A generalized Cyclic-Clustering Approach for Solving Structured CSPs

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Abstract

We propose a new method for solving structured CSPs which generalizes and improves the Cyclic-Clustering approach [4]. First, the cutset and the tree-decomposition of the constraint network, which are used for taking advantage of the CSP structure, are computed independently of the notion of triangulated induced subgraph. Then, unlike Cyclic-Clustering, our method can try to solve the tree-decomposition part of the problem without having assigned all the variables of the cutset. Regarding the solving of the tree-decomposition part, we use the BTD method [6] like in [7]. As BTD records and exploits structural (no)goods, we provide some conditions which make possible the use of structural (no)goods recorded during previous calls of BTD and we implement them in a dedicated version of BTD. By so doing, from a theoretical viewpoint, we can provide a theoretical time complexity bound related to parameters of the cutset and the tree-decomposition and, from a practical viewpoint we expect to detect failures earlier and to avoid more redundancies in the search.

1 Preliminaries

The CSP formalism (Constraint Satisfaction Problem) offers a powerful framework for representing and solving efficiently many problems, in particular, many academic or real problems (e.g. graph coloring, planning, frequency assignment problems, ...). A *finite constraint satisfaction problem* (X, D, C, R) is defined as a set of variables $X = \{x_1, \ldots x_n\}$, a set of domains $D = \{d_1, \ldots d_n\}$ (the domain d_i contains all the possible values for the variable x_i), and a set C of constraints. A constraint $c_i \in C$ on an ordered subset of variables, $c_i = (x_{i_1}, \ldots x_{i_{a_i}})$ is defined by an associated relation $r_{c_i} \in R$ of allowed combinations of values for the variables in c_i ($r_{c_i} \subseteq d_{i_1} \times \ldots \times d_{i_{a_i}}$). Note that we take the same notation for the constraint c_i and its scope. Let $Y = \{x_1, \ldots x_k\}$ be a subset of X. An *assignment* $\mathcal{A}$ on Y is a tuple $(v_1, \ldots, v_k)$ of $d_1 \times \ldots \times d_i$. We also write $\mathcal{A}$ in the form $\{x_1 \leftarrow v_1, ..., x_i \leftarrow v_i\}$. Then we denote $\mathcal{A}_1 \subseteq \mathcal{A}_2$ if the assignment A_2 is an extension of A_1 (i.e. we have $\mathcal{A}_1 = \{x_1 \leftarrow v_1, ..., x_i \leftarrow v_i\}$ and $\mathcal{A}_2 = \{x_1 \leftarrow v_1, ..., x_i \leftarrow v_i, ..., x_{i+j} \leftarrow v_{i+j}\}$ with $j \geq 0$). An assignment $\mathcal{A}$ on Y satisfies a constraint $c \in C$ s.t. $c \subseteq Y$ if $\mathcal{A}[c] \in r_c$ with $\mathcal{A}[c]$ the restriction of $\mathcal{A}$ to the variables involved in c. $\mathcal{A}$ is said *consistent* if it satisfies each constraint $c \subseteq Y$. A solution is an assignment of each variable which satisfies all the constraints. Determining if a solution exists is an NP-complete problem. We denote $Sol(\mathcal{P})$ the set of solutions of the CSP $\mathcal{P}$. In the following, for sake of simplicity, we only consider binary CSPs (i.e. CSPs whose each constraint involves exactly two variables). Of course, this work can be extended to non-binary CSPs.

