Deciding Non-linear Numerical Constraints: an Overview

Stefan Ratschan

Academy of Sciences of the Czech Republic

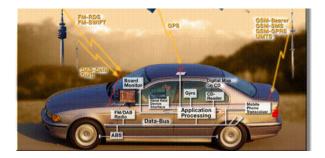
January 30, 2010

◆□ > ◆□ > ◆三 > ◆三 > ・三 のへで

1/21

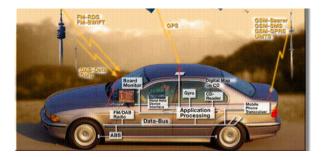
Motivation I

By far most micro-processors nowadays do not occur in desktop PC's but embedded in technical systems (trains, cars, robots, your washing machine etc.)



Motivation I

By far most micro-processors nowadays do not occur in desktop PC's but embedded in technical systems (trains, cars, robots, your washing machine etc.)



Models of technical systems usually in numerical domains.

Motivation II

Continuous is simpler then discrete!

Motivation II

Continuous is simpler then discrete!

	integers	reals
		polynomial time
sat. of polynomial constraints	undecidable	decidable

Motivation II

Continuous is simpler then discrete!

	integers	reals
sat. of linear constraints	NP-hard	polynomial time
sat. of polynomial constraints	undecidable	decidable

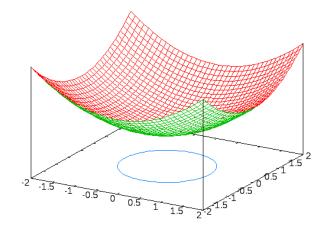
So: to solve discrete problem,

exploit corresponding continuous problem ("relaxation").

Example: MILP

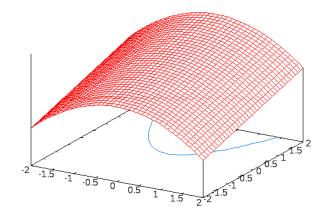
$$x^2 + y^2 - 1 = 0 \land y - x^2 = 0$$

Example $x^2 + y^2 - 1 = 0 \wedge y - x^2 = 0$



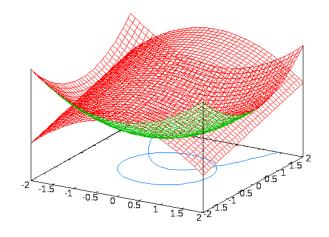
(ロ)、(部)、(目)、(目)、目)、(2)、(2)、(4)(2)
(4)(2)

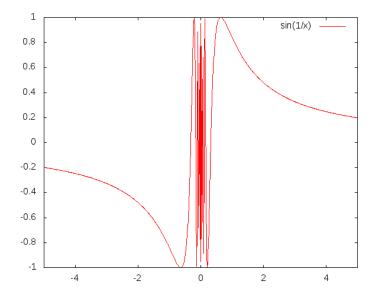
$$x^2 + y^2 - 1 = 0 \land y - x^2 = 0$$



(ロ)
(日)

$$x^2 + y^2 - 1 = 0 \land y - x^2 = 0$$





◆□ → < 団 → < 目 → < 目 → < 目 → ○ Q ペ 5/21

Problem Definition

Given: formula in certain sub-class of $FO(\mathbb{R}, =, \leq, <, +, \times, \sin, ...)$ Decide: sat/unsat Given: formula in certain sub-class of $FO(\mathbb{R}, =, \leq, <, +, \times, \sin, ...)$ Decide: sat/unsat + certificate (if possible) Given: formula in certain sub-class of $FO(\mathbb{R}, =, \leq, <, +, \times, \sin, ...)$ Decide: sat/unsat + certificate (if possible) Subclasses: quantifier-free, polynomial, linear, ...

Contents

- Certificates
- Decidability and Complexity
- Let's solve undecidable problems!

Quantifier-free case: (e.g., $x^2 = 2$)

Quantifier-free case: (e.g., $x^2 = 2$)

Certificate: satisfying valuation (solution)

Quantifier-free case: (e.g., $x^2 = 2$)

Certificate: satisfying valuation (solution)

But: how to represent solution?

