Description** Smallest domain size to degree ratio variable selection heuristic.

**Type** String, read only

**Values** `*h`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. This heuristic selects the variable having the smallest domain size to degree ratio. The degree of a variable is defined as the number of constraints using this variable.

**See also** KALIS_INPUT_ORDER KALIS_MAX_DEGREE KALIS_LARGEST_MIN KALIS_LARGEST_MAX KALIS_MAXREGRET_LB KALIS_MAXREGRET_UB KALIS_RANDOM_VARIABLE KALIS_SMALLEST_DOMAIN KALIS_SMALLEST_MAX KALIS_SMALLEST_MIN

## KALIS_SMALLEST_DOMAIN

**Description** Smallest domain variable selection heuristic (finite domain and continuous variables)

**Type** String, read only

**Values** `*i`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The smallest domain heuristic selects non instantiated variables with the smallest domain size (number of distinct values in the domain).

**See also** KALIS_INPUT_ORDER KALIS_MAX_DEGREE KALIS_LARGEST_MIN KALIS_LARGEST_MAX KALIS_MAXREGRET_LB KALIS_MAXREGRET_UB KALIS_RANDOM_VARIABLE KALIS_SDOMDEG_RATIO KALIS_SMALLEST_MAX KALIS_SMALLEST_MIN KALIS_WIDEST_DOMAIN

## KALIS_SMALLEST_MAX

**Description** Smallest maximum variable selection heuristic

**Type** String, read only

**Values** `*j`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The smallest maximum heuristic selects non instantiated variables with the smallest upper bound.

**See also** KALIS_INPUT_ORDER KALIS_MAX_DEGREE KALIS_LARGEST_MIN KALIS_LARGEST_MAX KALIS_MAXREGRET_LB KALIS_MAXREGRET_UB KALIS_RANDOM_VARIABLE KALIS_SDOMDEG_RATIO KALIS_SMALLEST_DOMAIN KALIS_SMALLEST_MIN

## KALIS_SMALLEST_MIN

**Description** Smallest minimum variable selection heuristic

**Type** String, read only

**Values** `*k`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the variable selection heuristic. The smallest mininimum heuristic selects non instantiated variables with the smallest lower bound.

**See also** KALIS_INPUT_ORDER KALIS_MAX_DEGREE KALIS_LARGEST_MIN KALIS_LARGEST_MAX KALIS_MAXREGRET_LB KALIS_MAXREGRET_UB KALIS_RANDOM_VARIABLE KALIS_SDOMDEG_RATIO KALIS_SMALLEST_DOMAIN KALIS_SMALLEST_MAX

## KALIS_WIDEST_DOMAIN

**Description** Widest domain variable selection heuristic (continuous variables)

**Type** String, read only

**Values** `*1`

**Notes** Passes this constant to the constructor of branching schemes for continuous decision variables (`split_domain`) to specify the variable selection heuristic. The widest domain heuristic selects non instantiated variables with the largest value interval.

**See also** `KALIS_INPUT_ORDER` `KALIS_MAX_DEGREE` `KALIS_LARGEST_MIN` `KALIS_LARGEST_MAX` `KALIS_MAXREGRET_LB` `KALIS_MAXREGRET_UB` `KALIS_RANDOM_VARIABLE` `KALIS_SDOMDEG_RATIO` `KALIS_SMALLEST_DOMAIN` `KALIS_SMALLEST_MAX` `KALIS_SMALLEST_MIN`

## KALIS_MAX_TO_MIN

**Description** Maximum to minimum value selection heuristic

**Type** String, read only

**Values** `+1`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the value selection heuristic. The max to min heuristic selects values in decreasing order.

**See also** `KALIS_MIN_TO_MAX` `KALIS_MIDDLE_VALUE` `KALIS_NEAREST_VALUE` `KALIS_RANDOM_VALUE`

## KALIS_MIN_TO_MAX

**Description** Minimum to maximum value selection heuristic

**Type** String, read only

**Values** `+2`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the value selection heuristic. The min to max heuristic selects values in increasing order.

**See also** `KALIS_MAX_TO_MIN` `KALIS_MIDDLE_VALUE` `KALIS_NEAREST_VALUE` `KALIS_RANDOM_VALUE`

## KALIS_MIDDLE_VALUE

**Description** Middle value selection heuristic

**Type** String, read only

**Values** `+3`

**Notes** Passes this constant to the constructor of branching schemes (for example `assign_var`) to specify the value selection heuristic. The middle value heuristic selects the value in the domain of a variable that minimizes the distance to the median value of the domain.

**See also** KALIS_MAX_TO_MIN KALIS_MIN_TO_MAX KALIS_NEAREST_VALUE KALIS_RANDOM_VALUE

## KALIS_NEAREST_VALUE

**Description** Nearest to target value selection heuristic

**Type** String, read only

**Values** +4

**Notes** Passes this constant to the constructor of branching schemes (for example assign_var) to specify the value selection heuristic. The nearest value heuristic selects the value in the domain of a variable that minimizes the distance to the target value of the variable.

**See also** KALIS_MAX_TO_MIN KALIS_MIN_TO_MAX KALIS_MIDDLE_VALUE KALIS_RANDOM_VALUE

## KALIS_RANDOM_VALUE

**Description** Random value selection heuristic

**Type** String, read only

**Values** +5

**Notes** Passes this constant to the constructor of branching schemes (for example assign_var) to specify the value selection heuristic. The random value heuristic selects a random value in the domain of a variable.

**See also** KALIS_MAX_TO_MIN KALIS_MIN_TO_MAX KALIS_MIDDLE_VALUE KALIS_NEAREST_VALUE

## KALIS_RANDOM_SEED

**Description** Seed of the random generator

**Type** Integer, read/write

**Values** 0

**Notes** Initialize the random number generator.

## KALIS_COPYRIGHT

**Description** Xpress Kalis copyright information

**Type** String, read only

**Values** (c) Copyright Artelys S.A. 2000-2026

## KALIS_UNARY_RESOURCE

**Description** Unary resource

**Type** Integer, read only

**Values** 0

**Notes** Passes this constant to the `set_resource_attributes` subroutine to specify a unary resource (a resource that can be used only by one task at a time).

**See also** `KALIS_DISCRETE_RESOURCE`

## KALIS_DISCRETE_RESOURCE

**Description** Discrete resource

**Type** Integer, read only

**Values** 1

**Notes** Passes this constant to the `set_resource_attributes` subroutine to specify a discrete resource (a resource than can be used by several tasks at the same time).

**See also** `KALIS_UNARY_RESOURCE`

## KALIS_SMALLEST_ECT

**Description** Smallest Earliest Completion time task selection heuristic

**Type** String, read only

**Values** $1

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT KALIS_SMALLEST_EST KALIS_SMALLEST_LCT KALIS_SMALLEST_LST KALIS_LARGEST_ECT KALIS_LARGEST_EST KALIS_LARGEST_LCT KALIS_LARGEST_LST`

## KALIS_SMALLEST_EST

**Description** Smallest Earliest Start time task selection heuristic

**Type** String, read only

**Values** $2

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT KALIS_SMALLEST_EST KALIS_SMALLEST_LCT KALIS_SMALLEST_LST KALIS_LARGEST_ECT KALIS_LARGEST_EST KALIS_LARGEST_LCT KALIS_LARGEST_LST`

## KALIS_SMALLEST_LCT

**Description** Smallest Latest Completion time task selection heuristic

**Type** String, read only

**Values** `$3`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_SMALLEST_LST

**Description** Smallest Latest Start time task selection heuristic

**Type** String, read only

**Values** `$4`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_LARGEST_ECT

**Description** Largest Earliest Completion time task selection heuristic

**Type** String, read only

**Values** `$5`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_LARGEST_EST

**Description** Largest Earliest Start time task selection heuristic

**Type** String, read only

**Values** `$6`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_LARGEST_LCT

**Description** Largest Latest Completion time task selection heuristic

**Type** String, read only

**Values** `$7`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_LARGEST_LST

**Description** Largest Latest Start time task selection heuristic

**Type** String, read only

**Values** `$8`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_TASK_INPUT_ORDER

**Description** Input order task selection heuristic

**Type** String, read only

**Values** `$9`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_TASK_RANDOM_ORDER` `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_TASK_RANDOM_ORDER

**Description** Random order task selection heuristic

**Type** String, read only

**Values** `$a`

**Notes** Passes this constant to the constructor of `task_serialize` to specify the task selection heuristic.

**See also** `KALIS_TASK_INPUT_ORDER` `KALIS_SMALLEST_ECT` `KALIS_SMALLEST_EST` `KALIS_SMALLEST_LCT` `KALIS_SMALLEST_LST` `KALIS_LARGEST_ECT` `KALIS_LARGEST_EST` `KALIS_LARGEST_LCT` `KALIS_LARGEST_LST`

## KALIS_DISJ_INPUT_ORDER

**Description** Input order disjunction selection heuristic

**Type** String, read only

**Values** `%0`

**Notes** Passes this constant to the constructor of `settle_disjunction` or `probe_settle_disjunction` to specify the disjunction selection heuristic.

**See also** `KALIS_DISJ_PRIORITY_ORDER`

## KALIS_DISJ_PRIORITY_ORDER

**Description** Input order disjunction selection heuristic

**Type** String, read only

**Values** `%1`

**Notes** Passes this constant to the constructor of `settle_disjunction` or `probe_settle_disjunction` to specify the disjunction selection heuristic.

**See also** `KALIS_DISJ_INPUT_ORDER`

## KALIS_TIMETABLING

**Description** Timetabling propagation type for resource constraints

**Type** Integer, read only

**Values** `1`

**Notes** This constant is passed to the `set_resource_attributes` function to specify the kind of propagation to be used for filtering the resource constraint. The KALIS_TIMETABLING filtering algorithm achieves a very simple and fast filtering. Although less powerful than the algorithms KALIS_DISJUNCTIONS (unary resources only) and KALIS_TASK_INTERVALS that may lead to a stronger pruning, the speed of the KALIS_TIMETABLING filtering allows the search process to explore more nodes in the same amount of time which makes the algorithm competitive for simple problems and also for very large problems where the computational overhead of other filtering algorithms is prohibitive.

**See also** `KALIS_TASK_INTERVALS` `KALIS_DISJUNCTIONS` `KALIS_EDGE_FINDING`

## KALIS_TASK_INTERVALS

**Description** Task intervals propagation type for resource constraints

**Type** Integer, read only

**Values** `2`

**Notes** This constant is passed to the `set_resource_attributes` procedure to specify the type of propagation to be used for filtering the resource constraint. The KALIS_TASK_INTERVALS filtering algorithm achieves a very strong and relatively slow filtering. Although more powerful than the simple algorithm (KALIS_TIMETABLING), the computational cost of the KALIS_TASK_INTERVALS filtering makes it competitive for medium sized hard problems but is prohibitive for large problems with many tasks per resource (cf. [CL94a], [CL94b]).

**See also** `KALIS_TIMETABLING` `KALIS_DISJUNCTIONS` `KALIS_EDGE_FINDING`

## KALIS_DISJUNCTIONS

**Description** Disjunctions propagation type for unary resource constraints

**Type** Integer, read only

**Values** `4`

**Notes** This constant is passed to the `set_resource_attributes` procedure to specify the type of propagation to be used for filtering the resource constraint for unary resources. With KALIS_DISJUNCTIONS the resource constraint will be implemented as n*(n-1)/2 disjunctions between pairs of tasks. This algorithm is more powerful than the KALIS_TIMETABLING algorithm but less powerful than the algorithm KALIS_TASK_INTERVALS that may lead to a stronger pruning at the cost of additional computation overhead. This algorithm is generally competitive for small to medium size problems where the number of tasks using the resource is not overly large.

**See also** `KALIS_TASK_INTERVALS` `KALIS_TIMETABLING` `KALIS_EDGE_FINDING`

## KALIS_EDGE_FINDING

**Description** Tasks Interval + Edge finding propagation type for discrete resource constraints

**Type** Integer, read only

**Values** `4`

**Notes** This constant is passed to the `set_resource_attributes` procedure to specify the kind of propagation used to filter the resource constraint. When KALIS_EDGE_FINDING is used, the resource constraint will add Edge finding propagation rules to the Tasks Interval propgation scheme. This algorithm is more powerful than KALIS_TASK_INTERVALS algorithm and may lead to a stronger pruning at the cost of additional computation overhead. This algorithm is generally competitive for small to medium size problems where the number of tasks using the resource is not too large (cf. [LP96], [MVH08]).

**See also** `KALIS_TASK_INTERVALS` `KALIS_TIMETABLING` `KALIS_DISJUNCTIONS`

## KALIS_INITIAL_SOLUTION

**Description** Schedule search strategy choice: heuristic solution

**Type** Integer, read only

**Values** `0`

**Notes** This constant is passed to the `cp_set_schedule_strategy` subroutine to specify the phase of the algorithm. KALIS_INITIAL_SOLUTION denotes the first phase of the algorithm and KALIS_OPTIMAL_SOLUTION selects the second phase of the algorithm.

**See also** `KALIS_OPTIMAL_SOLUTION` `cp_schedule`

## KALIS_OPTIMAL_SOLUTION

**Description** Schedule search strategy choice: improving bound and prove optimality

**Type** Integer, read only

**Values** `1`

**Notes** This constant is passed to the `cp_set_schedule_strategy` subroutine to specify the phase of the algorithm. KALIS_INITIAL_SOLUTION denotes the first phase of the algorithm and KALIS_OPTIMAL_SOLUTION selects the second phase of the algorithm.

**See also** `KALIS_INITIAL_SOLUTION` `cp_schedule`

## KALIS_RESET_PARAMS_ALL

**Description** Group parameter choice for all parameters

**Type** Integer, read only

**Values** `0`

**Notes** This constant is passed to the `cp_reset_params` procedure to specify the group of control parameters. KALIS_RESET_PARAMS_ALL resets all variables and strategy parameters:

- KALIS_DEFAULT_LB
- KALIS_DEFAULT_UB
- KALIS_DEFAULT_CONTINUOUS_LB
- KALIS_DEFAULT_CONTINUOUS_UB
- KALIS_DEFAULT_PRECISION_VALUE
- KALIS_DEFAULT_PRECISION_RELATIVITY
- KALIS_AUTO_PROPAGATE
- KALIS_OPTIMIZE_WITH_RESTART
- KALIS_DICHOTOMIC_OBJ_SEARCH
- KALIS_USE_3B_CONSISTENCY
- KALIS_VERBOSE_LEVEL
- KALIS_MAX_NODES
- KALIS_MAX_SOLUTIONS
- KALIS_MAX_DEPTH
- KALIS_OPT_ABS_TOLERANCE
- KALIS_OPT_REL_TOLERANCE
- KALIS_MAX_BACKTRACKS
- KALIS_MAX_COMPUTATION_TIME
- KALIS_MAX_NODES_BETWEEN_SOLUTIONS

## KALIS_RESET_VAR_BOUNDS

**Description** Group parameter choice for variable bounds

**Type** Integer, read only

**Values** 1

**Notes** This constant is passed to the `cp_reset_params` procedure to specify the group of control parameters. KALIS_RESET_VAR_BOUNDS resets bounds of discrete and continuous variables:

- KALIS_DEFAULT_LB
- KALIS_DEFAULT_UB
- KALIS_DEFAULT_CONTINUOUS_LB
- KALIS_DEFAULT_CONTINUOUS_UB

## KALIS_RESET_VAR_PRECISION

**Description** Group parameter choice for variable precisions

**Type** Integer, read only

**Values** 2

**Notes** This constant is passed to the cp_reset_params function to specify the group of control parameters. KALIS_RESET_VAR_PRECISION resets the precision for continuous variables:

- KALIS_DEFAULT_PRECISION_VALUE
- KALIS_DEFAULT_PRECISION_RELATIVITY

## KALIS_RESET_OPT_PARAMS

**Description** Group parameter choice for strategy optimisation

**Type** Integer, read only

**Values** 3

**Notes** This constant is passed to the `cp_reset_params` procedure to specify the group of control parameters. KALIS_RESET_OPT_PARAMS resets mechanisms of search:

- KALIS_AUTO_PROPAGATE
- KALIS_OPTIMIZE_WITH_RESTART
- KALIS_DICHOTOMIC_OBJ_SEARCH
- KALIS_USE_3B_CONSISTENCY

## KALIS_RESET_SEARCH_PARAMS

**Description** Group parameter choice for strategy properties

**Type** Integer, read only

**Values** `4`

**Notes** This constant is passed to the `cp_reset_params` procedure to specify the group of control parameters. KALIS_RESET_SEARCH_PARAMS resets properties of search :

- KALIS_VERBOSE_LEVEL
- KALIS_MAX_NODES
- KALIS_MAX_SOLUTIONS
- KALIS_MAX_DEPTH
- KALIS_OPT_ABS_TOLERANCE
- KALIS_OPT_REL_TOLERANCE
- KALIS_MAX_BACKTRACKS
- KALIS_MAX_COMPUTATION_TIME
- KALIS_MAX_NODES_BETWEEN_SOLUTIONS

## KALIS_NB_SOLUTIONS

**Description** Number of solutions already found for the problem

**Type** Integer, read only

**Notes** This parameter indicates the number of found solutions for the problem.

## KALIS_MAX_MIN_BOUND_CONSISTENCY

**Description** For maximum and minimum constraints, if true only the bound consistency will be propagated (no holes in the domains).

**Type** Boolean, read/write

**Values** `true` default value

**See also** `maximum` `minimum`

## KALIS_TASK_VARIABLES_DOMAIN_TYPE

**Description** Control if task variables are using bound domains or dense domains. Must be set before the creation of the tasks.

**Type** Integer, read/write

**Values**

| | |
|---|---|
| `-1` | automatic setting |
| `0` | bound domain only |
| `1` | dense domain |

## KALIS_TOPNODE_RELAX_SOLVER

**Description** Top node relaxation solver configuration

**Type** Integer, read only

**Values** 200

**Notes** This constant is passed to the `get_linrelax_solver` function to specify the predefined relaxation solver configuration. In this configuration, the relaxation is solved only once at the top node of the search tree.

**See also** KALIS_BILEVEL_RELAX_SOLVER KALIS_TREENODE_RELAX_SOLVER

## KALIS_TREENODE_RELAX_SOLVER

**Description** Tree node relaxation solver configuration

**Type** Integer, read only

**Values** 201

**Notes** This constant is passed to the `get_linrelax_solver` function to specify the predefined relaxation solver configuration. In this configuration, the relaxation is solved at all nodes (except the top node) of the search tree.

**See also** KALIS_TOPNODE_RELAX_SOLVER KALIS_BILEVEL_RELAX_SOLVER

## KALIS_BILEVEL_RELAX_SOLVER

**Description** Bilevel node relaxation solver configuration

**Type** Integer, read only

**Values** 202

**Notes** This constant is passed to the `get_linrelax_solver` function to specify the predefined relaxation solver configuration. In this configuration, the relaxation is solved only when a user defined set of variables are instantiated (by default all the cpfloatvars).

**See also** KALIS_TOPNODE_RELAX_SOLVER KALIS_TREENODE_RELAX_SOLVER

## KALIS_LINEAR_CONSTRAINTS

**Description** Set of linear constraints

**Type** Integer, read only

**Values** 0

**Notes** This constant is passed to the `cp_get_linrelax` function to specify the type of constraints to be relaxed.

**See also** KALIS_NON_LINEAR_CONSTRAINTS KALIS_LOGICAL_CONSTRAINTS KALIS_DISTANCE_CONSTRAINTS KALIS_ALL_CONSTRAINTS cp_get_linrelax

## KALIS_NON_LINEAR_CONSTRAINTS

**Description** Set of non linear constraints

**Type** Integer, read only

**Values** 1

**Notes** This constant is passed to the cp_get_linrelax function to specify the type of constraints to be relaxed.

**See also** KALIS_LINEAR_CONSTRAINTS KALIS_LOGICAL_CONSTRAINTS KALIS_DISTANCE_CONSTRAINTS KALIS_ALL_CONSTRAINTS cp_get_linrelax

## KALIS_LOGICAL_CONSTRAINTS

**Description** Set of logical constraints

**Type** Integer, read only

**Values** 2

**Notes** This constant is passed to the cp_get_linrelax function to specify the type of constraints to be relaxed.

**See also** KALIS_LINEAR_CONSTRAINTS KALIS_NON_LINEAR_CONSTRAINTS KALIS_DISTANCE_CONSTRAINTS KALIS_ALL_CONSTRAINTS cp_get_linrelax

## KALIS_DISTANCE_CONSTRAINTS

**Description** Set of the distance constraints

**Type** Integer, read only

**Values** 3

**Notes** This constant is passed to the cp_get_linrelax function to specify the type of constraints to be relaxed.

**See also** KALIS_LINEAR_CONSTRAINTS KALIS_NON_LINEAR_CONSTRAINTS KALIS_LOGICAL_CONSTRAINTS KALIS_ALL_CONSTRAINTS cp_get_linrelax

## KALIS_ALL_CONSTRAINTS

**Description** Set of all the constraints

**Type** Integer, read only

**Values** 4

**Notes** This constant is passed to the cp_get_linrelax function to specify the type of constraints to be relaxed.

**See also** KALIS_LINEAR_CONSTRAINTS KALIS_NON_LINEAR_CONSTRAINTS KALIS_LOGICAL_CONSTRAINTS KALIS_DISTANCE_CONSTRAINTS cp_get_linrelax

## KALIS_MINIMIZE

**Description** Minimize objective in linear relaxation

**Type** Integer, read only

**Values** `100`

**Notes** This constant is passed to the `lp_optimize` and `get_linrelax_solver` functions to specify the sense of objective.

## KALIS_MAXIMIZE

**Description** Maximize objective in linear relaxation

**Type** Integer, read only

**Values** `101`

**Notes** This constant is passed to the `lp_optimize` and `get_linrelax_solver` functions to specify the sense of objective.

## KALIS_SOLVE_AS_LP

**Description** Use LP relaxation

**Type** Integer, read only

**Values** `10`

**Notes** This constant is passed to the `get_linrelax_solver` function to specify the type of method use.

## KALIS_SOLVE_AS_MIP

**Description** Use MIP relaxation

**Type** Integer, read only

**Values** `11`

**Notes** This constant is passed to the `get_linrelax_solver` function to specify the type of method use.

## KALIS_RELAX_PRESOLVE

**Description** Use presolve for relaxation

**Type** Integer, read only

**Values** `10001`

**Notes** This constant is passed to the `set_linrelax_solver_attribute` procedure to select the parameter to set. Possible settings: 1 — use presolve, 0 — presolve off.

## KALIS_RELAX_RCOSTS_PROPAG

**Description** Use reduced costs for propagation

**Type** Integer, read only

**Values** `10002`

**Notes** This constant is passed to the `set_linrelax_solver_attribute` procedure to select the parameter to set. Possible settings: 1 — use reduced cost information, 0 — do not use reduced costs.

## KALIS_RELAX_RELOAD_BASIS

**Description** Use reload basis for relaxation

**Type** Integer, read only

**Values** `10003`

**Notes** This constant is passed to the `set_linrelax_solver_attribute` procedure to select the parameter to set. Possible settings: 1 — save/reload basis, 0 — do not load any basis.

## KALIS_RELAX_MIP

**Description** Set MIP search flag for the linear relaxation

**Type** Integer, read only

**Values** `10006`

**Notes** This constant is passed to the `set_linrelax_solver_attribute` procedure to select the parameter to set. Possible settings: 1 — treat problem as MIP, 0 — treat problem as LP (*i.e.*, ignore any MIP information).

## KALIS_RELAX_ALGORITHM

**Description** Set the solution algorithm for the relaxation

**Type** Integer, read only

**Values** `10005`

**Notes** This constant is passed to the `set_linrelax_solver_attribute` procedure to select the solution algorithm, possible values for this parameter: `KALIS_PRIMAL_SIMPLEX`, `KALIS_DUAL_SIMPLEX`, `KALIS_BARRIER`, `KALIS_NETWORK_SIMPLEX`

**See also** `KALIS_PRIMAL_SIMPLEX` `KALIS_DUAL_SIMPLEX` `KALIS_BARRIER` `KALIS_NETWORK_SIMPLEX`

## KALIS_RELAX_OPT_TOL

**Description** Set the optimality tolerance for the resolution of the linear relaxation solver

**Type** Integer, read only

**Values** `10010`

**Notes** This constant is passed to the procedure `set_linrelax_solver_attribute` as value for the `KALIS_RELAX_OPT_TOL` parameter.

**See also** `KALIS_RELAX_OPT_TOL`

## KALIS_RELAX_MIP_REL_STOP

**Description** Set the MIP relative tolerance to optimality for the resolution of the linear relaxation solver

**Type** Integer, read only

**Values** `10011`

**Notes** This constant is passed to the procedure `set_linrelax_solver_attribute` as value for the `KALIS_RELAX_MIP_REL_STOP` parameter.

**See also** `KALIS_RELAX_MIP_ABS_STOP`

## KALIS_RELAX_MIP_ABS_STOP

**Description** Set the MIP absolute tolerance to optimality for the resolution of the linear relaxation solver

**Type** Integer, read only

**Values** `10012`

**Notes** This constant is passed to the procedure `set_linrelax_solver_attribute` as value for the `KALIS_RELAX_MIP_ABS_STOP` parameter.

**See also** `KALIS_RELAX_MIP_REL_STOP`

## KALIS_PRIMAL_SIMPLEX

**Description** Set the solution algorithm for the relaxation to primal simplex

**Type** Integer, read only

**Values** `20001`

**Notes** This constant is passed to the procedure `set_linrelax_solver_attribute` as value for the `KALIS_RELAX_ALGORITHM` parameter.

**See also** `KALIS_RELAX_ALGORITHM`

## KALIS_DUAL_SIMPLEX

**Description** Set the solution algorithm for the relaxation to dual simplex

**Type** Integer, read only

**Values** `20002`

**Notes** This constant is passed to the procedure `set_linrelax_solver_attribute` as value for the `KALIS_RELAX_ALGORITHM` parameter.

**See also** `KALIS_RELAX_ALGORITHM`

## KALIS_BARRIER

**Description** Set the solution algorithm for the relaxation to barrier

**Type** Integer, read only

**Values** `20003`

**Notes** This constant is passed to the procedure `set_linrelax_solver_attribute` as value for the `KALIS_RELAX_ALGORITHM` parameter.

**See also** `KALIS_RELAX_ALGORITHM`

## KALIS_NETWORK_SIMPLEX

**Description** Set the solution algorithm for the relaxation to network simplex

**Type** Integer, read only

**Values** `20004`

**Notes** This constant is passed to the procedure `set_linrelax_solver_attribute` as value for the `KALIS_RELAX_ALGORITHM` parameter.

**See also** `KALIS_RELAX_ALGORITHM`

CHAPTER 8

# Parameters


KALIS_AUTO_PROPAGATE Propagates automatically p. 55

KALIS_AUTO_RELAX Use linear relaxation automatically p. 61

KALIS_BACKTRACKS Number of backtracks p. 56

KALIS_CHECK_SOLUTION Automated solution checking p. 59

KALIS_COMPUTATION_TIME Computation time p. 57

KALIS_DEFAULT_CONTINUOUS_LB Default lower bound for domains of cpfloatvar p. 59

KALIS_DEFAULT_CONTINUOUS_UB Default upper bound for domains of cpfloatvar p. 59

KALIS_DEFAULT_LB Default lower bound for finite domain variables p. 55

KALIS_DEFAULT_PRECISION_RELATIVITY Precision relativity for continuous variables p. 60

KALIS_DEFAULT_PRECISION_VALUE Default precision for continuous variables p. 60

KALIS_DEFAULT_SCHEDULE_HORIZ_MAX Default maximal time horizon for schedules p. 60

KALIS_DEFAULT_SCHEDULE_HORIZ_MIN Default minimal time horizon for schedules p. 60

KALIS_DEFAULT_UB Default upper bound for finite domain variables p. 55

KALIS_DEPTH Depth of tree search p. 56

KALIS_DICHOTOMIC_OBJ_SEARCH Uses a dichotomic strategy to find the optimal objective value p. 60

KALIS_MAX_BACKTRACKS Maximum number of backtracks p. 58

KALIS_MAX_COMPUTATION_TIME Maximum computation time p. 58

KALIS_MAX_DEPTH Maximum depth p. 57

KALIS_MAX_NODES Maximum number of nodes p. 57

KALIS_MAX_NODES_BETWEEN_SOLUTIONS Number of nodes between two solutions p. 58

KALIS_MAX_SOLUTIONS Maximum number of solutions p. 57

KALIS_NARY_OBJ_SEARCH Uses an n-ary search strategy to find the optimal objective value p. 62

KALIS_NODES Counter for number of nodes p. 56

KALIS_OPT_ABS_TOLERANCE Absolute optimality tolerance p. 58

KALIS_OPT_REL_TOLERANCE Relative optimality tolerance p. 59

| | | |
|---|---|---|
| KALIS_OPTIMIZE_WITH_RESTART | Whether to restart search after each solution | p. 55 |
| KALIS_SCHEDULE_ENABLE_SHAVING | Enable shaving during initial step of schedule search | p. 62 |
| KALIS_SEARCH_LIMIT | Search limit reached | p. 56 |
| KALIS_THREADS | Number of threads | p. 61 |
| KALIS_TOLERANCE_LIMIT | Tolerance limit reached | p. 56 |
| KALIS_USE_3B_CONSISTENCY | Activates 3B consistency for continuous variables | p. 61 |
| KALIS_VERBOSE_LEVEL | Verbosity level of Xpress Kalis | p. 61 |


## KALIS_DEFAULT_LB

**Description** Default lower bound for finite domain variables

**Type** Integer, read/write

**Values** `-10000` default value

**Notes** Sets the default lower bound for the initial domain of enumerated domain decision variables.

**See also** `KALIS_DEFAULT_UB` `getlb`

## KALIS_DEFAULT_UB

**Description** Default upper bound for finite domain variables

**Type** Integer, read/write

**Values** `+10000` default value

**Notes** Sets the default upper bound for the initial domain of enumerated domain decision variables.

**See also** `KALIS_DEFAULT_LB` `getub`

## KALIS_AUTO_PROPAGATE

**Description** Propagates automatically

**Type** Boolean, read/write

**Values** `true` default value

**Notes** Enables propagating constraints instead of posting them or searching for solutions. Note that domain definition of decision variables is always taken into account irrespective of whether this control is on or off.

**See also** `cp_propagate` `cp_post`

## KALIS_OPTIMIZE_WITH_RESTART

**Description** Decides whether to restart the search after each solution or to continue search from the present point with the new bound on the objective.

**Type** Boolean, read/write

**Values** `false` default value (no restart)

**Affects routines** `cp_minimize` `cp_maximize`

## KALIS_NODES

**Description** Counter for number of nodes

**Type** Integer, read only

**Notes** Current number of nodes explored by the branch and bound search. This parameter does not work with `cp_schedule`.

**See also** KALIS_MAX_NODES KALIS_DEPTH KALIS_BACKTRACKS KALIS_COMPUTATION_TIME

## KALIS_DEPTH

**Description** Depth of tree search

**Type** Integer, read only

**Notes** Maximal depth of the search tree reached by the branch and bound search. This parameter does not work with `cp_schedule`.

**See also** KALIS_MAX_DEPTH KALIS_NODES KALIS_BACKTRACKS KALIS_COMPUTATION_TIME

## KALIS_SEARCH_LIMIT

**Description** Search limit reached

**Type** Integer, read only

**Notes** Active search limit on the search process if any

**See also** KALIS_SLIM_UNREACHED KALIS_SLIM_BY_NODES KALIS_SLIM_BY_SOLUTIONS KALIS_SLIM_BY_DEPTH KALIS_SLIM_BY_TIME KALIS_SLIM_BY_BACKTRACKS

## KALIS_TOLERANCE_LIMIT

**Description** Tolerance limit reached

**Type** Integer, read only

**Notes** Active tolerance limit on the search process if any

**See also** KALIS_TLIM_UNREACHED KALIS_TLIM_ABS_OPT KALIS_TLIM_REL_OPT KALIS_OPT_REL_TOLERANCE KALIS_OPT_ABS_TOLERANCE

## KALIS_BACKTRACKS

**Description** Number of backtracks

**Type** Integer, read only

**Notes** Current number of backtracks that occurred during the branch and bound search.

**See also** KALIS_MAX_SOLUTIONS KALIS_MAX_NODES KALIS_MAX_COMPUTATION_TIME KALIS_MAX_DEPTH KALIS_MAX_BACKTRACKS KALIS_MAX_NODES_BETWEEN_SOLUTIONS

## KALIS_COMPUTATION_TIME

**Description** Computation time

**Type** Double, read only

**Notes** Current computation time (in seconds) of the search process.

**See also** KALIS_MAX_SOLUTIONS KALIS_MAX_NODES KALIS_MAX_COMPUTATION_TIME KALIS_MAX_DEPTH KALIS_MAX_BACKTRACKS KALIS_MAX_NODES_BETWEEN_SOLUTIONS

## KALIS_MAX_NODES

**Description** Maximum number of nodes

**Type** Integer, read/write

**Values**
- −1 default value (no limit)

**Notes** Limits the number of nodes explored during the branch and bound tree search.

**Affects routines** cp_find_next_sol cp_minimize cp_maximize

**See also** KALIS_NODES KALIS_MAX_SOLUTIONS KALIS_MAX_COMPUTATION_TIME KALIS_MAX_DEPTH KALIS_MAX_BACKTRACKS KALIS_MAX_NODES_BETWEEN_SOLUTIONS

## KALIS_MAX_SOLUTIONS

**Description** Maximum number of solutions

**Type** Integer, read/write

**Values**
- −1 default value (no limit)

**Notes** Limits the number of solutions to be found during the branch and bound tree search.

**Affects routines** cp_find_next_sol cp_minimize cp_maximize

**See also** KALIS_MAX_NODES KALIS_MAX_COMPUTATION_TIME KALIS_MAX_DEPTH KALIS_MAX_BACKTRACKS KALIS_MAX_NODES_BETWEEN_SOLUTIONS

## KALIS_MAX_DEPTH

**Description** Maximum depth

**Type** Integer, read/write

**Values**
- −1 default value (no limit)
- n>0 maximum depth limited to n levels.

**Notes** Limits the depth of the search tree during the branch and bound search. This parameter does not work with cp_schedule.

**Affects routines** cp_find_next_sol cp_minimize cp_maximize

**See also** KALIS_DEPTH KALIS_MAX_SOLUTIONS KALIS_MAX_NODES KALIS_MAX_COMPUTATION_TIME KALIS_MAX_BACKTRACKS KALIS_MAX_NODES_BETWEEN_SOLUTIONS

## KALIS_MAX_BACKTRACKS

**Description** Maximum number of backtracks

**Type** Integer, read/write

**Values** −1 default value (no limit)

**Notes** Limits the number of backtracks that can occur during the search process before termination

**Affects routines** `cp_find_next_sol` `cp_minimize` `cp_maximize`

**See also** `KALIS_BACKTRACKS` `KALIS_MAX_SOLUTIONS` `KALIS_MAX_NODES` `KALIS_MAX_COMPUTATION_TIME` `KALIS_MAX_DEPTH` `KALIS_MAX_NODES_BETWEEN_SOLUTIONS`

## KALIS_MAX_COMPUTATION_TIME

**Description** Maximum computation time

**Type** Double, read/write

**Values** −1 default value (no limit)

**Notes** Limits the maximum computation time (in seconds) allowed to the branch and bound

**Affects routines** `cp_find_next_sol` `cp_minimize` `cp_maximize`

**See also** `KALIS_COMPUTATION_TIME` `KALIS_MAX_SOLUTIONS` `KALIS_MAX_NODES` `KALIS_MAX_DEPTH` `KALIS_MAX_BACKTRACKS`

## KALIS_MAX_NODES_BETWEEN_SOLUTIONS

**Description** Number of nodes between two solutions

**Type** Integer, read/write

**Notes** Maximum number of nodes explored between two solutions. With `cp_schedule` the limit only applies to the last phase of the solution algorithm.

**Affects routines** `cp_minimize` `cp_maximize`

**See also** `KALIS_NODES` `KALIS_MAX_NODES` `KALIS_MAX_SOLUTIONS` `KALIS_MAX_COMPUTATION_TIME` `KALIS_MAX_DEPTH` `KALIS_MAX_BACKTRACKS`

## KALIS_OPT_ABS_TOLERANCE

**Description** Absolute optimality tolerance

**Type** Integer, read/write

**Values** 0 default value (no tolerance)

**Notes** Enables the search process to stop when the distance between the current solution and the overall optimum is ensured to be less than KALIS_OPT_ABS_TOLERANCE.