The usual methods for solving CSPs (e.g. Forward-Checking [3]) are based on backtracking search. This approach, often efficient in practice, has an exponential theoretical time complexity in $O(m.d^n)$ (denoted $O(exp(n))$) for an instance having n variables and m constraints and whose largest domain has d values. Several works have been developed to improve this theoretical complexity bound thanks to particular features of the instance. Generally, they exploit some structural properties of the CSP. The structure of a CSP (X, D, C, R) can be represented by the graph (X, C), called the *constraint graph*. In this context, the tree-decomposition notion [9] plays a central role. A *tree-decomposition* of a graph $G = (X, C)$ is a pair (E, T) where $T = (I, F)$ is a tree with nodes I and edges F and $E = \{E_i : i \in I\}$ a family of subsets of X, s.t. each subset (called cluster) E_i is a node of T and verifies: (i) $\cup_{i \in I} E_i = X$, (ii) for each edge $\{x, y\} \in C$, there exists $i \in I$ with $\{x, y\} \subseteq E_i$, and (iii) for all $i, j, k \in I$, if k is in a path from i to j in T, then $E_i \cap E_j \subseteq E_k$. We will denote S_j the separator $E_i \cap E_j$ between the clusters E_i and E_j such that E_j is a son of E_i, and $Desc(E_j)$ the set of variables belonging to the descent of the cluster E_i rooted in E_j. The width w of a tree-decomposition (E,T) is equal to $max_{i \in I}|E_i| - 1$. The *tree-width* w^* of G is the minimal width over all the tree-decompositions of G. On the one hand, it leads to one of the best known theoretical time complexity bounds, namely $O(exp(w^* + 1))$ with w^* the tree-width. Different methods (e.g. [2, 6]) have been proposed to reach this bound. They aim to cluster variables s.t. the cluster arrangement is a tree.

From a theoretical viewpoint, reach the best theoretical complexity bound requires to compute an optimal tree-decomposition (i.e. a tree-decomposition with a minimum width), which is an NP-hard problem [1]. In practice, it is clear that solving an NP-hard problem as a preliminary step of the solving of an NP-complete problem is not reasonable. So heuristic methods are generally used. They often provide a relevant approximation of an optimal tree-decomposition when the constraint graph has a small tree-width. Methods like BTD [6] are then well-suited for solving such problems. In contrast, when the constraint graph does not have a small tree-width, heuristic methods may often produce a poor approximation of an optimal tree-decomposition. In such a case, instead of running a structural method on a tree-decomposition with an excessive width, exploiting a method like Cyclic-Clustering [4] may be more interesting and more adapted. Cyclic-Clustering relies on a subset V of vertices, called a *cutset* of the graph (X,C), such that the graph $(X - V, \{\{x,y\} \in C\ s.t.\ x,y \in X - V\})$ induced by $X - V$ is triangulated (i.e. it has no cycle of length greater than 3 without an edge joining two non consecutive vertices in the cycle). The triangulated part of the constraint graph corresponds to a tree-decomposition. For instance, Figure 1(a) presents a graph having 19 vertices. The set $\{y_1, y_2\}$ forms a cutset of this graph s.t. the induced graph involving the vertices $x_1, \ldots, x_{17}$ is triangulated, which corresponds to a tree-decomposition with 7 clusters $E_1, \ldots, E_7$. We have $S_2 = E_1 \cap E_2 = \{x_3\}$, $Desc(E_1) = \{x_1, x_2, x_3, x_4, x_5\}$ and $Desc(E_2) = \{x_3, x_5\}$. In [7], two implementations of Cyclic-Clustering, called CC-BTD$_1$ and CC-BTD$_2$ are proposed. They solve the cutset part of the problem with a classical enumerative algorithm and the triangulated part with BTD. CC-BTD$_2$ differs from CC-BTD$_1$ in calling BTD before solving the cutset part. By so doing, the no-goods recorded during this preliminary call can be exploited in the following calls of BTD. Unfortunately, the Cyclic-Clustering approach has some limits. For instance, informations recorded during the search are not fully exploited to avoid redundant parts of the search space. Moreover, the triangulated part must be computed thanks to the notion of Triangulated Induced Subgraph (TIS).

