Lecture 12

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Boolean Constraint Propagation

Unit resolution rule:

$$\frac{C, \neg\ell \qquad \ell}{C}$$

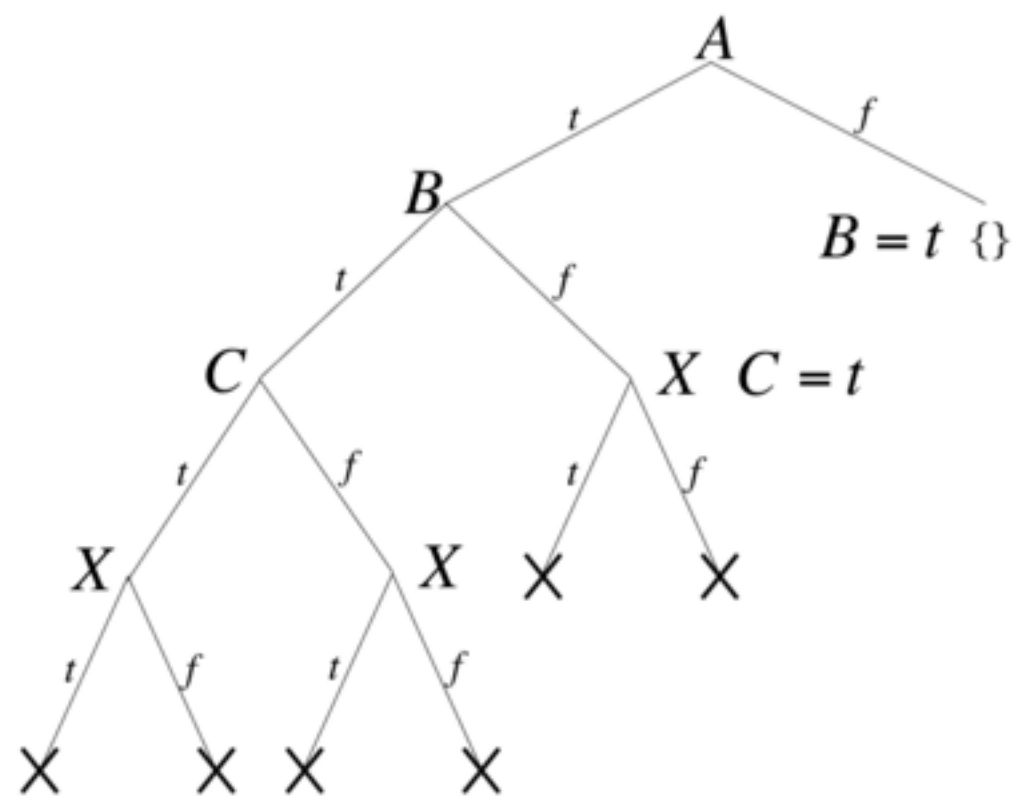
- BCP: given a set of clauses including $\{\ell\}$
  - remove all other clauses containing ℓ (subsumption)
  - remove all occurrences of $\neg\ell$ in clauses (unit resolution)
  - repeat until a fixpoint is reached

DPLL SAT Algorithm

- BCP
- Base case: empty clause: UNSAT
- Remove clauses containing pure literals (modern solvers don't do this)
- Base case: no clauses: SAT
- Choose some var, say x
  (if removing pure literals, x has to appear in both phases)
  - Add {x} and recursively call DPLL
  - Add {¬x} and recursively call DPLL
  - If one of the calls returns SAT, return SAT
  - Else return UNSAT
- Correctness follows from Shannon expansion
- In contrast to DP, space is not a problem