Quantifier-free case: (e.g., $x^2 = 2$)

Certificate: satisfying valuation (solution)

But: how to represent solution?

Linear case: rational number (e.g., 3x = 2 $x \mapsto \frac{2}{3}$)

Quantifier-free case: (e.g., $x^2 = 2$)

Certificate: satisfying valuation (solution)

But: how to represent solution?

Linear case: rational number (e.g., 3x = 2 $x \mapsto \frac{2}{3}$)

Polynomial case:

- in general, no expression in terms of roots (Abel-Ruffini theorem),
- real algebraic numbers (unintuitive, inefficient [Roy and Szpirglas, 1990]), x < y?

Quantifier-free case: (e.g., $x^2 = 2$)

Certificate: satisfying valuation (solution)

But: how to represent solution?

Linear case: rational number (e.g., 3x = 2 $x \mapsto \frac{2}{3}$)

Polynomial case:

- in general, no expression in terms of roots (Abel-Ruffini theorem),
- real algebraic numbers (unintuitive, inefficient [Roy and Szpirglas, 1990]), x < y?

In general: (arbitrary precise) approximation

Quantifier-free case: (e.g., $x^2 = 2$)

Certificate: satisfying valuation (solution)

But: how to represent solution?

Linear case: rational number (e.g., 3x = 2 $x \mapsto \frac{2}{3}$)

Polynomial case:

- in general, no expression in terms of roots (Abel-Ruffini theorem),
- real algebraic numbers (unintuitive, inefficient [Roy and Szpirglas, 1990]), x < y?

In general: (arbitrary precise) approximation $5 \mapsto 4.6557...$

Example: p(x) < 0

Example: p(x) < 0, certificate: polynomial q s.t. $q^2 = p$

Example: p(x) < 0, certificate: polynomial q s.t. $q^2 = p$ Works always? Can be generalized?

Example: p(x) < 0, certificate: polynomial q s.t. $q^2 = p$

Works always? Can be generalized?

Solution to Hilbert's 17th problem:

Every polynomial that is non-negative on \mathbb{R}^n is a sum of squares of rational functions [Artin, 1927]

Example: p(x) < 0, certificate: polynomial q s.t. $q^2 = p$

Works always? Can be generalized?

Solution to Hilbert's 17th problem: Every polynomial that is non-negative on \mathbb{R}^n is

a sum of squares of rational functions [Artin, 1927]

Sums of squares of polynomials do not suffice?

Example: p(x) < 0, certificate: polynomial q s.t. $q^2 = p$

Works always? Can be generalized?

Solution to Hilbert's 17th problem: Every polynomial that is non-negative on \mathbb{R}^n is a sum of squares of rational functions [Artin, 1927]

Sums of squares of polynomials do not suffice?

No: Motzkin form $1 + x^4y^2 + x^2y^4 - 3x^2y^2$

Example: p(x) < 0, certificate: polynomial q s.t. $q^2 = p$

Works always? Can be generalized?

Solution to Hilbert's 17th problem: Every polynomial that is non-negative on \mathbb{R}^n is a sum of squares of rational functions [Artin, 1927]

Sums of squares of polynomials do not suffice?

No: Motzkin form $1 + x^4y^2 + x^2y^4 - 3x^2y^2$

However: all univariate polynomials, and all polynomials with degree up to 2 can be written as SOS

 $f_1(x) = 0, \ldots, f_r(x) = 0$ does not have a solution iff there exist

- polynomials a_1, \ldots, a_r , and
- sums of squares of polynomials d,

such that

$$\sum_i a_i f_i + d + 1$$

is the polynomial 0.