In this paper, we propose a generalization of CC-BTD, called CC-BTD-gen. Like the Cyclic-Clustering approach, CC-BTD-gen relies on a cutset and a tree-decomposition. Yet, it uses a tree-decomposition computed thanks to any method and so not necessarily related to the TIS notion, unlike Cyclic-Clustering. Regarding the solving, CC-BTD-gen exploits a specialized version of BTD which allows it to exploit some part of (no)goods recorded in previous calls to BTD, what leads to avoid more redundancies in practice. Finally, we have noted that CC-BTD assigns consistently all the variables of the cutset before solving the triangulated part even if after having assigned some of them, the triangulated part has no solution. So, in order to avoid this drawback, CC-BTD-gen can call BTD after having assigned consistently some variables of the cutset. If the subproblem associated to the tree-decomposition has a solution, the search keeps on the remaining variables of the cutset. Otherwise a backtrack occurs. In both cases, some (no)goods are recorded and may be exploited later.

The paper is organized as follows. Section 2 presents the theoretical framework of CC-BTD-gen while section 3 describes the CC-BTD-gen algorithm. Finally, we conclude and discuss about future works in section 4.

2 Theoretical framework

In this section, we describe the theoretical framework required to present formally CC-BTD-gen. This framework is presented in a general way before focusing in the next section on a special case where Y will be the cutset and $X - Y$ the variables belonging to the associated tree-decomposition used by CC-BTD-gen. In the following, we consider a CSP $\mathcal{P} = (X,D,C,R)$. First, we define the notion of subproblem induced by a subset Y of variables.

Definition 1 *Let $Y \subseteq X$ be a subset of variables. The **CSP induced by** Y is the CSP (Y, D_Y, C_Y, R_Y) where $D_Y = \{d_i \in D | x_i \in Y\}$, $C_Y = \{c_{ij} = \{x_i, x_j\} \in C | x_i, x_j \in Y\}$ and $R_Y = \{r_{c_{ij}} \in R | c_{ij} \in C_Y\}$.*

In the next definitions and properties, we consider the following notations. Y_1, Y_2, Y and Z will be subsets of X such that $Y_1 \subseteq Y$, $Y_2 \subseteq Y$, $Y \subseteq X$ and $Z \subseteq X - Y$. $\mathcal{A}_1$, $\mathcal{A}_2$ and $\mathcal{A}$ will be assignments respectively on Y_1, Y_2 and Y. TD will be the considered tree-decomposition of the CSP $\mathcal{P}(X - Y)$. By lack of place, we do not provide the proofs of the following properties, theorems and corollaries (these proofs are available in [8]).

Now, we propose a limited (but sufficient) definition of the deletion of some values by Forward-Checking (FC [3]).

Definition 2 *The resulting filtering of an assignment $\mathcal{A}$ performed by FC is the operation which consists in deleting the values from the domain d_i of each unassigned variable x_i, which become incompatible with respect to at least a constraint $\{x_i, y\}$ where y is an assigned variable in $\mathcal{A}$. More*

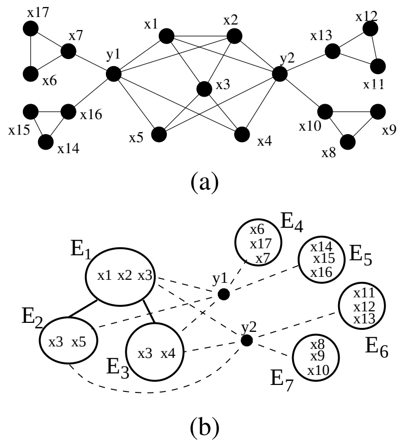

Figure 1. (a) A constraint graph (b) An example of tree-decomposition with clusters $E_1, \ldots, E_7$ and cutset $\{y1, y2\}$ for this graph.

formally, $d_i^{\mathcal{A}} = \{v \in d_i | \forall c = \{x_i, y\} \in C,\ (v, w) \in r_c \text{ with } w \text{ the value assigned to } y \text{ in } \mathcal{A}\}$.