DPLL SAT Example

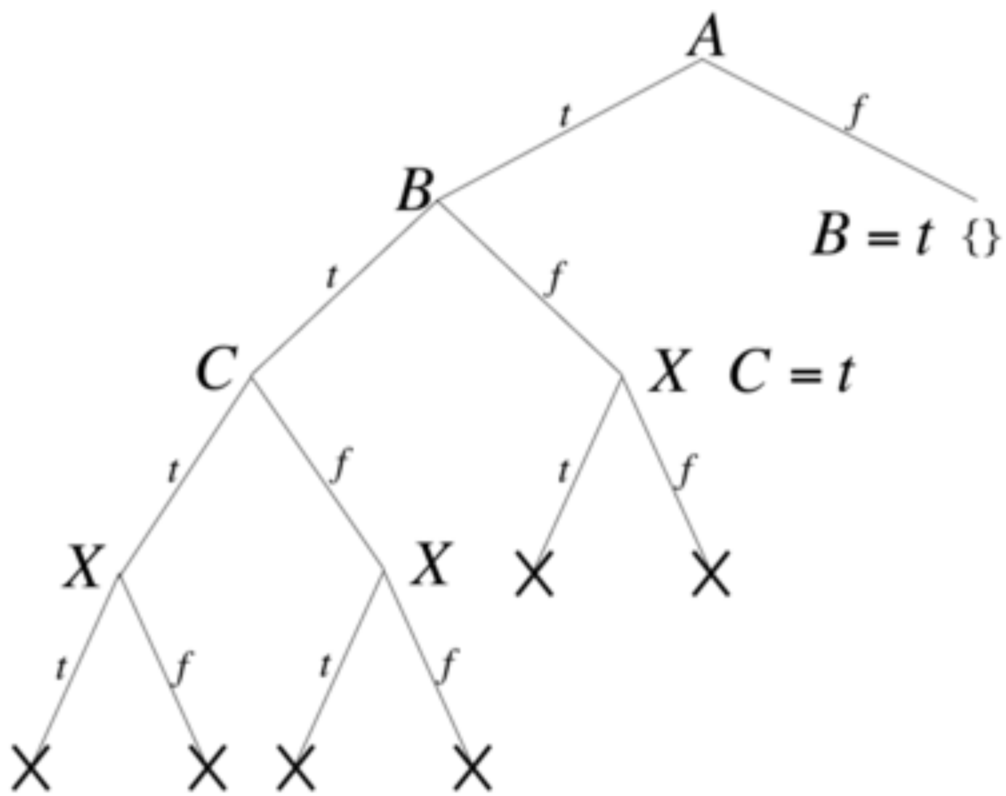
$$\Delta = \begin{array}{l} 1.\ \{A, B\} \\ 2.\ \{B, C\} \\ 3.\ \{\neg A, \neg X, Y\} \\ 4.\ \{\neg A, X, Z\} \\ 5.\ \{\neg A, \neg Y, Z\} \\ 6.\ \{\neg A, X, \neg Z\} \\ 7.\ \{\neg A, \neg Y, \neg Z\} \end{array}$$



- Note that when DPLL detects contradictions it backtracks chronologically
- When we get a contradiction with X, we try ¬X, then we go back and try ¬C and X, ¬X again, …
- But the real problem was that we set A; can we avoid this exponential search?
- Yes: non-chronological backtracking, a major improvement