 $f_1(x) = 0, \ldots, f_r(x) = 0$ does not have a solution iff there exist

- polynomials a_1, \ldots, a_r , and
- sums of squares of polynomials d,

such that

$$\sum_i a_i f_i + d + 1$$

is the polynomial 0.

for a given solution, the expression cannot be zero

 $f_1(x) = 0, \ldots, f_r(x) = 0$ does not have a solution iff there exist

- polynomials a_1, \ldots, a_r , and
- sums of squares of polynomials d,

such that

$$\sum_i a_i f_i + d + 1$$

is the polynomial 0.

for a given solution, the expression cannot be zero

 $f_1(x) = 0, \ldots, f_r(x) = 0$ does not have a solution iff there exist

- polynomials a_1, \ldots, a_r , and
- sums of squares of polynomials d,

such that

$$\sum_i a_i f_i + d + 1$$

is the polynomial 0.

for a given solution, the expression cannot be zero

Example: $f_0 \equiv 1$:

 $f_1(x) = 0, \ldots, f_r(x) = 0$ does not have a solution iff there exist

- polynomials a_1, \ldots, a_r , and
- sums of squares of polynomials d,

such that

$$\sum_i a_i f_i + d + 1$$

is the polynomial 0.

for a given solution, the expression cannot be zero

Example: $f_0 \equiv 1$: $a_0 \equiv -1$, $d \equiv 0$

 $f_1(x) = 0, \ldots, f_r(x) = 0$ does not have a solution iff there exist

- polynomials a_1, \ldots, a_r , and
- sums of squares of polynomials d,

such that

$$\sum_i a_i f_i + d + 1$$

is the polynomial 0.

for a given solution, the expression cannot be zero

Example: $f_0 \equiv 1$: $a_0 \equiv -1$, $d \equiv 0$

System of polynomial equations and inequalities: Positivstellensatz [Stengle, 1974]

Discussion

Several further interesting and widely used special cases (e.g., S-procedure)

Several further interesting and widely used special cases (e.g., S-procedure)

How to compute such certificates?

Several further interesting and widely used special cases (e.g., S-procedure)

How to compute such certificates?

- choose template polynomials $\sum a_i \vec{x}_i$
- solve for the coefficients (in polynomial time, using SDP) [Parrilo, 2000]

Several further interesting and widely used special cases (e.g., S-procedure)

How to compute such certificates?

- choose template polynomials $\sum a_i \vec{x_i}$
- solve for the coefficients (in polynomial time, using SDP) [Parrilo, 2000]

Necessary degree of template polynomials:

- in linear case: 0 (Farkas Lemma), we just have to solve a linear problem
- otherwise: may be huge! usually is incrementally increased

Several further interesting and widely used special cases (e.g., S-procedure)

How to compute such certificates?

- choose template polynomials $\sum a_i \vec{x}_i$
- solve for the coefficients (in polynomial time, using SDP) [Parrilo, 2000]

Necessary degree of template polynomials:

- in linear case: 0 (Farkas Lemma), we just have to solve a linear problem
- otherwise: may be huge! usually is incrementally increased

What about certificates after adding sin, ...?

Theorem (A. Tarski, 1930ies): $FO(\mathbb{R}, =, <, +, \times)$ allows quantifier elimination, and hence is decidable.

Theorem (A. Tarski, 1930ies): $FO(\mathbb{R}, =, <, +, \times)$ allows quantifier elimination, and hence is decidable.

However: doubly exponential in number of quantifier alternations, exponential in number of variables [Davenport and Heintz, 1988, Weispfenning, 1988]

Theorem (A. Tarski, 1930ies): $FO(\mathbb{R}, =, <, +, \times)$ allows quantifier elimination, and hence is decidable.

However: doubly exponential in number of quantifier alternations, exponential in number of variables [Davenport and Heintz, 1988, Weispfenning, 1988]

What about $FO(\mathbb{R}, =, <, +, \times, \sin)$?

Theorem (A. Tarski, 1930ies): $FO(\mathbb{R}, =, <, +, \times)$ allows quantifier elimination, and hence is decidable.

However: doubly exponential in number of quantifier alternations, exponential in number of variables [Davenport and Heintz, 1988, Weispfenning, 1988]

What about $FO(\mathbb{R}, =, <, +, \times, \sin)$?

undecidable (would allow encoding of polynomial Diophantine equations, whose solution undecidable [Matiyasevich, 1970])

Theorem (A. Tarski, 1930ies): $FO(\mathbb{R}, =, <, +, \times)$ allows quantifier elimination, and hence is decidable.