In other words, $d_i^{\mathcal{A}}$ is the current domain of the unassigned variable x_i obtained thanks to the filtering achieved after each assignment of a variable in the assignment $\mathcal{A}$. We then define the set of deleted values by the filtering.

Definition 3 *Let $Y \subseteq X$ be such that $|Y| = k$ and $\mathcal{A} = \{x_1 \leftarrow v_1, ..., x_k \leftarrow v_k\}$ an assignment on Y. The set of deleted values of $\mathcal{P}(X - Y)$ by the filtering related to $\mathcal{A}$ is $\mathcal{F}_{\mathcal{A}}(X - Y) = \{(x_i, v) \in (X - Y) \times (d_i - d_i^{\mathcal{A}})\}$.*

Next, we refine the definition 1 by introducing the notion of filtered subproblem.

Definition 4 *The filtered subproblem $\mathcal{P}_{\mathcal{A}}(X - Y)$ refers to the induced CSP $(X - Y, D_{X-Y}^{\mathcal{A}}, C_{X-Y}, R_{X-Y}^{\mathcal{A}})$ with $D_{X-Y}^{\mathcal{A}} = \{d_i^{\mathcal{A}} | x_i \in X - Y\}$ and $R_{X-Y}^{\mathcal{A}} = \{r_c^{\mathcal{A}} = r_c \cap (d_j^{\mathcal{A}} \times d_k^{\mathcal{A}}) | c = \{x_j, x_k\} \in C_{X-Y} \text{ and } r_c \in R\}$.*

We can note that the filtering of FC does not change the structure defined by the constraint graph of a problem.

Property 1 *A tree-decomposition of $\mathcal{P}(X - Y)$ is a tree-decomposition of $\mathcal{P}_{\mathcal{A}_1}(X - Y)$ and conversely.*

Henceforth, thanks to the following property, we aim to measure the effect of a filtering on the domains and relations of a given problem.

Property 2 *If $\mathcal{F}_{\mathcal{A}_1}(Z) \subseteq \mathcal{F}_{\mathcal{A}_2}(Z)$, then $\forall z_i \in Z$, $d_i^{A_2} \subseteq d_i^{A_1}$ and $\forall c_{jk} \in C_Z$, $r_{c_{jk}}^{\mathcal{A}_2} \subseteq r_{c_{jk}}^{\mathcal{A}_1}$.*

We compare now the set of solutions of two subproblems induced by the same set of variables but with any different filtering.

Property 3 *If $\mathcal{F}_{\mathcal{A}_1}(Z) \subseteq \mathcal{F}_{\mathcal{A}_2}(Z)$, then we have $Sol(\mathcal{P}_{\mathcal{A}_2}(Z)) \subseteq Sol(\mathcal{P}_{\mathcal{A}_1}(Z))$ and $|Sol(\mathcal{P}_{\mathcal{A}_2}(Z))| \leq |Sol(\mathcal{P}_{\mathcal{A}_1}(Z))|$.*

In the next corollary, we present the specific case where $\mathcal{A}_2$ is an extension of $\mathcal{A}_1$.

Corollary 1 *If $\mathcal{A}_2[Y_1] = \mathcal{A}_1$, then $Sol(\mathcal{P}_{\mathcal{A}_2}(Z)) \subseteq Sol(\mathcal{P}_{\mathcal{A}_1}(Z))$ and $|Sol(\mathcal{P}_{\mathcal{A}_2}(Z))| \leq |Sol(\mathcal{P}_{\mathcal{A}_1}(Z))|$.*

We will then exploit these properties and corollary in order to decide whether structural (no)goods can be reused validly. But, first, we remind the notion of structural (no)good which is used in the BTD algorithm [6].

Definition 5 *Given a cluster E_i and E_j one of its sons, a **good** (resp. **nogood**) of E_i with respect to E_j is a consistent assignment $\mathcal{A}$ on $S_j = E_i \cap E_j$ such that $\mathcal{A}$ can (resp. cannot) be extended to a consistent extension of $\mathcal{A}$ on $Desc(E_j)$.*

We see now the cases where the (no)goods for the subproblem $\mathcal{P}(X - Y)$ can stay valid if we change the assignment on Y.