**Affects routines** `cp_minimize` `cp_maximize`

**See also** `KALIS_OPT_REL_TOLERANCE`

## KALIS_OPT_REL_TOLERANCE

**Description** Relative optimality tolerance

**Type** Double, read/write

**Values** `0.0` default value (no tolerance)

**Notes** Enables the search process to stop when the relative distance between the current solution and the overall optimum solution is ensured to be less than KALIS_OPT_REL_TOLERANCE.

**Affects routines** `cp_minimize` `cp_maximize`

**See also** `KALIS_OPT_ABS_TOLERANCE`

## KALIS_CHECK_SOLUTION

**Description** Automated solution checking

**Type** Integer, read/write

**Values** `false` default value (no solution checking)

**Notes** Enables the automated checking that the solution found is really a solution

**Affects routines** `cp_find_next_sol` `cp_minimize` `cp_maximize`

## KALIS_DEFAULT_CONTINUOUS_LB

**Description** Default lower bound for domains of cpfloatvar

**Type** Double, read/write

**Values** `-1000000` default value

**Notes** Sets the default lower bound for the initial domain of continuous decision variables

**See also** `KALIS_DEFAULT_CONTINUOUS_UB` `getlb`

## KALIS_DEFAULT_CONTINUOUS_UB

**Description** Default upper bound for domains of cpfloatvar

**Type** Double, read/write

**Values** `+1000000` default value

**Notes** Sets the default upper bound for the initial domain of continuous decision variables

**See also** `KALIS_DEFAULT_CONTINUOUS_LB` `getub`

## KALIS_DEFAULT_PRECISION_VALUE

**Description** Default precision for continuous variables

**Type** Double, read/write

**Values** `+1e-6` default value

**Notes** Default precision for continuous variables

**See also** `setprecision`

## KALIS_DEFAULT_PRECISION_RELATIVITY

**Description** Precision relativity for continuous variables

**Type** Boolean, read/write

**Values** `false` default value

**Notes** Precision relativity for continuous variables

**See also** `setprecision`

## KALIS_DEFAULT_SCHEDULE_HORIZ_MIN

**Description** Default minimal time horizon for schedules

**Type** Integer, read/write

**Values** `0` default value

**Notes** Default minimal time horizon for schedules

**See also** `KALIS_DEFAULT_SCHEDULE_HORIZ_MAX`

## KALIS_DEFAULT_SCHEDULE_HORIZ_MAX

**Description** Default maximal time horizon for schedules

**Type** Integer, read/write

**Values** `10000` default value

**Notes** Default maximal time horizon for schedules

**See also** `KALIS_DEFAULT_SCHEDULE_HORIZ_MIN`

## KALIS_DICHOTOMIC_OBJ_SEARCH

**Description** Uses a dichotomic strategy to find the optimal objective value

**Type** Boolean, read/write

**Values** `false` default value

**Notes** Uses a dichotomic strategy to find the optimal objective value. By default the optimization algorithm imposes an amelioration constraint stating that the objective value of the solution to be found must be better than the objective value of the best solution already found. With a dichotomic optimization strategy, this constraint is replaced by a binary search tree over the objective variable domain.

**Affects routines** `cp_minimize` `cp_maximize`

## KALIS_USE_3B_CONSISTENCY

**Description** Activates 3B consistency for continuous variables

**Type** Boolean, read/write

**Values** `true` default value

**Notes** Activates 3B consistency for continuous variables

**Affects routines** `cp_propagate`

## KALIS_VERBOSE_LEVEL

**Description** Verbosity level of Xpress Kalis

**Type** Integer, read/write

**Values**

| | |
|---|---|
| `0` | all output disabled |
| `1` | enable summary output printing |
| `2` | more detailed output |
| `3` | debug output |

**Notes** Verbosity level of Xpress Kalis

## KALIS_AUTO_RELAX

**Description** Indicates whether to use linear relaxation automatically

**Type** Boolean, read/write

**Values** `false` default value

**Notes** Enables automatic problem relaxation.

**See also** `cp_propagate` `cp_post`

## KALIS_THREADS

**Description** Number of threads

**Type** Integer, read/write

**Values** `1`

**Notes** Sets the number of threads to be used during the search process. This parameter MUST be set before any variable, task or resource is declared/created.

**Affects routines** `cp_find_next_sol` `cp_minimize` `cp_maximize` `cp_schedule`

## KALIS_NARY_OBJ_SEARCH

**Description** Uses an n-ary search strategy to find the optimal objective value

**Type** Boolean, read/write

**Values** `false` default value

**Notes** Uses an n-ary search strategy to find the optimal objective value. By default the optimization algorithm imposes an amelioration constraint stating that the objective value of the solution to be found must be better than the objective value of the best solution already found. With an n-ary optimization strategy, this constraint is replaced by n search subtrees over the objective variable domain.

**Affects routines** `cp_minimize` `cp_maximize`

## KALIS_SCHEDULE_ENABLE_SHAVING

**Description** Enable shaving during initial step of schedule search

**Type** Boolean, read/write

**Values** `true` default value

**Notes** Enable shaving during initial step of schedule search. By default the optimization algorithm shaves the lower bound (for minimization) or upper bound (for maximization) of the objective variable.

**Affects routines** `cp_schedule`

CHAPTER 9

# Subroutines

## 9.1 Constraints


| | | |
|---|---|---|
| `abs` | Absolute value constraint | p. 77 |
| `all_different` | All different constraint | p. 78 |
| `and` | Conjunction composite constraint | p. 66 |
| `cplinctr` | Linear constraints | p. 64 |
| `cpnlinctr` | Non-linear constraints | p. 72 |
| `cumulative` | Cumulative constraint | p. 101 |
| `cycle` | Cycle constraint | p. 80 |
| `disjunctive` | Disjunctive constraint | p. 103 |
| `distance` | Distance constraint | p. 76 |
| `distribute` | Distribute constraint with fixed bounds | p. 99 |
| `dot` | Dot product | p. 71 |
| `element` | Element constraint | p. 89 |
| `equiv` | Equivalence composite constraint | p. 68 |
| `exp` | Exponential of a non-linear expression | p. 75 |
| `generic_binary_constraint` | Generic Binary constraint | p. 91 |
| `generic_nary_constraint` | Generic nary constraint | p. 93 |
| `implies` | Implication composite constraint | p. 70 |
| `ln` | Natural logarithm of a non-linear expression | p. 74 |
| `maximum, minimum` | Maximum/minimum constraint | p. 85 |
| `occurrence` | Occurrence constraint | p. 87 |
| `or` | Disjunction composite constraint | p. 67 |
| `producer_consumer` | Producer Consumer constraint | p. 105 |
| `table_constraint` | Generic nary table constraint | p. 96 |

# cplinctr

## Purpose

Linear constraints are arithmetic constraints over decision variables. Linear constraints are defined with linear expressions combined by arithmetic operators such as =, $\neq$, $\leqslant$, and $\geqslant$.
Objects of type cplinexp are linear expressions of decision variables. Typically, these objects result as intermediate objects in the definition of linear constraints.
Linear expressions of decision variables are obtained by applying the operators +, - and * to decision variables and integer values. The standard priority rules used by Mosel apply to the evaluation order of the arithmetic operators. Brackets may be used in the definition of linear expressions to change this order. The following are examples of valid linear expressions:

```
declarations
   A, B: integer
   x, y: cpvar
   z: array(1..10) of cpfloatvar
end-declarations
A*x*B
-x + 2*A*y
B*(x-y)
(abs(A) + ceil(2.9) + round(-3.4)) * x
sum(i in 1..10) z(i)
```

The following definitions are not valid for objects of type cplinexp:

```
x*y
ln(2) * x
y/3
```

## Synopsis

```
x op I with x:cpvar and I:integer and op one of =, ⩾ , ⩽ , <>
x op y with x,y:cpvar and op one of =, ⩾ , ⩽ , <>
z op R with z:cplinexp and R:real and op one of =, ⩾ , ⩽ , <>
z op x with z:cplinexp and x:cpvar and op one of =, ⩾ , ⩽ , <>
z op w with z,w:cplinexp and op one of =, ⩾ , ⩽ , <>
I op x with I:integer and x:cpvar and op one of =, ⩾ , ⩽
R op z with R:real and z:cplinexp and op one of =, ⩾ , ⩽ , <>
x op z with x:cpvar and z:cplinexp and op one of =, ⩾ , ⩽ , <>
I <>z with I:integer and z:cplinexp
x op R with x:cpfloatvar and R:real and op one of ⩾ , ⩽
```

## Return value

A linear constraint combining the two arguments

## Example

The following example shows how to state different kinds of linear constraints:

```
model "Linear constraints"
 uses "kalis"

 declarations
  N = 3
  R = 1..N
  x: array(R) of cpvar
  c1: cpctr
 end-declarations

 forall(i in R) do
  0 <= x(i); x(i) <= 50
  setname(x(i), "x"+i)
```

```
 end-do

! Automated post+propagation
 x(1) >= x(3) + 5
 writeln(x(1), " ", x(3))

! Named constraint (explicit post)
 c1:= x(3) >= x(2) + 10

 if cp_post(c1) then
  writeln("With constraint c1: ", x)
 else exit(1)
 end-if

! Stop automated propagation
 setparam("kalis_auto_propagate", false)

! Automated post w/o propagation
 x(2) >= 10
 writeln("new bound for x2: ", x)
 if cp_propagate then
  writeln("after propagation: ", x)
 end-if

! Minimize the value of x(1)
 if cp_minimize(x(1)) then
  write("Solution: ")
  forall(i in R) write(getsol(x(i)), " ")
  writeln
 end-if
end-model
```

**Related topics**

getval

# and

### Purpose

This composite constraint states a conjunction between two constraints C1 and C2 ($C1 \wedge C2$). The satisfaction of the resulting constraint is given by the following truth table:

```
  C1     C2       C1 and C2
  -------------------------
  false  false    false
  false  true     false
  true   false    false
  true   true     true
```

### Synopsis

```
C1 and C2
```

### Arguments

`C1` the left member constraint of the conjunction

`C2` the right member constraint of the conjunction

### Return value

A conjunction constraint over C1 and C2

### Example

The following example shows how to use the conjunction constraint

```
model "Logical constraints"
 uses "kalis"

! Default bounds for all variables
 setparam("KALIS_DEFAULT_LB", 0); setparam("KALIS_DEFAULT_UB", 1)

 declarations
  a,b: cpvar
 end-declarations

 setname(a,"a")
 setname(b,"b")

 writeln(a,b)
 (a >= 1) and (b >= 1) or (a <= 0) and (b >= 1)

 while (cp_find_next_sol)
  writeln("a:", getsol(a), " b:", getsol(b))

end-model
```

### Related topics

`implies` `and` `or`

## or

### Purpose

This composite constraint states a disjunction between two constraints C1 and C2 ($C1 \vee C2$). The satisfaction of the resulting constraint is given by the following truth table:

```
C1     C2       C1 or C2
-------------------------
false  false    false
false  true     true
true   false    true
true   true     true
```

### Synopsis

```
C1 or C2
```

### Arguments

| | |
|---|---|
| `C1` | the left member constraint of the disjunction |
| `C2` | the right member constraint of the disjunction |

### Return value

A disjunction constraint over C1 and C2

### Example

See the example provided for `and` on how to use the disjunction constraint.

### Related topics

`implies` `and` `or`

## equiv

### Purpose

This composite constraint states an equivalence between two constraints C1 and C2 ($C1 \Leftrightarrow C2$), which are not individually posted. The satisfaction of the resulting constraint is given by the following truth table:

```
 C1     C2       C1 equiv C2
 -------------------------
 false  false    true
 false  true     false
 true   false    false
 true   true     true
```

### Synopsis

```
function equiv(C1:cpctr,C2:cpctr) : cpctr
```

### Arguments

| | |
|---|---|
| C1 | the left member constraint of the equivalence |
| C2 | the right member constraint of the equivalence |

### Return value

An equivalence constraint over C1 and C2

### Example

The following example shows how to use the equivalence constraint

```
model "Logical constraints"
 uses "kalis"

! Default bounds for all variables
 setparam("KALIS_DEFAULT_LB", 0); setparam("KALIS_DEFAULT_UB", 5)

 declarations
  A, B, C, D, E: cpctr
  x,y,z,b: cpvar
 end-declarations

 setname(b, "b"); setname(x, "x")
 setname(y, "y"); setname(z, "z")
 b <= 1

! Definition of constraints (without posting)
 A:= x >= y + 5 + z + b
 B:= b = 1
 C:= all_different({x, y, z})    ! Cannot be used with 'equiv'
 D:= y <= z
 E:= distance(y,z) <= 2

 writeln("Original domains: ", b, " ", x, " ", y, " ", z)

! If x, y and z are all different then b equals 1 (C=>B),
! if b equals 1 then x, y and z are all different (B=>C).
 implies(C, B)
 implies(B, C)

! E<=>B: b equals 1 if and only if |y-z| <= 2
 equiv(E, B)

! A<=>D: x >= y + 5 + z + b if and only if y <= z
```

```
 equiv(A, D)

 writeln("With constraints: ", b, " ", x, " ", y, " ", z)

 while (cp_find_next_sol)
  writeln("Solution: ", b, " ", x, " ", y, " ", z)

end-model
```

**Related topics**

implies and or

# implies

### Purpose

This composite constraint states an implication between two constraints C1 and C2 ($C1 \Rightarrow C2$), which are not individually posted. The satisfaction of the resulting constraint is given by the following truth table:

```
C1     C2       C1 implies C2
-------------------------
false  false    true
false  true     true
true   false    false
true   true     true
```

### Synopsis

```
function implies(C1:cpctr, C2:cpctr) : cpctr
```

### Arguments

| | |
|---|---|
| `C1` | the left member constraint of the implication |
| `C2` | the right member constraint of the implication |

### Return value

An implication constraint over C1 and C2

### Example

See the example provided for `equiv` on how to use the implication constraint.

### Related topics

`equiv` `and` `or`

# dot

### Purpose

Dot/Scalar product between two arrays. This operator returns the dot product between an array of variables (`cpvar` or `cpfloatvar`) and an array of numbers (`integer` or `real`).

### Synopsis

```
dot(x, A) or dot(A, x) with x:array of cpvar and A:array of real
dot(x, A) or dot(A, x) with x:array of cpvar and A:array of integer
dot(x, A) or dot(A, x) with x:array of cpfloatvar and A:array of real
dot(x, A) or dot(A, x) with x:array of cpfloatvar and A:array of integer
```

### Return value

A `cplinexp` corresponding to the dot product.

# cpnlinctr

## Purpose

Non-linear constraints are arithmetic constraints over decision variables. Non-linear constraints are defined with non-linear expressions combined by arithmetic operators such as =, ⩽ , and ⩾ . Non-linear expressions of decision variables have the type cpnlinexp. Typically, these objects result as intermediate objects in the definition of non-linear constraints.
Non-linear expressions of decision variables are obtained by applying the operators +, -, *, div, or functions like `ln`, `exp`, `abs` to decision variables and numeric values. The standard priority rules used by Mosel apply to the evaluation order of the arithmetic operators. Brackets may be used in the definition of non-linear expressions to change this order. The following are examples of valid non-linear expressions:

```
declarations
 y: cpvar
 x1,x2,x3,x4,x5: cpfloatvar
end-declarations
0.4*x3*x5 + 0.1*x3*x4 >= 10.7
x1^2 = y
exp(x3-x4)  2
ln(x5) = 1
(x1*x2^2) div (x4-x3) = 3
```

## Synopsis

X *op* v with X:cpnlinexp and v:cpfloatvar and *op* one of =, ⩾ , ⩽
X *op* r with X:cpnlinexp and r:real and *op* one of =, ⩾ , ⩽
X *op* v with X:cpnlinexp and v:cpvar and *op* one of =, ⩾ , ⩽
X *op* l with X:cpnlinexp and l:cplinexp and *op* one of =, ⩾ , ⩽

## Return value

A non-linear constraint combining the two arguments

## Example

The following example shows how to state different kinds of non-linear constraints:

```
model "Non-linear constraints"
 uses "kalis"

 parameters
  PREC =  1e-10
 end-parameters

! Setting default precision of continuous variables
 setparam("KALIS_DEFAULT_PRECISION_VALUE", PREC)

 declarations
  ISET = 1..8
  x: array(ISET) of cpfloatvar
 end-declarations

 ! Setting variable names
 forall(i in ISET) x(i).name:= "x"+i

 ! Setting variable bounds
 forall(i in ISET) do
  x(i) >= -100; x(i) <= 100
 end-do

 ! Defining and posting non-linear constraints
 x(1) + x(2)*(x(1)+x(3)) + x(4)*(x(3)+x(5)) + x(6)*(x(5)+x(7)) -
   (x(8)*((1/8)-x(7))) = 0
```

```
 x(2) + x(3)*(x(1)+x(5)) + x(4)*(x(2)+x(6)) + x(5)*x(7) -
   (x(8)*((2/8)-x(6))) = 0
 x(3)*(1 + x(6)) + x(4)*(x(1)+x(7)) + x(2)*x(5) -
   (x(8)*((3/8)-x(5))) = 0
 x(4) + x(1)*x(5) + x(2)*x(6) + x(3)*x(7) - (x(8)*((4/8)-x(4))) = 0
 x(5) + x(1)*x(6) + x(2)*x(7) - (x(8)*((5/8)-x(3))) = 0
 x(6) + x(1)*x(7) - (x(8)*((6/8)-x(2))) = 0
 x(7) - (x(8)*((7/8)-x(1))) = 0
 sum(i in ISET) x(i) = -1

 ! Set the enumeration strategy
 cp_set_branching(split_domain(KALIS_WIDEST_DOMAIN, KALIS_MIDDLE_VALUE,
                               x, true, 0))

 ! Find one solution
 if cp_find_next_sol then
  writeln("Solution number 1" )
  cp_show_sol
  cp_show_stats
 end-if

end-model
```

**Related topics**

getval

# ln

### Purpose

Natural logarithm of a non-linear expression

### Synopsis

```
function ln(x:cpnlinexp) : cpnlinexp
function ln(x:cplinexp) : cpnlinexp
function ln(x:cpfloatvar) : cpnlinexp
function ln(x:cpvar) : cpnlinexp
```

### Argument

`x` Non-linear expression

### Return value

A natural logarithm constraint over a non-linear expression x: $y = \ln x$

### Related topics

`exp` `abs`

## exp

### Purpose

Exponential of a non-linear expression

### Synopsis

```
function exp(x:cpnlinexp) : cpnlinexp
function exp(x:cplinexp) : cpnlinexp
function exp(x:cpfloatvar) : cpnlinexp
function exp(x:cpvar) : cpnlinexp
```

### Argument

`x` Non-linear expression

### Return value

An exponential constraint over a non-linear expression x: $y = e^x$

### Related topics

`ln` `abs`

# distance

### Purpose

This constraint specifies the distance between two variables.

### Synopsis

```
function distance(x:cpvar, y:cpvar) : 0cpabs
```

### Argument

`x,y` finite domain variables

### Return value

An absolute value constraint over x and y corresponding to the expressed distance constraint: $|x - y|$

### Example

The following example shows how to use the distance constraint

```
model "Distance constraints"
 uses "kalis"

 setparam("KALIS_DEFAULT_LB", -50); setparam("KALIS_DEFAULT_UB", 50)

 declarations
  x, y, z: cpvar
  Dist: cpctr
 end-declarations

 setname(x,"x")
 setname(y,"y")
 setname(z,"z")

 abs(x) = y
 writeln("Absolute value of x: ", x,y,z)

 y >= 20
 writeln("Bounding y by 20: ", x,y,z)

! abs(y-z) <= 3
! Equivalent version of this constraint:
 distance(y,z) <= 3

 writeln("Max distance betw. y and z: ", x,y,z)

 Dist:= distance(x,z) = 5

 if(cp_post(Dist)) then
  writeln("Distance between x and z: ", x,y,z)
 else
  writeln("Problem is infeasible")
 end-if

 cp_show_prob

end-model
```

### Related topics

`abs`

# abs

### Purpose

This constraint states that a variable y equals the absolute value of another variable x

### Synopsis

```
abs(x) = y with x,y:cpvar
abs(x) op I with x:cpvar and I:integer and op one of =, ⩾ , ⩽ , <>
x = abs(y) with x,y:cpvar
I op abs(x) with I:integer and x:cpvar and op one of =, ⩾ , ⩽ , <>
```

### Arguments

| | |
|---|---|
| `x` | absolute value variable (of type `cpvar`, `cpfloatvar`, `cplinexp`, `cpnlinexp`) |
| `y` | value variable (of the same type as `x`) |
| `I` | integer value |

### Return value

An absolute value constraint over the arguments

### Example

See the example provided for `distance` on how to use the absolute value constraint.

### Related topics

`distance`

# all_different

### Purpose

The all_different constraint states that all variables in this constraint must be pairwise different:

### Synopsis

```
function all_different(vars:set of cpvar, propagation: integer) : cpctr
function all_different(vars:set of cpvar) : cpctr
function all_different(vars:array(range) of cpvar, propagation:integer) :
      cpctr
function all_different(vars:array(range) of cpvar) : cpctr
function all_different(vars:cpvarlist, propagation:integer) : cpctr
function all_different(vars:cpvarlist) : cpctr
```

### Arguments

| | |
|---|---|
| `vars` | the list of variables |
| `propagation` | Propagation type selected using a constant `KALIS_FORWARD_CHECKING`, `KALIS_GEN_ARC_CONSISTENCY` |

### Return value

An all different constraint over vars

### Example

Consider the following simple problem where one must determine the arrival positions of a set of six runners:Dominique, Ignace, Naren, Olivier, Philippe and Pascal.
The constraints are the following:

1. All runners have different positions
2. Olivier is not last
3. Dominique, Pascal, and Ignace are before Naren and Olivier
4. Dominique is better than third
5. Philippe is among the first four
6. Ignace is neither second nor third
7. Pascal is three places higher than Naren
8. Neither Ignace nor Dominique are in fourth position

This problem can be modeled as follows. We create one variable per runner, whose value will be his arrival position. The initial domains of the variables will be the available arrival positions (1-6). Since we admit there are no ties, the positions are all pairwise different.

```
model "all_different example"
 uses "kalis"

 declarations
  PEOPLE = {"Sebastian", "Frederic", "Jan-Georg",
            "Krzysztof","Maarten","Luca"}  ! Set of speakers
  x: array(PEOPLE) of cpvar                ! Time slot per person
 end-declarations

 3 <= x("Sebastian") ; x("Sebastian") <= 6
 3 <= x("Frederic")  ;  x("Frederic") <= 4
 2 <= x("Jan-Georg") ; x("Jan-Georg") <= 5
 2 <= x("Krzysztof") ; x("Krzysztof") <= 4
 3 <= x("Maarten")   ;   x("Maarten") <= 4
 1 <= x("Luca")      ;      x("Luca") <= 6

! A different time slot for every person
```

```
 all_different(x)

! Solve the problem
 if not cp_find_next_sol then
  writeln("Problem is infeasible")
  exit(1)
 end-if

! Solution printout
 writeln(x)

end-model
```

**Related topics**

distribute KALIS_GEN_ARC_CONSISTENCY KALIS_FORWARD_CHECKING

## cycle

### Purpose

The cycle constraint ensures that the graph implicitly represented by a set of variables (= nodes) and their domains (= possible successors of a node) contains no sub-tours, that is, tours visiting only a subset of the nodes. The constraint can take an optional second set of variables Preds, representing the inverse relation of the Succ function and ensure the following equivalences: $\mathrm{succ}_i = j \Leftrightarrow \mathrm{pred}_j = i$ for all i and j. Another optional parameter of the cycle constraint allows to take into account an accumulated quantity along the tour such as distance, time or weight. More formally, it ensures the following constraint: $quantity = \sum_{i,j} \mathrm{distmatrix}_{ij}$ for all arcs i $\rightarrow$ j belonging to the tour.

### Synopsis

```
function cycle(succ:array of cpvar) : cpctr
function cycle(succ:array of cpvar, pred:array of cpvar) : cpctr
function cycle(succ:array of cpvar, dist:cpvar,
      distmatrix:array(range,range) of integer) : cpctr
function cycle(succ:array of cpvar, pred:array of cpvar, dist:cpvar,
      distmatrix:array(range,range) of integer) : cpctr
```

### Arguments

| | |
|---|---|
| `succ` | the list of successors variables |
| `pred` | the list of predecessors variables |
| `dist` | the accumulated quantity variable |
| `distmatrix` | a (nodes $\times$ nodes) matrix of integers representing the quantity to add to the accumulated quantity variable when an edge (i,j) belongs to the tour. |

### Return value

A cycle constraint

### Example

To illustrate the cycle constraint we show an implementation of the Traveling Salesman Problem (TSP). The objective of the Traveling Salesman Problem (TSP) is to find the shortest tour through a given set of cities that visits each city exactly once (a Hamiltonian tour). More formally, given a set of n points and a distance between every pair of points, a solution to the TSP is a path of N edges, with identical first and last vertices, containing all n points and with minimal total length. This problem can be modeled as follows: a solution is represented by a function Succ associating with each node its immediate successor. We use an array of N variables 'succ(i)' (one for each city $i \in \{0, ..., N-1\}$) to represent the next city visited after city number i where the domain of the variables succ(i) is set to $\{0, ..., N-1\} - \{i\}$.

```
model "TSP"
 uses "kalis"

 parameters
  S = 14  ! Number of cities to visit
 end-parameters

 declarations
  TC : array(0..3*S) of integer
 end-declarations

 ! TSP DATA
 TC :: [
  1 , 1647,  9610,
  2 , 1647,  9444,
  3 , 2009,  9254,
  4 , 2239,  9337,
  5 , 2523,  9724,
  6 , 2200,  9605,
```

```
 7 , 2047,  9702,
 8 , 1720,  9629,
 9 , 1630,  9738,
 10, 1405,  9812,
 11, 1653,  9738,
 12, 2152,  9559,
 13, 1941,  9713,
 14, 2009,  9455]

forward procedure print_solution
forward public function bestregret(Vars: cpvarlist): integer
forward public function bestneighbor(x: cpvar): integer

setparam("KALIS_DEFAULT_LB", 0)
setparam("KALIS_DEFAULT_UB", S-1)

declarations
 CITIES = 0..S-1                  ! Set of cities
 succ: array(CITIES) of cpvar     ! Array of successor variables
 prev: array(CITIES) of cpvar     ! Array of predecessor variables
end-declarations

setparam("KALIS_DEFAULT_UB", 10000)

declarations
 dist_matrix: array(CITIES,CITIES) of integer  ! Distance matrix
 totaldist: cpvar                 ! Total distance of the tour
 succpred: cpvarlist              ! Variable list for branching
end-declarations

! Setting the variable names
forall(p in CITIES) do
 setname(succ(p),"succ("+p+")")
 setname(prev(p),"prev("+p+")")
end-do

! Add succesors and predecessors to succpred list for branching
forall(p in CITIES) succpred += succ(p)
forall(p in CITIES) succpred += prev(p)

! Build the distance matrix
forall(p1,p2 in CITIES | p1<>p2)
  dist_matrix(p1,p2) :=  round(sqrt((TC(3*p2+1) - TC(3*p1+1)) *
   (TC(3*p2+1) - TC(3*p1+1)) + (TC(3*p2+2) - TC(3*p1+2)) *
   (TC(3*p2+2) - TC(3*p1+2))))

! Set the name of the distance variable
setname(totaldist, "total_distance")

! Posting the cycle constraint
cycle(succ, prev, totaldist, dist_matrix)

! Print all solutions found
cp_set_solution_callback(->print_solution)

! Set the branching strategy
cp_set_branching(assign_and_forbid("bestregret", "bestneighbor",
                 succpred))
setparam("KALIS_MAX_COMPUTATION_TIME", 10)
```

```
 ! Find the optimal tour
 if cp_minimize(totaldist) then
  if getparam("KALIS_SEARCH_LIMIT")=KALIS_SLIM_BY_TIME then
   writeln("Search time limit reached")
  else
   writeln("Done!")
  end-if
 end-if

!-------------------------------------------------------------------
! **** Solution printing ****
 procedure print_solution
  writeln("TOUR LENGTH = ", getsol(totaldist))

  thispos:=getsol(succ(0))
  nextpos:=getsol(succ(thispos))
  write("  Tour: ", thispos)
  while (nextpos <> getsol(succ(0))) do
    write(" -> ", nextpos)
    thispos:=nextpos
    nextpos:=getsol(succ(thispos))
  end-do
  writeln
 end-procedure

!-------------------------------------------------------------------
! **** Variable choice ****
 public function bestregret(Vars: cpvarlist): integer

 ! Get the number of elements of "Vars"
  listsize:= getsize(Vars)
  minindex := 0
  mindist := 0

 ! Set on uninstantiated variables
  forall(i in 1..listsize) do
    if not is_fixed(getvar(Vars,i)) then
      if i <= S then
        bestn := getlb(getvar(Vars,i))
        v:=bestn
        mval:=dist_matrix(i-1,v)
        while (v < getub(getvar(Vars,i))) do
          v:=getnext(getvar(Vars,i),v)
          if dist_matrix(i-1,v)<=mval then
            mval:=dist_matrix(i-1,v)
            bestn:=v
          end-if
        end-do
        sbestn := getlb(getvar(Vars,i))
        mval2:= 10000000
        v:=sbestn
        if dist_matrix(i-1,v)<=mval2 and v <> bestn then
          mval2:=dist_matrix(i-1,v)
          sbestn:=v
        end-if
        while (v < getub(getvar(Vars,i))) do
          v:=getnext(getvar(Vars,i),v)
          if (dist_matrix(i-1,v)<=mval2 and v <> bestn) then
            mval2:=dist_matrix(i-1,v)
            sbestn:=v
```

```
          end-if
        end-do

      else

        bestn := getlb(getvar(Vars,i))
        v:=bestn
        mval:=dist_matrix(v,i-S-1)
        while (v < getub(getvar(Vars,i))) do
          v:=getnext(getvar(Vars,i),v)
          if dist_matrix(v,i-S-1)<=mval then
            mval:=dist_matrix(v,i-S-1)
            bestn:=v
          end-if
        end-do
        sbestn := getlb(getvar(Vars,i))
        mval2:= 10000000
        v:=sbestn
        if dist_matrix(v,i-S-1)<=mval2 and v <> bestn then
          mval2:=dist_matrix(v,i-S-1)
          sbestn:=v
        end-if
        while (v < getub(getvar(Vars,i))) do
          v:=getnext(getvar(Vars,i),v)
          if dist_matrix(v,i-S-1)<=mval2 and v <> bestn then
            mval2:=dist_matrix(v,i-S-1)
            sbestn:=v
          end-if
        end-do
      end-if

      dsize := getsize(getvar(Vars,i))

      rank := integer(10000/ dsize +(mval2 - mval))
      if mindist<= rank then
        mindist := rank
        minindex := i
      end-if

    end-if
  end-do

  returned := minindex

 end-function

!-------------------------------------------------------------------
! **** Value choice: choose value resulting in smallest distance
 public function bestneighbor(x: cpvar): integer

  issucc := false
  idx := -1
  forall (i in CITIES)
    if (is_same(succ(i),x)) then
      idx:= i
      issucc := true
    end-if
  forall (i in CITIES)
    if (is_same(prev(i),x)) then
      idx:= i
```

```
    end-if

  if issucc then
    returned:= getlb(x)
    v:=getlb(x)
    mval:=dist_matrix(idx,v)
    while (v < getub(x)) do
      v:=getnext(x,v)
      if dist_matrix(idx,v)<=mval then
        mval:=dist_matrix(idx,v)
        returned:=v
      end-if
    end-do
  else
    returned:= getlb(x)
    v:=getlb(x)
    mval:=dist_matrix(v,idx)
    while (v < getub(x)) do
      v:=getnext(x,v)
      if dist_matrix(v,idx)<=mval then
        mval:=dist_matrix(v,idx)
        returned:=v
      end-if
     end-do
  end-if

 end-function

end-model
```

**Related topics**

distribute all_different

## maximum, minimum

### Purpose

The maximum (resp) minimum constraint states that a variable z is the maximum (resp) minimum of a list of variables vars

### Synopsis

```
minimum(vars) = z or maximum(vars) = z
z = minimum(vars) or z = maximum(vars)
```

### Arguments

`vars` list of decision variables: {set of cpvar | array(range) of cpvar | cpvarlist}

`z` decision variable for the maximum/minimum: cpvar

### Return value

A maximum/minimum constraint over z and vars

### Example

The following example shows how to use the maximum/minimum constraints:

```
model "Min and Max"
 uses "kalis"

 declarations
  R = 1..5
  x: array(R) of cpvar
  v, w, y: cpvar
  L: cpvarlist
  MaxCtr: cpctr
 end-declarations

 setname(v,"v")
 setname(w,"w")
 setname(y,"y")

 forall(i in R) do
  setname(x(i),"x"+i+"")
  setdomain(x(i), 0, 2*i + round(5*random + 0.5))
 end-do

 writeln("Initial domains:\n ", x, "  ", v)

! Minimum constraint with automated posting
 v = minimum(x)
 writeln("With minimum constraint:\n ", x, "  ", v)

 x(1) = 2
 writeln("Fixing x(1) to 2: ", v)

! Maximum constraint with explicit posting
 MaxCtr:= w = maximum({x(2), x(3), x(5)})
 if cp_post(MaxCtr) then
  writeln("With maximum constraint:\n ", x, "  ", w)
 else exit(1)
 end-if

 w <= 7
 writeln("Bounding w by 7:\n ", x, "  ", w)

! Maximum constraint on list of variables
```

```
 L += x(2); L += x(3); L += x(4)
 y = maximum(L)
 writeln("With 2nd maximum constraint:\n ", x, "  ", y)

 if cp_find_next_sol then
  writeln("A solution:\n ", x, "  ", v, "  ", w, "  ", y)
 end-if
end-model
```

## occurrence

### Purpose

Constrains the number of occurrences of a specific value or a set of values among a list/set of decision variables

### Synopsis

```
occurrence(value,vars) op target with target:integer and op one of =, ≥ , ≤
target op occurrence(value,vars) with target:integer and op one of =, ≥ , ≤
occurrence(value,vars) op occvar with occvar:cpvar and op one of =, ≥ , ≤
occvar op occurrence(value,vars) with occvar:cpvar and op one of =, ≥ , ≤
occurrence(varset:set of cpvar, values:set of integer, minocc:integer,
      maxocc:integer)
```

### Arguments

| | |
|---|---|
| `target` | the (fixed) target occurrence count for the specified value |
| `occvar` | the variable occurrence count for the specified value |
| `value` | the integer value whose occurences in the variable list should be constrained |
| `vars` | the list of decision variables: {set of cpvar \| array of cpvar \| cpvarlist} |
| `varset` | a set of decision variables |
| `values` | a set of values |
| `minocc` | minimum number of occurrences |
| `maxocc` | maximum number of occurrences |

### Return value

An occurrence constraint over the given arguments

### Example

The following example shows how to use the occurence constraint:

```
model "Cardinality"
 uses "kalis"

 setparam("KALIS_DEFAULT_LB", 0)

 declarations
  R = 1..6
  S = 1..10
  x: array(R) of cpvar
  y: array(S) of cpvar
  a,b,c: cpvar
  Card: cpctr
  Vlist: cpvarlist
 end-declarations

 forall(i in R) setname(x(i), "x"+i)
 forall(i in 1..3) x(i) = 1
 forall(i in 4..6) x(i) <= 10
 setname(c, "c")
 c <= 15

 writeln("Initial domains:\n ", x, "  ", c)

! Explicit posting of an occurrence constraint
 Card:= occurrence(1, x) = c
 if cp_post(Card) then
  writeln("With occurrence constraint:\n ", x, "  ", c)
```

```
 else exit(1)
 end-if

 c = 6
 writeln("Fixing occurrence to 6:\n ", x, "  ", c)

 forall(i in S) do
  setname(y(i), "y"+i)
  i <= y(i); y(i) <= i*2
 end-do
 setname(a, "a"); setname(b,"b")

 writeln("Initial domains:\n ", y, "  ", a, "  ", b)

! Occurrence constraint on an array of variables
 occurrence(4, y) <= 2

! Occurrence constraint on a list of variables
 Vlist += y(1); Vlist += y(2); Vlist += y(4)
 occurrence(2, Vlist) = 0

! Occurrence constraint on a set of variables
 occurrence(9, {y(6), y(7), y(9)}) >= 3

! Occurrences bounded by variables
 occurrence(5, y) >= a
 occurrence(8, {y(4), y(5), y(6), y(7), y(8)}) <= b
 writeln("With all constraints:\n ", y, "  ", a, "  ", b)

 if cp_find_next_sol then
  writeln("A solution:\n ", y, "  ", a, "  ", b)
 end-if

end-model
```

**Related topics**

distribute

# element

## Purpose

This constraint states that a variable z is the $x^{th}$ element of an ordered list of integer V, in its ternary form it states that z is the [x,y]-th element of a matrix of integers M

## Synopsis

```
element(x+I) = C
element(V,x{,I}) = C
element(V,x{,I}) = z with x,z cpvar and I integer
z = element(V,x{,I}) with x,z cpvar and I integer
element(M,x,y) = z with x,y,z cpvar
z = element(M,x,y) with x,y,z cpvar
```

## Arguments

| | |
|---|---|
| C | a constant integer value |
| z | the value variable |
| x | first index variable |
| y | second index variable |
| I | optional constant offset for index |
| V | a one-dimensional array of integer values |
| M | a matrix (two-dimensional array) of integers |

## Return value

An element constraint over z, x and y in the ternary form, over x and z in the binary form

## Example

The following example shows how to use the element constraint:

```
model "Element"
 uses "kalis"

 declarations
  RY = 43..52
  RX = 1..2
  D: array(RY) of integer
  D2: array(RX,RY) of integer
  x,y,d_of_y,d_of_x_y: cpvar
 end-declarations

 D :: (43..52)[ 0,  1,  2,  3,  4,  5,  6,  7,  8,  9]

 D2:: (1..2,43..52)[10, 11, 12, 13, 14, 15, 16, 17, 18, 19,
                    20, 21, 22, 23, 24, 25, 26, 27, 28, 29]

 setname(x, "x")
 setname(y, "y")
 setname(d_of_y, "d_of_y")
 setname(d_of_x_y, "d_of_x_y")

 writeln("Original domains: ", x, y, d_of_y, d_of_x_y)

 element(D,y) = d_of_y
 element(D2,x,y) = d_of_x_y

 writeln("After propagation: ", x, y, d_of_y, d_of_x_y)

! Solve the problem
```

```
 while (cp_find_next_sol) do
  nbSolutions += 1
  writeln("Solution ", nbSolutions, ": x:", getsol(x),
    " y:", getsol(y), " d_of_y:", getsol(d_of_y),
    " d_of_x_y:", getsol(d_of_x_y))
 end-do
 writeln("done!")

end-model
```

## generic_binary_constraint

### Purpose

This constraint can be used to propagate a user-defined constraint over two variables (its propagation is based on the AC2001 algorithm (cf. [BR01]).