Examples/figures from chp. 3 SAT handbook: pure literals not removed

Implication Graphs



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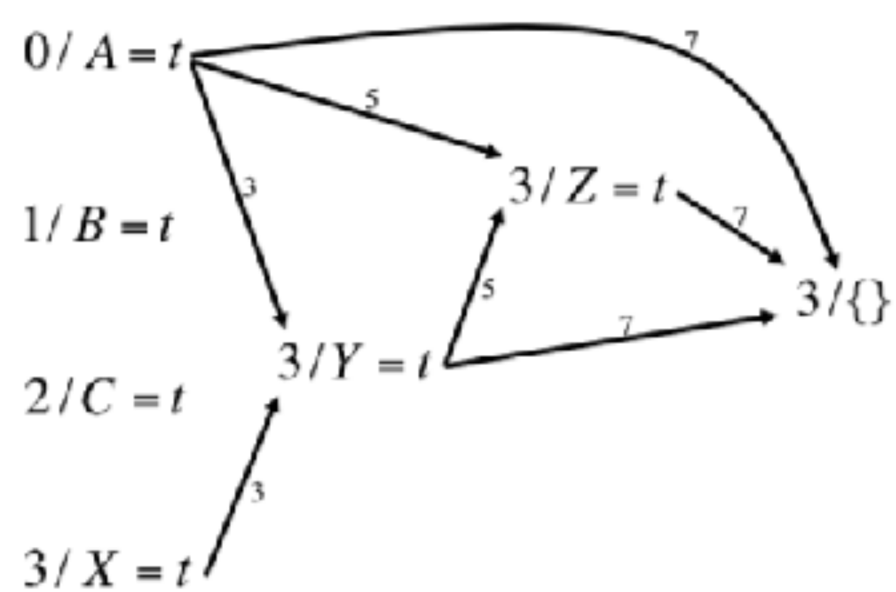
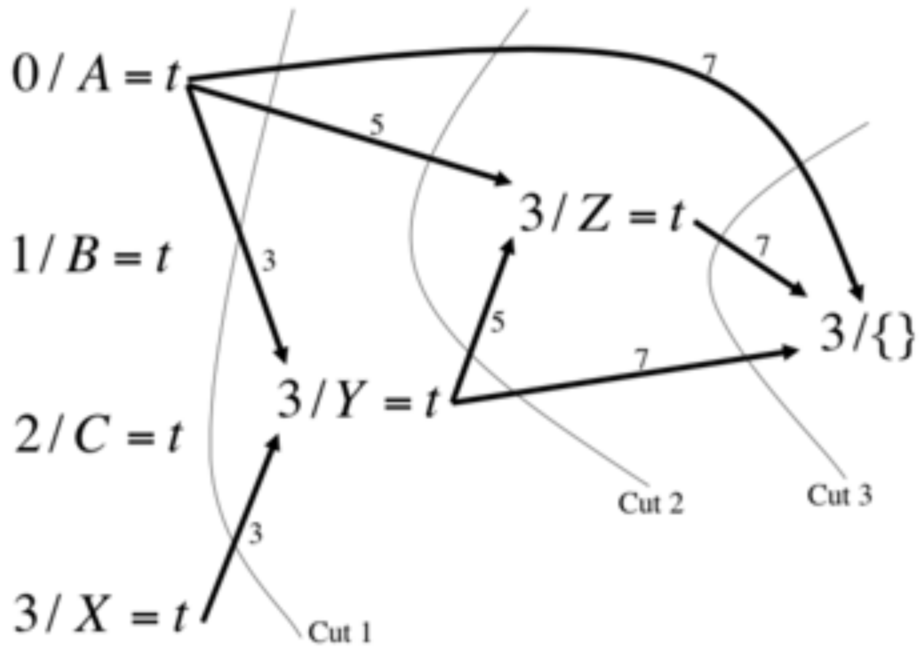


- Nodes are l/V=v: var V set to v @ level l
- If node implied, justification recorded (clause #, edges from assignments)
- {} denotes contradiction

Conflict-Driven Clauses



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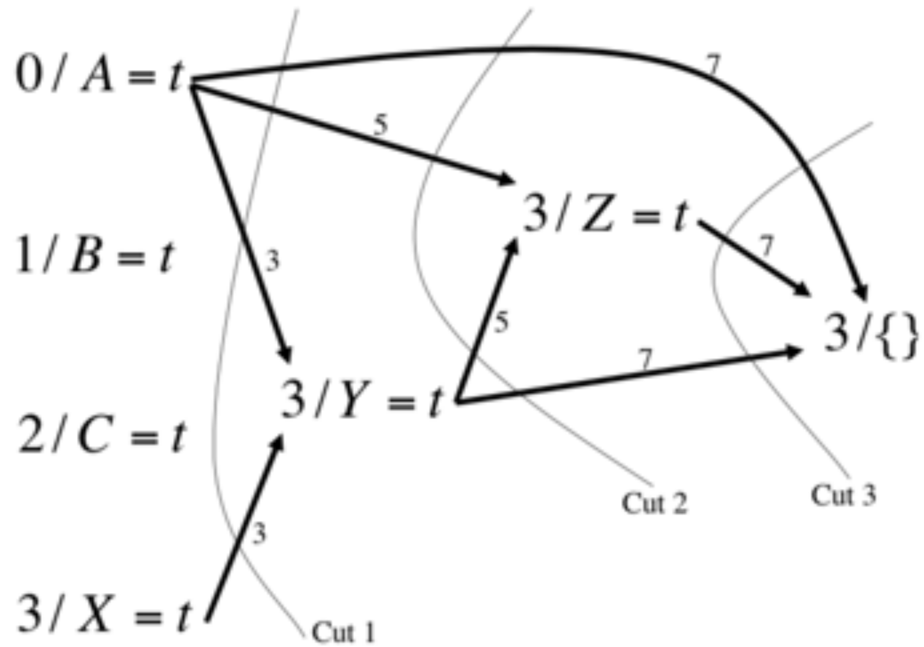
- Consider any cut of the implication graph that separates decision vars from {}
- The nodes with an edge that crosses the cut are in conflict set
- Negate the assignments in the set to obtain a conflict-driven clause
- Conflict clauses: Cut1: {¬A,¬X}, Cut2: {¬A, ¬Y}, Cut3: {¬A, ¬Z, ¬Y}
- Conflict–driven clauses generated from cuts that contain exactly one variable assigned at the level of conflict are said to be asserting: Cut1 & Cut2 (not Cut 3)