Theorem 1 *If $\mathcal{F}_{\mathcal{A}_1}(X - Y) \subseteq \mathcal{F}_{\mathcal{A}_2}(X - Y)$ and $ng(S_j)$ is a nogood for the problem $\mathcal{P}_{\mathcal{A}_1}(X - Y)$ then $ng(S_j)$ is a nogood for $\mathcal{P}_{\mathcal{A}_2}(X - Y)$ too.*

The previous theorem lays a condition (inclusion) on the set of values which are filtered to deduce the validity of a nogood already recorded. However, from an algorithmic and practical viewpoint, exploiting this theorem may leads to an expensive check (with respect to time). Hence, in the next corollary, we propose a restriction on the resulting filtering of the two assignments.

Corollary 2 *If $\mathcal{A}_2[Y_1] = A_1$ and $ng(S_j)$ is a nogood for the problem $\mathcal{P}_{\mathcal{A}_1}(X - Y)$ then $ng(S_j)$ is a nogood for $\mathcal{P}_{\mathcal{A}_2}(X - Y)$ too.*

Then, we are interested in preserving the validity of goods.

Theorem 2 *If $\mathcal{F}_{\mathcal{A}_2}(Desc(E_j)) \subseteq \mathcal{F}_{\mathcal{A}_1}(Desc(E_j))$ and $g(S_j)$ is a good for the problem $\mathcal{P}_{\mathcal{A}_1}(X - Y)$ then $g(S_j)$ is a good for $\mathcal{P}_{\mathcal{A}_2}(X - Y)$ too.*

All these properties can be applied by the CC-BTD-gen algorithm to deduce the informations remaining true between different calls to BTD. For that, Y will be the cutset and so $X - Y$ the variables belonging to the associated tree-decomposition. The theorem 1 allows to conclude

Algorithm 1: CC-BTD-gen($in : \mathcal{A}, V, NG_p, in/out : G_p$)

```
1  Cons ← true
2  if ChoiceBTD(V) or V = ∅ then
3      G ← ∅ ; NG ← ∅
4      Cons ← BTD-gen(∅, E_1, V_{E_1}, NG_p, G_p, NG, G)
5      G_p ← G_p ∪ G ; NG_p ← NG_p ∪ NG
6  if Cons and V ≠ ∅ then
7      Choose x_i ∈ V ; d_i ← D_i ; Cons ← false
8      while d_i ≠ ∅ and ¬Cons do
9          Choose v ∈ d_i ; d_i ← d_i − {v}
10         if Filtering(A ∪ {x_i ← v}, x_i) then
11             Cons ←
               CC-BTD-gen(A ∪ {x_i ← v}, V − {x_i}, NG_p, G_p)
12         Unfiltering(A, x_i)
13 return Cons
```

that considering two partials assignments $\mathcal{A}_1$ and $\mathcal{A}_2$ on the cutset such that $\mathcal{A}_2$ filters at least the same values as $\mathcal{A}_1$, then the nogoods recorded by BTD on $\mathcal{P}_{\mathcal{A}_1}$ stay valid on $\mathcal{P}_{\mathcal{A}_2}$. However, due to the limited memory space, we cannot record the effects of resulting filtering generated by each consistent partial assignment on the cutset. Therefore, we exploit the corollary 2 which allows to record and reuse the nogoods in the case where we extend a consistent partial assignment of cutset. Likewise, for the reuse of goods, we keep all recorded goods and check their validity when we use them. In the next section, we describe and study the CC-BTD-gen algorithm.