### Synopsis

```
function generic_binary_constraint(v1:cpvar, v2:cpvar, fct:
      function(integer, integer): boolean) : cpctr
function generic_binary_constraint(v1:cpvar,v2:cpvar, fctname:string) :
      cpctr
```

### Arguments

| | |
|---|---|
| `v1` | the first decision variable |
| `v2` | the second decision variable |
| `fct` | reference to a function taking two integers as arguments and returning a boolean |
| `fctname` | name of the function specifying the user-defined constraint, taking two integers as arguments and returning a boolean |

### Return value

A binary constraint over 'v1' and 'v2'

### Example

The following example shows how to use the generic_binary_constraint constraint to solve the classical Euler Knight Tour problem:

```
model "Euler Knight Moves"
 uses "kalis"

 parameters
  S = 8                                  ! No. of rows/columns
 end-parameters

 N:= S * S                               ! Total number of cells
 setparam("KALIS_DEFAULT_LB", 0)
 setparam("KALIS_DEFAULT_UB", N-1)

 forward function valid_knight_move(a:integer, b:integer): boolean

 declarations
  PATH = 1..N                            ! Cells on the board
  pos: array(PATH) of cpvar              ! Position p in tour
 end-declarations

! Setting names of decision variables
 forall(i in PATH) setname(pos(i), "Position"+i)

! Fix the start position
 pos(1) = 0

! Each cell is visited once
 all_different(pos, KALIS_GEN_ARC_CONSISTENCY)

! The knight's path obeys the chess rules for valid knight moves
 forall(i in 1..N-1)
  generic_binary_constraint(pos(i), pos(i+1), ->valid_knight_move)
 generic_binary_constraint(pos(N), pos(1), ->valid_knight_move)

! Setting enumeration parameters
```

```
 cp_set_branching(probe_assign_var(KALIS_SMALLEST_MIN,
                  KALIS_MAX_TO_MIN, pos, 14))

! Search for up to NBSOL solutions
 solct:= 0
 if not cp_find_next_sol then
  writeln("No solution")
 else
  writeln(pos)
 end-if

! **** Test whether the move from a to b is admissible ****
 function valid_knight_move(a:integer, b:integer): boolean
  declarations
   xa,ya,xb,yb,delta_x,delta_y: integer
  end-declarations
  xa := a div S
  ya := a mod S
  xb := b div S
  yb := b mod S
  delta_x := abs(xa-xb)
  delta_y := abs(ya-yb)
  returned := (delta_x<=2) and (delta_y<=2) and (delta_x+delta_y=3)
 end-function

end-model
```

## generic_nary_constraint

### Purpose

This constraint can be used to propagate a user-defined constraint over n variables (its propagation is based on the GAC2001 algorithm (cf. [BR01]).

### Synopsis

```
function generic_nary_constraint(vars:arrray of cpvar, fctname:string,
      userparam:integer) : cpctr
function generic_nary_constraint(vars:arrray of cpvar, fct:
      function(cptuple, integer): boolean, userparam:integer) : cpctr
function generic_nary_constraint(vars:cpvarlist, fctname:string,
      userparam:integer) : cpctr
function generic_nary_constraint(vars:cpvarlist, fct: function(cptuple,
      integer): boolean, userparam:integer) : cpctr
function generic_nary_constraint(vars:arrray of cpvar, fctname:string,
      propagation: integer, userparam:integer) : cpctr
function generic_nary_constraint(vars:arrray of cpvar, fct:
      function(cptuple, integer): boolean, propagation: integer,
      userparam:integer) : cpctr
function generic_nary_constraint(vars:cpvarlist, fctname:string,
      propagation: integer, userparam:integer) : cpctr
function generic_nary_constraint(vars:cpvarlist, fct: function(cptuple,
      integer): boolean, propagation: integer, userparam:integer) : cpctr
function generic_nary_constraint(vars:set of cpvar, fctname:string,
      userparam:integer) : cpctr
function generic_nary_constraint(vars:set of cpvar, fct: function(cptuple,
      integer): boolean, userparam:integer) : cpctr
function generic_nary_constraint(vars:set of cpvar, fctname:string,
      propagation: integer, userparam:integer) : cpctr
function generic_nary_constraint(vars:set of cpvar, fct: function(cptuple,
      integer): boolean, propagation: integer, userparam:integer) : cpctr
```

### Arguments

| | |
|---|---|
| `vars` | a set, array, or cpvarlist of decision variables |
| `fct` | reference to the function specifying the user-defined constraint, such a function necessarily takes a `cptuple` and an integer (the value of `userparam`) as arguments and returns a Boolean |
| `fctname` | name of the function specifying the user-defined constraint, such a function necessarily takes a `cptuple` and an integer (the value of `userparam`) as arguments and returns a Boolean |
| `userparam` | a user parameter |
| `propagation` | the level of propagation to achieve. 0 stands for GAC algorithm, 1 for AC algorithm and 2 for Forward-Checking algorithm |

### Return value

An n-ary constraint over a set of variables

### Example

The following example shows how to use the generic_nary_constraint constraint to solve the classical Euler Knight Tour problem:

```
model "Euler Knight Moves"
 uses "kalis"

 parameters
```

```
 S = 8                                  ! No. of rows/columns
end-parameters

N:= S * S                               ! Total number of cells
setparam("KALIS_DEFAULT_LB", 0)
setparam("KALIS_DEFAULT_UB", N-1)

forward function valid_knight_move(vals: cptuple, s: integer): boolean

declarations
 PATH = 1..N                            ! Cells on the board
 pos: array(PATH) of cpvar              ! Position p in tour
 propagation : integer                  ! Alg choice: 0, 1, or 2
end-declarations

! Selecting the propagation algorithm for the generic nary constraint
propagation := 0

! Setting names of decision variables
forall(i in PATH) setname(pos(i), "Position"+i)

! Fix the start position
pos(1) = 0

! Each cell is visited once
all_different(pos, KALIS_GEN_ARC_CONSISTENCY)

! The knight's path obeys the chess rules for valid knight moves
forall(i in 1..N-1)
 generic_nary_constraint({pos(i), pos(i+1)}, ->valid_knight_move,propagation,S)
generic_nary_constraint({pos(N), pos(1)}, ->valid_knight_move,propagation,S)

! Setting enumeration parameters
cp_set_branching(probe_assign_var(KALIS_SMALLEST_MIN,
                 KALIS_MAX_TO_MIN, pos, 14))

! Search for up to NBSOL solutions
solct:= 0
if not cp_find_next_sol then
 writeln("No solution")
else
 writeln(pos)
end-if

! **** Test whether the move from a to b is admissible ****
function valid_knight_move(vals: cptuple, s: integer): boolean
 declarations
  xa,ya,xb,yb,delta_x,delta_y: integer
  a,b : integer
 end-declarations
 ! Current position data
 a := getelt(vals,1)  ! 1 : pos(i)
 b := getelt(vals,2)  ! 2 : pos(i+1)

 xa := a div s
 ya := a mod s
 xb := b div s
 yb := b mod s
 delta_x := abs(xa-xb)
 delta_y := abs(ya-yb)
```

```
  returned := (delta_x<=2) and (delta_y<=2) and (delta_x+delta_y=3)
 end-function

end-model
```

## table_constraint

### Purpose

This constraint can be used to propagate a user-defined constraint over n variables defined through a list of valid tuples (its propagation is based on the GAC2001 algorithm (cf. [BR01]).

### Synopsis

```
function table_constraint(vars:array of cpvar, tuple:array) : cpctr
function table_constraint(vars:array of cpvar, tuple:set) : cpctr
function table_constraint(vars:cpvarlist, tuple:array) : cpctr
function table_constraint(vars:cpvarlist, tuple:set) : cpctr
```

### Arguments

`vars` an array or cpvarlist of decision variables

`tuple` the list of valid tuples for the decision variables

### Return value

An n-ary table constraint over a set of variables

### Example

The following example shows how to use the table_constraint constraint to solve a bin packing problem:

```
model "table_constraint example"
 uses "kalis"

 parameters
  N = 30           ! Max number of bins
  MAX_TIME = 15    ! Max time allowed to solver
 end-parameters

 setparam("KALIS_MAX_COMPUTATION_TIME",MAX_TIME)

 forward procedure print_sol

 declarations
   ! *** Data ***
   MATERIAL = 1..5 ! Corresponds to ["Glass","Plastic","Steel","Wood","Copper"]
   INITIAL_SUPPLY : array(MATERIAL) of integer
   BINTYPE = 0..3  ! Corresponds to ["Unassigned", "Red", "Blue", "Green"]
   BINS = 1..N                                  ! Set of bins
   CAPACITY : array(BINTYPE) of integer         ! Capacity per type
   WEIGHT : array(BINTYPE) of integer           ! Weights for bin type selection

   ! *** Decision variables ***
   var_bin : array(BINS) of cpvar               ! Bin usage
   var_type : array(BINS) of cpvar              ! Bin type
   var_capa : array(BINS) of cpvar              ! Bin capacity
   var_qty_material : array(BINS,MATERIAL) of cpvar ! Qty per material in bins
   objective : cpvar

   strategy : cpbranching                       ! Branching strategy

   ! Configuration of the table_constraint
   var_table : array(BINS) of cpvarlist         ! Assignment variables per bin
   list_valid_tuple : set of list of integer    ! Permissible tuples
 end-declarations

 ! Initialisation of the data arrays
 INITIAL_SUPPLY::(1..5)[12,10,8,12,8]
 CAPACITY::(0..3)[0,5,5,6]
```

```
 WEIGHT::(0..3)[0,1,1,1]

! Define the cpvar and their domains
 forall(i in BINS) do
   setname(var_bin(i), "use of bin (" + i + ")")
   setdomain(var_bin(i),0,1)

   setname(var_type(i), "type of bin (" + i + ")")
   setdomain(var_type(i),BINTYPE)

   setname(var_capa(i), "capacity of bin (" + i + ")")
   var_capa(i) = element(CAPACITY,var_type(i))
   forall(m in MATERIAL) do
     setname(var_qty_material(i,m),
       "Quantity of material (" + m + ") in bin (" + i + ")")
     setdomain(var_qty_material(i,m),0,max(c in BINTYPE) CAPACITY(c))
   end-do
 end-do

 ! Capacity constraint
 forall(i in BINS) do
   sum(m in MATERIAL) var_qty_material(i,m) <= var_capa(i)
   var_bin(i) = element(WEIGHT,var_type(i))
 end-do

 ! Satisfy of the supply constraint
 forall(m in MATERIAL)
   sum(i in BINS) var_qty_material(i,m) = INITIAL_SUPPLY(m)

 ! Define a list of valid tuples
 maxcap:= max(c in BINTYPE) CAPACITY(c)
 forall(type in BINTYPE, qmat_1,qmat_2,qmat_3,
        qmat_4,qmat_5 in 0..maxcap) do
   ! red can contain glass, cooper, wood and at most 1 wood component
   if type = 1 and
      qmat_2 = 0 and qmat_3 = 0 and qmat_4 <= 1 then
     list_valid_tuple += {[type, qmat_1, qmat_2,qmat_3,qmat_4,qmat_5]}
   ! blue can contain glass, steel, cooper
   elif type = 2 and qmat_2 = 0 and qmat_4 = 0 then
     list_valid_tuple += {[type, qmat_1, qmat_2,qmat_3,qmat_4,qmat_5]}
   ! green can contain plastic, copper, wood and at most 2 wood components
   elif type = 3 and
        qmat_1 = 0 and qmat_3 = 0 and qmat_4 <= 2 then
     list_valid_tuple += {[type, qmat_1, qmat_2,qmat_3,qmat_4,qmat_5]}
   ! unassigned
   elif type = 0 and
        qmat_1 = 0 and qmat_2 = 0 and qmat_3 = 0 and qmat_4 = 0 and qmat_5 = 0 then
      list_valid_tuple += {[type, qmat_1, qmat_2,qmat_3,qmat_4,qmat_5]}
   end-if

   ! wood requires plastic;
   if qmat_4 >= 1 and qmat_2 >= 1 then
     list_valid_tuple += {[type, qmat_1, qmat_2,qmat_3,qmat_4,qmat_5]}
   end-if

   ! glass exclusive with copper;
   if qmat_1 = 0 or qmat_5 = 0 then
     list_valid_tuple += {[type, qmat_1, qmat_2,qmat_3,qmat_4,qmat_5]}
   end-if
   ! copper excludes plastic.
```

```
   if qmat_5 = 0 or qmat_2 = 0 then
     list_valid_tuple += {[type, qmat_1, qmat_2,qmat_3,qmat_4,qmat_5]}
   end-if
 end-do

 ! Definition of table constraint
 forall(i in BINS) do
  var_table(i) += var_type(i)
  forall(m in MATERIAL) var_table(i) += var_qty_material(i,m);
  table_constraint(var_table(i), list_valid_tuple)
 end-do

! Define the objective
 setname(objective,"total number of bins")
 setdomain(objective,0,N)
 objective = sum(i in BINS) var_bin(i)

! Propagate the constraints
 if not cp_propagate then
   writeln("Problem is infeasible")
   exit(1)
 end-if

! Define a branching strategy
 strategy := assign_var(KALIS_MAX_DEGREE,KALIS_MAX_TO_MIN)
 cp_set_branching(strategy)

! And solve the problem
 if not cp_minimize(objective) then
   writeln("Problem is infeasible")
   exit(1)
 end-if

! Display solution and solver stats
 print_sol
 cp_show_stats

! **** Solution display ****
 procedure print_sol
   forall(i in BINS | getsol(var_type(i)) > 0) do
      writeln("Bin ",i, " chosen : type=", getsol(var_type(i)),
        "; capa=", getsol(var_capa(i)),
        "; Glass=", getsol(var_qty_material(i,1)),
        "; Plastic=", getsol(var_qty_material(i,2)),
        "; Steel=", getsol(var_qty_material(i,3)),
        "; Wood=", getsol(var_qty_material(i,4)),
        "; Copper=", getsol(var_qty_material(i,5)))
   end-do
 end-procedure

end-model
```

## distribute

### Purpose

A distribute constraint also known as GCC (Global Cardinality Constraint) over a set of variables is defined by three arrays called values, lowerBound, and upperBound. The constraint is satisfied if, and only if, the number of variables of the given set, which are assigned to values[i], is greater than or equal to lowerBound[i], and less than or equal to upperBound[i] for all i, and if no variable of the given set is assigned to a value which does not belong to values. The constraint is equivalent, from a modelization point of view, to posting two instances of `occurrence` constraints for each value. But this is absolutely not equivalent from a propagation point of view: distribute acquires a far better propagation, using the Regin algorithm.

### Synopsis

```
function distribute(vars:array of cpvar, values:set of integer,
      bound:array(integer) of integer) : cpctr
function distribute(vars:array of cpvar, values:set of integer,
      lowerBound:array(integer) of integer, upperBound:array(integer) of
      integer) : cpctr
function distribute(vars:set of cpvar,vals:set of integer,
      lowerBound:array(integer) of integer, upperBound:array(integer) of
      integer) : cpctr
function distribute(vars:cpvarlist, vals:set of integer,
      lowerBound:array(integer) of integer, upperBound:array(integer) of
      integer) : cpctr
```

### Arguments

| | |
|---|---|
| `vars` | Array/set/list of variables |
| `values` | Set of values represented by their names |
| `lowerBound` | Array of lower bounds on occurrences |
| `upperBound` | Array of upper bounds on occurrences |
| `bound` | Array of occurrence values |

### Return value

A distribute constraint

### Example

A simple planning problem for personnel in a theater. Suppose that a movie theatre director has to decide in which location each of his employees should be posted. There are eight employees: Andrew, David, Jane, Jason, Leslie, Michael, Marilyn and Oliver. There are four locations: the ticket office, the first entrance, the second entrance and the coat check. These locations require three, two, two, and one person respectively. This constraint will be modeled by one distribute constraint:

```
model "Distribute example"
 uses "kalis"

 declarations
  PERS = {"David","Andrew","Leslie","Jason","Oliver","Michael",
          "Jane","Marilyn"}          ! Set of personnel
  LOC = 1..4                         ! Set of locations
  REQ: array(LOC) of integer         ! No. of pers. req. per loc.
  place: array(PERS) of cpvar        ! Workplace for each peson
 end-declarations

! Initialize data
 REQ:: [3, 2, 2, 1]

! Each variable has a lower bound of 1 (Ticket office) and
```

```
!  an upper bound of 4 (Cloakroom)
 forall(p in PERS) do
  setname(place(p), "workplace("+p+")")
  1 <= place(p); place(p) <= 4
 end-do

! Creation of a resource constraint of for every location
 forall(d in LOC) occurrence(d, place) = REQ(d)

! Elegant way to declare theses constraints,
! moreover achieving stronger prunning (using global
! cardinality constraint)
 distribute(place, LOC, REQ)

! Solve the problem
 if not cp_find_next_sol then
  writeln("Problem is infeasible")
  exit(1)
 end-if

! Solution printout
 writeln(place)

end-model
```

**Related topics**

occurrence all_different

## cumulative

### Purpose

This constraint states that the tasks requiring a resource do not exceed the resource capacity. The primary use of this constraint is to express resource constraints.

### Synopsis

```
function cumulative(starts: array(integer) of cpvar,
      durations:array(integer) of cpvar, ends: array(integer) of cpvar,
      usages: array(integer) of cpvar, sizes: array(integer) of cpvar, cap:
      integer) : cpctr
function cumulative(starts: array(integer) of cpvar,
      durations:array(integer) of cpvar, ends: array(integer) of cpvar,
      usages: array(integer) of cpvar, sizes: array(integer) of cpvar, cap:
      array(integer) of integer) : cpctr
function cumulative(starts: array(integer) of cpvar,
      durations:array(integer) of cpvar, ends: array(integer) of cpvar,
      usages: array(integer) of cpvar, sizes: array(integer) of cpvar, cap:
      integer, alg: integer) : cpctr
```

### Arguments

| | |
|---|---|
| `starts` | Array of variables representing the start times of the tasks |
| `ends` | Array of variables representing the completion times of the tasks |
| `durations` | Array of variables representing the durations of the tasks |
| `usages` | Array of variables representing the resource consumptions of the tasks |
| `sizes` | Array of variables representing the sizes of the tasks |
| `cap` | Integer representing the initial capacity of the resource (constant over time or capacity value for each time period) |
| `alg` | Choice of the propagation algorithm: `KALIS_TIMETABLING` or `KALIS_TASK_INTERVALS` |

### Return value

A cumulative constraint ensuring that the maximal resource capacity is never exceeded. More formally the constraint ensures that

$starts_j + durations_j = ends_j$ for all j in Tasks

$usages_j \cdot durations_j = sizes_j$ for all j in Tasks

$\sum_{j \in Tasks | t \in [UB(start_j)..LB(end_j)]} usages_j \leqslant C_t$ for all times t in the planning period

### Example

The following example shows how to use the cumulative constraint to express resource constraints for five tasks using the same resource:

```
model "Cumulative scheduling"
 uses "kalis"

 declarations
  TASKS = 1..5
  obj : cpvar
  starts, ends, durations, usages, sizes : array(TASKS) of cpvar
 end-declarations

 C := 2                        ! Resource capacity
 HORIZON := 10                 ! Time horizon
```

```
! Setting up the variables representing task properties
 forall (t in TASKS) do
  starts(t).name:= "T"+t+".start"
  ends(t).name:= "T"+t+".end"
  durations(t).name:= "T"+t+".duration"
  sizes(t).name:= "T"+t+".size"
  usages(t).name:= "T"+t+".use"
  0 <= starts(t); starts(t) <= HORIZON
  0 <= ends(t); ends(t) <= HORIZON
  t <= durations(t); durations(t) <= t+1
  1 <= sizes(t); sizes(t) <= 100
  1 <= usages(t); usages(t) <= 1
  obj >= ends(t)
 end-do

! Cumulative resource constraint
 cumulative(starts, durations, ends, usages, sizes, C)

! Define the branching strategy
 cp_set_branching(assign_var(KALIS_SMALLEST_MIN,KALIS_MIN_TO_MAX))

! Solve the problem
 if cp_minimize(obj) then
  cp_show_sol
  write("Resource use profile: ")
  forall(t in TASKS, time in 0..HORIZON)
   if (starts(t).sol <= time) and (ends(t).sol > time) then
    rload(time) += usages(t).sol
   end-if
  forall(time in 0..HORIZON) write(rload(time))
  writeln
 else
  writeln("No solution found")
 end-if

end-model
```

**Related topics**

disjunctive settle_disjunction or

## disjunctive

### Purpose

This constraint states that the given tasks are not overlapping chronologically.

### Synopsis

```
procedure disjunctive(starts: set of cpvar, durations:array(cpvar) of
      integer, disj:set of cpctr, resource:integer)
procedure disjunctive(starts: array(integer) of cpvar,
      durations:array(integer) of cpvar, ends: array(integer) of cpvar)
```

### Arguments

| | |
|---|---|
| `starts` | Array of variables representing the start times of the tasks |
| `durations` | Array of integers representing the durations of the tasks |
| `ends` | Array of variables representing the completion times of the tasks |
| `disj` | Empty array that will be filled with the list of disjunctions that will be created by this constraint |
| `resource` | Resource flag (argument currently unused) |

### Return value

A disjunctive constraint ensuring that the tasks defined by 'starts' and 'durations' are not overlapping chronologically.

### Example

The following example shows how to use the disjunctive constraint to express resource constraints in a small disjunctive scheduling problem:

```
model "Disjunctive scheduling with settle_disjunction"
 uses "kalis", "mmsystem"

 declarations
  NBTASKS = 5
  TASKS = 1..NBTASKS                      ! Set of tasks
  DUR: array(TASKS) of integer            ! Task durations
  DURs: array(set of cpvar) of integer    ! Durations
  DUE: array(TASKS) of integer            ! Due dates
  WEIGHT: array(TASKS) of integer         ! Weights of tasks
  start: array(TASKS) of cpvar            ! Start times
  tmp: array(TASKS) of cpvar              ! Aux. variable
  tardiness: array(TASKS) of cpvar        ! Tardiness
  twt: cpvar                              ! Objective variable
  zeroVar: cpvar                          ! 0-valued variable
  Strategy: array(range) of cpbranching   ! Branching strategy
  Disj: set of cpctr                      ! Disjunctions
 end-declarations

 DUR :: [21,53,95,55,34]
 DUE :: [66,101,232,125,150]
 WEIGHT :: [1,1,1,1,1]

 setname(twt, "Total weighted tardiness")
 zeroVar = 0
 setname(zeroVar, "zeroVar")

! Setting up the decision variables
 forall(t in TASKS) do
  start(t) >= 0
  setname(start(t), "Start("+t+")")
```

```
  DURs(start(t)):= DUR(t)
  tmp(t) = start(t) + DUR(t) - DUE(t)
  setname(tardiness(t), "Tard("+t+")")
  tardiness(t) = maximum({tmp(t), zeroVar})
 end-do

 twt = sum(t in TASKS) (WEIGHT(t) * tardiness(t))

! Create the disjunctive constraints
 disjunctive(union(t in TASKS) {start(t)}, DURs, Disj, 1)

! Define the search strategy
 Strategy(1):= settle_disjunction
 Strategy(2):= split_domain(KALIS_LARGEST_MIN,KALIS_MIN_TO_MAX)
 cp_set_branching(Strategy)
 setparam("KALIS_DICHOTOMIC_OBJ_SEARCH",true)

 if not cp_minimize(twt) then
  writeln("Problem is inconsistent")
  exit(0)
 end-if

 forall(t in TASKS)
  writeln(formattext("[%3d==>%3d]:\t %2d  (%d)", start(t).sol,
          start(t).sol + DUR(t), tardiness(t).sol, tmp(t).sol))
 writeln("Total weighted tardiness: ", getsol(twt))

end-model
```

**Related topics**

or `settle_disjunction`

## producer_consumer

### Purpose

A Producer Consumer Scheduling constraint. More formally the constraint ensures that:

$productions_j \cdot durations_j = prodsizes_j$ for all j in Tasks

$consumptions_j \cdot durations_j = consosizes_j$ for all j in Tasks

$\sum_{j \in R | t \in [LB(start_j)..LB(end_j)]} (productions_j - consumptions_j) \leqslant C_t$ for all t in Times

### Synopsis

```
function producer_consumer(starts:array(range) of cpvar, ends:array(range)
      of cpvar, durations:array(range) of cpvar, productions:array(range)
      of cpvar, prod_sizes:array(range) of cpvar, consumptions:array(range)
      of cpvar, conso_sizes:array(range) of cpvar, C:array(range) of
      integer) : cpctr
```

### Arguments

| | |
|---|---|
| `starts` | array of starting times |
| `ends` | array of ending times |
| `durations` | array of durations |
| `productions` | array of tasks' requirements |
| `prod_sizes` | array of tasks' productions |
| `consumptions` | array of tasks' provisions |
| `conso_sizes` | array of tasks' consumptions |
| `C` | initial resource capacity array indexed by time |

### Example

The following example shows how to use the producer_consumer constraint for the problem of planning the construction of a house (an example of resource-constrained project scheduling).

```
model "Cumulative Scheduling"
 uses "kalis"

 setparam("KALIS_DEFAULT_LB",0)
 setparam("KALIS_DEFAULT_UB",100)

 declarations
 ! Task indices
  Masonry = 1; Carpentry= 2; Roofing       = 3; Windows      = 4
  Facade  = 5; Garden   = 6; Plumbing      = 7; Ceiling      = 8
  Painting= 9; MovingIn =10; InitialPayment=11; SecondPayment=12
  BUILDTASKS = 1..10
  PAYMENTS = 11..12
  TASKS = BUILDTASKS+PAYMENTS
  TNAMES: array(TASKS) of string

  obj:cpvar                                  ! Objective variable
  starts   : array(TASKS) of cpvar           ! Start times variables
  ends     : array(TASKS) of cpvar           ! Completion times
  durations: array(TASKS) of cpvar           ! Durations of tasks
  consos   : dynamic array(TASKS) of cpvar ! Res. consumptions
  sizes    : dynamic array(TASKS) of cpvar ! Consumption sizes
  prods    : dynamic array(TASKS) of cpvar ! Res. production
  sizep    : dynamic array(TASKS) of cpvar ! Production sizes
  Strategy : cpbranching                     ! Branching strategy
 end-declarations
```

```
 TNAMES:: (1..12)["Masonry", "Carpentry", "Roofing", "Windows",
           "Facade", "Garden", "Plumbing", "Ceiling", "Painting",
    "MovingIn", "InitialPayment", "SecondPayment"]

! Setting the names of the variables
  forall(j in TASKS) do
    starts(j).name := TNAMES(j)+".start"
    ends(j).name := TNAMES(j)+".end"
    durations(j).name := TNAMES(j)+".duration"
  end-do

! Creating consumption variables
  forall(j in BUILDTASKS) do
    create(sizes(j))
    sizes(j).name := TNAMES(j)+".size"
    create(consos(j))
    consos(j).name := TNAMES(j)+".conso"
  end-do

! Setting durations of building tasks
 durations(Masonry) =7; durations(Carpentry)=3; durations(Roofing) =1
 durations(Windows) =1; durations(Facade)   =2; durations(Garden)  =1
 durations(Plumbing)=8; durations(Ceiling)  =3; durations(Painting)=2
 durations(MovingIn)=1

! Precedence constraints among building tasks
 starts(Carpentry) >= ends(Masonry)
 starts(Roofing)   >= ends(Carpentry)
 starts(Windows)   >= ends(Roofing)
 starts(Facade)    >= ends(Roofing)
 starts(Garden)    >= ends(Roofing)
 starts(Plumbing)  >= ends(Masonry)
 starts(Ceiling)   >= ends(Masonry)
 starts(Painting)  >= ends(Ceiling)
 starts(MovingIn)  >= ends(Windows)
 starts(MovingIn)  >= ends(Facade)
 starts(MovingIn)  >= ends(Garden)
 starts(MovingIn)  >= ends(Painting)

! Setting task consumptions
 consos(Masonry)  = 7; consos(Carpentry) = 3; consos(Roofing)  = 1
 consos(Windows)  = 1; consos(Facade)    = 2; consos(Garden)   = 1
 consos(Plumbing) = 8; consos(Ceiling)   = 3; consos(Painting) = 2
 consos(MovingIn) = 1

! Production (amount) of payment tasks
 forall(j in PAYMENTS) do
  create(prods(j))
  prods(j).name := TNAMES(j)+".prod"
  create(sizep(j))
  sizep(j).name := TNAMES(j)+".sizep"
 end-do

! Payment data
 prods(InitialPayment)    = 20; prods(SecondPayment)     = 9
 durations(InitialPayment) = 1; durations(SecondPayment) = 1
 starts(InitialPayment)    = 0; starts(SecondPayment)    = 15
```

```
! Objective: makespan of the schedule
 obj = maximum({ ends(Masonry) , ends(Carpentry), ends(Roofing),
         ends(Windows), ends(Facade), ends(Garden), ends(Plumbing),
  ends(Ceiling), ends(Painting), ends(MovingIn)})

! Posting the producer_consumer constraint
 producer_consumer(starts,ends,durations,prods,sizep,consos,sizes)

! Setting the search strategy
 Strategy:= assign_var(KALIS_SMALLEST_MIN, KALIS_MIN_TO_MAX, starts)
 cp_set_branching(Strategy)

! Find the optimal solution
 if cp_minimize(obj) then
  writeln("Minimum makespan: ", obj.sol)
  forall(j in BUILDTASKS)
    writeln(TNAMES(j), ": ", starts(j).sol, " - ", ends(j).sol)
 else
  writeln("No solution found")
 end-if

end-model
```

**Related topics**

cumulative

# 9.2 Constraint parameters

| | | |
|---|---|---|
| `getactivebranch` | Gets the active branch of a disjunction | p. 115 |
| `getarity` | Returns the number of variables in the constraint | p. 109 |
| `getpriority` | Returns the priority of a constraint | p. 110 |
| `gettag` | Gets the tag of a constraint | p. 112 |
| `setfirstbranch` | Sets the first branch of a disjunction to be activated | p. 114 |
| `setpriority` | Sets the priority of a constraint | p. 111 |
| `settag` | Sets the tag of a constraint | p. 113 |

## getarity

### Purpose

Returns the number of decision variables involved in the constraint; this function can be used, for instance, to design advanced search heuristics

### Synopsis

```
function getarity(ctr:cpctr) : integer
```

### Argument

`ctr` the constraint to explore

### Return value

The number of variables involved in ctr

### Example

The following example shows how to get the arity of a constraint

```
getarity(x + y = 3)
```

# getpriority

### Purpose

Returns the priority of a disjunction passed in argument; this feature is intended for advanced use in dynamically prioritizing the disjunction for solving (highest priority constraints are handled first)

### Synopsis

```
function getpriority(ctr:cpctr) : integer
```

### Argument

`ctr` The constraint to explore (disjunction only)

### Return value

The associated priority

### Example

The following example shows how to get the priority of a constraint

```
getpriority((x + y = 3) or (x + y = 1))
```

### Related topics

`setpriority`

## setpriority

### Purpose

Sets the priority of a constraint passed in argument

### Synopsis

```
procedure setpriority(ctr:cpctr, priority:integer)
```

### Arguments

| | |
|---|---|
| `ctr` | the constraint (disjunction only) |
| `priority` | a user-defined integer (the higher it will be, the quicker the disjunction will be activated) |

### Example

The following example shows how to set the priority of a constraint:

```
setpriority((x + y = 3) or (x + y = 1),2)
```

### Related topics

`getpriority`

# gettag

### Purpose

Gets the tag (user-defined integer information) of a constraint

### Synopsis

```
function gettag(ctr:cpctr) : integer
```

### Argument

`ctr` the constraint

### Return value

The tag that has been previously associated to it

### Example

The following example shows how to get the tag of a constraint ctr

```
writeln(gettag(ctr))
```

### Related topics

`settag`

## settag

### Purpose

Sets the tag (user-defined integer information) of a constraint

### Synopsis

```
procedure settag(ctr:cpctr,tag:integer)
```

### Arguments

`ctr` the constraint

`tag` the tag

### Example

The following example shows how to set the tag of a constraint to '32'

```
settag(ctr,32)
```

### Related topics

`gettag`

## setfirstbranch

### Purpose

This procedure enables the user to specify the first constraint of a disjunction to be activated; thus, it is possible to create dynamical heuristics for disjunctions.

### Synopsis

```
procedure setfirstbranch(disj:cpctr, firstbranch:integer)
```

### Arguments

| | |
|---|---|
| `disj` | the involved constraint (only a disjunction) |
| `firstbranch` | 0 to activate the first part and 1 else |

### Related topics

`disjunctive` or `getactivebranch`

## getactivebranch

### Purpose

This function enables the user to know which part of a disjunction is active; if the first constraint of the disjunction is satisfied, it returns zero, else it returns one.

### Synopsis

```
function getactivebranch(disj:cpctr) : integer
```

### Argument

`disj` the involved constraint (only a disjunction)

### Return value

Zero if the first part of the disjunction is satisfied, one otherwise.