Non-Chronological Backtracking



$\Delta =$
1. $\{A, B\}$
2. $\{B, C\}$
3. $\{\neg A, \neg X, Y\}$
4. $\{\neg A, X, Z\}$
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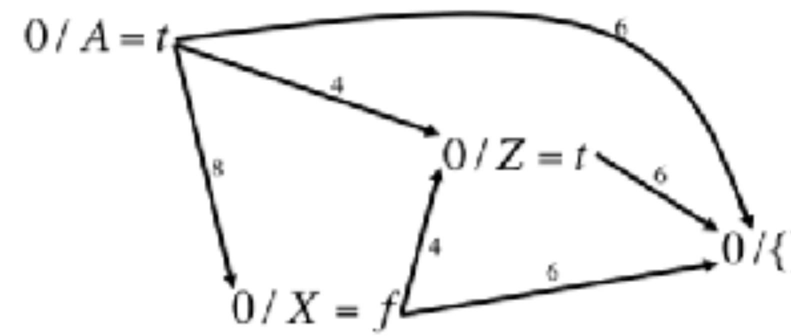


- Asserting conflict clauses: Cut1: 8. {¬A,¬X}, Cut2: {¬A, ¬Y}
- Assertion level: 2nd highest level in asserting clause (0 for cuts 1, 2) or -1
- Backtrack to assertion level and add a learned clause (non-chronological!)
- We can now immediately infer (BCP) ¬X (we use Cut1), so we have A, ¬X
- Then by BCP: Z (4), ¬Z (6) so we get a new implication graph
- Asserting clauses: {¬A} at level -1, so we have ¬A, BCP: B and we're done
- Compare to previous search, where the algorithm had to go back a level at a time
- Clause learning can generate exponentially shorter proofs of unsat!

Modern CDCL Solvers

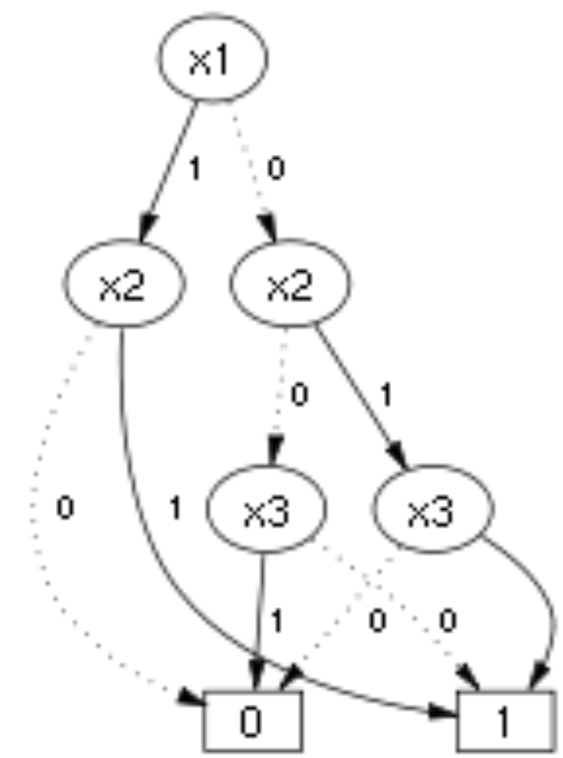
- Based on DPLL, but with conflict-driven clause learning
- Data structures to speed up BCP: 2-watched literal scheme
- Data structures for clause learning
- Decision heuristics: select recently active literals (VSIDS)
- Preprocessing: greedy variable elimination
- Inprocessing: interleave preprocessing & search
- Clause deletion: learned clauses lead to memory & efficiency problems, so delete large, inactive clauses
- Random restarts: keep learned clauses, but restart
  - avoids getting stuck in hard part of search space
  - phase saving: pick last phase of assignment