However: doubly exponential in number of quantifier alternations, exponential in number of variables [Davenport and Heintz, 1988, Weispfenning, 1988]

What about $FO(\mathbb{R}, =, <, +, \times, \sin)$?

undecidable (would allow encoding of polynomial Diophantine equations, whose solution undecidable [Matiyasevich, 1970])

Even equivalence of terms to zero is undecidable [Caviness, 1970], and hence also equivalence of terms (so, limited symbolic computation etc., no Nelson-Oppen, no Positivstellensatz-type certificates,)

Theorem (A. Tarski, 1930ies): $FO(\mathbb{R}, =, <, +, \times)$ allows quantifier elimination, and hence is decidable.

However: doubly exponential in number of quantifier alternations, exponential in number of variables [Davenport and Heintz, 1988, Weispfenning, 1988]

What about $FO(\mathbb{R}, =, <, +, \times, \sin)$?

undecidable (would allow encoding of polynomial Diophantine equations, whose solution undecidable [Matiyasevich, 1970])

Even equivalence of terms to zero is undecidable [Caviness, 1970], and hence also equivalence of terms (so, limited symbolic computation etc., no Nelson-Oppen, no Positivstellensatz-type certificates,)

Situation hopeless?

No algorithm that terminates for all problem instances.

No algorithm that terminates for all problem instances.

Algorithm that terminates for all interesting problem instances?

No algorithm that terminates for all problem instances.

Algorithm that terminates for all interesting problem instances?

"Interesting"?

No algorithm that terminates for all problem instances.

Algorithm that terminates for all interesting problem instances?

"Interesting"?

Observation: model only reflects reality up to perturbations

"interesting": satisfiability does not change under such perturbations

No algorithm that terminates for all problem instances.

Algorithm that terminates for all interesting problem instances?

"Interesting"?

Observation: model only reflects reality up to perturbations

"interesting": satisfiability does not change under such perturbations

Well known in numerical analysis (well-posed problems), but in the context of decidability questions new (independently introduced by several people since ~ 2000 , usually called *robust problem*).

Constraints:

Constraints:

$$x^2 \le 0$$
 $x^2 \le -0.00001$

Constraints:

$$x^2 \leq 0$$
 $x^2 \leq -0.00001$: not robust

Constraints:

 $x^2 \leq 0$ $x^2 \leq -0.00001$: not robust $x^2 \leq 1$ $x^2 \leq 1.00001$

Constraints:

 $x^2 \leq 0$ $x^2 \leq -0.00001$: not robust $x^2 \leq 1$ $x^2 \leq 1.00001$: robust

Constraints:

- $x^2 \leq 0$ $x^2 \leq -0.00001$: not robust
- $x^2 \leq 1$ $x^2 \leq 1.00001$: robust

 $d(\phi,\phi'):$ if same up to constants then maximal distance of constant, otherwise ∞

Constraint ϕ robust iff there is an ε such that for all ϕ' with $d(\phi, \phi') \leq \varepsilon$, ϕ and ϕ' are equi-satisfiable

Constraints:

- $x^2 \leq 0$ $x^2 \leq -0.00001$: not robust
- $x^2 \leq 1$ $x^2 \leq 1.00001$: robust

 $d(\phi,\phi'):$ if same up to constants then maximal distance of constant, otherwise ∞

```
\begin{array}{l} \text{Constraint } \phi \ \textit{robust iff} \\ \text{there is an } \varepsilon \ \text{such that} \\ \text{for all } \phi' \ \text{with} \ d(\phi,\phi') \leq \varepsilon \text{, } \phi \ \text{and} \ \phi' \ \text{are equi-satisfiable} \end{array}
```

Problem *quasi-decidable* iff there is an algorithm that correctly checks satisfiability and terminates for all robust problem instances.