### Example

The following code shows how to retrieve the active branch information from the disjunction disj:

```
b:=getactivebranch(disj)
```

### Related topics

`disjunctive` or `setfirstbranch`

# 9.3 Variables


| | | |
|---|---|---|
| `contains` | Tests if a value is in the domain of a variable | p. 128 |
| `cp_show_var` | Shows the current domain of the variable | p. 137 |
| `cp_show_var_constraints` | Shows the constraints of involved in the variable | p. 138 |
| `getdegree` | Returns the degree of a variable | p. 123 |
| `getlb` | Returns the current lower bound of a variable | p. 117 |
| `getmiddle` | Returns the middle value of a variable | p. 119 |
| `getnext` | Gets the next value in the domain of a finite domain variable | p. 126 |
| `getprev` | Gets the previous value in the domain of a finite domain variable | p. 127 |
| `getrand` | Returns a random value belonging to the domain of a variable | p. 125 |
| `getsize` | Returns the cardinality of the variable domain | p. 120 |
| `gettarget` | Returns the target value of a variable | p. 124 |
| `getub` | Returns the current upper bound of a variable | p. 118 |
| `getval` | Returns the instantiation value of a variable | p. 121 |
| `is_equal` | Tests if two variable domains are equal | p. 129 |
| `is_fixed` | Tests if the variable passed in argument is instantiated | p. 122 |
| `is_same` | Tests if two decision variables represent the same variable | p. 130 |
| `setdomain` | Sets the domain of a variable | p. 132 |
| `setlb` | Sets the lower bound of a variable | p. 133 |
| `setprecision` | Sets the precision relativity and value of a continuous variable | p. 136 |
| `settarget` | Sets the target value of a variable | p. 131 |
| `setub` | Sets the upper bound of a variable | p. 134 |
| `setval` | Instantiate the value of a variable | p. 135 |

# getlb

### Purpose

This function returns the current lower bound of the domain of the variable passed in the argument.

### Synopsis

```
function getlb(x:cpvar) : integer
function getlb(x:cpfloatvar) : real
```

### Argument

`x` the decision variable

### Return value

The current lower bound of variable x

### Example

The following example shows how to get the lower bound of a cpvar `x`

```
val:=getlb(x)
```

### Related topics

`KALIS_DEFAULT_LB` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev` `contains`

# getub

### Purpose

This function returns the current upper bound of the domain of the variable passed in the argument.

### Synopsis

```
function getub(x:cpvar) : integer
function getub(x:cpfloatvar) : real
```

### Argument

`x` the decision variable

### Return value

The current upper bound of x

### Example

The following example shows how to get the upper bound of a cpvar `x`

```
val:=getub(x)
```

### Related topics

`KALIS_DEFAULT_UB` `getlb` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev` `contains`

# getmiddle

### Purpose

This function returns the value nearest to the middle of the domain of the variable passed in the argument. It can be useful for specific search strategies.

### Synopsis

```
function getmiddle(x:cpvar) : integer
function getmiddle(x:cpfloatvar) : real
```

### Argument

`x` the decision variable

### Return value

The middle value of a variable

### Example

The following example shows how to get the middle value of a cpvar `x`'

```
val:=getmiddle(x)
```

### Related topics

`getlb` `getub` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev` `contains`

# getsize

### Purpose

This function returns the cardinality (number of distinct values) of the domain of the variable passed in argument in the case of cpvar and the size of the domain interval representation of the domain in the case of a cpfloatvar.

### Synopsis

```
function getsize(x:cpvar) : integer
function getsize(x:cpfloatvar) : integer
```

### Argument

`x` the decision variable

### Return value

The cardinality / size of the interval representation of the domain of `x`

### Example

The following example shows how to get the size of the domain of a cpvar `x`

```
sz:=getsize(x)
```

### Related topics

`getlb` `getub` `getmiddle` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev` `contains`

# getval

### Purpose

This function returns the instantiation value of a variable passed in argument. Note that the variable must be instantiated before calling this function, else it will return its lower bound.

### Synopsis

```
function getval(x:cpvar) : integer
```

### Argument

`x` the decision variable

### Return value

The instantiation value of x (or by default its lower bound)

### Example

The following example shows how to get the instantiation value of a cpvar X

```
val:=getval(X)
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev` `contains`

# is_fixed

### Purpose

Returns `true` if the variable passed in argument has a domain reduced to a singleton.

### Synopsis

```
function is_fixed(var:cpvar) : boolean
function is_fixed(var:cpfloatvar) : boolean
```

### Argument

`var` the decision variable

### Return value

`true` if var has been instantiated

### Example

The following example shows how to see if a cpvar `var` is instantiated

```
if is_fixed(var) then
  write('value of var is ', getval(var))
end-if
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getsol` `getval` `getdegree` `gettarget` `getrand` `getnext` `getprev` `contains`

# getdegree

### Purpose

Returns the degree in the constraint graph of the decision variable passed in argument (i.e., the number of constraints that involve it); this can be used for advanced search heuristics.

### Synopsis

```
function getdegree(x:cpvar) : integer
function getdegree(x:cpfloatvar) : integer
```

### Argument

`x` the decision variable

### Return value

The degree of x

### Example

The following example shows how to get the degree of a cpvar `x`

```
d:=getdegree(x)
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `gettarget` `getrand` `getnext` `getprev` `contains`

# gettarget

### Purpose

Returns the target value (preferred value for instantiation) for the variable passed in argument

### Synopsis

```
function gettarget(var:cpvar) : integer
function gettarget(var:cpfloatvar) : real
```

### Argument

`var` the decision variable

### Return value

The target value of var

### Example

The following example shows how to get the target value of a cpvar 'x'

```
tval := gettarget(x)
```

### Related topics

`settarget` `getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `getrand` `getnext` `getprev` `contains`

# getrand

### Purpose

Returns a value at random (uniform distribution) in the domain of the variable passed in argument.

### Synopsis

```
function getrand(x:cpvar) : integer
function getrand(x:cpfloatvar) : real
```

### Argument

`x` the decision variable

### Return value

A random value in the domain of x

### Example

The following example shows how to get a random value in the domain a cpvar `x`

```
r:=getrand(x)
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getnext` `getprev` `contains`

# getnext

### Purpose

Returns the value nearest to and greater than `val` in the domain of a variable passed in argument. This function is useful to enumerate the values of the domain of a variable from the lowest to the highest value; note that if 'val' is larger than the upper bound of the domain of x, the upper bound will be returned.

### Synopsis

```
function getnext(x:cpvar,val:integer) : integer
```

### Arguments

| | |
|---|---|
| `x` | the decision variable |
| `val` | a value in the domain of the variable |

### Return value

The next value in the domain of x

### Example

The following example shows how to enumerate in increasing order the values in the domain of a cpvar `x`

```
curVal := getlb(x)
while (curVal < getub(x)) do
   curVal := getnext(x, curVal)
   writeln("curVal= ", curVal)
end-do
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getprev` `contains`

# getprev

### Purpose

Returns the value nearest to and lower than 'val' in the domain of a variable passed in argument. This function is useful to enumerate the values of the domain of a variable from the highest to the lowest value; note that if 'val' is below the lower bound of x domain, the lower bound will be returned.

### Synopsis

```
function getprev(x:cpvar,val:integer) : integer
```

### Arguments

| | |
|---|---|
| `x` | the decision variable |
| `val` | a value in the domain of the variable |

### Return value

The previous value in the domain of x

### Example

The following example shows how to enumerate in decreasing order the values in the domain of a cpvar `x`

```
curVal := getub(x)
while (curVal > getlb(x)) do
   curVal := getprev(x, curVal)
   writeln("curVal= ",curVal)
end-do
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `contains`

## contains

### Purpose

Returns `true` if the value 'val' belongs to the domain of the variable passed in argument

### Synopsis

```
function contains(x:cpvar,val:integer) : boolean
function contains(x:cpfloatvar,val:real) : boolean
```

### Arguments

| | |
|---|---|
| `x` | the decision variable |
| `val` | the value |

### Return value

`true` if x can be instantiated to `val`

### Example

The following example shows how to test if a value belongs to the domain of a cpvar `x`

```
if contains(x,3) then
  write("x can be instantiated to three!")
end-if
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev`

## is_equal

### Purpose

Returns `true` if the domains of the two variables passed in argument contain exactly the same values

### Synopsis

```
function is_equal(var1:cpvar,var2:cpvar) : boolean
function is_equal(var1:cpfloatvar,var2:cpfloatvar) : boolean
```

### Arguments

`var1` the first decision variable

`var2` the second decision variable

### Return value

`true` if the domain of `var1` equals the domain of `var2`, else `false`

### Example

The following example shows how to test whether the domains of two cpvar `var1` and `var2` are equal

```
if is_equal(var1,var2) then
  write("the domains of var1 and var2 are the same!")
end-if
```

### Related topics

`is_same`

## is_same

### Purpose

Returns `true` if two decision variables passed in argument represent the same variable; this function is mainly used by advanced users to specify branching heuristics (see example below).

### Synopsis

```
function is_same(var1:cpvar,var2:cpvar) : boolean
function is_same(var1:cpfloatvar,var2:cpfloatvar) : boolean
```

### Arguments

`var1` the first decision variable

`var2` the second decision variable

### Return value

`true` if `var1` and `var2` represent the same variable

### Example

The following example shows how to test whether two cpvar represent the same variable

```
if is_same(var1,var2) then
  write("var1 and var2 represent the same variable!")
end-if
```

### Related topics

`is_equal`

## settarget

### Purpose

Sets the target value (preferred instantiation value) for the variable passed in argument.

### Synopsis

```
procedure settarget(x:cpvar,value:integer)
procedure settarget(x:cpfloatvar,value:real)
```

### Arguments

`x` the decision variable

`value` the target value

### Example

The following example shows how to set the target value of a cpvar `x` to three:

```
settarget(x,3)
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev`

# setdomain

### Purpose

Sets the domain of the variable to the set of integers passed in argument.

### Synopsis

```
procedure setdomain(x:cpvar, domain:set of integers)
procedure setdomain(x:cpvar, lowerBound:integer, upperBound:integer)
procedure setdomain(x:cpfloatvar, lowerBound:real, upperBound:real)
procedure setdomain(x:cpauxvar, lowerBound:real, upperBound:real)
```

### Arguments

| | |
|---|---|
| `x` | the decision variable |
| `domain` | Set of integers representing the target domain. |
| `lowerBound` | lower bound of the interval |
| `upperBound` | upper bound of the interval |

### Example

The following example shows how to set the domain of a cpvar `x` to the set of integers {1,3,5,7,9}

```
setdomain(x,{1,3,5,7,9})
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev`

# setlb

### Purpose

Sets the lower bound of the variable to the value passed in argument. This procedure can be used during the CP search.

### Synopsis

```
procedure setlb(x:cpvar, value:integer)
procedure setlb(x:cpfloatvar, value:real)
```

### Arguments

| | |
|---|---|
| `x` | the decision variable |
| `value` | value representing the lower bound |

### Example

The following example shows how to set the lower bound of a cpvar `x` to the integer value `1`.

```
setlb(x,1)
```

### Related topics

`setval` `setub` `getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev`

# setub

### Purpose

Sets the upper bound of the variable to the value passed in argument. This procedure can be used during the CP search.

### Synopsis

```
procedure setub(x:cpvar, value:integer)
procedure setub(x:cpfloatvar, value:real)
```

### Arguments

`x` the decision variable

`value` value representing the upper bound.

### Example

The following example shows how to set the upper bound of a cpvar `x` to the integer value `1`.

```
setub(x,1)
```

### Related topics

`setval` `setlb` `getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev`

## setval

### Purpose

Sets the value of the variable to the value passed in argument. This procedure can be used during the CP search.

### Synopsis

```
procedure setval(x:cpvar, value:integer)
procedure setval(x:cpfloatvar, value:real)
```

### Arguments

`x` the decision variable

`value` instantiation value

### Example

The following example shows how to instantiate the value of a cpvar `x` to the integer value `1`.

```
setval(x,1)
```

### Related topics

`setlb` `setub` `getlb` `getub` `getmiddle` `getsize` `getval` `is_fixed` `getdegree` `gettarget` `getrand` `getnext` `getprev`

# setprecision

### Purpose

Sets the precision relativity and value of a cpfloatvar

### Synopsis

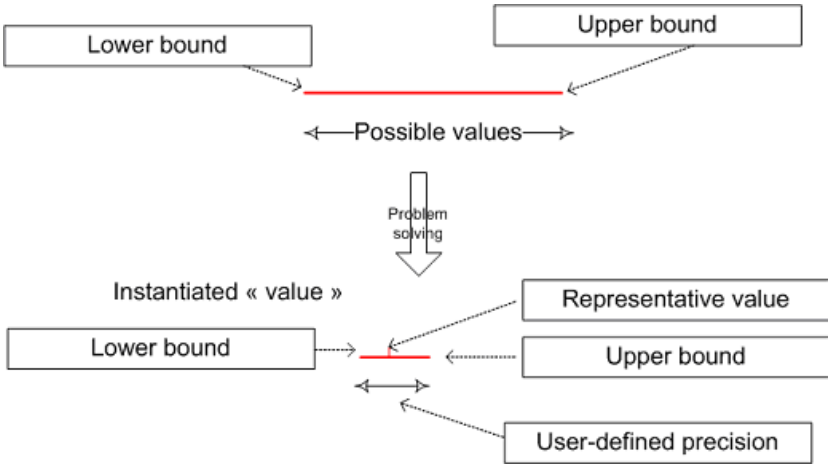
```
procedure setprecision(x:cpfloatvar, relativity:boolean, precision:real)
procedure setprecision(x:cpfloatvar, precision:real)
```

### Arguments

| | |
|---|---|
| `x` | the variable |
| `relativity` | relativity of precision |
| `precision` | precision value |

### Example

The following picture illustrates the concept of precision for a cpfloatvar



## cp_show_var

### Purpose

This procedure prints the current domain of the variable passed in argument

### Synopsis

```
procedure cp_show_var(var:cpvar)
procedure cp_show_var(var:cpfloatvar)
```

### Argument

`var` the decision variable to show

### Related topics

`cp_show_prob` `cp_show_var_constraints` `cp_show_stats` `cp_print_stats`

## cp_show_var_constraints

### Purpose

This procedure prints the current domain of the variable passed in argument and the constraints where the variable is involved.

### Synopsis

```
procedure cp_show_var_constraints(var:cpvar)
procedure cp_show_var_constraints(var:cpfloatvar)
```

### Argument

`var` the decision variable to show

### Example

See the example provided for `update_duration_with_idle_times`.

### Related topics

`cp_show_prob` `cp_show_var` `cp_show_stats` `cp_print_stats`

# 9.4 Problem


| | | |
|---|---|---|
| cp_find_next_sol | Finds the next solution of the problem | p. 142 |
| cp_infeas_analysis | Compute a minimal conflict set for an inconsistent problem | p. 156 |
| cp_local_optimize | Optimize an integer objective variable with local optimization. | p. 160 |
| cp_maximise | Alias for cp_maximize | p. 144 |
| cp_maximize | Maximizes a variable | p. 145 |
| cp_minimise | Alias for cp_minimize | p. 146 |
| cp_minimize | Minimizes a variable | p. 147 |
| cp_post | Posts a constraint to the problem | p. 140 |
| cp_propagate | Propagates the constraints | p. 141 |
| cp_reset_params | Reset parameters to their default value. | p. 162 |
| cp_reset_search | Resets the search process | p. 143 |
| cp_restore_state | Restore a solver state from the stack | p. 158 |
| cp_save_state | Save a marker in the stack | p. 157 |
| cp_shave | Shave the variables of the problem | p. 155 |
| cp_show_best_sol | Pretty printing of the best solution found. | p. 151 |
| cp_show_prob | Pretty printing of the problem | p. 149 |
| cp_show_sol | Pretty printing of the last solution. | p. 150 |
| getelt | Retrieve the value of a reversible array element. | p. 167 |
| getindex | Gets the index of a variable / task / resource | p. 154 |
| getname | Gets the name of a variable / task / resource | p. 152 |
| getsize | Returns the size of a reversible array. | p. 168 |
| getsol | Returns the solution value of a variable | p. 148 |
| getval | Retrieve the value of a reversible number. | p. 165 |
| path_order | Return a path-order branching scheme | p. 159 |
| set_reversible_attributes | Sets the attributes of a reversible number or array. | p. 163 |
| set_sol_as_target | Set last solution found as target values. | p. 161 |
| setelt | Set the value of an element of an array of reversibles. | p. 166 |
| setname | Sets the name of a variable / task / resource | p. 153 |
| setval | Set the value of a reversible number. | p. 164 |

## cp_post

### Purpose

This function posts the constraint ctr to the problem. Note that posting a constraint does not imply that the involved variables will be instantiated.

### Synopsis

```
function cp_post(ctr:cpctr) : boolean
```

### Argument

`ctr` the constraint to post

### Return value

Returns `true` if the constraint is compatible with already posted constraints, else `false`.

### Example

The following example shows how to post the constraint x = y + 1 where x and y are two decision variables of the problem

```
cp_post(x = y + 1)
```

### Related topics

`cp_propagate` `KALIS_AUTO_PROPAGATE` `cp_post`

## cp_propagate

### Purpose

This function reaches a fixed point during constraint propagation. The constraint deduction rules are applied successively until no more deductions are possible. Note that propagating a constraint does not imply that the involved variables will be instantiated.

### Synopsis

```
function cp_propagate : boolean
```

### Return value

Returns `false` if the propagation reaches a contradiction (infeasible problem), else returns `true`

### Related topics

`cp_post` `KALIS_AUTO_PROPAGATE`

## cp_find_next_sol

### Purpose

Finds the next solution of the problem

### Synopsis

```
function cp_find_next_sol : boolean
```

### Return value

Returns `true` if an additional solution can be found, else `false`

### Example

The following code shows how to scan all the solutions of a predefined problem containing b, x, y and z as decision variables:

```
while (cp_find_next_sol)
 writeln("b:", b, " x:", x, " y:", y, " z:", z)
```

### Related topics

`cp_reset_search` `cp_minimize` `cp_maximize` `cp_set_branching`

## cp_reset_search

### Purpose

This procedure resets the search process: it finalizes the tree search and returns to the first node of the tree. While it is not called, the branch and bound stays at a node in the tree search and the problem cannot be modified. It needs to be called only if tree search was not finished.

### Synopsis

```
procedure cp_reset_search
```

## cp_maximise

### Purpose

Alias for cp_maximize. See `cp_maximize` for description.

### Synopsis

```
function cp_maximise(obj:cpvar) : boolean
function cp_maximise(obj:cpfloatvar) : boolean
```

### Related topics

`cp_maximize`

## cp_maximize

### Purpose

This function starts the search for an optimal solution of the problem that maximizes a specific variable. Upon termination of the search (when no limitation has been set on the search process), the last solution found (if any exists) is proven optimal.

### Synopsis

```
function cp_maximize(obj:cpvar) : boolean
function cp_maximize : boolean
```

### Argument

`obj` the decision variable to maximize

### Return value

`true` if a solution has been found, `false` if the problem is inconsistent (no solution exists)

### Example

The following code shows how to use this function to maximize the Benefit objective

```
optimizeProcess := cp_maximize(Benefit)
```

### Related topics

`cp_minimize` `cp_find_next_sol`

## cp_minimise

### Purpose

Alias for cp_minimize. See `cp_maximize` for description.

### Synopsis

```
function cp_minimise(obj:cpvar) : boolean
function cp_minimise(obj:cpfloatvar) : boolean
```

### Related topics

`cp_minimize`

## cp_minimize

### Purpose

This function starts the search for an optimal solution of the problem that minimizes a specific variable. Upon termination of the function (when no limitation has been set on the search process), the last solution found (if any exists) is proven optimal.

### Synopsis

```
function cp_minimize(obj:cpvar) : boolean
function cp_minimize(obj:cpfloatvar) : boolean
```

### Argument

`obj` the decision variable to minimize

### Return value

`true` if a solution has been found, `false` if the problem is inconsistent (no solution exists)

### Example

The following code shows how to use this function to minimize the objective `Cost`:

```
optimizeProcess := cp_minimize(Cost)
```

### Related topics

`cp_maximize` `getsol` `cp_find_next_sol`

# getsol

### Purpose

This function returns the solution value of a variable or linear expression passed in argument. Note that the variable must be instantiated before calling this function, else it will return its lower bound.

### Synopsis

```
function getsol(x:cpvar) : integer
function getsol(x:cpfloatvar) : real
function getsol(l:cplinexp) : real
```

### Arguments

| | |
|---|---|
| `x` | a decision variable |
| `l` | a linear expression |

### Return value

The instantiation value of x (or by default its lower bound), respectively the evaluation of the linear expression

### Example

The following example shows how to get the solution value of a cpvar `x`

```
val:= getsol(x)
```

### Related topics

`getlb` `getub` `is_fixed` `getsize`

## cp_show_prob

### Purpose

This procedure prints an overview of the current state of the problem (variables and constraints)

### Synopsis

```
procedure cp_show_prob
```

### Related topics

`cp_show_var` `cp_show_var_constraints` `cp_show_stats` `cp_print_stats`

## cp_show_sol

### Purpose

This procedure prints an overview of the last solution found.

### Synopsis

```
procedure cp_show_sol
```

### Related topics

`cp_show_var` `cp_show_var_constraints` `cp_show_stats` `cp_print_stats`

## cp_show_best_sol

### Purpose

This procedure prints an overview of the best solution found if the problem has an objective, or of the last solution found otherwise.

### Synopsis

```
procedure cp_show_best_sol
```

### Related topics

`cp_show_sol` `cp_show_var` `cp_show_var_constraints` `cp_show_stats` `cp_print_stats`

# getname

### Purpose

Gets the name of a variable / task / resource passed in argument. The name of the modeling object is used by problem and variable printing routines

### Synopsis

```
function getname(var:cpvar): string
function getname(fvar:cpfloatvar): string
function getname(task:cptask): string
function getname(resource:cpresource): string
```

### Arguments

| | |
|---|---|
| `var` | a finite domain variable |
| `fvar` | a continuous variable |
| `task` | a task |
| `resource` | a resource |

### Return value

The name of the entity (as specified via `setname` or automatically generated default name).

### Example

The following example shows how to print out the name of a cpvar `x`.

```
declarations
 x: cpvar
end-declarations
setname(x, "myvar")
writeln(getname(x))
```

### Related topics

`setname` `cp_show_prob` `cp_show_var` `cp_show_schedule`

## setname

### Purpose

Sets the name of a variable / task / resource passed in argument, the name of the variable / task / resource is used by problem and variable printing routines

### Synopsis

```
procedure setname(var:cpvar,name:string)
procedure setname(fvar:cpfloatvar,name:string)
procedure setname(task:cptask,name:string)
procedure setname(resource:cpresource,name:string)
```

### Arguments

| | |
|---|---|
| `var` | a finite domain variable |
| `fvar` | a continuous variable |
| `task` | a task |
| `resource` | a resource |
| `name` | the name to set |

### Example

The following example shows how to set the name of a cpvar `x` to 'AMOUNT'.

```
declarations
 x: cpvar
end-declarations
setname(x,"AMOUNT")
```

### Related topics

`getname` `cp_show_prob` `cp_show_var` `cp_show_schedule`

# getindex

### Purpose

Gets the index of a variable / task / resource passed in argument. The index is unique for each type of object (cpvar, cpfloatvar, cptask, cpresource). For example, it can be used to map variables to problem data in a user branching scheme or to compare two variable objects.

### Synopsis

```
function getindex(var:cpvar): integer
function getindex(fvar:cpfloatvar): integer
function getindex(task:cptask): integer
function getindex(resource:cpresource): integer
```

### Arguments

| | |
|---|---|
| `var` | a finite domain variable |
| `fvar` | a continuous variable |
| `task` | a task |
| `resource` | a resource |

### Example

The following example displays the index of a cpvar `x`.

```
declarations
 x: cpvar
end-declarations
writeln("Index value of 'x': ", getindex(x))
```

### Related topics

`getname`

## cp_shave

### Purpose

Shaving consists in tentatively setting variables to a value in their domain. If the assignment fails (considering the complete constraint set), then this value can be removed from the domain, possibly eliminating many inconsistent values before starting search.

### Synopsis

```
function cp_shave: boolean
```

### Return value

`false` if problem is proven to be inconsistent, `true` otherwise

### Example

The following example shows how to apply shaving to the variables of a problem:

```
res := cp_shave
```

### Related topics

`cp_propagate`

## cp_infeas_analysis

### Purpose

This method computes a minimal conflict set for an inconsistent problem. A minimal conflict set is a minimal size set of constraints that causes a contradiction (infeasibility).

### Synopsis

```
procedure cp_infeas_analysis
```

### Example

The following example shows how to compute a minimal conflict set:

```
...    ! definition of constraints
...
cp_save_state
if (not cp_propagate) then
  cp_restore_state
  writeln("Problem is infeasible")
  cp_infeas_analysis
  exit(0)
end-if
cp_restore_state
...     ! problem solving
```

### Related topics

cp_save_state cp_restore_state

## cp_save_state

### Purpose

Save a marker in the CP solver stack to enable restoration of the domains of decision variables at a later stage, *e.g.*, for performing infeasibility analysis.

### Synopsis

```
procedure cp_save_state
```

### Example

The following example shows how to save the state of a constraint system:

```
...     ! definition of constraints
...
cp_save_state
if (not cp_propagate) then
  cp_restore_state
  writeln("Problem is infeasible")
  cp_infeas_analysis
  exit(0)
end-if
cp_restore_state
...     ! problem solving
```

### Related topics

cp_restore_state

# cp_restore_state

### Purpose

Restore the state of the CP solver at a previously saved state marker. Note: this function only restores the domains of decision variables, constraints that have been posted after saving the state marker are not removed.

### Synopsis

```
procedure cp_restore_state
```

### Example

The following example shows how to restore the state of a constraint system:

```
...    ! definition of constraints
...
cp_save_state
if (not cp_propagate) then
 cp_restore_state
 writeln("Problem is infeasible")
 cp_infeas_analysis
 exit(0)
end-if
cp_restore_state
...     ! problem solving
```

### Related topics

cp_save_state

# path_order

### Purpose

The path-heuristic is specifically designed to work in conjunction with the cycle constraint. It selects the first unassigned 'succ' variable in the order of the current subpath implied by the current values of the successors variables. When the subpath is empty (no 'succ' variables are currently instantiated) the path order-heuristic selects a node at random.

### Synopsis

```
function path_order(succ:array of cpvar, nodeSelection:string) :
      cpbranching
```

### Arguments

| | |
|---|---|
| `succ` | The list of successors variables |
| `nodeSelection` | The value selection heuristic |

### Related topics

`cycle`

## cp_local_optimize

### Purpose

This function starts the search for a near-optimal solution of the problem that optimizes a specific objective variable.

### Synopsis

```
function cp_local_optimize(obj:cpvar, minimize: integer) : boolean
function cp_local_optimize(obj:cpfloatvar, minimize: integer) : boolean
```

### Arguments

| | |
|---|---|
| `obj` | the objective variable |
| `minimize` | `0` for minimization or `1` for maximization |

### Related topics

`cp_minimize` `cp_maximize`

## set_sol_as_target

### Purpose

Set the target values of all the variables to their value in the last solution found.

### Synopsis

```
procedure set_sol_as_target
```

### Related topics

`gettarget` `settarget` `KALIS_NEAREST_VALUE`

## cp_reset_params

### Purpose

Reset parameters to their default value.

### Synopsis

```
procedure cp_reset_params(parameterSet:integer)
```

### Argument

| | |
|---|---|
| `parameterSet` | the set of parameters to reset (`KALIS_RESET_PARAMS_ALL`, `KALIS_RESET_VAR_BOUNDS`, `KALIS_RESET_VAR_PRECISION`, `KALIS_RESET_OPT_PARAMS`, `KALIS_RESET_SEARCH_PARAMS`) |

### Example

The following example shows how to use the cp_reset_params function to reset all parameters of Xpress Kalis:

```
cp_reset_params(KALIS_RESET_PARAMS_ALL)
```

### Related topics

`KALIS_RESET_PARAMS_ALL`, `KALIS_RESET_VAR_BOUNDS`, `KALIS_RESET_VAR_PRECISION`, `KALIS_RESET_OPT_PARAMS`, `KALIS_RESET_SEARCH_PARAMS`, `setparam`

# set_reversible_attributes

### Purpose

Sets the attributes of a reversible number or array.

### Synopsis

```
procedure set_reversible_attributes(revarray:cpreversiblearray,
       first:integer, last:integer, initValue:integer)
procedure set_reversible_attributes(rev:cpreversible, initValue:real)
```

### Arguments

| | |
|---|---|
| `revarray` | a reversible array |
| `first` | the smallest index number |
| `last` | the highest index number |
| `rev` | a reversible number |
| `initValue` | the initialization value |

### Example

The following example shows how to set the attributes of a reversible array :

```
declarations
  reva: cpreversiblearray
end-declarations

! Create a reversible array of 10 elements initialized with value 0
set_reversible_attributes(reva, 1, 10, 0)

! Return the number of elements in the reversible array
writeln("Array contains ", getsize(reva), " elements")

! Get the 5'th element of the array
writeln("The 5'th element of reva is ", getelt(reva,5))
```

### Related topics

`setval` `getval` `getsize` `getelt` `setelt`

## setval

### Purpose

Sets the value of a reversible number. If this procedure is used during the CP search, the reversible will be restored to its previous value on backtracking beyond the state where this value has been set.

### Synopsis

```
procedure setval(k:cpreversible, value:real)
```

### Arguments

`k` a reversible number,

`value` instantiation value.

### Example

The following example shows how to set the current value of a reversible `rev` to the integer value `10`.

```
setval(rev, 10)
```

### Related topics

`set_reversible_attributes` `getval`

# getval

### Purpose

Retrieves the value of a reversible number at the current state of the constraint system.

### Synopsis

```
function getval(k:cpreversible): real)
```

### Argument

`k` a reversible number.

### Return value

The current value of the reversible.

### Example

The following example saves the state of the constrain system, changes the value of the reversible `rev`, then restores the previous state of th constraint system and displays the restored value of the reversible number.

```
set_reversible_attributes(rev, 20.54)

! Save current state of constraint system
cp_save_state

setval(rev, 5)
writeln("Value of the reversible is ", getval(rev))

! Restore the saved system state
cp_restore_state
writeln("After state restoration reversible is ", rev)
```

### Related topics

`set_reversible_attributes` `setval`

# setelt

### Purpose

Sets the value of an element of an array of reversibles. If this procedure is used during the CP search, the reversible will be restored to its previous value on backtracking beyond the state where this value has been set.

### Synopsis

```
procedure setelt(ra:cpreversiblearray, ind: integer, value:integer)
```

### Arguments

`ra` an array of reversibles,

`ind` the index of an array element,

`value` new value for the reversible.

### Example

The following example saves the state of the constraint system, changes the value of an element the reversible array `reva`, then restores the previous state of the constraint system and displays the restored value of the reversible number.

```
set_reversible_attributes(reva, 1, 10, 0)

! Save current state of constraint system
cp_save_state

setelt(reva, 4, -10)
writeln("The 4'th element of 'reva' is ", setelt(reva, 4))

! Revert to the saved system state
cp_restore_state
writeln("After state restoration reversible array is: ", reva)
```

### Related topics

`set_reversible_attributes` `getelt` `getsize`

# getelt

### Purpose

Retrieves the value of the specified element of an array of reversible numbers at the current state of the constraint system.

### Synopsis

```
function getelt(ra:cpreversiblearray, ind:integer): integer)
```

### Arguments

| | |
|---|---|
| `ra` | an array of reversibles, |
| `ind` | the index of an array element. |

### Return value

The current value of the specified entry of the array.

### Example

See `setelt`.

### Related topics

`set_reversible_attributes` `setelt` `getsize`

# getsize

### Purpose

This function returns the size (= number of elements) of a reversible array.

### Synopsis

```
function getsize(ra:cpreversiblearray): integer
```

### Argument

`ra` the array of reversibles

### Return value

The size of the array of reversibles.

### Example

The following example shows how to get the size of the array `reva`.

```
set_reversible_attributes(reva, 1, 10, 0)
writlen("Size of array 'reva': ", reva.size)
```

### Related topics

`set_reversible_attributes` `getelt` `setelt`

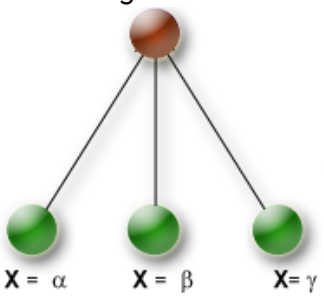
# 9.5 Search


| | | |
|---|---|---|
| assign_and_forbid | assign_and_forbid branching scheme | p. 173 |
| assign_var | assign_var branching scheme | p. 170 |
| bs_group | Create a group of branching schemes | p. 198 |
| cp_get_nb_solutions | Return the number of solutions already found for the problem. | p. 189 |
| cp_get_total_backtracks | Returns the total number of backtracks of the scheduling solver | p. 197 |
| cp_get_total_computation_time | Returns the total computation time of the scheduling solver | p. 194 |
| cp_get_total_depth | Returns the total depth of the scheduling solver | p. 196 |
| cp_get_total_number_of_nodes | Returns the total number of nodes of the scheduling solver | p. 195 |
| cp_print_stats | Dumps in a CSV file some statistics about the search | p. 188 |
| cp_set_branching | Sets the strategy to use during the search for a solution | p. 186 |
| cp_show_stats | Shows some statistics about the search | p. 187 |
| gettag | Gets the tag associated with a branching scheme group | p. 202 |
| group_serializer | Creates a branching scheme Group Serializer | p. 199 |
| probe_assign_var | probe_assign_var branching scheme | p. 176 |
| probe_settle_disjunction | probe_settle_disjunction branching scheme | p. 177 |
| settle_disjunction | settle_disjunction branching scheme | p. 174 |
| split_domain | split_domain branching scheme | p. 179 |
| task_serialize | task_serialize branching scheme | p. 181 |

# assign_var

## Purpose

Creates an assign_var (Constraint programming style) branching scheme; in this scheme, a discrete value is assigned to the branching variable at each branch.




## Synopsis

```
function assign_var(varsel:function or string,valsel:function or
      string,variables:set of cpvar) : cpbranching
function assign_var(varsel:function or string,valsel:function or
      string,variables:array(range) of cpvar) : cpbranching
function assign_var(varsel:function or string,valsel:function or
      string,variables:cpvarlist) : cpbranching
function assign_var(varsel:function or string,valsel:function or string) :
      cpbranching
```

## Arguments

| | |
|---|---|
| `varsel` | name of the variable selector (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `valsel` | name of the value selector (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `variables` | list of variables to branch on |

## Return value

assign_var branching scheme with default value and variable selector

## Example

The following example shows how to use an 'assign_var' branching scheme for the search process.