DIMACS Format

- Modern SAT solvers accept input in CNF
  - Dimacs format:
  - 1 -3 4 5 0
  - 2 -4 7 0
  - …

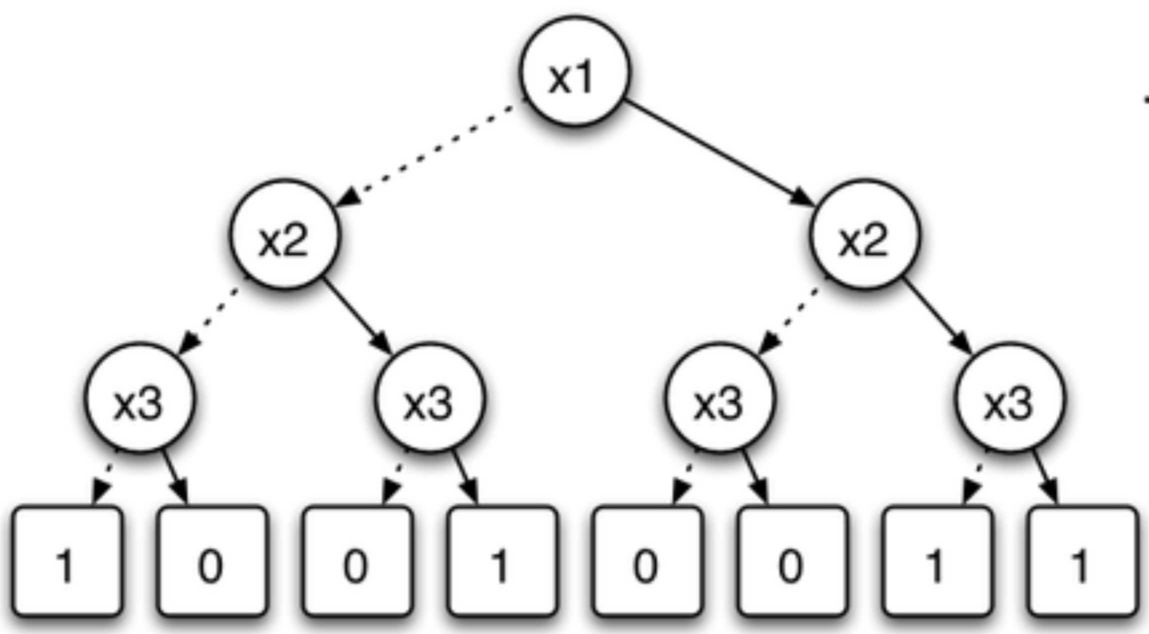
BDDs and Decision Trees

- A BDD on $x_1, \ldots, x_n$ is a DAG $G=(V, E)$ where
  - exactly 1 vertex has indegree 0 (the root)
  - all vertices have outdegree 0 (leaves) or 2 (inner nodes)
  - the inner nodes are labeled from $\{x_1, \ldots, x_n\}$
  - the leaves are labeled from $\{0, 1\}$
  - one of the edges from an inner node is labeled by 0; the other by 1
- The BDD $G=(V, E)$ represents a Boolean function, say f
  - for any assignment A in B^n, f(A) is computed recursively from root
  - if we reach a leaf, return the label
  - for inner nodes, say labeled with x_i, take the edge labeled by $A(x_i)$
- A decision tree is a BDD whose graph is a tree
- A BDD is an OBDD if there is a permutation on $p=\{1,2, \ldots, n\}$ s.t. for all edges (u, v) in E, where u, v are labeled by x_i, x_j, we have that $p_i < p_j$
- An OBDD is an ROBDD if it has no isomorphic subgraphs and all children are distinct