Quasi-decidability of ${\mathbb R}$

Theorem (Ratschan [2002, 2006]) $FO(\mathbb{R}, =, <, +, \times, \exp, \sin, ...)$ is quasi-decidable.

Assumptions:

- all variables bounded
- f = 0 shortcut for $f \le 0 \land f \ge 0$

Quasi-decidability of ${\mathbb R}$

Theorem (Ratschan [2002, 2006]) $FO(\mathbb{R}, =, <, +, \times, \exp, \sin, ...)$ is quasi-decidable.

Assumptions:

- all variables bounded
- f = 0 shortcut for $f \le 0 \land f \ge 0$

Implementation: http://rsolver.sourceforge.net

Special algorithms for sat and for unsat! Why?

Special algorithms for sat and for unsat! Why?

due to undecidability

failure to prove sat, does not imply unsat, and vice versa

Special algorithms for sat and for unsat! Why?

due to undecidability

failure to prove sat, does not imply unsat, and vice versa

satisfiability: statement over one valuation, good search method suffices (e.g., Newton's method)

approximation errors (e.g., due to rounding errors) during search o.k., formal a-posteriori verification [Neumaier, 1990]

Special algorithms for sat and for unsat! Why?

due to undecidability

failure to prove sat, does not imply unsat, and vice versa

satisfiability: statement over one valuation, good search method suffices (e.g., Newton's method)

approximation errors (e.g., due to rounding errors) during search o.k., formal a-posteriori verification [Neumaier, 1990]

non-satisfiability: statement over uncountable set, symbolic representation needed

assumption: bounded domain *B* for variables (e.g., $I_1 \times \cdots \times I_n$)

assumption: bounded domain *B* for variables (e.g., $I_1 \times \cdots \times I_n$) test(ϕ , *B*) \in {unsat, unknown}

assumption: bounded domain B for variables (e.g., $I_1 \times \cdots \times I_n$) test(ϕ , B) \in {unsat, unknown}

Algorithm $BB(\phi, B)$: either returns unsat or runs forever

```
\begin{split} S &\leftarrow test(\phi, B) \\ \text{if } S &= \text{unsat then } S \\ \text{else} \\ \text{let } B \text{ be such that } B &= B_1 \cup B_2, \\ & \text{non-overlapping} \\ \text{if } BB(\phi, B_1) &= BB(\phi, B_2) = \text{unsat then unsat} \end{split}
```

assumption: bounded domain B for variables (e.g., $I_1 \times \cdots \times I_n$) test(ϕ , B) \in {unsat, unknown}

Algorithm $BB(\phi, B)$: either returns unsat or runs forever

```
\begin{split} & S \leftarrow test(\phi, B) \\ & \text{if } S = \text{unsat then } S \\ & \text{else} \\ & \text{let } B \text{ be such that } B = B_1 \cup B_2, \\ & \text{non-overlapping} \\ & \text{if } BB(\phi, B_1) = BB(\phi, B_2) = \text{unsat then unsat} \end{split}
```

Can be interleaved with a satisfiability test.

Special case: one single equality

Special case: one single equality

Input: $f(x_1, \ldots, x_n) = 0$, intervals I_1, \ldots, I_n

Special case: one single equality

Input: $f(x_1, \ldots, x_n) = 0$, intervals I_1, \ldots, I_n

Interval arithmetic computes interval $f(I_1, \ldots, I_n)$ such that $\{f(x_1, \ldots, x_n) \mid x_1 \in I_1, \ldots, x_n \in I_n\} \subseteq f(I_1, \ldots, I_n)$