```
model "User branching"
 uses "kalis"

 parameters
  ALG=1
 end-parameters

 forward function varchoice(Vars: cpvarlist): integer
 forward function varchoice2(Vars: cpvarlist): integer
 forward function valchoice(x: cpvar): integer
 forward function valchoice2(x: cpvar): integer

 setparam("KALIS_DEFAULT_LB", 0);
 setparam("KALIS_DEFAULT_UB", 20)

 declarations
  R = 1..10
  y: array(R) of cpvar
  C: array(R) of integer
```

```
  Strategy: array(range) of cpbranching
 end-declarations

 C:: [4, 7, 2, 6, 9, 0,-1, 3, 8,-2]

 all_different(y)
 forall(i in R | isodd(i)) y(i) >= y(i+1) + 1
 y(4) + y(1) = 13; y(8) <= 15; y(7) <> 5

! Definition of user branching strategies:
 Strategy(1):= assign_and_forbid(->varchoice2, ->valchoice, y)
 Strategy(2):= assign_var(->varchoice, ->valchoice, y)
 Strategy(3):= split_domain(->varchoice, ->valchoice2, y, true, 2)
 Strategy(4):= split_domain(->varchoice2, ->valchoice, y, false, 5)

! Select a branching strategy
 cp_set_branching(Strategy(ALG))

 if cp_find_next_sol then
  forall(i in R) write(getsol(y(i)), " ")
  writeln
 end-if

!-------------------------------------------------------------------
! **** Variable choice ****
! **** Choose variable with largest degree + smallest domain
 function varchoice(Vars: cpvarlist): integer
  declarations
   Vset,Iset: set of integer
  end-declarations

  ! Get the number of elements of "Vars"
  listsize:= getsize(Vars)

  ! Set on uninstantiated variables
  forall(i in 1..listsize)
   if not is_fixed(getvar(Vars,i)) then Vset+= {i}; end-if

  if Vset={} then
   returned:= 0
  else
  ! Get the variables with max. degree
   dmax:= max(i in Vset) getdegree(getvar(Vars,i))
   forall(i in Vset)
    if getdegree(getvar(Vars,i)) = dmax then Iset+= {i}; end-if
   dsize:= MAX_INT

  ! Choose var. with smallest domain among those indexed by 'Iset'
   forall(i in Iset)
    if getsize(getvar(Vars,i)) < dsize then
     returned:= i
     dsize:= getsize(getvar(Vars,i))
    end-if
 end-if
 writeln(returned)
 end-function


! **** Choose variable y(i) with smallest value of C(i)
 function varchoice2(Vars: cpvarlist): integer
```

```
  declarations
   Vset,Iset: set of integer
   VarInd: array(Iset) of integer
  end-declarations

 ! Set on uninstantiated variables
  listsize:= getsize(Vars)
  forall(i in 1..listsize)
   if not is_fixed(getvar(Vars,i)) then Vset+= {i}; end-if

  if getsize(Vset)=0 then
   returned:= 0
  else
  ! Establish a correspondence of indices between 'Vars' and 'y'
   forall(i in R)
    forall(j in Vset)
    if is_same(getvar(Vars,j), y(i)) then
     VarInd(i):= j
     Vset -= {j}
     break 1
    end-if

  ! Choose the variable
   imin:= min(i in Iset) i; cmin:= C(imin)
   forall(i in Iset)
    if C(i) < cmin then
     imin:= i; cmin:= C(i)
    end-if
   returned:= VarInd(imin)
  end-if
  writeln(imin, " ", returned)
 end-function

!-------------------------------------------------------------------
! *** Value choice ****
! **** Choose the next value one third larger than lower bound
! (Strategy may be used with any branching scheme since it
!  makes sure that the chosen value lies in the domain)
 function valchoice(x: cpvar): integer
!  returned:= getlb(x)
  returned:= getnext(x, getlb(x) + round((getub(x)-getlb(x))/3))
  writeln("Value: ", returned, " ", contains(x,returned),
          " x: ",  x)
 end-function

! **** Split the domain into lower third and upper two thirds
! (Strategy to be used only with 'split_domain' branching since
!  the chosen value may not be in the domain)
 function valchoice2(x: cpvar): integer
  returned:= getlb(x) + round((getub(x)-getlb(x))/3)
  writeln("Value: ", returned, " x: ", x)
 end-function
end-model
```

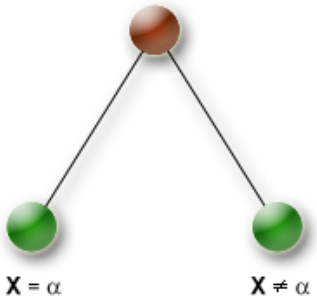
**Related topics**

assign_and_forbid settle_disjunction probe_assign_var split_domain

## assign_and_forbid

### Purpose

Creates an assign_and_forbid (MIP style) branching scheme; that will assign a value to the branching variable on one branch and forbid that value on the other branch.




### Synopsis

```
function assign_and_forbid(varsel:function or string,valsel:function or
      string,variables:set of cpvar) : cpbranching
function assign_and_forbid(varsel:function or string,valsel:function or
      string,variables:array(range) of cpvar) : cpbranching
function assign_and_forbid(varsel:function or string,valsel:function or
      string,variables:cpvarlist) : cpbranching
function assign_and_forbid(varsel:function or string,valsel:function or
      string) : cpbranching
```

### Arguments

| | |
|---|---|
| `varsel` | name of the variable selector (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `valsel` | name of the value selector (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `variables` | list of variables to branch on |

### Return value

assign_and_forbid branching scheme with value selector 'valsel' and variable selector 'varsel' working on all specified variables

### Example

See the example provided for `assign_var` on how to define an 'assign_and_forbid' branching scheme for the search process.

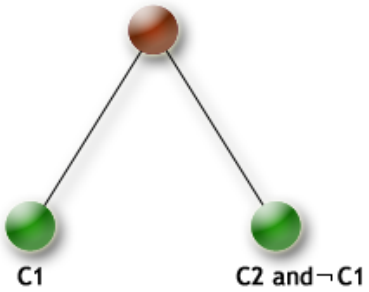
### Related topics

`assign_var` `settle_disjunction` `probe_assign_var` `split_domain`

# settle_disjunction

## Purpose

Creates a settle_disjunction branching scheme that resolves the status of all the disjunctions passed in argument. The branching consists in choosing one branch of the disjunction and posting the constraint stated by this branch. The branches are tested from left to right




## Synopsis

```
function settle_disjunction(constraints: set of cpctr): cpbranching
function settle_disjunction(constraints: array(range) of cpctr):
      cpbranching
function settle_disjunction: cpbranching
function settle_disjunction(disjsel: function or string, constraints: set
      of cpctr): cpbranching
function settle_disjunction(disjsel: function or string, array(range) of
      cpctr): cpbranching
function settle_disjunction(disjsel: function or string): cpbranching
```

## Arguments

| | |
|---|---|
| `constraints` | the disjunctions |
| `disjsel` | a disjunction selection function |

## Return value

The resulting settle_disjunction branching scheme

## Example

The following example shows how to use the settle_disjunction branching scheme to solve a small disjunctive scheduling problem: The problem is to find a schedule for a set of tasks on one machine. The machine can process only one task at the time and the goal is to minimize the total weighted tardiness of the schedule.

```
model "Disjunctive scheduling with settle_disjunction"
uses "kalis", "mmsystem"

 declarations
  NBTASKS = 5
  TASKS = 1..NBTASKS                      ! Set of tasks
  DUR: array(TASKS) of integer            ! Task durations
  DUE: array(TASKS) of integer            ! Due dates
  WEIGHT: array(TASKS) of integer         ! Weights of tasks
  start: array(TASKS) of cpvar            ! Start times
  tmp: array(TASKS) of cpvar              ! Aux. variable
  tardiness: array(TASKS) of cpvar        ! Tardiness
  twt: cpvar                              ! Objective variable
  zeroVar: cpvar                          ! 0-valued variable
  Strategy: array(range) of cpbranching   ! Branching strategy
 end-declarations
```

```
DUR :: [21,53,95,55,34]
DUE :: [66,101,232,125,150]
WEIGHT :: [1,1,1,1,1]

setname(twt, "Total weighted tardiness")
zeroVar = 0
setname(zeroVar, "zeroVar")

forall (t in TASKS) do
 start(t) >= 0
 setname(start(t), "Start("+t+")")
 tmp(t) = start(t) + DUR(t) - DUE(t)
 setname(tardiness(t), "Tard("+t+")")
 tardiness(t) = maximum({tmp(t),zeroVar})
end-do

twt = sum(t in TASKS) (WEIGHT(t) * tardiness(t))

! Create the disjunctive constraints
forall(t in 1..NBTASKS-1, s in t+1..NBTASKS)
 (start(t) + DUR(t) <= start(s)) or
 (start(s) + DUR(s) <= start(t))

! Define the branching strategy
Strategy(1):= settle_disjunction
Strategy(2):= split_domain(KALIS_LARGEST_MIN,KALIS_MIN_TO_MAX)
cp_set_branching(Strategy)

! Solve the problem
if not(cp_minimize(twt)) then
 writeln("Problem is inconsistent")
 exit(0)
end-if

forall (t in TASKS)
 writeln(formattext("[%3d==>%3d]:\t %2d  (%d)",start(t).sol,
         start(t).sol + DUR(t), tardiness(t).sol, tmp(t).sol))
writeln("Total weighted tardiness: ", getsol(twt))

end-model
```

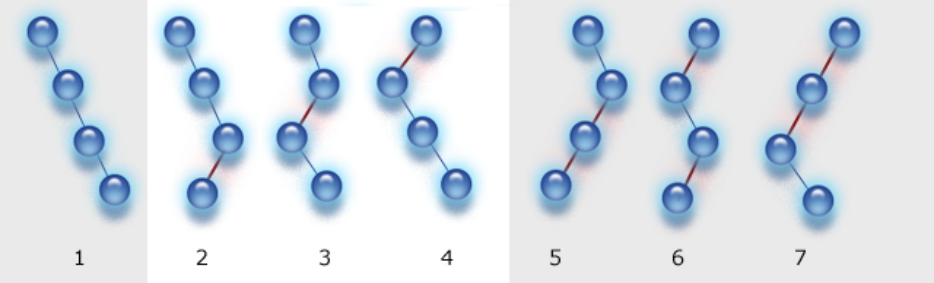
**Related topics**

assign_var assign_and_forbid probe_assign_var split_domain

# probe_assign_var

## Purpose

Creates a probe_assign_var branching scheme, in which probing and assignment are applied simultaneously




## Synopsis

```
function probe_assign_var(varsel:function or string,valsel:function or
      string,variables:set of cpvar, probelevel:integer) : cpbranching
function probe_assign_var(varsel:function or string, valsel:function or
      string, variables:array(range) of cpvar, probelevel:integer) :
      cpbranching
function probe_assign_var(varsel:function or string, valsel:function or
      string,variables:cpvarlist, probelevel:integer) : cpbranching
function probe_assign_var(varsel:function or string, valsel:function or
      string, probelevel:integer) : cpbranching
function probe_assign_var(varsel:function or string,valsel:function or
      string) : cpbranching
```

## Arguments

| | |
|---|---|
| `varsel` | the variable selector name (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `valsel` | the value selector (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `variables` | list of variables to branch on |
| `probelevel` | maximal probing level |

## Return value

The resulting probe_assign_var branching scheme

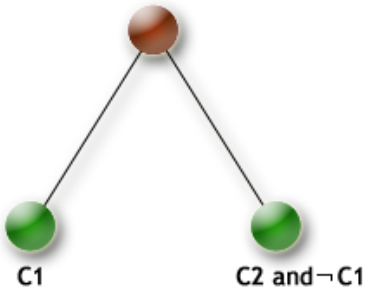
## Related topics

`assign_var` `assign_and_forbid` `settle_disjunction` `split_domain`

# probe_settle_disjunction

### Purpose

Creates a probe_settle_disjunction branching scheme that resolves the status of all the disjunctions passed in argument. The branching consists in choosing one branch of the disjunction and posting the constraint stated by this branch. The branches are tested from left to right




### Synopsis

```
function probe_settle_disjunction(disjunctions:set of cpctr,
      probeLevel:integer) : cpbranching
function probe_settle_disjunction(disj_selector:function or string,
      disjunctions:set of cpctr, probeLevel:integer) : cpbranching
function probe_settle_disjunction(disj_selector:function or string,
      disjunctions:array(range) of cpctr, probeLevel:integer) : cpbranching
function probe_settle_disjunction(disjunctions:array(range) of cpctr,
      probeLevel:integer) : cpbranching
function probe_settle_disjunction(disj_selector:function or string,
      probeLevel:integer) : cpbranching
function probe_settle_disjunction(probeLevel:integer) : cpbranching
```

### Arguments

| | |
|---|---|
| `disj_selector` | the disjunction selector name (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `disjunctions` | the set or array of disjunctions |
| `probeLevel` | maximal probing level |

### Return value

The resulting probe_settle_disjunction branching scheme

### Example

The following example shows how to use the probe_settle_disjunction branching scheme to solve a small disjunctive scheduling problem:The problem consists of finding a schedule for some tasks on one machine. The machine can process only one task at the time and the goal is to minimize the total weighted tardiness of the schedule. Note that the result may be (and will be in this case) suboptimal as the search tree is not fully explored.

```
model "Disjunctive scheduling with probe_settle_disjunction"
 uses "kalis", "mmsystem"

 declarations
  NBTASKS = 5
  TASKS = 1..NBTASKS                    ! Set of tasks
  DUR: array(TASKS) of integer          ! Task durations
  DUE: array(TASKS) of integer          ! Due dates
  WEIGHT: array(TASKS) of integer       ! Weights of tasks
  start: array(TASKS) of cpvar          ! Start times
  tmp: array(TASKS) of cpvar            ! Aux. variable
```

```
 tardiness: array(TASKS) of cpvar       ! Tardiness
 twt: cpvar                             ! Objective variable
 zeroVar: cpvar                         ! 0-valued variable
 Strategy: array(range) of cpbranching  ! Branching strategy
end-declarations

DUR :: [21,53,95,55,34]
DUE :: [66,101,232,125,150]
WEIGHT :: [1,1,1,1,1]

setname(twt, "Total weighted tardiness")
zeroVar = 0
setname(zeroVar, "zeroVar")

forall(t in TASKS) do
 start(t) >= 0
 start(t).name:= "Start("+t+")"
 tmp(t) = start(t) + DUR(t) - DUE(t)
 tardiness(t).name:= "Tard("+t+")"
 tardiness(t) = maximum({tmp(t),zeroVar})
end-do

twt = sum(t in TASKS) (WEIGHT(t) * tardiness(t))

! Create the disjunctive constraints
forall(t in 1..NBTASKS-1, s in t+1..NBTASKS)
 (start(t) + DUR(t) <= start(s)) or
 (start(s) + DUR(s) <= start(t))

! Define the branching strategy
Strategy(1):= probe_settle_disjunction(1)
Strategy(2):= split_domain(KALIS_LARGEST_MIN,KALIS_MIN_TO_MAX)
cp_set_branching(Strategy)

! Solve the problem
if not cp_minimize(twt) then
 writeln("problem is inconsistent")
 exit(0)
end-if

forall(t in TASKS)
 writeln(formattext("[%3d==>%3d]:\t %2d  (%d)", start(t).sol,
         start(t).sol + DUR(t), tardiness(t).sol, tmp(t).sol))
writeln("Total weighted tardiness: ", twt.sol)

end-model
```

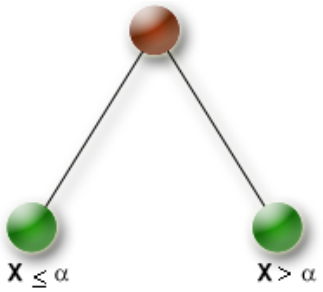
**Related topics**

settle_disjunction probe_assign_var split_domain

# split_domain

## Purpose

Creates a split_domain branching scheme. This will split the domain of every branching variable X in two parts, one branch with the case X ⩽ alpha and the other branch X >alpha where alpha is a value in the domain of X.




## Synopsis

```
function split_domain(varsel:function or string, valsel:function or string,
      variables:set of cpvar, leqfirst:boolean, stopsplit: integer) :
      cpbranching
function split_domain(varsel:function or string, valsel:function or string,
      variables:array(range) of cpvar, leqfirst:boolean, stopsplit:
      integer) : cpbranching
function split_domain(varsel:function or string, valsel:function or string,
      variables:cpvarlist, leqfirst:boolean, stopsplit: integer) :
      cpbranching
function split_domain(varsel:function or string, valsel:function or string,
      leqfirst:boolean, stopsplit: integer) : cpbranching
function split_domain(varsel:function or string, valsel:function or string)
      : cpbranching
function split_domain(varsel:function or string, valsel:function or string,
      variables:array(range) of cpvar, leqfirst:boolean, stopsplit:
      integer, probeLevel:integer) : cpbranching
function split_domain(varsel:function or string, valsel:function or string,
      variables:set of cpfloatvar, leqfirst:boolean, stopsplit: integer) :
      cpbranching
function split_domain(varsel:function or string, valsel:function or string,
      variables:array(range) of cpfloatvar, leqfirst:boolean, stopsplit:
      integer) : cpbranching
```

## Arguments

| | |
|---|---|
| `varsel` | the variable selector name (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `valsel` | the value selector (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `variables` | list of variables to branch on |
| `leqfirst` | Explore the case ⩽ first if `true` |
| `stopsplit` | stop branching if the size of the domain of the variable is less than stopsplit |

## Return value

split_domain branching scheme

## Example

See the example provided for `assign_var` on how to define a 'split_domain' branching scheme for the search process.

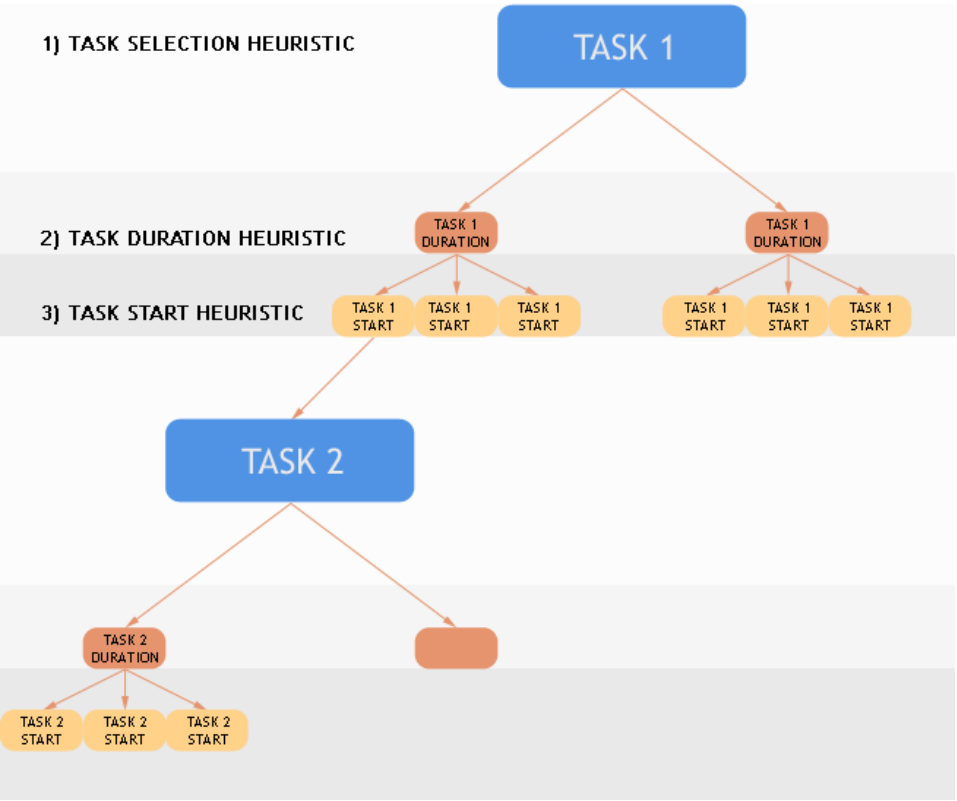
### Related topics

`assign_var` `assign_and_forbid` `probe_assign_var` `settle_disjunction`

# task_serialize

## Purpose

Creates a Task Serializer branching scheme that serializes the tasks passed in argument. The branching consists in choosing one task to schedule. Then a branch is created for each possible duration for this task. Once the duration is determined a branch is created for each posssible starting values for this task. When the start and the duration are fixed, the task is scheduled and the process is repeated until all the tasks are serialized.



### Synopsis

```
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, tasks:set of cptask) : cpbranching
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, tasks:array of cptask) : cpbranching
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, tasks:set of cptask, limit:integer) : cpbranching
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, tasks:array of cptask, limit:integer) : cpbranching
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, tasks:set of cptask, limit:integer, varOrder:integer) :
      cpbranching
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, tasks:array of cptask, limit:integer, varOrder:integer) :
      cpbranching
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, assignSelector:string or function, assignHeuristic:string
      or function, tasks:array of cptask, limit:integer, varOrder:integer)
      : cpbranching
function task_serialize(taskSelector:string or function,
      durationHeuristic:string or function, startHeuristic:string or
      function, assignSelector:string or function, assignHeuristic:string
      or function, tasks:set of cptask, limit:integer, varOrder:integer) :
      cpbranching
```

### Arguments

| | |
|---|---|
| `taskSelector` | the task selector (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `durationHeuristic` | the task duration assignment heuristic (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `startHeuristic` | the task start time assignment heuristic (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `assignSelector` | a variable selection heuristic to choose among assignments of resources provided, produced, required or consumed by the task (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `assignHeuristic` | a value selection heuristic (pre-defined constant, name of user-defined function or reference to user-defined function) |
| `tasks` | the set of tasks to be serialized. |
| `limit` | discrepancy limit: value 0 means strictly following the branching scheme, positive values indicate the permissible number of deviations from the branching scheme. It can be set to `MAX_INT` for no limitations. |
| `varOrder` | the branching order of the variables resource assignment (A), start (S) and duration (D) of one task, values can be:<br>0 A → D → S<br>1 A → S → D<br>2 D → S → A<br>3 D → A → S<br>4 S → D → A<br>5 S → A → D |

### Return value

The resulting Task Serializer branching scheme

### Example

The following example shows how to use the task_serialize branching scheme to solve a small cumulative scheduling problem:

```
model "Tasks serialization example"
 uses "kalis"

 declarations
  Masonry, Carpentry, Roofing, Windows, Facade, Garden, Plumbing,
    Ceiling, Painting, MovingIn : cptask    ! Declaration of tasks
  Taskset : set of cptask
  money_available : cpresource              ! Resource declaration
 end-declarations

 forward function selectNextTask(tasks: cptasklist) : integer

! 'money_available' is a cumulative resource with max. amount of 29$
 set_resource_attributes(money_available,KALIS_DISCRETE_RESOURCE,29)

! Limit resource availability to 20$ in the time interval [0,14]
 setcapacity(money_available, 0, 14, 20)

! Setting the task durations and predecessor sets
 set_task_attributes(Masonry  , 7)
 set_task_attributes(Carpentry, 3, {Masonry})
 set_task_attributes(Roofing  , 1, {Carpentry})
 set_task_attributes(Windows  , 1, {Roofing})
 set_task_attributes(Facade   , 2, {Roofing})
 set_task_attributes(Garden   , 1, {Roofing})
```

```
 set_task_attributes(Plumbing , 8, {Masonry})
 set_task_attributes(Ceiling  , 3, {Masonry})
 set_task_attributes(Painting , 2, {Ceiling})
 set_task_attributes(MovingIn , 1, {Windows,Facade,Garden,Painting})

! Setting the resource consumptions
 consumes(Masonry  , 7, money_available)
 consumes(Carpentry, 3, money_available)
 consumes(Roofing  , 1, money_available)
 consumes(Windows  , 1, money_available)
 consumes(Facade   , 2, money_available)
 consumes(Garden   , 1, money_available)
 consumes(Plumbing , 8, money_available)
 consumes(Ceiling  , 3, money_available)
 consumes(Painting , 2, money_available)
 consumes(MovingIn , 1, money_available)

! Set of tasks to schedule
 Taskset := {Masonry, Carpentry, Roofing, Windows, Facade, Garden,
             Plumbing, Ceiling, Painting, MovingIn}

! Set the custom branching strategy using task_serialize:
! - the task serialization process will use the function
!   "selectNextTask" to look for the next task to fix
! - it will use the "KALIS_MAX_TO_MIN" value selection heuristic
!   to set the tasks duration variable
! - and the "KALIS_MIN_TO_MAX" value selection heuristic to set
!   the start of the task
 cp_set_branching(task_serialize(->selectNextTask,
                  KALIS_MAX_TO_MIN, KALIS_MIN_TO_MAX, Taskset))

! Find the optimal schedule (minimizing the makespan)
 if 0 <> cp_schedule(getmakespan) then
   cp_show_sol
 else
   writeln("No solution found")
 end-if

!-------------------------------------------------------------
! **** Function to select the next task to schedule
 function selectNextTask(tasks: cptasklist) : integer
  write("selectNextTask : ")
  declarations
   Vset,Iset: set of integer
  end-declarations

 ! Get the number of elements of "tasks"
  listsize:= getsize(tasks)

 ! Set of uninstantiated variables
  forall(i in 1..listsize)
   if not is_fixed(getstart(gettask(tasks,i))) or
      not is_fixed(getduration(gettask(tasks,i))) then
     Vset+= {i};
   end-if

  if Vset={} then
    returned:= 0
  else
  ! Get the variables with max. degree
```

```
    dmax:= max(i in Vset) getsize(getduration(gettask(tasks,i)))
    forall(i in Vset)
      if getsize(getduration(gettask(tasks,i))) = dmax then
       Iset+= {i}; end-if
    dsize:= MAX_INT

  ! Choose var. with smallest domain among those indexed by 'Iset'
    forall(i in Iset)
      if getsize(getstart(gettask(tasks,i))) < dsize then
        returned:= i
        dsize:= getsize(getstart(gettask(tasks,i)))
      end-if
  end-if

  if returned <> 0 then
   writeln(gettask(tasks,returned))
  end-if
 end-function

end-model
```

**Related topics**

assign_var assign_and_forbid probe_assign_var split_domain

## cp_set_branching

### Purpose

Sets the branching strategy to use during the search for a solution; please refer to the 'Paradigm' section of this reference manual for further details.

### Synopsis

```
procedure cp_set_branching
procedure cp_set_branching(Strategy:cpbranching)
procedure cp_set_branching(Strategy:array(range) of cpbranching)
```

### Argument

`Strategy` a branching strategy (single cpbranching or cpbranching array)

### Example

See the example provided for `assign_var` on how to set the search strategy.

### Related topics

`settle_disjunction` `assign_var` `assign_and_forbid` `split_domain` Chapter 4

## cp_show_stats

### Purpose

This procedure prints some statistics about the search process (time elapsed, number of nodes, depth, number of backtracks and total time spent in callbacks)

### Synopsis

```
procedure cp_show_stats
```

### Related topics

`cp_show_prob` `cp_show_var` `cp_print_stats`

## cp_print_stats

### Purpose

This procedure dumps some statistics about the search process (time elapsed, number of nodes, depth, number of backtracks and total time spent in callbacks) into a CSV-format file, overwriting any existing contents of the specified file.

### Synopsis

```
procedure cp_print_stats(fname: string)
```

### Argument

`fname` the name (filepath) of the file to be used for the output

### Related topics

`cp_show_stats` `cp_show_prob` `cp_show_var`

## cp_get_nb_solutions

### Purpose

This function returns the number of solutions in CP search.

### Synopsis

```
function cp_get_nb_solutions: integer
```

### Related topics

KALIS_NB_SOLUTIONS

## cp_get_computation_time

### Purpose

*This subroutine is deprecated and will be removed in a future release. Use* `getparam` *instead.*
This function returns the total current computation time since the optimization call (in seconds). This includes both optimization phases.

### Synopsis

```
function cp_get_computation_time: real
```

## cp_get_number_of_nodes

### Purpose

*This subroutine is deprecated and will be removed in a future release. Use* `getparam` *instead.*
This function returns the current number of nodes in the CP search tree. This includes both optimization phases.

### Synopsis

```
function cp_get_number_of_nodes: integer
```

## cp_get_depth

### Purpose

*This subroutine is deprecated and will be removed in a future release. Use* `getparam` *instead.*
This function returns the depth of the CP search tree.

### Synopsis

```
function cp_get_depth: integer
```

## cp_get_backtracks

### Purpose

*This subroutine is deprecated and will be removed in a future release. Use* `getparam` *instead.*
This function returns the current number of backtracks in CP search.

### Synopsis

```
function cp_get_backtracks: integer
```

## cp_get_total_computation_time

### Purpose

This function returns the total current computation time since the optimization call (in seconds). This includes both optimization phases.

### Synopsis

```
function cp_get_total_computation_time: real
```

## cp_get_total_number_of_nodes

### Purpose

This function returns the current number of nodes in the CP search tree. This includes both optimization phases.

### Synopsis

```
function cp_get_total_number_of_nodes: integer
```

## cp_get_total_depth

### Purpose

This function returns the depth of the CP search tree.

### Synopsis

```
function cp_get_total_depth: integer
```

## cp_get_total_backtracks

### Purpose

This function returns the current number of backtracks in CP search.

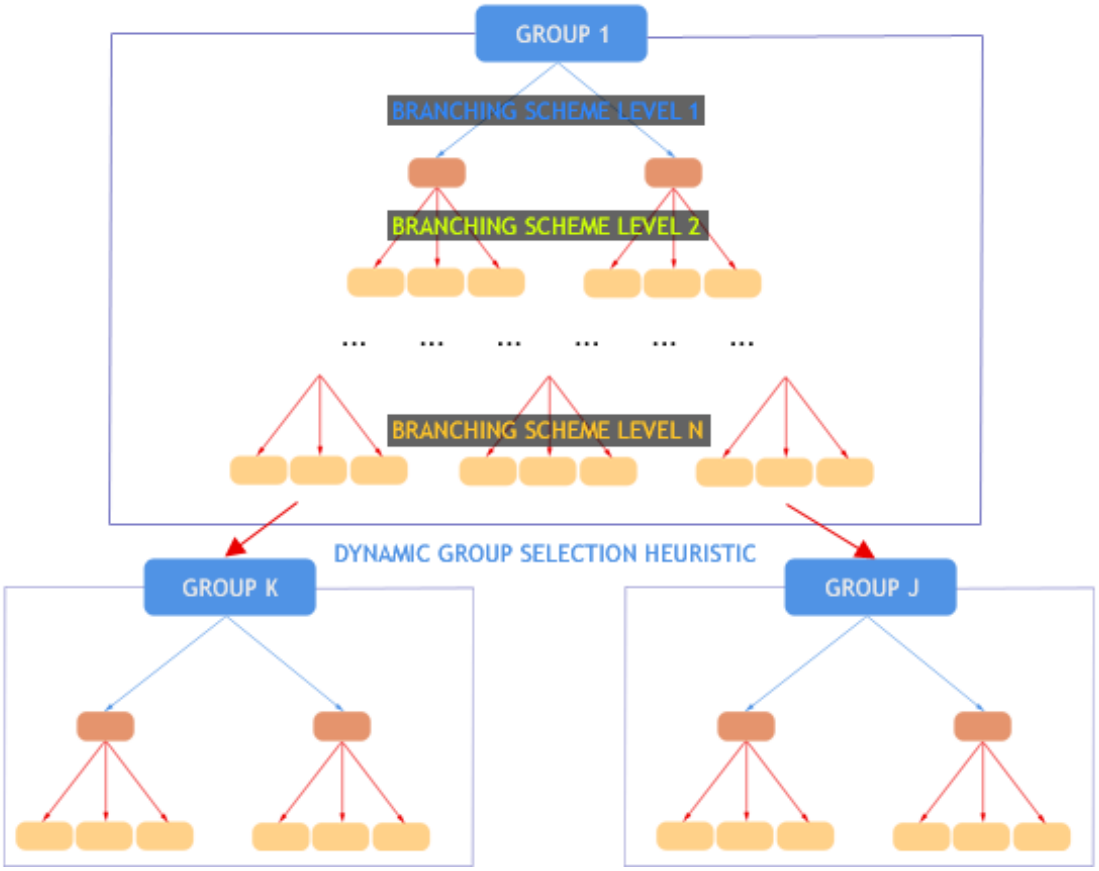
### Synopsis

```
function cp_get_total_backtracks: integer
```

# bs_group

## Purpose

Create a group of branching schemes. A group of branching schemes is an ordered list of branching schemes. It is used as input to the `group_serializer` branching scheme. A user 'tag' information can be associated with a group in order to link this group to a specific user structure.




## Synopsis

```
function bs_group(branchings: set of cpbranching, tag:integer) : cpbsgroup
function bs_group(branchings: array of cpbranching, tag:integer) :
      cpbsgroup
```

## Arguments

| | |
|---|---|
| `branchings` | the branching schemes forming the group |
| `tag` | tag associated with the branching scheme group (use and interpretation entirely up to the user) |

## Related topics

`group_serializer`

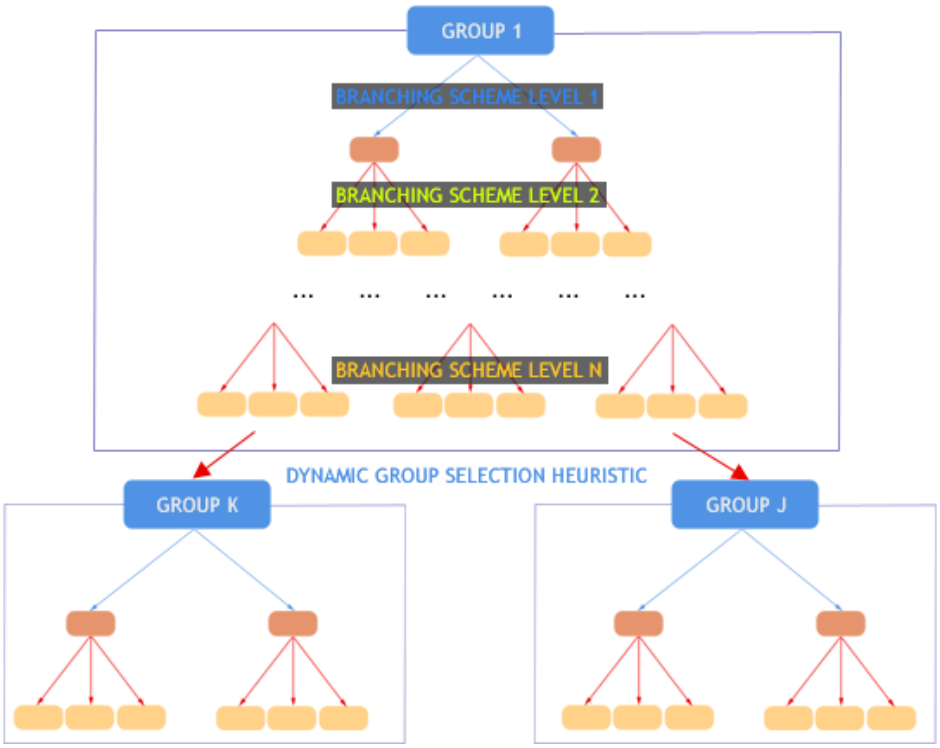
# group_serializer

## Purpose

A branching scheme Group Serializer is a branching scheme of branching schemes. That means, it can be seen as a meta-branching scheme. The search can be decomposed into clusters of branching schemes that will be explored based upon a specific dynamic group selection heuristic. When a specific group is selected, the ordered branching scheme list of this group will be treated sequentially. Once all the branching schemes of the group have been treated, another branching scheme group is selected with the group selection heuristic. Note that the probing level of the overall group serializer is checked before the probing of the group branching scheme.
For example, the task_serializer branching scheme is a particular kind of group serializer heuristic tailored for task based search tree exploration. In this case a group corresponds to a task and the list of branching schemes is the following :

1. start time variable
2. duration variable

.




## Synopsis

```
function group_serializer(groups: set of cpbsgroup, groupSelector: function
      or string) : cpbranching
function group_serializer(groups: set of cpbsgroup, groupSelector: function
      or string, probe: integer) : cpbranching
```

## Arguments

| | |
|---|---|
| `groups` | the set of branching scheme groups |
| `groupselector` | the group selection heuristic |
| `probe` | the probe level |

## Example

The following example shows how to implement a branching scheme group serializer with similar

branching strategy to a task serializer:

```
model "Groups serialization example"
 uses "kalis"

 declarations
  Masonry, Carpentry, Roofing, Windows, Facade, Garden, Plumbing,
    Ceiling, Painting, MovingIn : cptask    ! Declaration of tasks
  Taskset : set of cptask
  money_available : cpresource              ! Resource declaration
  ! Branching strategy
  Strategy: cpbranching
  TaskBranching: dynamic array(string) of set of cpbranching
  TaskGroups: set of cpbsgroup
  TaskTag: dynamic array(range) of string
 end-declarations

 forward public function select_task_group(glist: cpbsgroup): real

! 'money_available' is a cumulative resource with max. amount of 29$
 set_resource_attributes(money_available,KALIS_DISCRETE_RESOURCE,29)

! Limit resource availability to 20$ in the time interval [0,14]
 setcapacity(money_available, 0, 14, 20)

! Setting task name
 Masonry.name   := "Masonry"
 Carpentry.name := "Carpentry"
 Roofing.name   := "Roofing"
 Windows.name   := "Windows"
 Facade.name    := "Facade"
 Garden.name    := "Garden"
 Plumbing.name  := "Plumbing"
 Ceiling.name   := "Ceiling"
 Painting.name  := "Painting"
 MovingIn.name  := "MovingIn"

! Setting the task durations and predecessor sets
 set_task_attributes(Masonry  , 7)
 set_task_attributes(Carpentry, 3, {Masonry})
 set_task_attributes(Roofing  , 1, {Carpentry})
 set_task_attributes(Windows  , 1, {Roofing})
 set_task_attributes(Facade   , 2, {Roofing})
 set_task_attributes(Garden   , 1, {Roofing})
 set_task_attributes(Plumbing , 8, {Masonry})
 set_task_attributes(Ceiling  , 3, {Masonry})
 set_task_attributes(Painting , 2, {Ceiling})
 set_task_attributes(MovingIn , 1, {Windows,Facade,Garden,Painting})