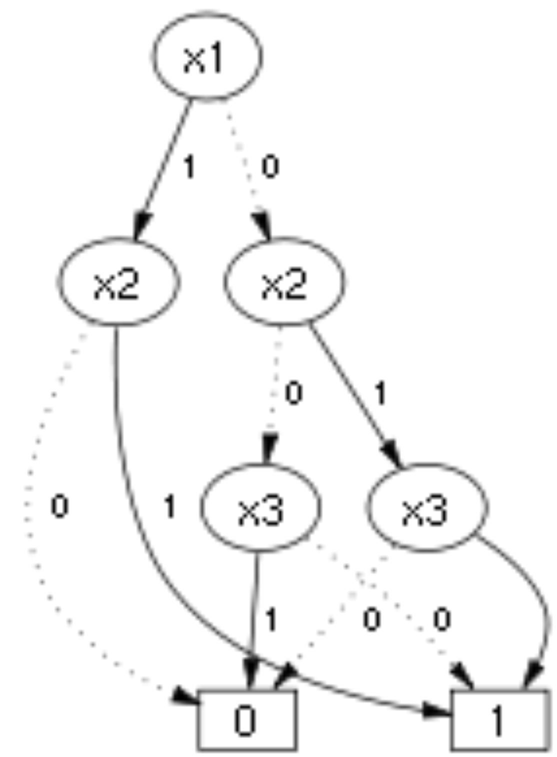


Images from Wikipedia

BDDs and Decision Trees



x1	x2	x3	*f*
0	0	0	1
0	0	1	0
0	1	0	0
0	1	1	1
1	0	0	0
1	0	1	0
1	1	0	1
1	1	1	1



Decision Tree for f

ROBDD for f

How do we generate DNF from a decision tree? ROBDD?