Special case: one single equality

Input: $f(x_1, \ldots, x_n) = 0$, intervals I_1, \ldots, I_n

Interval arithmetic computes interval $f(I_1, \ldots, I_n)$ such that $\{f(x_1, \ldots, x_n) \mid x_1 \in I_1, \ldots, x_n \in I_n\} \subseteq f(I_1, \ldots, I_n)$

if $0 \notin f(I_1, \ldots, I_n)$ then unsat else unknown

Special case: one single equality

Input: $f(x_1, \ldots, x_n) = 0$, intervals I_1, \ldots, I_n

Interval arithmetic computes interval $f(I_1, \ldots, I_n)$ such that $\{f(x_1, \ldots, x_n) \mid x_1 \in I_1, \ldots, x_n \in I_n\} \subseteq f(I_1, \ldots, I_n)$

if $0 \notin f(I_1, \ldots, I_n)$ then unsat else unknown

More powerful techniques based on

- advanced interval techniques [Neumaier, 1990, Moore et al., 2009],
- constraint propagation [Cleary, 1987, Jaulin et al., 2001],
- LP-relaxations [McCormick, 1976, Neumaier, 2004]

Challenges

In decidable polynomial case, many symbolic techniques available (Gröbner basis computation, resultants, ...). Sometimes efficient, combine [Passmore and Jackson, 2009].

Challenges

In decidable polynomial case, many symbolic techniques available (Gröbner basis computation, resultants, ...). Sometimes efficient, combine [Passmore and Jackson, 2009].

Traditionally, computer science does not take into account perturbation, and assumes decision procedures.

Use quasi-decision procedures, that is, algorithms that need not terminate for non-robust inputs.

Literature I

- E. Artin. Über die Zerlegung definiter Funktionen in Quadrate. *Hamb. Abh.*, 5:100–115, 1927.
- B. F. Caviness. On canonical forms and simplification. J. ACM, 17 (2):385–396, 1970. ISSN 0004-5411. doi: http://doi.acm.org/10.1145/321574.321591.
- J. G. Cleary. Logical arithmetic. *Future Computing Systems*, 2(2): 125–149, 1987.
- J. H. Davenport and J. Heintz. Real quantifier elimination is doubly exponential. *Journal of Symbolic Computation*, 5:29–35, 1988.
- Luc Jaulin, Michel Kieffer, Olivier Didrit, and Éric Walter. *Applied Interval Analysis, with Examples in Parameter and State Estimation, Robust Control and Robotics.* Springer, Berlin, 2001.
- Yuri Matiyasevich. Enumerable sets are diophantine. *Doklady Akademii Nauk SSSR*, 191:279–282, 1970.

Literature II

- Garth P. McCormick. Computability of global solutions to factorable nonconvex programs: Part I convex underestimating problems. *Mathematical Programming*, 10(1): 147–175, 1976.
- Ramon E. Moore, R. Baker Kearfott, and Michael J. Cloud. Introduction to Interval Analysis. SIAM, 2009.
- Arnold Neumaier. Complete search in continuous global optimization and constraint satisfaction. *Acta Numerica*, 2004.
- Arnold Neumaier. Interval Methods for Systems of Equations. Cambridge Univ. Press, Cambridge, 1990.
- Pablo Parrilo. Structured Semidefinite Programs and Semialgebraic Geometry Methods in Robustness and Optimization. PhD thesis, California Institute of Technology, 2000.
- Grant Olney Passmore and Paul B. Jackson. Combined decision techniques for the existential theory of the reals. In *Intelligent Computer Mathematics*, 2009.

Literature III

Stefan Ratschan. Continuous first-order constraint satisfaction. In

J. Calmet, B. Benhamou, O. Caprotti, L. Henocque, and

- V. Sorge, editors, *Artificial Intelligence, Automated Reasoning, and Symbolic Computation*, number 2385 in LNCS, pages 181–195. Springer, 2002.
- Stefan Ratschan. Efficient solving of quantified inequality constraints over the real numbers. *ACM Transactions on Computational Logic*, 7(4):723–748, 2006.
- M.-F. Roy and A. Szpirglas. Complexity of computation of real algebraic numbers. *Journal of Symbolic Computation*, 10:39–51, 1990.
- Gilbert Stengle. A Nullstellensatz and a Positivstellensatz in semialgebraic geometry. *Mathematische Annalen*, 207(2):87–97, 1974.
- Volker Weispfenning. The complexity of linear problems in fields. Journal of Symbolic Computation, 5(1–2):3–27, 1988.