! Setting the resource consumptions
 consumes(Masonry  , 7, money_available)
 consumes(Carpentry, 3, money_available)
 consumes(Roofing  , 1, money_available)
 consumes(Windows  , 1, money_available)
 consumes(Facade   , 2, money_available)
 consumes(Garden   , 1, money_available)
 consumes(Plumbing , 8, money_available)
 consumes(Ceiling  , 3, money_available)
 consumes(Painting , 2, money_available)
 consumes(MovingIn , 1, money_available)
```

```
! Set of tasks to schedule
 Taskset := {Masonry, Carpentry, Roofing, Windows, Facade, Garden,
             Plumbing, Ceiling, Painting, MovingIn}

! Set the custom branching strategy using group_serializer:
! - the group serialization process will use the function
!   "select_task_group" to look for the next group to set
! - this function will score each group and the group with the best score is
!   selected next
! - the "KALIS_MAX_TO_MIN" value selection heuristic is used to choose values
!   for the tasks duration variable
! - and the "KALIS_MIN_TO_MAX" value selection heuristic is applied for
!   the start of the task
! - group serializer gives the user a high level of refinement within the
!   definition of the search strategy
 cnt_task := 1
 forall(task in Taskset) do
   TaskBranching(task.name) +=
     {assign_var(KALIS_SMALLEST_DOMAIN, KALIS_MIN_TO_MAX, {getstart(task)})}
   TaskBranching(task.name) +=
     {assign_var(KALIS_SMALLEST_DOMAIN, KALIS_MAX_TO_MIN, {getduration(task)})}
   TaskBranching(task.name) +=
     {assign_var(KALIS_SMALLEST_DOMAIN, KALIS_MAX_TO_MIN,
                 {getconsumption(task, money_available)})}
   TaskGroups += {bs_group(TaskBranching(task.name), cnt_task)}
   TaskTag(cnt_task) := task.name
   cnt_task += 1
 end-do

 Strategy := group_serializer(TaskGroups, "select_task_group")

 cp_set_schedule_strategy(KALIS_INITIAL_SOLUTION, Strategy)
! Find the optimal schedule (minimizing the makespan)
 if 0 <> cp_schedule(getmakespan) then
   cp_show_sol
 else
   writeln("No solution found")
 end-if

!-------------------------------------------------------------
! **** Function to select the next group to branch on
! Each group will be scored and the group with the best score will be picked
! as the next group
 public function select_task_group(glist: cpbsgroup): real
  ! Retrieve task from tag
   tag := gettag(glist)
  ! Initializing score value
   returned := 0.0
  ! Build score value as a combination of 1/ max degree and 2/ smallest domain
   forall(task in Taskset | TaskTag(tag) = task.name) do
     returned += 100 * getsize(getduration(task))
     returned -= getsize(getstart(task))
   end-do
 end-function

end-model
```

**Related topics**

bs_group

# gettag

### Purpose

Get the tag associated with the branching scheme group passed in argument. The tag is defined by the user when creating the group (see `bs_group`).

### Synopsis

```
function gettag(group: cpbsgroup) : integer
```

### Argument

`group` the set of branching scheme groups

### Related topics

`group_serializer` `bs_group`

# 9.6 Callbacks

`cp_set_branch_callback` Sets the branch callback procedure p. 208

`cp_set_node_callback` Sets the node callback procedure p. 207

`cp_set_solution_callback` Sets the solution callback procedure p. 204

## cp_set_solution_callback

### Purpose

Sets the solution callback procedure that will be called each time that a solution has been found by the solver. Note that this callback procedure does not take any argument.

### Synopsis

```
procedure cp_set_solution_callback(callback:procedure)
procedure cp_set_solution_callback(callbackName:string)
```

### Arguments

| | |
|---|---|
| `callback` | the procedure to call |
| `callbackName` | the name of the procedure to call (must be declared as `public`) |

### Example

The following example shows how to use the solution callback:

```
model "Using callbacks"
 uses "kalis"

 declarations
  NBTASKS = 5
  TASKS = 1..NBTASKS                      ! Set of tasks
  DUR: array(TASKS) of integer            ! Task durations
  DURs: array(set of cpvar) of integer    ! Durations
  DUE: array(TASKS) of integer            ! Due dates
  WEIGHT: array(TASKS) of integer         ! Weights of tasks
  start: array(TASKS) of cpvar            ! Start times
  tmp: array(TASKS) of cpvar              ! Aux. variable
  tardiness: array(TASKS) of cpvar        ! Tardiness
  twt: cpvar                              ! Objective variable
  zeroVar: cpvar                          ! 0-valued variable
  Strategy: array(range) of cpbranching   ! Branching strategy
  Disj: set of cpctr                      ! Disjunctions
  nodesx: array(range) of integer         ! x-coordinates
  nodesy: array(range) of integer         ! y-coordinates
  currentpos: integer
 end-declarations

! Initialization of search tree data
 nodesx(0) := 1
 nodesy(0) := 0
 currentpos := 1

! *********************************************************
! solution_found: called each time a solution is found
! *********************************************************
 procedure solution_found
  writeln("A solution has been found :")
  forall (t in TASKS)
   writeln("[", getsol(start(t)), "==>",
           (getsol(start(t)) + DUR(t)), "]:\t ",
           getsol(tardiness(t)), "  (", getsol(tmp(t)), ")")
  writeln("Total weighted tardiness: ", getsol(twt))
 end-procedure

! *********************************************************
! node_explored: called each time a node is explored
! *********************************************************
 procedure node_explored
```

```
  nodesx(currentpos) += 1
  if nodesx(currentpos-1)>nodesx(currentpos) then
   nodesx(currentpos) := nodesx(currentpos-1)
  end-if
  nodesy(currentpos) := -currentpos
  writeln("[Node explored depth : " , (-nodesy(currentpos)), "]")
 end-procedure

! ********************************************************
! go_down_branch: called each time the search goes down
!                 a branch of the search tree
! ********************************************************
 procedure go_down_branch
  writeln("[Branch go_down " , (-nodesy(currentpos)) , "]")
  currentpos := currentpos + 1
 end-procedure

! ********************************************************
! go_up_branch: called each time the search goes up
!               a branch of the search tree
! ********************************************************
 procedure go_up_branch
  currentpos := currentpos - 1
  writeln("[Branch go_up " , (-nodesy(currentpos)) , "]")
 end-procedure

! ********************************************************
! Problem definition
! ********************************************************

 DUR :: [21,53,95,55,34]
 DUE :: [66,101,232,125,150]
 WEIGHT :: [1,1,1,1,1]

 setname(twt, "Total weighted tardiness")
 zeroVar = 0
 setname(zeroVar, "zeroVar")

! Setting up the decision variables
 forall (t in TASKS) do
  start(t) >= 0
  setname(start(t), "Start("+t+")")
  DURs(start(t)):= DUR(t)
  tmp(t) = start(t) + DUR(t) - DUE(t)
  setname(tardiness(t), "Tard("+t+")")
  tardiness(t) = maximum({tmp(t), zeroVar})
 end-do

 twt = sum(t in TASKS) (WEIGHT(t) * tardiness(t))

 ! Create the disjunctive constraints
 disjunctive(union(t in TASKS) {start(t)}, DURs, Disj, 1)

 ! The setxxxcallback methods must be called before
 ! setting the branching with 'cp_set_branching'
 cp_set_solution_callback(->solution_found)
 cp_set_node_callback(->node_explored)
 cp_set_branch_callback(->go_down_branch, ->go_up_branch)

 Strategy(0):= settle_disjunction
```

```
 Strategy(1):= split_domain(KALIS_MAX_DEGREE,KALIS_MIN_TO_MAX)
 cp_set_branching(Strategy)

 if not cp_minimize(twt) then
  writeln("problem is inconsistent")
  exit(0)
 end-if

end-model
```

**Related topics**

getsol cp_set_node_callback cp_set_branch_callback

## cp_set_node_callback

### Purpose

Sets the node callback procedure that will be called each time that a node is explored by the search algorithm. Note that this callback procedure does not take any argument.

### Synopsis

```
procedure cp_set_node_callback(callback:procedure)
procedure cp_set_node_callback(callbackName:string)
```

### Arguments

| | |
|---|---|
| `callback` | the procedure to call |
| `callbackName` | the name of the procedure to call (must be declared as `public`) |

### Example

See the example provided for `cp_set_solution_callback` on how to use the node callback.

### Related topics

`getsol` `cp_set_solution_callback` `cp_set_branch_callback`

## cp_set_branch_callback

### Purpose

Sets the branch callback procedure that will be called each time that a branch is explored by the search algorithm. Note that this callback procedure does not take any argument.

### Synopsis

```
procedure cp_set_branch_callback(callbackDown:procedure,
      callbackUp:procedure)
procedure cp_set_branch_callback(callbackNameDown:string,
      callbackNameUp:string)
```

### Arguments

| | |
|---|---|
| `callbackDown, callbackUp` | the procedure to call, in the case the branch is explored downward (resp. upward) |
| `callbackNameDown, callbackNameUp` | the name of the procedure to call, in the case the branch is explored downward (resp. upward) (must be declared as `public`) |

### Example

See the example provided for `cp_set_solution_callback` on how to use the branch callback.

### Related topics

`getsol` `cp_set_solution_callback` `cp_set_node_callback`

# 9.7 Scheduling

| | | |
|---|---|---|
| addpredecessors | Adds a set of predecessors for a task | p. 222 |
| addsuccessors | Adds a set of tasks as successors of a task | p. 224 |
| consumes | Sets the minimal and maximal amount of resource consumed by a task for a particular resource | p. 241 |
| cp_close_schedule | Close the schedule. | p. 267 |
| cp_get_default_schedule_strategy | Gets the default schedule search strategy of cp_schedule | p. 257 |
| cp_schedule | Optimizes the schedule with respect to an objective variable. | p. 239 |
| cp_set_schedule_strategy | Sets the schedule search strategy for cp_schedule | p. 256 |
| cp_show_schedule | Shows a textual representation of the current schedule | p. 226 |
| get_earliest_start_possible | Gets the earliest time at which the task can start on the given resource. | p. 261 |
| get_start_based_duration | Query for a start based duration value | p. 215 |
| getassignment | Gets the cpvar representing the assignment of a task for a particular resource. | p. 262 |
| getcapacity | Get the maximal capacity of a resource for a specific time period. | p. 252 |
| getconsumption | Gets the cpvar representing the consumption of a task for a particular resource | p. 230 |
| getduration | Gets the cpvar representing a task duration | p. 229 |
| getend | Gets the cpvar representing a task completion time | p. 228 |
| getmakespan | Gets the cpvar representing the makespan of the schedule. | p. 240 |
| getproduction | Gets the cpvar representing the production of a task for a particular resource | p. 233 |
| getprovision | Gets the cpvar representing the provision of a task for a particular resource | p. 234 |
| getrequirement | Gets the cpvar representing the requirement of a task for a particular resource | p. 232 |
| getsetuptime | Gets the sequence dependent setup times between two tasks | p. 254 |
| getstart | Gets the cpvar representing a task start time | p. 227 |
| has_assignment | Tests whether an assignment decision variable for a task and a particular resource exists. | p. 264 |
| is_consuming | Tests whether a task consumes a specific resource | p. 235 |
| is_fixed | Tests if a task is fixed | p. 211 |
| is_fixed | Tests if a disjunction is fixed | p. 255 |
| is_idletime | Tests if a timestep is an idle timestep for a resource. | p. 266 |
| is_producing | Tests whether a task produces a specific resource | p. 237 |

| | | |
|---|---|---|
| `is_providing` | Tests whether a task provides a specific resource | p. 238 |
| `is_requiring` | Tests whether a task requires a specific resource | p. 236 |
| `produces` | Sets the minimal and maximal amount of resource produced by a task for a particular resource | p. 245 |
| `provides` | Sets the minimal and maximal amount of resource provided by a task for a particular resource. | p. 246 |
| `requires` | Sets the minimal and maximal amount of resource required by a task for a particular resource | p. 244 |
| `resusage` | Creates a resource usage | p. 258 |
| `set_duration_with_idle_times` | Set a duration constraint conditional to some idle time windows and on the task assignment. | p. 216 |
| `set_resource_attributes` | Sets some attributes for a resource | p. 247 |
| `set_start_based_duration` | Set a duration computed from the value taken by the start variable if the task is assigned to this resource. | p. 214 |
| `set_task_attributes` | Sets some attributes for a task | p. 212 |
| `setcapacity` | Sets the maximal capacity of a resource between two time bounds. | p. 248 |
| `setduration` | Sets the duration of a task | p. 213 |
| `setidletimes` | Specifies the set of timesteps where a resource is idle. | p. 265 |
| `setmaxavailability` | Sets the maximal capacity of a resource between two time bounds. | p. 250 |
| `setminusage` | Sets the minimum usage of a resource between two time bounds. | p. 251 |
| `setpredecessors` | Sets the tasks that must precede a task | p. 223 |
| `setsetuptime` | Sets sequence dependent setup times between two tasks | p. 253 |
| `setsuccessors` | Sets the set of tasks that must succeed a task | p. 225 |
| `update_duration_with_idle_times` | Set a duration constraint conditional to some idle time windows and on the task assignment. | p. 218 |

# is_fixed

### Purpose

Returns `true` if the task passed in argument has its start and completion times fixed.

### Synopsis

```
function is_fixed(task:cptask) : boolean
```

### Argument

`task` the task

### Return value

`true` if task is fixed

### Example

The following example shows how to see if a cptask `task` is fixed

```
if is_fixed(task) then
 write('task is fixed! ')
end-if
```

### Related topics

`getlb` `getub` `getmiddle` `getsize` `getval` `getdegree` `gettarget` `getrand` `getnext` `getprev` `contains`

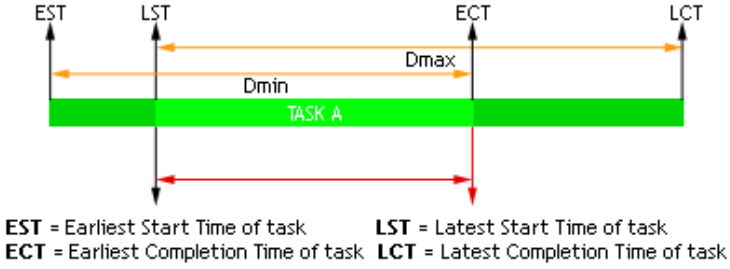
# set_task_attributes

## Purpose

Sets some attributes for a task.
A cptask is represented by three cpvar:

- start representing the start time of the task
- end representing the completion time of the task
- duration representing the duration of the task.

These three structural variables are linked with the following constraint: task + duration $\leqslant$ end. The start time variable represents two specific parameters of the task: the Earliest Start Time (EST, represented by its lower bound) and its Latest Start Time (LST, represented by its upper bound). The end variable represents another two parameters of the task: the Earliest Completion Time (ECT, represented by its lower bound) and its Latest Completion Time (LCT, represented by its upper bound). The duration variable represents the following two parameters of the task: the minimum task duration (Dmin, represented by its lower bound) and the maximum task duration (Dmax, represented by its upper bound). The graphic below illustrates these properties:




## Synopsis

```
procedure set_task_attributes(task:cptask, duration:integer,
      resource:cpresource, precedences:set of cptask)
procedure set_task_attributes(task:cptask, duration:integer,
      resource:cpresource)
procedure set_task_attributes(task:cptask, duration:integer)
procedure set_task_attributes(task:cptask, duration:integer,
      precedences:set of cptask)
procedure set_task_attributes(task:cptask, resource:cpresource,
      requirement:integer)
```

## Arguments

| | |
|---|---|
| `task` | the task to set attributes |
| `duration` | the duration of the task |
| `resource` | a resource that is required during the execution of the task |
| `precedences` | the set of tasks that must precede t in the schedule |
| `requirement` | amount of the specified resource required per time unit |

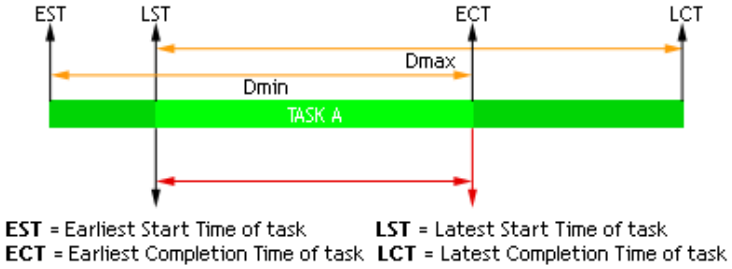
# setduration

## Purpose

A cptask is represented by three cpvar:

- 'start' representing the start time of the task
- 'end' representing the completion time of the task
- 'duration' representing the duration of the task.

These three structural variables are linked with the following constraint: task + duration $\leqslant$ end. The duration variable represents two specific parameters of the task: The minimum task duration (Dmin, represented by its lower bound) and the maximum task duration (Dmax, represented by its upper bound). The graphic below illustrates these properties.
When the resource is given as an argument, the duration of the task will be effective only if the task is assigned to the given resource: `(task.assign(r) = 1) =>task.duration = duration`.




## Synopsis

```
procedure setduration(task:cptask, duration:integer)
procedure setduration(task:cptask, durationMin:integer,
      durationMax:integer)
procedure setduration(resource: cpresource, task:cptask, duration:integer)
```

## Arguments

| | |
|---|---|
| `task` | a task |
| `duration` | fixed duration of the task |
| `durationMin` | minimum duration for the task |
| `durationMax` | maximum duration for the task |
| `resource` | a resource (*e.g.* for alternative resources) |

## Related topics

`getduration` `set_start_based_duration` `update_duration_with_idle_times`
`set_duration_with_idle_times` `get_start_based_duration`

# set_start_based_duration

### Purpose

If the task is allocated to this resource, the duration will take the given 'duration' value if the start of the task is between the given interval:
`(t1 <= task.start <= t2) and (task.assign(r) = 1)` ⇒ `task.duration = duration`
This method can be called repeatedly to specify different durations on different intervals. Calling it successively with intersectings intervals will override existing values on the intersection. Also, propagation should not be called between successive calls.
Note: All values not included in any of the given intervals will be forbidden for the start variable.

### Synopsis

```
procedure set_start_based_duration(resource: cpresource, task:cptask,
      t1:integer, t2:integer, duration:integer)
```

### Arguments

| | |
|---|---|
| `resource` | a resource |
| `task` | a task |
| `t1` | The first interval extremity |
| `t2` | The second interval extremity |
| `duration` | The actual duration taken if the start is in the given interval |

### Related topics

`get_start_based_duration` `setduration` `set_duration_with_idle_times` `cp_show_var_constraints`

## get_start_based_duration

### Purpose

When declaring a task having a start based duration (through `set_start_based_duration` or `set_duration_with_idle_times`), this method will return the actual duration of the task if it begins at the `start` timestep.
If the `start` value is not available in the start-based duration domain, `-1` will be returned.

### Synopsis

```
function get_start_based_duration(resource: cpresource, task:cptask,
      start:integer): integer
```

### Arguments

| | |
|---|---|
| `resource` | a resource |
| `task` | a task |
| `start` | The start timestep to query |

### Return value

The duration if the task starts at the given timestep, `-1` if it is an impossible start time.

### Related topics

`get_start_based_duration` `setduration` `set_duration_with_idle_times` `cp_show_var_constraints`

# set_duration_with_idle_times

## Purpose

If the task is assigned to this resource, the then the following statements will be enforced:
From the given nominal `duration`, the duration variable will be constrained to take the following values:

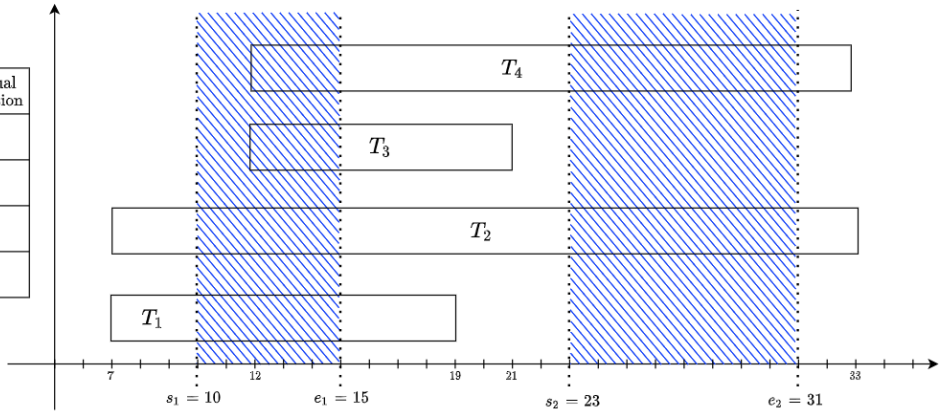
- `duration` if the task does not intersect any idle time window
- `duration` increased by total length of the intersecting idle time windows

For example, if a resource is idle on two time windows `[s1, e1)` and `[s2, e2)`, then this method declares that the tasks intersecting those idle times windows will be extended.

- If a task T1 starts before `s1` but its `duration` make it intersect `[s1, e1)`, then its duration variable will be `T1.duration = duration + e1 - s1`
- If a task T2 starts before `s1` but its updated duration make it intersect `[s1, e1)` and `[s2, e2)`, then its duration variable will be `T2.duration = duration + (e1 - s1) + (e2 - s2)`
- If a task T3 starts in the idle interval `[s1, e1)`, then its duration variable will be `T3.duration = duration + (e1 - T3.start)`
- If a task T4 starts in the idle interval `[s1, e1)` and its updated duration make it intersect `[s2, e2)` then its duration variable will be `T4.duration = duration + (e1 - T4.start) + (e2 - s2)`

Note that if `allow_start_in_idle` is false then T3 and T4 cases will be forbidden. The idle time windows can be given in any order and can be intersecting (union is made). Note that idle time windows are a strict end interval (end time step is not in the interval). If the nominal duration is dependent on the start time of the task, the `update_duration_with_idle_times` procedure can be used instead. When developing the model, it is recommended to check the start-based duration constraint by printing the constraint: `cp_show_var_constraints(getduration(task))`

| Task | Nominal duration | Actual duration |
|---|---|---|
| $T_1$ | 7 | 12 |
| $T_2$ | 13 | 26 |
| $T_3$ | 6 | 9 |
| $T_4$ | 10 | 21 |




## Synopsis

```
procedure set_duration_with_idle_times(resource: cpresource, task:cptask,
      duration:integer, idle_starts:list of integer, idle_ends:list of
      integer, allow_start_in_idle:boolean)
```

## Arguments

| | |
|---|---|
| `resource` | a resource |
| `task` | a task |
| `duration` | The expected nominal duration of the task without idle times |
| `idle_starts` | The idle time windows start (must be of same length as `idle_ends`) |

| | |
|---|---|
| `idle_ends` | The idle time windows end (must be of same length as `idle_starts`) |
| `allow_start_in_idle` | If true, the `task` will be able to start in an idle time window. |

**Related topics**

`get_start_based_duration` `setduration` `update_duration_with_idle_times` `cp_show_var_constraints`

## update_duration_with_idle_times

### Purpose

When having previously set a start-based duration (through `setduration` or `set_start_based_duration`), this method will update the start-based durations to simulate idle time windows.
Warning: when adding several idle time windows for a resource and a task, they must be added in increasing time order and all time windows must be disjoint. If not done this way, durations might be inconsistent. Also, propagation should not be called between successive calls.
When developing the model, it is recommended to check the start-based duration constraint by printing the constraint: `cp_show_var_constraints(getduration(task))`

### Synopsis

```
procedure update_duration_with_idle_times(resource: cpresource,
      task:cptask, t1:integer, t2:integer, allow_start_in_idle:boolean)
```

### Arguments

| | |
|---|---|
| `resource` | a resource |
| `task` | a task |
| `t1` | The idle time window start |
| `t2` | The idle time window end |
| `allow_start_in_idle` | If true, the `task` will be able to start in the idle time window. |

### Example

The following example shows how to use update_duration_with_idle_times for stating a scheduling problem with resource choice and variable durations:

```
model "Scheduling with alternative resources"
 uses "kalis", "mmsystem"

 setparam("KALIS_DEFAULT_LB", 0)
 setparam("KALIS_VERBOSE_LEVEL", 1)

 declarations
  JOBS: set of string                       ! Index set of jobs
  TEAMS: set of string                      ! Index set of teams (resources)
  DURATIONS: array(JOBS, TEAMS) of integer  ! Durations of JOBS for each team
  POSSIBLE_TEAMS: array(JOBS) of set of string  ! Possible team for each task
  PRECEDENCES: list of list of string       ! Pairs of precedence constraints
  SOFT_BREAKS: array(TEAMS) of list of list of integer  ! Start and end times
                                            ! of soft breaks for each team
  ALLOW_START_IN_IDLE: boolean

  job: array(JOBS) of cptask                ! Jobs
  team: array(TEAMS) of cpresource          ! Teams

  procedure print_and_check_solution
  function get_actual_duration(j: string, t: string, start: integer): integer
 end-declarations

 ! *************** Data ***************
 ! -1 duration indicates the team cannot process the task
 DURATIONS::(["J0", "J1", "J2", "J3", "J4", "J5", "J6", "J7", "J8", "J9",
     "J10", "J11", "J12", "J13", "J14", "J15", "J16", "J17"],
    ["T1", "T2", "T3"])[
       2, -1,  2,
      16, 14, 15,
       9, -1,  8,
```

```
       8,  5,  8,
      10, 11,  8,
       6,  5,  7,
      -1,  3,  4,
       2,  1,  2,
       9,  6,  9,
       5,  7, -1,
       3, -1,  1,
       2,  3,  3,
       1, -1,  1,
       7,  4,  7,
       4,  6,  4,
       3,  2,  1,
       9,  9, -1,
       1,  2,  3]

forall(j in JOBS)
 POSSIBLE_TEAMS(j) := union(t in TEAMS | DURATIONS(j, t) <> -1) {t}

PRECEDENCES:= [ ["J1", "J0"], ["J2", "J1"], ["J3", "J1"], ["J13", "J1"],
      ["J4", "J2"], ["J5", "J3"], ["J6", "J3"], ["J8", "J3"],
      ["J9", "J3"], ["J14", "J3"], ["J5", "J4"], ["J7", "J5"],
      ["J8", "J5"], ["J10", "J5"], ["J12", "J6"], ["J15", "J7"],
      ["J11", "J8"], ["J15", "J10"], ["J16", "J11"],
      ["J14", "J13"], ["J15", "J13"], ["J17", "J16"]]

SOFT_BREAKS::(["T1", "T2", "T3"]) [[[10, 25], [42, 52]], [[15, 37]],
      [[25, 35], [45, 58]]]
ALLOW_START_IN_IDLE := true

! *************** Problem formulation ***************
! Define discrete resources
forall(t in TEAMS) do
 set_resource_attributes(team(t), KALIS_DISCRETE_RESOURCE, 1)
 team(t).name := t
end-do

! Define possible teams for each task
forall(j in JOBS) do
 job(j).name := j
 requires(job(j), union(t in POSSIBLE_TEAMS(j)) {resusage(team(t), 1)})
end-do

! Define associated duration for each task
forall(j in JOBS) do
 ! Initialize duration bounds
 setdomain(getduration(job(j)),
     min(t in POSSIBLE_TEAMS(j)) DURATIONS(j, t),
     max(t in POSSIBLE_TEAMS(j)) DURATIONS(j, t))

 forall(t in POSSIBLE_TEAMS(j)) do
  ! Set nominal duration
  setduration(team(t), job(j), DURATIONS(j, t))
  ! Update the actual duration with idle times
  forall(b in SOFT_BREAKS(t))
   update_duration_with_idle_times(team(t), job(j), b.first, b.last,
    ALLOW_START_IN_IDLE)
 end-do
end-do
! Display all constraints involving the duration of task 'J0'
```

```
 cp_show_var_constraints(getduration(job("J0")))

 ! Define precedences
 forall(j in JOBS)
  setpredecessors(job(j), union(p in PRECEDENCES | p(1) = j) {job(p.last)})

 cp_close_schedule

 ! *************** Solving ***************
 ! Perform constraint propagation
 if not cp_propagate then
  writeln("Problem is infeasible")
  exit(1)
 end-if

 setparam("KALIS_MAX_COMPUTATION_TIME", 10)

 ! Solve the problem
 if cp_schedule(getmakespan)=0 then
  writeln("No solution")
  exit(0)
 end-if

 ! Solution printing
 print_and_check_solution

! *************** Subroutine definitions ***************
 procedure print_and_check_solution
  declarations
   starts: array(JOBS) of integer
   ends: array(JOBS) of integer
   operating_teams: array(JOBS) of string
  end-declarations

  ! Display the solution
  writeln("makespan=", getsol(getmakespan))
  forall(j in JOBS) do
   starts(j) := getsol(getstart(job(j)))
   ends(j) := getsol(getend(job(j)))
   forall(t in POSSIBLE_TEAMS(j) | getsol(getassignment(job(j),team(t)))>0) do
    operating_teams(j) := t
    break
   end-do
   writeln(formattext("%3s: %2d - %2d team=%s", j, starts(j), ends(j),
    operating_teams(j)))
  end-do

  ! Check solution
  forall(j in JOBS | operating_teams(j) not in TEAMS)
   writeln("Error: ", j, " doesn't have an operating team.")

  forall(p in PRECEDENCES | starts(getfirst(p)) < ends(getlast(p)))
   writeln("Error: Precedence constraint ", p, " is violated.")

  forall(j in JOBS | starts(j) + get_actual_duration(j, operating_teams(j),
                     starts(j)) <> ends(j))
   writeln("Error: Job ", j, " has a wrong duration.")

  if max(j in JOBS) ends(j) <> getsol(getmakespan) then
   writeln("Error: Objective value is different from computed makespan value.")
```

```
 end-if
end-procedure

! **** Return the actual duration of a job given its team and start
function get_actual_duration(j: string, t: string, start: integer): integer
 expected_end := start + DURATIONS(j, t)
 forall(b in SOFT_BREAKS(t)) do
   if start >= b.last then
    next
   end-if
   ! Adding soft break duration
   if expected_end > b.first then
    expected_end += b.last - maxlist(start, b.first)
   end-if
 end-do
 returned := expected_end - start
end-function

end-model
```

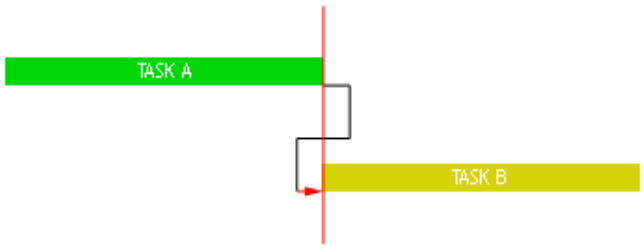
**Related topics**

get_start_based_duration setduration set_duration_with_idle_times
cp_show_var_constraints

# addpredecessors

## Purpose

Adds a set of tasks as predecessors to a task. A task precedes some other task when it must be completed before the start of the second task. The following graphic shows two tasks A and B where A precedes B (and respectively B succeeds A as the relation is reflexive):




## Synopsis

```
procedure addpredecessors(task:cptask, predset:set of cptask)
```

## Arguments

| | |
|---|---|
| `task` | the task |
| `predset` | the set of tasks that must precede 'task' |

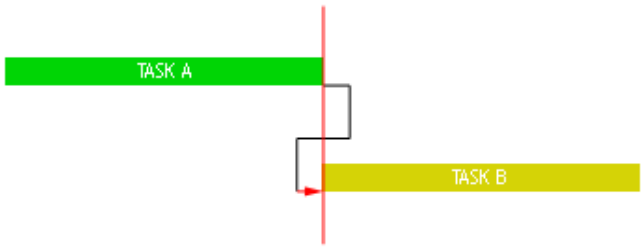
## Related topics

`addsuccessors` `setpredecessors` `setsuccessors`

# setpredecessors

## Purpose

Sets the set of tasks that must precede a task. A task precedes some other task when it must be completed before the start of the second task. The following graphic shows two tasks A and B where A precedes B (and respectively B succedes A as the relation is reflexive):




## Synopsis

```
procedure setpredecessors(task:cptask, predset:set of cptask)
```

## Arguments

| | |
|---|---|
| `task` | the task |
| `predset` | the set of tasks that must precede 'task' |

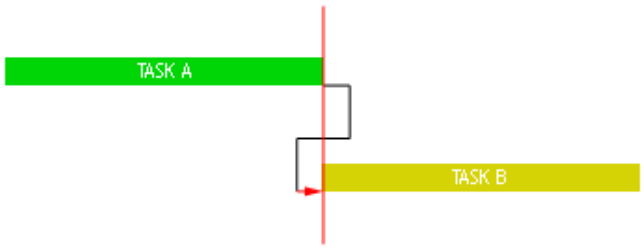
## Related topics

`addpredecessors` `addsuccessors` `setsuccessors`

# addsuccessors

## Purpose

Adds a set of tasks as successors of a task. A task succeeds some other task when its processing cannot start before the completion of this task. The following graphic shows two tasks A and B where A precedes B (and respectively B succeeds to A as the relation is reflexive):




## Synopsis

```
procedure addsuccessors(task:cptask, succset:set of cptask)
```

## Arguments

| | |
|---|---|
| `task` | the task |
| `succset` | the set of tasks that must succeed 'task' |

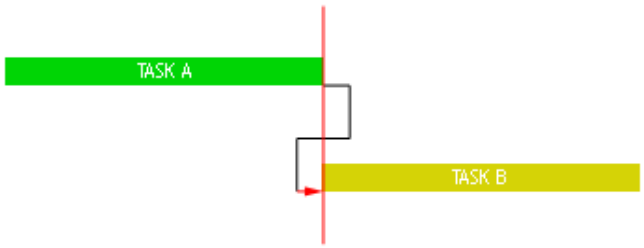
## Related topics

`addpredecessors` `setpredecessors` `setsuccessors`

## setsuccessors

### Purpose

Sets the set of tasks that must succeed a task. A task succeeds some other task when its processing cannot start before the completion of this task. The following schema shows two tasks A and B where A precedes B (and respectively B succeeds A as the relation is reflexive):




### Synopsis

```
procedure setsuccessors(task:cptask, succset:set of cptask)
```

### Arguments

| | |
|---|---|
| `task` | the task |
| `succset` | the set of tasks that must succeed 'task' |

### Related topics

`addpredecessors` `addsuccessors` `setpredecessors`

## cp_show_schedule

**Purpose**

Shows a textual representation of the current schedule

**Synopsis**

```
procedure cp_show_schedule
```

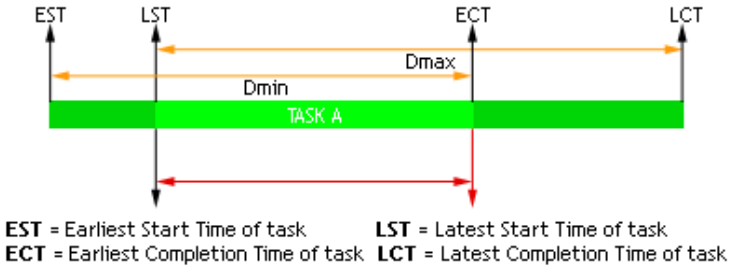
# getstart

## Purpose

Retrieves the 'start' variable of a task.
A cptask is represented by three cpvar:

- 'start' representing the start time of the task
- 'end' representing the completion time of the task
- 'duration' representing the duration of the task.

These three structural variables are linked with the following constraint: start + duration $\leqslant$ end.
The start time variable represents two specific parameters of the task: the Earliest Starting Time (EST represented by its lower bound) and its Latest Starting Time (LST represented by its upper bound). The graphic below illustrates these properties:




## Synopsis

```
function getstart(t:cptask) : cpvar
```

## Argument

`t` the task

## Return value

The cpvar representing the start time of t

## Related topics

`getend` `getduration` `getconsumption` `getrequirement` `getproduction` `getprovision`

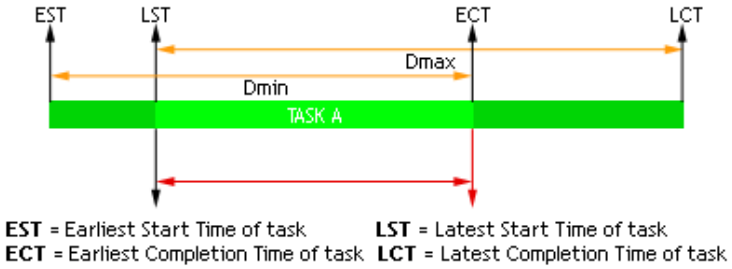
# getend

## Purpose

Retrieves the 'end' variable of a task.
A cptask is represented by three cpvar:

- 'start' representing the start time of the task
- 'end' representing the completion time of the task
- 'duration' representing the duration of the task.

These three structural variables are linked with the following constraint: start + duration $\leqslant$ end.
The 'end' variable represents two specific parameters of the task: the Earliest Completion Time (ECT, represented by its lower bound) and its Latest Completion Time (LCT, represented by its upper bound).
The graphic below illustrates these properties:




## Synopsis

```
function getend(t:cptask) : cpvar
```

## Argument

`t` the task

## Return value

The cpvar representing the completion time of t

## Related topics

`getstart` `getduration` `getconsumption` `getrequirement` `getproduction` `getprovision`

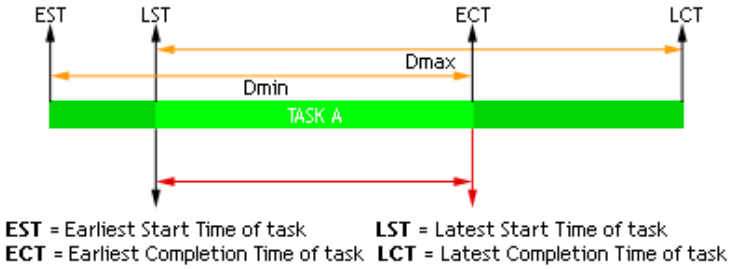
# getduration

## Purpose

Retrieves the 'duration' variable of a task.
A cptask is represented by three cpvar:

- 'start' representing the start time of the task
- 'end' representing the completion time of the task
- 'duration' representing the duration of the task.

These three structural variables are linked with the following constraint: start + duration $\leqslant$ end.
The duration variable represents two specific parameters of the task: the minimum task duration (Dmin, represented by its lower bound) and the maximum task duration (Dmax represented by its upper bound). The graphic below illustrates these properties:




## Synopsis

```
function getduration(t:cptask) : cpvar
```

## Argument

`t` the task

## Return value

The cpvar representing the duration of t

## Related topics

`getstart` `getend` `getconsumption` `getrequirement` `getproduction` `getprovision`

# getconsumption

## Purpose

Gets the cpvar representing the consumption of a task for a particular resource.
A task consumes some amount of processing power of a resource when this amount must be made available for the execution of the task. The resource is considered as renewable which means that whenever the task ends the processing power that was used is no longer available for processing other tasks.

## Synopsis

```
function getconsumption(task:cptask, resource:cpresource) : cpvar
function getconsumption(task:cptask, resource:cpresource, p:integer) :
      integer
```

## Arguments

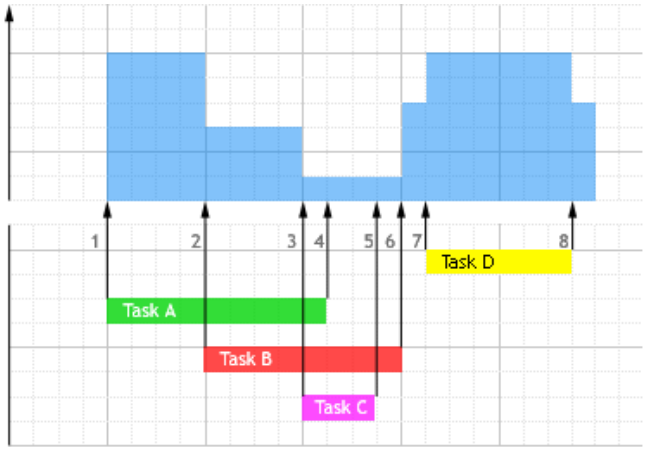
| | |
|---|---|
| `task` | the task |
| `resource` | the resource |
| `p` | the timestep |

## Return value

The cpvar representing the consumption of 'resource' by 'task'

## Example

The following example illustrates this:




Task A produces 6 units of resource
Task B requires 3 units of resource
Task C consumes 2 units of resource
Task D provides 2 units of resource

1) Task A starts and produces 6 units of resource that will be available until the end of the schedule
2) Task B starts and requires 3 units of resource for it's execution. The resource availability is now 3 units less.
3) Task C starts and consumes 2 units of resource. The resource availability is lowered by two units until the end of the schedule.
4) Task A ends and the resource availability remains constant as the production is definitive.
5) Task C ends and the resource availability remains constant as the consumption of resource is definitive.
6) Task B ends and 3 units of resource are available again since resource requirement is recoverable.
7) Task D starts and provides 2 units of resource during it's execution.
8) Task D ends and the resource availabilty drop down of two units as the resource provision is recoverable.