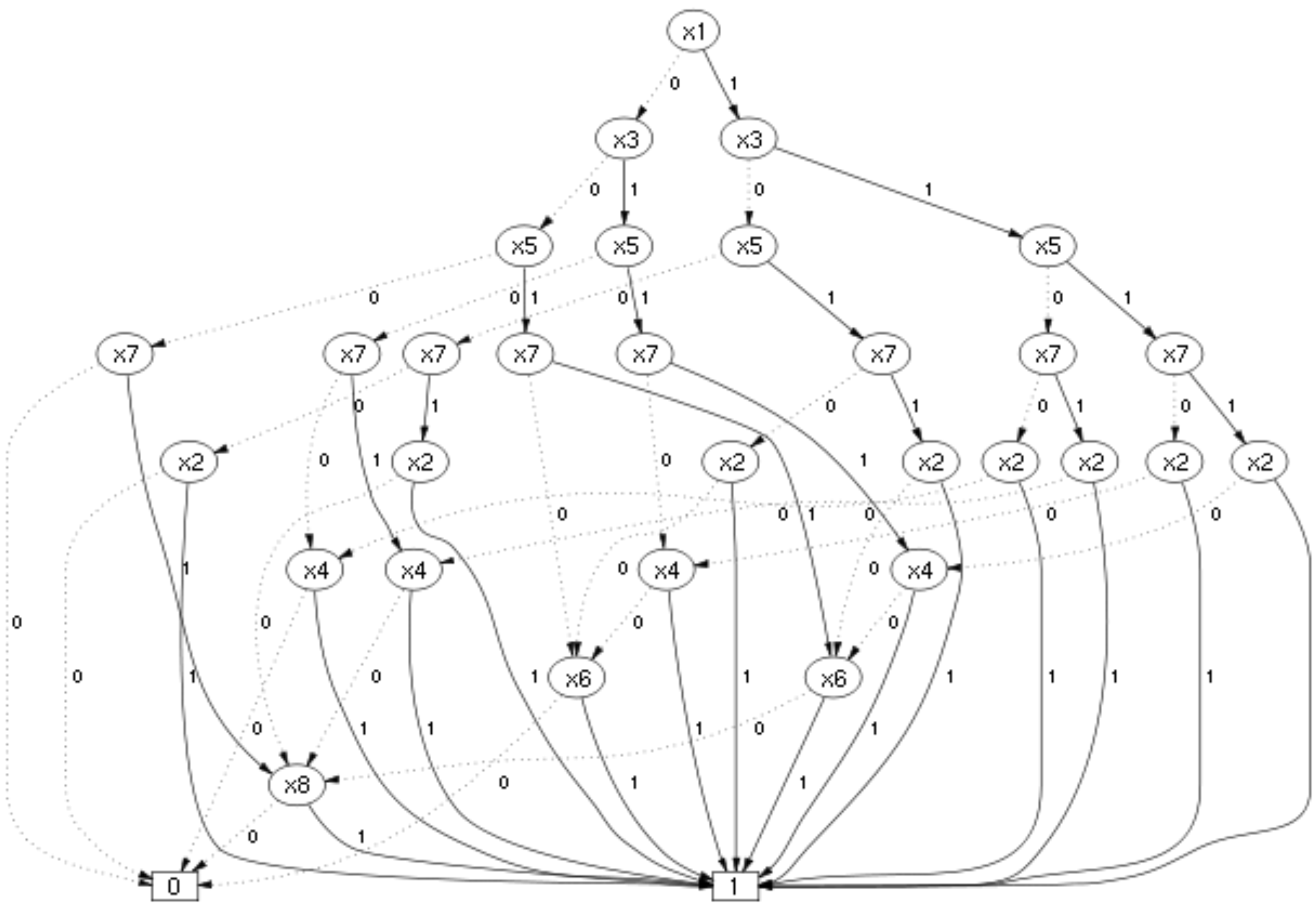
Images from Wikipedia

BDDs

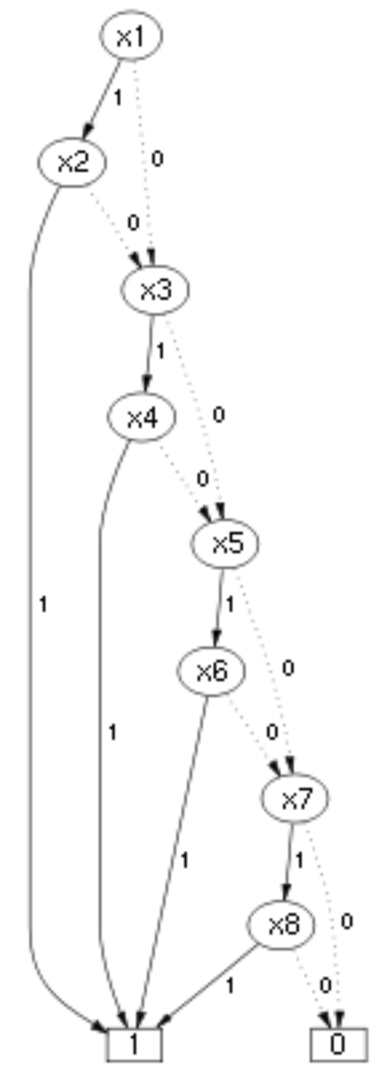
- Decision trees are widely used, e.g., in machine learning (ID3, C4.5, …)
- BDDs are widely used (BDD usually means ROBDD)
  - Popularized by Bryant
  - Very efficient algorithms for constructing, manipulating BDDs
  - Used in verification, synthesis, fault trees, security, AI, model checking, static analysis, …
  - Bryant's paper was the most cited research paper (at some point)
  - Many BDD packages available
- Once a variable ordering is selected, BDDs are canonical!
  - Construct decision tree using Shannon expansion and merge isomorphic nodes, remove nodes who children are equal until you reach a fixpoint
  - To see, this note that BDDs are essentially DFAs that recognize strings in $\{0,1\}^n$ and such automata can be minimized (note nodes with equal children remain)
  - So, checking equality is just pointer equality (with appropriate data structures)
  - Can be used for model checking: represent set of reachable states & transition system with BDDs

Variable Ordering for BDDs

Variable ordering matters: finding the best ordering is hard.



Bad Ordering



Good Ordering

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