```
model "Producer Consumer"
 uses "kalis"

 declarations
  Masonry, Carpentry, Roofing, Windows, Facade, Garden, Plumbing,
    Ceiling, Painting, MovingIn : cptask    ! Declaration of tasks
```

```
  money_available : cpresource              ! Resource declaration
 end-declarations

! 'money_available' is a cumulative resource with max. amount of 29$
 set_resource_attributes(money_available,KALIS_DISCRETE_RESOURCE,29)

! Limit resource availability to 20$ in the time interval [0,14]
 setcapacity(money_available, 0, 14, 20)

! Setting the task durations and predecessor sets
 set_task_attributes(Masonry  , 7 )
 set_task_attributes(Carpentry, 3, {Masonry} )
 set_task_attributes(Roofing  , 1, {Carpentry} )
 set_task_attributes(Windows  , 1, {Roofing} )
 set_task_attributes(Facade   , 2, {Roofing} )
 set_task_attributes(Garden   , 1, {Roofing} )
 set_task_attributes(Plumbing , 8, {Masonry} )
 set_task_attributes(Ceiling  , 3, {Masonry} )
 set_task_attributes(Painting , 2, {Ceiling} )
 set_task_attributes(MovingIn , 1, {Windows,Facade,Garden,Painting})

! Setting the resource consumptions
 consumes(Masonry  , 7, money_available )
 consumes(Carpentry, 3, money_available )
 consumes(Roofing  , 1, money_available )
 consumes(Windows  , 1, money_available )
 consumes(Facade   , 2, money_available )
 consumes(Garden   , 1, money_available )
 consumes(Plumbing , 8, money_available )
 consumes(Ceiling  , 3, money_available )
 consumes(Painting , 2, money_available )
 consumes(MovingIn , 1, money_available )

! Find the optimal schedule (minimizing the makespan)
 if cp_minimize(getmakespan) then
   cp_show_sol
 else
   writeln("No solution found")
 end-if

end-model
```

**Related topics**

getstart getend getduration getrequirement getproduction getprovision

## getrequirement

### Purpose

Gets the cpvar representing the requirement of a task for a particular resource.
A task requires some amount of processing power of a resource when this amount must be made available for the execution of the task. The resource is considered as recoverable which means that whenever the task ends the processing power that was used by it becomes available again for processing other tasks.

### Synopsis

```
function getrequirement(task:cptask, resource:cpresource) : cpvar
function getrequirement(task:cptask, resource:cpresource, p:integer) :
      integer
```

### Arguments

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |
| `p` | the timestep |

### Return value

The cpvar representing the requirement of 'resource' by 'task'

### Example

See the example provided for `getconsumption`.

### Related topics

`getstart` `getend` `getduration` `getconsumption` `getproduction` `getprovision`

# getproduction

### Purpose

Gets the cpvar representing the production of a task for a particular resource.
A task produces some amount of processing power for a resource at its start. The capacity produced is considered as non-renewable which means that the produced capacity remains available even after the termination of the task.

### Synopsis

```
function getproduction(task:cptask, resource:cpresource) : cpvar
function getproduction(task:cptask, resource:cpresource, p:integer) :
      integer
```

### Arguments

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |
| `p` | the timestep |

### Return value

The cpvar representing the production of 'resource' by 'task'

### Example

See the example provided for `getconsumption`.

### Related topics

`getstart` `getend` `getduration` `getconsumption` `getrequirement` `getprovision`

## getprovision

### Purpose

Gets the cpvar representing the provision of a task for a particular resource.
A task provides some amount of processing power for a resource during its execution. The capacity provided is considered as renewable which means that whenever the providing task ends, the provided capacity is no longer available.

### Synopsis

```
function getprovision(task:cptask, resource:cpresource) : cpvar
function getprovision(task:cptask, resource:cpresource, p:integer) :
      integer
```

### Arguments

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |
| `p` | the timestep |

### Return value

The cpvar representing the provision of 'resource' by 'task'

### Example

See the example provided for `getconsumption`.

### Related topics

`getstart` `getend` `getduration` `getconsumption` `getrequirement` `getproduction`

## is_consuming

**Purpose**

Returns true IFF the specified task consumes a specific resource.

**Synopsis**

```
function is_consuming(task:cptask, resource:cpresource) : boolean
```

**Arguments**

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |

**Return value**

`true` IFF the task consumes the specified resource, `false` otherwise

**Related topics**

`is_requiring` `is_producing` `is_providing`

## is_requiring

**Purpose**

Returns true IFF the specified task requires a specific resource.

**Synopsis**

```
function is_requiring(task:cptask, resource:cpresource) : boolean
```

**Arguments**

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |

**Return value**

`true` IFF the task requires the specified resource, `false` otherwise

**Related topics**

`is_consuming` `is_producing` `is_providing`

## is_producing

**Purpose**

Returns true IFF the specified task produces a specific resource.

**Synopsis**

```
function is_producing(task:cptask, resource:cpresource) : boolean
```

**Arguments**

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |

**Return value**

`true` IFF the task produces the specified resource, `false` otherwise

**Related topics**

`is_consuming` `is_requiring` `is_providing`

## is_providing

**Purpose**

Returns true IFF the specified task provides a specific resource.

**Synopsis**

```
function is_providing(task:cptask, resource:cpresource) : boolean
```

**Arguments**

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |

**Return value**

`true` IFF the task provides the specified resource, `false` otherwise

**Related topics**

`is_consuming` `is_requiring` `is_producing`

## cp_schedule

### Purpose

Optimizes the schedule with respect to an objective variable.

### Synopsis

```
function cp_schedule(obj:cpvar) : integer
function cp_schedule(obj:cpfloatvar) : integer
function cp_schedule(obj:cpfloatvar, maximization:boolean) : integer
function cp_schedule(obj:cpvar, maximization:boolean) : integer
```

### Arguments

| | |
|---|---|
| `obj` | the objective variable |
| `maximization` | `true` for maximization of the objective and `false` for minimization (default: minimization) |

### Return value

0 if schedule is inconsistent, 1 if schedule is suboptimal, 2 if schedule is optimal

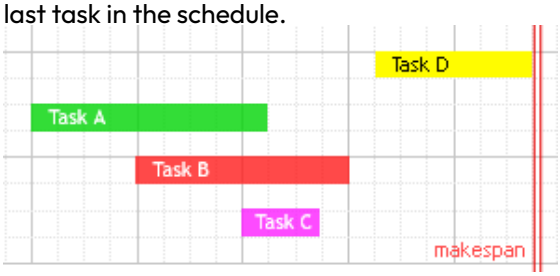
### Related topics

`getmakespan` `cp_set_schedule_strategy`

# getmakespan

### Purpose

Gets the cpvar representing the makespan of the schedule. The makespan is the completion time of the last task in the schedule.




### Synopsis

```
function getmakespan : cpvar
```

### Return value

The cpvar representing the makespan of the schedule

### Related topics

`cp_schedule`

## consumes

### Purpose

Sets the minimal and maximal amount of resource consumed by a task for a particular resource. A task consumes some amount of processing power of a resource when this amount must be made available for the execution of the task. The resource requirement is considered as renewable which means that whenever the tasks ends The processing power that was required is no longer available for processing other tasks. Note that a minimal amount of 0 is possible thus allowing modeling of alternative resources. The type of resource consumption can be defined in several ways:

- By specifying a resource and a constant consumption parameter *'consumption'*. In this case the resource consumption is constant other the execution of the task.
- By specifying a resource and a minimal *'minCons'* and maximal *'maxCons'* consumption parameters: In this case the resource consumption is a decision variable but is constant other the execution of the task.
- By specifying a cpresusage *'usage'* (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'*: This makes it possible to model alternative resources. The type of resource consumption is defined by the resource usage passed in argument (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'* , a minimal *'minalt'* and a maximal *'maxalt'* number of alternative resources that must be consumed: Between [minalt..maxalt] alternative consumptions from the set defined will be active which means that several resources will be chosen to be consumed by the task. The type of resource consumption is defined by the resource usage passed in argument (see `resusage` for further detail).

### Synopsis

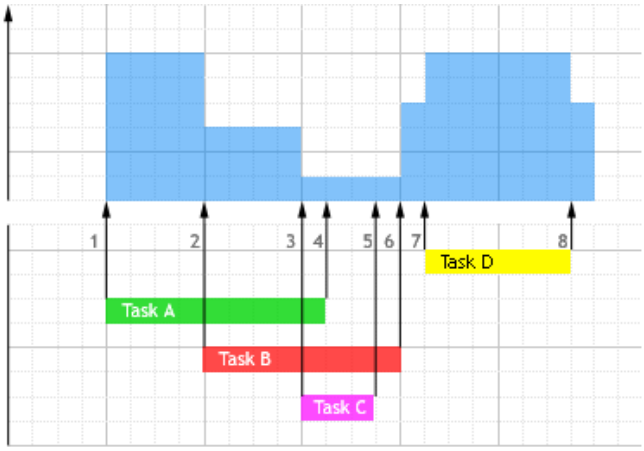
```
procedure consumes(task:cptask, consumption:integer, resource:cpresource)
procedure consumes(task:cptask, consumptionMin:integer, consumptionMax,
      resource:cpresource)
procedure consumes(task:cptask, usage:cpresusage)
procedure consumes(task:cptask, optUsages:set of cpresusage)
procedure consumes(task:cptask, optUsages:set of cpresusage,
      minalt:integer, maxalt:integer)
```

### Arguments

| | |
|---|---|
| `task` | the task |
| `consumption` | constant positive resource consumption |
| `minCons` | minimal resource consumption |
| `maxCons` | maximal resource consumption |
| `resource` | the resource to be consumed |
| `usage` | the resource usage |
| `optUsages` | the set of alternatives resource consumption |
| `minalt` | minimal number of resources that must be consumed |
| `maxalt` | maximal number of resources that may be consumed |

### Example

The following example illustrates this:




Task A produces 6 units of resource
Task B requires 3 units of resource
Task C consumes 2 units of resource
Task D provides 2 units of resource

1) Task A starts and produces 6 units of resource that will be available until the end of the schedule
2) Task B starts and requires 3 units of resource for it's execution. The resource availability is now 3 units less.
3) Task C starts and consumes 2 units of resource. The resource availability is lowered by two units until the end of the schedule.
4) Task A ends and the resource availability remains constant as the production is definitive.
5) Task C ends and the resource availability remains constant as the consumption of resource is definitive.
6) Task B ends and 3 units of resource are available again since resource requirement is recoverable.
7) Task D starts and provides 2 units of resource during it's execution.
8) Task D ends and the resource availabilty drop down of two units as the resource provision is recoverable.

```
model "Producer Consumer"
 uses "kalis"

 declarations
  Masonry, Carpentry, Roofing, Windows, Facade, Garden, Plumbing,
    Ceiling, Painting, MovingIn : cptask    ! Declaration of tasks
  money_available : cpresource              ! Resource declaration
 end-declarations

! 'money_available' is a cumulative resource with max. amount of 29$
 set_resource_attributes(money_available,KALIS_DISCRETE_RESOURCE,29)

! Limit resource availability to 20$ in the time interval [0,14]
 setcapacity(money_available, 0, 14, 20)

! Setting the task durations and predecessor sets
 set_task_attributes(Masonry  , 7 )
 set_task_attributes(Carpentry, 3, {Masonry} )
 set_task_attributes(Roofing  , 1, {Carpentry} )
 set_task_attributes(Windows  , 1, {Roofing} )
 set_task_attributes(Facade   , 2, {Roofing} )
 set_task_attributes(Garden   , 1, {Roofing} )
 set_task_attributes(Plumbing , 8, {Masonry} )
 set_task_attributes(Ceiling  , 3, {Masonry} )
 set_task_attributes(Painting , 2, {Ceiling} )
 set_task_attributes(MovingIn , 1, {Windows,Facade,Garden,Painting})

! Setting the resource consumptions
 consumes(Masonry  , 7, money_available )
 consumes(Carpentry, 3, money_available )
 consumes(Roofing  , 1, money_available )
 consumes(Windows  , 1, money_available )
```

```
 consumes(Facade   , 2, money_available )
 consumes(Garden   , 1, money_available )
 consumes(Plumbing , 8, money_available )
 consumes(Ceiling  , 3, money_available )
 consumes(Painting , 2, money_available )
 consumes(MovingIn , 1, money_available )

! Find the optimal schedule (minimizing the makespan)
 if cp_minimize(getmakespan) then
   cp_show_sol
 else
   writeln("No solution found")
 end-if

end-model
```

**Related topics**

produces provides requires is_providing is_consuming is_requiring is_producing resusage

## requires

### Purpose

Sets the minimal and maximal amount of resource required by a task for a particular resource. A task requires some amount of processing power of a resource when this amount must be made available for the execution of the task. The resource requirement is considered as renewable which means that whenever the tasks ends the processing power that was required is still available for processing other tasks. Note that a minimal amount of 0 is possible thus allowing modelisation of alternative resources. The type of resource requirement can be defined in several ways:

- By specifying a resource and a constant requirement parameter *'requirement'*. In this case the resource requirement is constant other the execution of the task.
- By specifying a resource and a minimal *'minReq'* and maximal *'maxReq'* requirement parameters: In this case the resource requirement is a decision variable but is constant other the execution of the task.
- By specifying a cpresusage *'usage'* (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'*: This makes it possible to model alternative resources. The type of resource requirement is defined by the resource usage passed in argument (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'*, a minimal *'minalt'* and a maximal *'maxalt'* number of alternative resources that are required: Between [minalt..maxalt] alternative requirements from the set will be active which means that several resources will be chosen as requirements by the task. The type of resource requirement is defined by the resource usage passed in argument (see `resusage` for further detail).

### Synopsis

```
procedure requires(task:cptask, requirement:integer, resource:cpresource)
procedure requires(task:cptask, minReq:integer, maxReq:integer,
      resource:cpresource)
procedure requires(task:cptask, usage:cpresusage)
procedure requires(task:cptask, optUsages:set of cpresusage)
procedure requires(task:cptask, optUsages:set of cpresusage,
      minalt:integer, maxalt:integer)
```

### Arguments

| | |
|---|---|
| `task` | the task |
| `requirement` | constant positive resource consumption |
| `minReq` | minimal resource requirement |
| `maxReq` | maximal resource requirement |
| `resource` | the resource to be required |
| `usage` | the resource usage |
| `optUsages` | the set of alternatives resource requirements |
| `minalt` | minimal number of resources that must be required |
| `maxalt` | maximal number of resources that may be required |

### Example

See the example provided for `consumes`.

### Related topics

`produces` `provides` `requires` `is_providing` `is_consuming` `is_requiring` `is_producing` `resusage`

## produces

### Purpose

Sets the minimal and maximal amount of resource produced by a task for a particular resource.
A task produces some amount of processing power for a resource at its start. The capacity produced is considered as non renewable which means that the produced capacity remains available even after the completion of the task. Note that a minimal amount of 0 is possible thus allowing modelisation of alternative resources. The type of resource production can be defined in several ways:

- By specifying a resource and a constant production parameter *'production'*. In this case the resource production is constant other the execution of the task.
- By specifying a resource and a minimal *'minProd'* and maximal *'maxProd'* production parameters: In this case the resource production is a decision variable but is constant over the execution of the task.
- By specifying a cpresusage *'usage'* (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'*: This makes it possible to model alternative resources. The type of resource production is defined by the resource usage passed in argument (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'*, a minimal *'minalt'* and a maximal *'maxalt'* number of alternative resources that may be produced: Between [minalt..maxalt] alternative productions from the set will be active which means that several resources will be chosen to be produced by the task. The type of resource production is defined by the resource usage passed in argument (see `resusage` for further detail)

### Synopsis

```
procedure produces(task:cptask, production:integer, resource:cpresource)
procedure produces(task:cptask,minProd:integer, maxProd:integer,
      resource:cpresource)
procedure produces(task:cptask, usage:cpresusage)
procedure produces(task:cptask, optUsages:set of cpresusage)
procedure produces(task:cptask, optUsages:set of cpresusage,
      minalt:integer, maxalt:integer)
```

### Arguments

| | |
|---|---|
| `task` | the task |
| `production` | constant positive resource production |
| `minProd` | minimal resource production |
| `maxProd` | maximal resource production |
| `resource` | the resource to be produced |
| `usage` | the resource usage |
| `optUsages` | the set of alternatives resource production |
| `minalt` | minimal number of resources that must be produced |
| `maxalt` | maximal number of resources that may be produced |

### Example

See the example provided for `consumes`.

### Related topics

`produces` `provides` `requires` `is_providing` `is_consuming` `is_requiring` `is_producing` `resusage`

# provides

## Purpose

Sets the minimal and maximal amount of resource provided by a task for a particular resource.
A task provides some amount of processing power for a resource during its execution. The capacity provided is considered as renewable which means that whenever the providing task ends, the provided capacity is no longer available. Note that a minimal amount of 0 is possible thus allowing modeling of alternative resources. The type of resource provision can be defined in several ways:

- By specifying a resource and a constant provision parameter *'provision'*. In this case the resource provision is constant over the execution of the task.
- By specifying a resource and minimal *'minProv'* and maximal *'maxProv'* provision parameters: In this case the resource provision is a decision variable but is constant over the execution of the task.
- By specifying a cpresusage *'usage'* (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'*: This makes it possible to model alternative resources. The type of resource provision is defined by the resource usage passed in argument (see `resusage` for further detail).
- By a set of alternative cpresusage *'optUsages'*, a minimal *'minalt'* and a maximal *'maxalt'* number of alternative resources that must be provided: Between [minalt..maxalt] alternative provisions from the set will be active which means that several resources will be chosen to be provided by the task. The type of resource provision is defined by the resource usage passed in argument (see `resusage` for further detail).

## Synopsis

```
procedure provides(task:cptask, provision:integer, resource:cpresource)
procedure provides(task:cptask, minProv:integer, maxProv:integer,
      resource:cpresource)
procedure provides(task:cptask, usage:cpresusage)
procedure provides(task:cptask, optUsages:set of cpresusage)
procedure provides(task:cptask, optUsages:set of cpresusage,
      minalt:integer, maxalt:integer)
```

## Arguments

| | |
|---|---|
| `task` | the task |
| `provision` | constant positive resource consumption |
| `minProv` | minimal resource consumption |
| `maxProv` | maximal resource provision |
| `resource` | the resource to be provided |
| `usage` | the resource usage |
| `optUsages` | the set of alternatives resource provision |
| `minalt` | minimal number of resources that must be provided |
| `maxalt` | maximal number of resources that may be provided |

## Example

See the example provided for `consumes`.

## Related topics

`produces` `provides` `requires` `is_providing` `is_consuming` `is_requiring` `is_producing` `resusage`

# set_resource_attributes

## Purpose

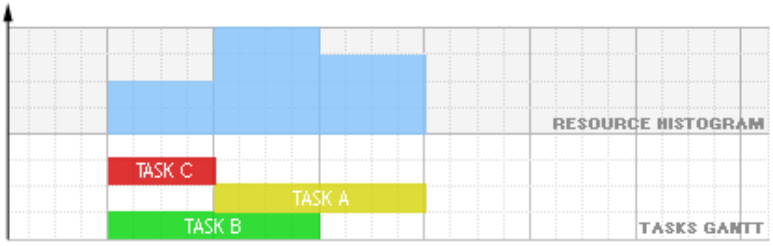
Sets some attributes for a resource.
A resource can be of two different types:

- *Disjunctive* when the resource can be used only by one task at a time.
- *Cumulative* when the resource can be used by several tasks at the same time.

Note that a disjunctive resource is semantically equivalent to a cumulative resource with maximal capacity one and unit resource usage for each task using this resource but this equivalence does not hold in terms of constraint propagation. The parameter 'type' allows the user to choose between a disjunctive resource (KALIS_UNARY_RESOURCE) and a cumulative resource (KALIS_DISCRETE_RESOURCE). The argument 'capacity' indicates the structural maximal capacity of the resource. When the resource is disjunctive this parameter must be equal to one. The structural capacity does not vary over time but a maximal temporal capacity can be imposed at any time point with the `setcapacity` function. The following graphic shows an example with three tasks A, B and C processed on a disjunctive resource and on a cumulative resource with resource usage 3 for task A, 1 for task B and 1 for task C.




DISJUNCTIVE RESOURCE




CUMULATIVE RESOURCE

## Synopsis

```
procedure set_resource_attributes(resource:cpresource, type:integer)
procedure set_resource_attributes(resource:cpresource, type:integer,
      capacity:integer)
procedure set_resource_attributes(resource:cpresource, type:integer,
      capacity:integer, alg:integer)
```

## Arguments

| | |
|---|---|
| `resource` | the resource |
| `type` | resource type: `KALIS_DISCRETE_RESOURCE` or `KALIS_UNARY_RESOURCE` |
| `capacity` | maximal capacity of a discrete resource |
| `alg` | propagation algorithm choice: `KALIS_TIMETABLING`, `KALIS_TASK_INTERVALS`, `KALIS_DISJUNCTIONS`, or `KALIS_EDGE_FINDING` |

## Related topics

`set_task_attributes`

## setcapacity

### Purpose

Sets the maximal capacity (the maximal amount of processing units available) of a discrete resource between two time bounds. This routine can only be applied to resources of type `KALIS_DISCRETE_RESOURCE`.

### Synopsis

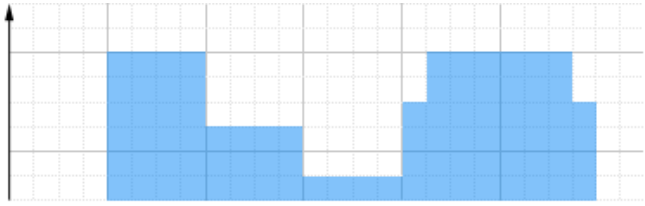
```
procedure setcapacity(resource:cpresource, tmin:integer, tmax:integer,
      capa:integer)
```

### Arguments

| | |
|---|---|
| `resource` | the resource |
| `tmin` | lower bound of the time interval |
| `tmax` | upper bound of the time interval |
| `capa` | the maximal amount of processing units available of resource in the interval [tmin,tmax] |

### Example

The following example shows how to use setcapacity:



```
model "Resource capacity"
 uses "kalis"

 declarations
  A, B, C : cptask            ! Declaration of tasks
  resource : cpresource       ! Declaration of resource
 end-declarations

 setname(A,"A"); setname(B,"B"); setname(C,"C")

! The resource is a cumulative resource with maximum capacity 6
 set_resource_attributes(resource, KALIS_DISCRETE_RESOURCE, 6)

! Setting the resource capacity in the interval 0..2 to 3
 setcapacity(resource, 0, 2, 3)
! Setting the resource capacity in the interval 3..4 to 2
 setcapacity(resource, 3, 4, 2)
! Setting the resource capacity in time period 5 to 1
 setcapacity(resource, 5, 5, 1)

! Setting the task durations
 set_task_attributes(A, 1)
 set_task_attributes(B, 2)
 set_task_attributes(C, 3)

! Setting the resource requirements of the tasks
 requires(A, 1, resource)
 requires(B, 2, resource)
 requires(C, 3, resource)

! Find the optimal schedule (minimizing the makespan)
```

```
 if cp_schedule(getmakespan) <> 0 then
  cp_show_sol
 else
  writeln("no solution found")
 end-if

end-model
```

**Related topics**

setmaxavailability setminusage set_resource_attributes

## setmaxavailability

### Purpose

Sets the maximal capacity (the maximal amount of processing units available) of a resource between two time bounds. This routine can only be applied to resources of type `KALIS_DISCRETE_RESOURCE`.

### Synopsis

```
procedure setmaxavailability(resource:cpresource, tmin:integer,
      tmax:integer, capa:integer)
```

### Arguments

| | |
|---|---|
| `resource` | the resource |
| `tmin` | lower bound of the time interval |
| `tmax` | upper bound of the time interval |
| `capa` | the maximal amount of processing units available of resource in the interval [tmin,tmax] |

### Example

See the example provided for `setcapacity`.

### Related topics

`setcapacity` `setminusage` `set_resource_attributes`

## setminusage

### Purpose

Sets the minimum usage (the minimum number of processing units used) of a resource between two time bounds. This routine can only be applied to resources of type `KALIS_DISCRETE_RESOURCE`.

### Synopsis

```
procedure setminusage(resource:cpresource, tmin:integer, tmax:integer,
      capa:integer)
```

### Arguments

| | |
|---|---|
| `resource` | the resource |
| `tmin` | lower bound of the time interval |
| `tmax` | upper bound of the time interval |
| `capa` | the minimum usage of processing units of resource in the interval [tmin,tmax] |

### Example

See the example provided for `setcapacity`.

### Related topics

`setcapacity` `setmaxavailability` `set_resource_attributes`

## getcapacity

### Purpose

Gets the maximal capacity (the maximal amount of processing units available) of a resource between two time bounds.

### Synopsis

```
function getcapacity(resource:cpresource, tmin:integer, tmax:integer,
      capa:integer) : integer
```

### Arguments

| | |
|---|---|
| `resource` | the resource |
| `tslot` | lowerbound of the time interval |

### Example

See the example provided for `setcapacity`.

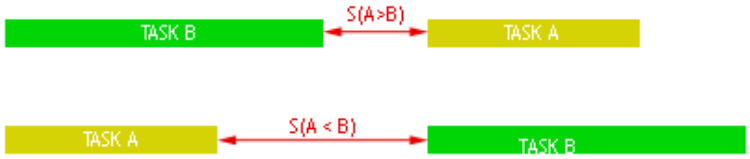
### Related topics

`setcapacity`

# setsetuptime

## Purpose

Sets sequence dependent setup times between two tasks. The setup time depends on the relative execution order in the schedule of the two tasks. The second version with an additional 'resource' argument applies the setup time relation if both tasks are assigned to the specified resource.




## Synopsis

```
procedure setsetuptime(task1:cptask, task2:cptask,
      task1_before_task2:integer, task2_before_task1:integer)
procedure setsetuptime(r:cpresource, task1:cptask, task2:cptask,
      task1_before_task2:integer, task2_before_task1:integer)
```

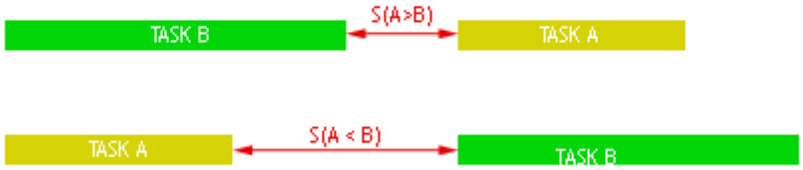
## Arguments

| | |
|---|---|
| `task1` | a task |
| `task2` | another task |
| `task1_before_task2` | setup time between the two tasks if task1 precedes task2 |
| `task2_before_task1` | setup time between the two tasks if task2 precedes task1 |
| `r` | a resource |

# getsetuptime

## Purpose

Return the sequence dependent setup times between task1 and task2 if task1 precedes task2. The setup time depends on the relative execution order in the schedule of the two tasks.




## Synopsis

```
function getsetuptime(task1:cptask, task2:cptask) : integer
```

## Arguments

`task1` a task

`task2` another task

# is_fixed

### Purpose

Returns `true` if the status of the disjunction passed in argument is known.

### Synopsis

```
function is_fixed(disj:cpctr) : boolean
```

### Argument

`disj` the disjunction

### Return value

`true` if disjunction is fixed

### Example

The following example shows how to see if a cpctr `disj` is fixed

```
if is_fixed(disj) then
 write('status of disj is known')
end-if
```

### Related topics

`setpriority` `getpriority`

## cp_set_schedule_strategy

### Purpose

The cp_schedule search algorithm is decomposed in two distinct phases. The first phase target the finding of an near optimal heuristic solution quiclly. The second and last phase focuses on improving the bound and prove optimality.

### Synopsis

```
procedure cp_set_schedule_strategy(phase:integer,
      arrayBranching:array(range) of cpbranching)
procedure cp_set_schedule_strategy(phase:integer, branching:cpbranching)
```

### Arguments

| | |
|---|---|
| `phase` | algorithm phase `KALIS_INITIAL_SOLUTION`,`KALIS_OPTIMAL_SOLUTION` |
| `branching` | the search strategy |
| `arrayBranching` | the search strategies |

### Example

The following example shows how to set the search stragey for the cp_schedule function

```
cp_set_schedule_strategy(KALIS_INITIAL_SOLUTION,
         assign_var(KALIS_SMALLEST_MIN,KALIS_MIN_TO_MAX))
```

### Related topics

`KALIS_INITIAL_SOLUTION` `KALIS_OPTIMAL_SOLUTION` `cp_schedule`

# cp_get_default_schedule_strategy

### Purpose

The cp_schedule search algorithm is decomposed in two distinct phases. The target of the first phase is finding quickly a near optimal heuristic solution. The second and last phase focuses on improving the bound and proving optimality.

### Synopsis

```
procedure cp_get_default_schedule_strategy(phase:integer,
      branching:cpbranching)
```

### Arguments

| | |
|---|---|
| `phase` | algorithm phase (`KALIS_INITIAL_SOLUTION`,`KALIS_OPTIMAL_SOLUTION`) |
| `branching` | the search strategy |

### Example

The following example shows how to set the search stragey for the cp_schedule function

```
cp_set_schedule_strategy(KALIS_INITIAL_SOLUTION,
         assign_var(KALIS_SMALLEST_MIN,KALIS_MIN_TO_MAX))
```

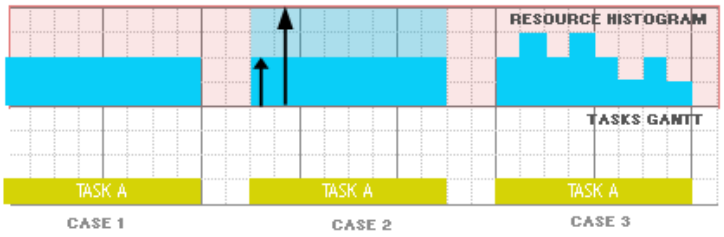
### Related topics

`KALIS_INITIAL_SOLUTION` `KALIS_OPTIMAL_SOLUTION` `cp_schedule`

## resusage

### Purpose

Creates a resource usage. A resource usage is a means to specify the way that a resource will be produced/consumed/provided/required by a task. Three types of resource usages can be used:




- **CASE 1: Constant resource usage**. This is the simplest case where the resource usage is constant all along the execution of the task. For example a task A will require 2 units of resource R during its execution.
- **CASE 2: Variable resource usage but constant over the execution of the task**. This case allows the resource usage to be variable but constant during the execution of the task. Therefore, a decision variable is associated with the resource usage that can be constrained like any other variable. For example a task A will require between 2 units and 4 units of resource R during its execution.
- **CASE 3: Variable resource usage over the execution of the task**. This case allows the resource usage to vary during the execution of the task using a resource usage profile defined as a list of integers. For example a task A will require [2,3,2,3,2,1,2,1] resource units wich means '2' for the first timestep of its execution; '3' for the second *etc.*. If the duration of the task exceeds the length of the profile, then the resource usage is considered as 0 after the end of the profile. If the task duration is smaller than the length of the profile, the profile will be truncated to the duration of the task.

### Synopsis

```
function resusage(resource:cpresource, usage:integer) : cpresusage
function resusage(resource:cpresource, usagemin:integer, usagemax:integer)
      : cpresusage
function resusage(resource:cpresource, profile:array of integer) :
      cpresusage
```

### Arguments

| | |
|---|---|
| `resource` | the resource |
| `usage` | the constant resource usage |
| `usagemin` | minimal resource usage |
| `usagemax` | maximal resource usage |
| `profile` | profile of resource usage |

### Example

The following example illustrates this:

```
model "Non constant resource usage"
 uses "kalis"

 forward procedure print_solution(tasks: set of cptask,
                                  resources: set of cpresource)

 declarations
  res1,res2: cpresource
  taska,taskb,taskc: cptask
 end-declarations
```

```
 taska.start    <= 15
 taska.duration = 4
 taskb.start    <= 15
 taskb.duration = 3
 taskc.start    <= 15
 taskc.duration = 5

! Define a discrete resource with periods of unavailability
 set_resource_attributes(res1, KALIS_DISCRETE_RESOURCE, 6)
 setcapacity(res1, 0, 15, 0)
 setcapacity(res1, 1, 5, 6)
 setcapacity(res1, 7, 11, 6)

 requires(taska, {resusage(res1,[1,3,5,6])})
 requires(taskb, {resusage(res1,[5,3,1])})
 requires(taskc, {resusage(res1,1,1)})

! Define a resource with initial capacity at 0
 set_resource_attributes(res2, KALIS_DISCRETE_RESOURCE, 0)

 provides(taska, resusage(res2,[1,3,1,2]))
 consumes(taskb, resusage(res2,[3,1,2]))
 produces(taskc, resusage(res2,[3,1,2,0,2]))

 if not cp_propagate then
  writeln("Problem is infeasible"); exit(1)
 end-if

 while (cp_find_next_sol) do
  print_solution({taska,taskb,taskc},{res1,res2})
 end-do

!-------------------------------------------------------------
!**** Display results ****
 procedure print_solution(tasks: set of cptask,
                          resources: set of cpresource)

  forall(res in resources) do
   writeln("Resource ", res.name)
   forall(timeindex in 0..getub(getmakespan)) do
    write(strfmt(timeindex,3), " Cap: ", getcapacity(res,timeindex))

    forall(t in tasks)
     if getrequirement(t,res,timeindex)>0 then
      write(", ", t.name, "(req):", getrequirement(t,res,timeindex))
     elif getproduction(t,res,timeindex)>0 then
      write(", ", t.name, "(prod):", getproduction(t,res,timeindex))
     elif getconsumption(t,res,timeindex)>0 then
      write(", ", t.name, "(cons):", getconsumption(t,res,timeindex))
     elif getprovision(t,res,timeindex)>0 then
      write(", ", t.name, "(prov):", getprovision(t,res,timeindex))
     end-if

    writeln
   end-do
  end-do

 end-procedure

end-model
```

**Related topics**

`set_task_attributes`

## get_earliest_start_possible

### Purpose

Gets the earliest time at which the task can start on the given resource.

### Synopsis

```
function get_earliest_start_possible(resource:cpresource, task:cptask) :
      integer
```

### Arguments

| | |
|---|---|
| `resource` | the resource |
| `task` | the task |

### Return value

An integer value representing the earliest possible start time.

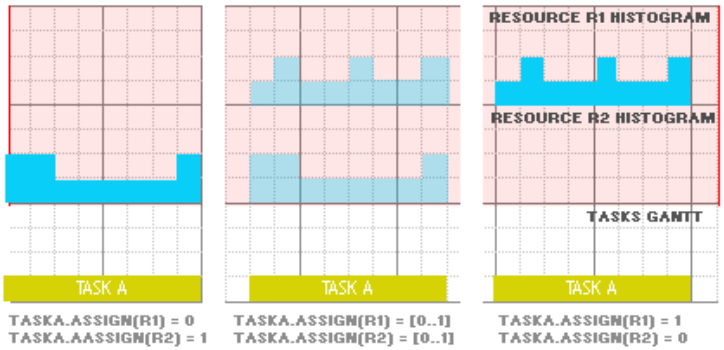
### Related topics

`getassignment` `has_assignment` `getstart` `getend` `getduration` `getconsumption` `getrequirement` `getproduction` `getprovision`

# getassignment

## Purpose

Gets the cpvar representing the assignment of a task for a particular resource. In the following example, either task A requires resource R1 with resource profile [1,2,1,1,2,1,1,2], or task A requires resource R2 with resource profile [2,2,1,1,1,1,1,2]. The choice depends on the value of the decision variables A.assignment(R1) and A.assignment(R2) that can both take a value of 0 (the task is not assigned to this resource) or a value of 1 (the task is assigned to this resource).




## Synopsis

```
function getassignment(task:cptask, resource:cpresource) : cpvar
```

## Arguments

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |

## Return value

The cpvar representing the assignment of 'task' to 'resource'

## Example

The following example illustrates this:

```
model "Alternative resources and non constant resource usage"
 uses "kalis"

 declarations
  res1,res2   : cpresource
  taska,taskb : cptask
  arr1,arr2   : list of integer
 end-declarations

! Fix start times and durations
 taska.start   = 3
 taska.duration = 4
 taskb.start   = 3
 taskb.duration = 4

! Define 2 cumulative resources
 set_resource_attributes(res1, KALIS_DISCRETE_RESOURCE, 4)
 set_resource_attributes(res2, KALIS_DISCRETE_RESOURCE, 4)

 setname(taska,"taska"); setname(taskb,"taskb")
 setname(res1,"R1"); setname(res2,"R2")

! Define alternative resources for both tasks
 arr1 := [1,3,2,3]
```

```
 arr2 := [2,4,1,3]
 requires(taska, {resusage(res1,arr1),resusage(res2,arr2)}, 1, 1)
 requires(taskb, {resusage(res1,1,1),resusage(res2,1,1)}, 1, 1)

! Find all solutions
 while (cp_find_next_sol) do
  cp_show_sol
 end-do

end-model
```

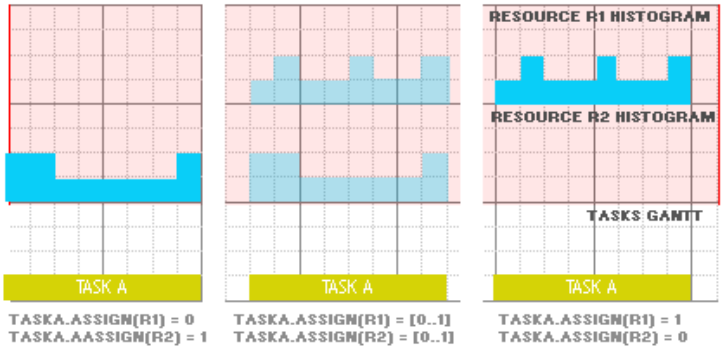
**Related topics**

has_assignment get_earliest_start_possible getstart getend getduration getconsumption getrequirement getproduction getprovision

# has_assignment

## Purpose

In the following example, either task A requires resource R1 with resource profile [1,2,1,1,2,1,1,2], or task A requires resource R2 with resource profile [2,2,1,1,1,1,1,2]. The choice depends on the value of the decision variables A.assignment(R1) and A.assignment(R2) that can both take a value of 0 (the task is not assigned to this resource) or a value of 1 (the task is assigned to this resource).




## Synopsis

```
function has_assignment(task:cptask, resource:cpresource) : boolean
```

## Arguments

| | |
|---|---|
| `task` | the task |
| `resource` | the resource |

## Return value

`true` IFF a cpvar representing the assignment of 'task' to 'resource' exists

## Example

See the example provided for `getassignment`.

## Related topics

`getassignment` `get_earliest_start_possible` `getstart` `getend` `getduration` `getconsumption` `getrequirement` `getproduction` `getprovision`

# setidletimes

## Purpose

Specifies the set of timesteps during which a resource should be considered as idle. When a task overlaps an idle timestep, resource usages are shifted to the right provided that the task duration is variable.

## Synopsis

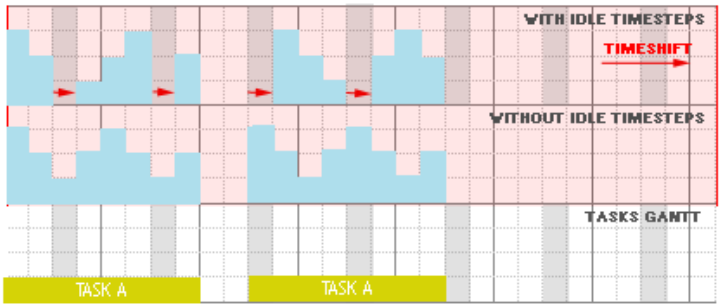
```
procedure setidletimes(resource:cpresource, idleTimeSteps: set of integer)
```

## Arguments

| | |
|---|---|
| `resource` | the resource |
| `idleTimeSteps` | The set of idle time steps |

## Example

Here is an example:




## Related topics

`consumes` `requires` `provides` `produces` `resusage` `is_idletime`

# is_idletime

### Purpose

Tests whether a specific timestep is defined as an idle time for the resource passed in the argument.

### Synopsis

```
function is_idletime(resource:cpresource, timestep: integer) : boolean
```

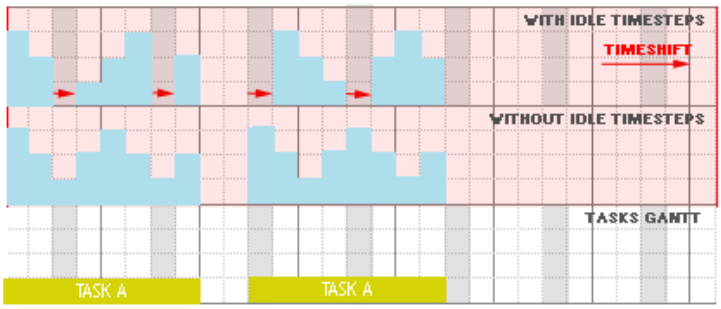
### Arguments

`resource` the resource

`timestep` The time step

### Example

Here is an example:




### Related topics

`consumes` `requires` `provides` `produces` `resusage` `is_idletime`

## cp_close_schedule

### Purpose

Close the schedule, *i.e.*, mark problem definition as complete, and post the underlying structural constraints of the tasks and resources. (A call to `propagate` does not automatically close the schedule.)

### Synopsis

```
procedure cp_close_schedule
```

# 9.8 Linear relaxations


`cp_add_linrelax_solver` Add a linear relaxation solver to the linear relaxation solver list p. 276

`cp_clear_linrelax_solver` Clear the linear relaxation solver list p. 278

`cp_get_linrelax` Returns an automatic relaxation of the cp problem p. 271

`cp_remove_linrelax_solver` Remove a linear relaxation solver from the linear relaxation solver list p. 277

`cp_show_relax` Pretty printing of a linear relaxation p. 275

`export_prob` Export the linear relaxation in LP format p. 284

`fix_to_relaxed` Fix the continuous variables to their optimal value in the relaxation solver passed in argument p. 273

`generate_cuts` Generate and add cuts to the relaxation passed in parameters p. 279

`get_indicator` Get an indicator variable for a given variable and a value. p. 282

`get_linrelax` Get the linear relaxation for a constraint p. 283

`get_linrelax_solver` Returns a linear relaxation solver from a linear relaxation, an objective variables and some configuration parameters p. 272

`get_reduced_cost` Get a reduced cost value from a linear relaxation solver p. 285

`get_relaxed_value` Returns the optimal relaxed value for a variable in a relaxation p. 286

`KALIS_LARGEST_REDUCED_COST` Get a largest reduced cost variable selector from a linear relaxation solver p. 269

`KALIS_NEAREST_RELAXED_VALUE` Get a nearest relaxed value selector from a linear relaxation solver p. 270

`lp_optimize` Launch LP/MIP solver without CP branching. p. 280

`set_integer` Set integrality flag for a variable in a linear relaxation p. 287

`set_linrelax_solver_attribute` Parameter setting for a linear relaxation solver. p. 281

`set_verbose_level` Set the verbose level for a specific linear relaxation solver p. 274

# KALIS_LARGEST_REDUCED_COST

### Purpose

Get a largest reduced cost variable selector from a linear relaxation solver.

### Synopsis

```
procedure KALIS_LARGEST_REDUCED_COST(relaxationSolver:cplinrelaxsolver)
```

### Argument

`relaxationSolver` the linear relaxation solver

### Example

The following example shows how to use this function with a specific relaxation solver

```
cp_set_branching(assign_var(KALIS_LARGEST_REDUCED_COST(mysolver),
                 KALIS_NEAREST_RELAXED_VALUE(mysolver)))
```

### Related topics

`KALIS_NEAREST_RELAXED_VALUE` `cp_set_branching`

# KALIS_NEAREST_RELAXED_VALUE

### Purpose

Get a nearest relaxed value selector from a linear relaxation solver.

### Synopsis

```
procedure KALIS_NEAREST_RELAXED_VALUE(relaxationSolver:cplinrelaxsolver)
```

### Argument

`relaxationSolver` the linear relaxation solver

### Example

The following example shows how to use this function with a specific cplinrelaxsolver

```
cp_set_branching(assign_var(KALIS_LARGEST_REDUCED_COST(mysolver),
                 KALIS_NEAREST_RELAXED_VALUE(mysolver)))
```

### Related topics

`KALIS_LARGEST_REDUCED_COST` `cp_set_branching`

# cp_get_linrelax

### Purpose

Returns an automatic relaxation of the cp problem

### Synopsis

```
function cp_get_linrelax(orientation: integer) : cplinrelax
function cp_get_linrelax(orientation: integer,constraints: set of integer)
      : cplinrelax
```

### Arguments

| | |
|---|---|
| `orientation` | 0 for an 'LP oriented' relaxation (convex hull) and 1 for a 'MIP oriented' relaxation (can be an exact representation of the underlying CP problem) |
| `constraints` | the set of constraints types to relax (`KALIS_LINEAR_CONSTRAINTS`, `KALIS_LOGICAL_CONSTRAINTS`, `KALIS_DISTANCE_CONSTRAINTS`, `KALIS_NON_LINEAR_CONSTRAINTS`, `KALIS_ALL_CONSTRAINTS`) |

### Return value

A linear relaxation

### Example

The following example shows how to obtain a 'MIP oriented' relaxation by relaxing only the linear part of the problem and the logical constraints.

```
relax := cp_get_linrelax(1,{KALIS_LINEAR_CONSTRAINTS,
                            KALIS_LOGICAL_CONSTRAINTS})
```

### Related topics

`get_linrelax_solver` `cp_add_linrelax_solver`

# get_linrelax_solver

### Purpose

Returns a linear relaxation solver from a linear relaxation, an objective variables and some configuration parameters

### Synopsis

```
function get_linrelax_solver(linrelax:cplinrelax, objective:cpvar,
      sense:integer, solvingType:integer, before_event:proc,
      must_relax:proc, after_event:proc) : cplinrelaxsolver
function get_linrelax_solver(linrelax:cplinrelax, objective:cpfloatvar,
      sense:integer, solvingType:integer, before_event:proc,
      must_relax:proc, after_event:proc) : cplinrelaxsolver
function get_linrelax_solver(linrelax:cplinrelax, objective:cpvar,
      sense:integer, solvingType:integer, configuration:integer) :
      cplinrelaxsolver
function get_linrelax_solver(linrelax:cplinrelax, objective:cpfloatvar,
      sense:integer, solvingType:integer, configuration:integer) :
      cplinrelaxsolver
function get_linrelax_solver(linrelax:cplinrelax, objective:cpvar,
      sense:integer, solvingType:integer, cpvarsToBeInstantiated:set of
      cpvar, floatvarsToBeInstantiated:set of cpfloatvar) :
      cplinrelaxsolver
function get_linrelax_solver(linrelax:cplinrelax, objective:cpfloatvar,
      sense:integer, solvingType:integer, cpvarsToBeInstantiated:set of
      cpvar, floatvarsToBeInstantiated:set of cpfloatvar) :
      cplinrelaxsolver
```

### Arguments

| | |
|---|---|
| `relax` | the linear relaxation |
| `objective` | the objective variable |
| `sense` | `KALIS_MINIMIZE` for minimization or `KALIS_MAXIMIZE` for maximization |
| `solvingType` | `KALIS_SOLVE_AS_LP` or `KALIS_SOLVE_AS_MIP` |
| `before_event` | a user callback triggered before the relaxation is solved |
| `must_relax` | a user callback saying when to solve the relaxation |
| `after_relax` | a user callback triggered after the resolution of the relaxation |
| `configuration` | One of the three predefined configurations (`KALIS_TOPNODE_RELAX_SOLVER`, `KALIS_TREENODE_RELAX_SOLVER`, or `KALIS_BILEVEL_RELAX_SOLVER`) |
| `cpvarsToBeInstantiated` | the set of cpvar to be instantiated before the resolution of the relaxation for a KALIS_BILEVEL_RELAX_SOLVER |
| `floatvarsToBeInstantiated` | the set of cpfloatvar to be instantiated before the resolution of the relaxation for a KALIS_BILEVEL_RELAX_SOLVER |

### Return value

A linear relaxation solver

# fix_to_relaxed

### Purpose

This method can be called during the tree search process to instantiate all the continuous variables to their values in the optimal solution of a relaxation.

### Synopsis

```
procedure fix_to_relaxed(linrelaxSolver:cplinrelax)
```

### Argument

`linrelaxSolver` the linear relaxation solver

### Example

The following example shows how to use the fix_to_relaxed method.

```
fix_to_relaxed(linrelaxSolver)
```

### Related topics

`get_relaxed_value`

## set_verbose_level

### Purpose

Set the verbose level for a specific linear relaxation solver.

### Synopsis

```
procedure set_verbose_level(linrelaxSolver:cplinrelaxsolver,flag:boolean)
```

### Arguments

| | |
|---|---|
| `linrelaxSolver` | the linear relaxation solver |
| `flag` | value `true` or `false` to enable/disable output printing |

### Example

The following example shows how to use the set_verbose_level function.

```
set_verbose_level(linrelaxSolver,true)
```

### Related topics

`get_linrelax_solver`

## cp_show_relax

### Purpose

Pretty printing of the linear relaxation to the standard output.

### Synopsis

```
procedure cp_show_relax(relax:cplinrelax)
```

### Argument

`relax` the linear relaxation to be printed

### Example

The following example shows how to use the cp_show_relax method.

```
cp_show_relax(relax)
```

### Related topics

`cp_show_var` `cp_show_stats` `cp_show_prob`

## cp_add_linrelax_solver

### Purpose

Add a linear relaxation solver to the linear relaxation solver list.

### Synopsis

```
procedure cp_add_linrelax_solver(linrelaxSolver:cplinrelaxsolver)
```

### Argument

`linrelaxSolver` the linear relaxation solver to add

### Example

The following example shows how to use the cp_add_linrelax_solver function.

```
cp_add_linrelax_solver(mylinrelaxsolver)
```

### Related topics

`get_linrelax_solver` `cp_clear_linrelax_solver` `cp_remove_linrelax_solver`

## cp_remove_linrelax_solver

### Purpose

Remove a linear relaxation solver from the linear relaxation solver list.

### Synopsis

```
procedure cp_remove_linrelax_solver(linrelaxSolver:cplinrelaxsolver)
```

### Argument

`linrelaxSolver` the linear relaxation solver to remove

### Example

The following example shows how to use the cp_remove_linrelax_solver function.

```
cp_remove_linrelax_solver(linrelaxsolver)
```

### Related topics

`get_linrelax_solver` `cp_clear_linrelax_solver` `cp_add_linrelax_solver`

# cp_clear_linrelax_solver

### Purpose

Clear the linear relaxation solver list.

### Synopsis

```
procedure cp_clear_linrelax_solver
```

### Example

The following example shows how to use the cp_remove_linrelax_solver function.

```
cp_clear_linrelax_solver
```

### Related topics

`get_linrelax_solver` `cp_remove_linrelax_solver` `cp_add_linrelax_solver`

## generate_cuts

### Purpose

Generate and add cuts to the relaxation passed in parameters

### Synopsis

```
procedure generate_cuts(linrelaxsolver:cplinrelaxsolver,
      linrelax:cplinrelax)
```

### Arguments

| | |
|---|---|
| `linrelaxsolver` | a linear relaxation solver |
| `linrelax` | the linear relaxation to use |

### Related topics

`get_linrelax_solver` `cp_get_linrelax` `get_linrelax`

# lp_optimize

### Purpose

Launch optimization of the relaxation solver with the LP/MIP solver alone (no branching by Kalis).

### Synopsis

```
function lp_optimize(linrelaxsolver:cplinrelaxsolver, sense: integer, alg:
      integer) : integer
```

### Arguments

| | |
|---|---|
| `linrelaxsolver` | a linear relaxation solver |
| `sense` | `KALIS_MINIMIZE` for minimization or `KALIS_MAXIMIZE` for maximization |
| `alg` | solve as LP (`0`) or as MIP (`1`) |

### Related topics

`get_linrelax_solver` `cp_get_linrelax` `get_linrelax`

# set_linrelax_solver_attribute

### Purpose

Sets the value of the indicated control parameter of a linear relaxation solver.

### Synopsis

```
procedure set_linrelax_solver_attribute(linrelaxSolver:cplinrelaxsolver,
      param:integer, value:integer)
```

### Arguments

| | |
|---|---|
| `linrelaxSolver` | a linear relaxation solver |
| `param` | identifier of a solver parameter (`KALIS_RELAX_PRESOLVE`, `KALIS_RELAX_RCOSTS_PROPAG`, `KALIS_RELAX_RELOAD_BASIS`, `KALIS_RELAX_MIP`, `KALIS_RELAX_ALGORITHM`) |
| `value` | the value to be set (0 or 1 in most cases, values for `KALIS_RELAX_ALGORITHM`: `KALIS_PRIMAL_SIMPLEX`, `KALIS_DUAL_SIMPLEX`, `KALIS_BARRIER`, `KALIS_NETWORK_SIMPLEX`) |

### Example

The following example shows how to set the solution algorithm for a linear relaxation solver.

```
set_linrelax_solver_attribute(mysolver, KALIS_RELAX_ALGORITHM,
                              KALIS_PRIMAL_SIMPLEX)
```

### Related topics

`get_linrelax_solver` `cp_remove_linrelax_solver` `cp_add_linrelax_solver`

# get_indicator

### Purpose

Get a 0-1 valued cpauxvar indicating whether the variable is instantiated (1) or not (0) to the specified value.

### Synopsis

```
function get_indicator(var:cpvar,i:integer) : cpauxvar
```

### Arguments

`var` the variable

`i` the value

### Return value

An auxiliary relaxation variable

### Example

The following example shows how to use the get_indicator function.

```
indvar:= get_indicator(var,i)
```

# get_linrelax

### Purpose

Get the linear relaxation for a constraint.

### Synopsis

```
function get_linrelax(ctr:cpctr, orientation:integer) : cplinrelax
```

### Arguments

| | |
|---|---|
| `ctr` | the constraint to relax |
| `orientation` | 0 for a 'LP oriented' relaxation and 1 for a 'MIP oriented' one |

### Return value

A linear relaxation

### Example

The following example shows how to get a 'MIP oriented' linear relaxation of a constraint 'ctr'.

```
get_linrelax(ctr,1)
```

### Related topics

`cp_get_linrelax`

## export_prob

### Purpose

Export the linear program from a linear relaxation solver to a text file in LP format.

### Synopsis

```
procedure export_prob(linrelaxsolver:cplinrelaxsolver, name:string)
```

### Arguments

| | |
|---|---|
| `linrelaxsolver` | the linear relaxation solver |
| `name` | a file name |

### Example

The following example shows how to use the export_prob function.

```
export_prob(mylinrelaxsolver, "mymatout")
```

### Related topics

`cp_get_linrelax` `get_linrelax_solver` `get_linrelax`

# get_reduced_cost

### Purpose

Get the reduced cost for a variable from a linear relaxation solver

### Synopsis

```
function get_reduced_cost(linsolver:cplinrelaxsolver, var:cpvar) : real
function get_reduced_cost(linsolver:cplinrelaxsolver, var:cpfloatvar) :
      real
```

### Arguments

| | |
|---|---|
| `linsolver` | the linear relaxation solver |
| `var` | a CP variable |

### Return value

The reduced cost value

### Example

The following example shows how to use the get_reduced_cost function.

```
rc := get_reduced_cost(linsolver, x)
```

### Related topics

`get_relaxed_value` `get_linrelax` `set_integer`

# get_relaxed_value

### Purpose

Returns the optimal relaxed value for a variable in a relaxation.

### Synopsis

```
function get_relaxed_value(linsolver:cplinrelaxsolver, var:cpvar) : real
function get_relaxed_value(linsolver:cplinrelaxsolver, var:cpfloatvar) :
      real
```

### Arguments

| | |
|---|---|
| `linsolver` | the linear relaxation solver |
| `var` | a CP variable |

### Return value

The relaxation solution value

### Example

The following example shows how to use the get_relaxed_value function.

```
rv := get_relaxed_value(linsolver, x)
```

### Related topics

`get_reduced_cost` `get_linrelax` `set_integer`

## set_integer

### Purpose

This method turns a variable into an integer variable in a linear relaxation.

### Synopsis

```
procedure set_integer(relax:cplinrelax, var:cpauxvar, ifmip:boolean)
procedure set_integer(relax:cplinrelax, var:cpvar, ifmip:boolean)
```

### Arguments

| | |
|---|---|
| `relax` | a linear relaxation |
| `var` | a relaxation variable |
| `ifmip` | `true` for a discrete variable, `false` otherwise |

### Example

The following example shows how to use the set_integer routine.

```
set_integer(myrelax, xaux, true)
```

### Related topics

`get_relaxed_value` `get_reduced_cost` `get_linrelax`

Appendix A

# Contacting FICO

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# Index


**A**
abs, 77
addpredecessors, 222
addsuccessors, 224
all_different, 78
and, 66
arity, 1
assign_and_forbid, 173
assign_var, 170
automatic relaxation, 21

**B**
benders decomposition, 24
branching
    relaxation, 24
branching scheme, 9
bs_group, 198

**C**
constraint graph, 1
Constraint Programming, 1
constraint propagation, 2
constraint satisfaction problem, 1
consumes, 241
contains, 128
CP, *see* Constraint Programming
cp_add_linrelax_solver, 276
cp_clear_linrelax_solver, 278
cp_close_schedule, 267
cp_find_next_sol, 142
cp_get_backtracks, 193
cp_get_computation_time, 190
cp_get_default_schedule_strategy, 257
cp_get_depth, 192
cp_get_linrelax, 271
cp_get_nb_solutions, 189
cp_get_number_of_nodes, 191
cp_get_total_backtracks, 197
cp_get_total_computation_time, 194
cp_get_total_depth, 196
cp_get_total_number_of_nodes, 195
cp_infeas_analysis, 156
cp_local_optimize, 160
cp_maximise, 144
cp_maximize, 145
cp_minimise, 146
cp_minimize, 147
cp_post, 140
cp_print_stats, 188
cp_propagate, 141
cp_remove_linrelax_solver, 277
cp_reset_params, 162
cp_reset_search, 143
cp_restore_state, 158
cp_save_state, 157
cp_schedule, 239
cp_set_branch_callback, 208
cp_set_branching, 186
cp_set_node_callback, 207
cp_set_schedule_strategy, 256
cp_set_solution_callback, 204
cp_shave, 155
cp_show_best_sol, 151
cp_show_prob, 149
cp_show_relax, 275
cp_show_schedule, 226
cp_show_sol, 150
cp_show_stats, 187
cp_show_var, 137
cp_show_var_constraints, 138
cpauxvar, 22
cpctr, 7
cpfloatvar, 5
cplinctr, 64
cpnlinctr, 72
cpresource, 14
cptask, 14
cpvar, 5
create, 6, 17
CSP, *see* constraint satisfaction problem
cumulative, 101
cycle, 80

**D**
disjunction selection heuristic, 12
disjunctive, 103
distance, 76
distribute, 99
domain, 1
dot, 71

**E**
Earliest Completion Time, 15
Earliest Start Time, 15
ECT, *see* Earliest Completion Time
element, 89
equiv, 68
EST, *see* Earliest Start Time
exp, 75
export_prob, 284

**F**
fix_to_relaxed, 273

**G**
generate_cuts, 279
generic_binary_constraint, 91
generic_nary_constraint, 93
get_earliest_start_possible, 261
get_indicator, 282
get_linrelax, 283
get_linrelax_solver, 272
get_reduced_cost, 285
get_relaxed_value, 286
get_start_based_duration, 215
getactivebranch, 115
getarity, 109
getassignment, 262
getcapacity, 252
getconsumption, 230
getdegree, 123
getduration, 229
getelt, 167
getend, 228
getindex, 154
getlb, 117
getmakespan, 240
getmiddle, 119
getname, 152
getnext, 126
getprev, 127
getpriority, 110
getproduction, 233
getprovision, 234
getrand, 125
getrequirement, 232
getsetuptime, 254
getsize, 120, 168
getsol, 148
getstart, 227
gettag, 112, 202
gettarget, 124
getub, 118
getval, 121, 165
group_serializer, 199

**H**
has_assignment, 264
hybrid model, 25

**I**
implies, 70
indicator variable, 22
is_consuming, 235
is_equal, 129
is_fixed, 122, 211, 255
is_idletime, 266
is_producing, 237
is_providing, 238
is_requiring, 236
is_same, 130

**K**
KALIS_ALL_CONSTRAINTS, 49
KALIS_AUTO_PROPAGATE, 55
KALIS_AUTO_RELAX, 61
KALIS_BACKTRACKS, 56
KALIS_BARRIER, 53
KALIS_BILEVEL_RELAX_SOLVER, 48
KALIS_CHECK_SOLUTION, 59
KALIS_COMPUTATION_TIME, 57
KALIS_COPYRIGHT, 39
KALIS_DEFAULT_CONTINUOUS_LB, 59
KALIS_DEFAULT_CONTINUOUS_UB, 59
KALIS_DEFAULT_LB, 55
KALIS_DEFAULT_PRECISION_RELATIVITY, 60
KALIS_DEFAULT_PRECISION_VALUE, 60
KALIS_DEFAULT_SCHEDULE_HORIZ_MAX, 60
KALIS_DEFAULT_SCHEDULE_HORIZ_MIN, 60
KALIS_DEFAULT_UB, 55
KALIS_DEPTH, 56
KALIS_DICHOTOMIC_OBJ_SEARCH, 60
KALIS_DISCRETE_RESOURCE, 40
KALIS_DISJ_INPUT_ORDER, 43
KALIS_DISJ_PRIORITY_ORDER, 43
KALIS_DISJUNCTIONS, 44
KALIS_DISTANCE_CONSTRAINTS, 49
KALIS_DUAL_SIMPLEX, 53
KALIS_EDGE_FINDING, 44
KALIS_FORWARD_CHECKING, 32
KALIS_GEN_ARC_CONSISTENCY, 32
KALIS_INITIAL_SOLUTION, 44
KALIS_INPUT_ORDER, 34
KALIS_LARGEST_ECT, 41
KALIS_LARGEST_EST, 41
KALIS_LARGEST_LCT, 42
KALIS_LARGEST_LST, 42
KALIS_LARGEST_MAX, 35
KALIS_LARGEST_MIN, 35
KALIS_LARGEST_REDUCED_COST, 269
KALIS_LINEAR_CONSTRAINTS, 48
KALIS_LOGICAL_CONSTRAINTS, 49
KALIS_MAX_BACKTRACKS, 58
KALIS_MAX_COMPUTATION_TIME, 58
KALIS_MAX_DEGREE, 35
KALIS_MAX_DEPTH, 57
KALIS_MAX_MIN_BOUND_CONSISTENCY, 47
KALIS_MAX_NODES, 57
KALIS_MAX_NODES_BETWEEN_SOLUTIONS, 58
KALIS_MAX_SOLUTIONS, 57
KALIS_MAX_TO_MIN, 38
KALIS_MAXIMIZE, 50
KALIS_MAXREGRET_LB, 36
KALIS_MAXREGRET_UB, 36
KALIS_MIDDLE_VALUE, 38
KALIS_MIN_TO_MAX, 38
KALIS_MINIMIZE, 50
KALIS_NARY_OBJ_SEARCH, 62
KALIS_NB_SOLUTIONS, 47
KALIS_NEAREST_RELAXED_VALUE, 270
KALIS_NEAREST_VALUE, 39
KALIS_NETWORK_SIMPLEX, 53
KALIS_NODES, 56
KALIS_NON_LINEAR_CONSTRAINTS, 49

KALIS_OPT_ABS_TOLERANCE, 58
KALIS_OPT_REL_TOLERANCE, 59
KALIS_OPTIMAL_SOLUTION, 45
KALIS_OPTIMIZE_WITH_RESTART, 55
KALIS_PRIMAL_SIMPLEX, 52
KALIS_RANDOM_SEED, 39
KALIS_RANDOM_VALUE, 39
KALIS_RANDOM_VARIABLE, 36
KALIS_RELAX_ALGORITHM, 51
KALIS_RELAX_MIP, 51
KALIS_RELAX_MIP_ABS_STOP, 52
KALIS_RELAX_MIP_REL_STOP, 52
KALIS_RELAX_OPT_TOL, 52
KALIS_RELAX_PRESOLVE, 50
KALIS_RELAX_RCOSTS_PROPAG, 51
KALIS_RELAX_RELOAD_BASIS, 51
KALIS_RESET_OPT_PARAMS, 46
KALIS_RESET_PARAMS_ALL, 45
KALIS_RESET_SEARCH_PARAMS, 47
KALIS_RESET_VAR_BOUNDS, 46
KALIS_RESET_VAR_PRECISION, 46
KALIS_SCHEDULE_ENABLE_SHAVING, 62
KALIS_SDOMDEG_RATIO, 36
KALIS_SEARCH_LIMIT, 56
KALIS_SLIM_BY_BACKTRACKS, 33
KALIS_SLIM_BY_DEPTH, 33
KALIS_SLIM_BY_NODES, 32
KALIS_SLIM_BY_SOLUTIONS, 33
KALIS_SLIM_BY_TIME, 33
KALIS_SLIM_UNREACHED, 32
KALIS_SMALLEST_DOMAIN, 37
KALIS_SMALLEST_ECT, 40
KALIS_SMALLEST_EST, 40
KALIS_SMALLEST_LCT, 41
KALIS_SMALLEST_LST, 41
KALIS_SMALLEST_MAX, 37
KALIS_SMALLEST_MIN, 37
KALIS_SOLVE_AS_LP, 50
KALIS_SOLVE_AS_MIP, 50
KALIS_TASK_INPUT_ORDER, 42
KALIS_TASK_INTERVALS, 43
KALIS_TASK_RANDOM_ORDER, 42
KALIS_TASK_VARIABLES_DOMAIN_TYPE, 47
KALIS_THREADS, 61
KALIS_TIMETABLING, 43
KALIS_TLIM_ABS_OPT, 34
KALIS_TLIM_REL_OPT, 34
KALIS_TLIM_UNREACHED, 34
KALIS_TOLERANCE_LIMIT, 56
KALIS_TOPNODE_RELAX_SOLVER, 48
KALIS_TREENODE_RELAX_SOLVER, 48
KALIS_UNARY_RESOURCE, 40
KALIS_USE_3B_CONSISTENCY, 61
KALIS_VERBOSE_LEVEL, 61
KALIS_WIDEST_DOMAIN, 38

**L**
Latest Completion Time, 15
Latest Start Time, 15
LCT, *see* Latest Completion Time
linear relaxation, 22
    branching, 24
ln, 74
lp_optimize, 280
LST, *see* Latest Start Time

**M**
Mathematical Programming, 21
maximum, 85
meta branching scheme, 199
minimum, 85

**O**
occurrence, 87
optimization, 12
or, 67

**P**
path_order, 159
probe_assign_var, 176
probe_settle_disjunction, 177
producer_consumer, 105
produces, 245
provides, 246

**R**
relaxation variable, 22
requires, 244
resusage, 258

**S**
search techniques, 2
set_duration_with_idle_times, 216
set_integer, 287
set_linrelax_solver_attribute, 281
set_resource_attributes, 247
set_reversible_attributes, 163
set_sol_as_target, 161
set_start_based_duration, 214
set_task_attributes, 212
set_verbose_level, 274
setcapacity, 248
setdomain, 132
setduration, 213
setelt, 166
setfirstbranch, 114
setidletimes, 265
setlb, 133
setmaxavailability, 250
setminusage, 251
setname, 153
setprecision, 136
setpredecessors, 223
setpriority, 111
setsetuptime, 253
setsuccessors, 225
settag, 113
settarget, 131
settle_disjunction, 174
setub, 134
setval, 135, 164

solution, 1
`split_domain`, 179

**T**
`table_constraint`, 96
`task_serialize`, 181
tree search, 2

**U**
`update_duration_with_idle_times`, 218

**V**
value selection heuristic, 12
variable selection heuristic, 11