3 A generalization of Cyclic-Clustering

The CC-BTD-gen algorithm (algorithm 1) relies on a cutset and a tree-decomposition of the constraint graph. The tree-decomposition and the cutset can be computed thanks to any method, and so are not necessarily related to the TIS notion, unlike in Cyclic-Clustering. The CC-BTD-gen algorithm consists in assigning consistently the variables of the cutset while checking, thanks to a dedicated version of BTD, whether the current partial assignment can be extended consistently on the tree-decomposition part. As this check can be expensive, after having assigned a value to a variable of the cutset, CC-BTD-gen decides thanks to the heuristic function $ChoiceBTD$ if it must be performed or not. If BTD returns $true$, CC-BTD-gen keeps on the search on the cutset. Otherwise, it tries a new value for the current variable (if any) or a backtrack occurs. We iterate this process until a solution is found (i.e. a consistent assignment of the cutset which can be consistently extended to the tree-decomposition part) or the whole search space is explored.

First, in order to be able to reuse (no)goods recorded by different executions of BTD, we propose a variant of BTD, called BTD-gen (algorithm 2), which implements the properties highlighted in the previous section. BTD-gen only differs from BTD in its ability to exploit (no)goods recorded during previous calls to BTD-gen. So, it has two additional parameters, namely the set G_p of goods and the set NG_p of nogoods recorded by previous calls to BTD-gen while G and NG denote respectively the set of goods and nogoods recorded by the current execution to BTD-gen. As we keep all the goods recorded previously, some of them cannot be reuse validly into some calls to BTD-gen. Therefore, before reusing such a good, BTD-gen must first check its validity for the current problem in order to respect the theorem 2. This test is performed by the function $CheckGood$ (algorithm 3). This function returns $true$ whether each variable of the descent of E_i can be assigned with the value it had when the good g had been recorded. In order to check easily this property, we need to record the extension of the good on the remaining variables of the cluster. Like BTD, BTD-gen returns the consistency of the subproblem associated to the tree-decomposition TD and rooted in the cluster E_i.

This dedicated version of BTD is exploited in CC-BTD-gen to check if the current partial assignment on the cutset can be extended consistently on the tree-decomposition part of the problem. If BTD-gen($\emptyset, E_1, V_{E_1}, NG_p, G_p, NG, G$) returns $false$, then CC-BTD-gen tries another value for the last assigned variable in the cutset (if any) or a backtrack occurs. Otherwise, it keeps on the search by assigning a new variable of the cutset. In both cases, the set G of goods recorded by BTD-gen is added into the set G_p. The process is similar for the nogoods except that NG_p cannot be modified out of the current call to CC-BTD-gen. In other words, when we come back from a call to CC-BTD-gen, we forget the nogoods recorded, during this call, by BTD-gen in order to respect the corollary 2.

Finally, in algorithm 1, the Boolean heuristic function $ChoiceBTD$ defines, after each assignment of a variable in the cutset, if BTD-gen must be called or not. If it returns $false$ and some cutset's variables are not yet assigned, CC-BTD-gen tries to assign one of them with Forward-Checking algorithm (lines 7-12). If $ChoiceBTD$ returns $true$, we run BTD-gen and we keep the new goods and nogoods recorded (lines 3-5). Note that this heuristic can be entirely dynamic since it can decide to call BTD-gen anytime during the assignment of the cutset.

Now, we illustrate the CC-BTD-gen algorithm with an example. Let us consider the constraint graph of Figure 1(a) and a possible tree-decomposition with 5 connected components and a cutset with 2 variables (y_1 and y_2) as depicted in Figure 1(b). CC-BTD-gen assigns some variables of the cutset. For instance, if it only assigns y_1, the filtering of FC can reduce the domains of the unassigned neighboring variables of y_1, namely x_1, x_2, x_4, x_5, x_7 and x_{16}. Next, the $ChoiceBTD$ heuristic can decide to solve the tree-decomposition part of the problem with BTD-gen. If BTD-gen returns $false$ then CC-BTD-gen will change the assignment on y_1. Otherwise CC-BTD-gen will assign the variable y_2 of the cutset. In this case, if it successes

Algorithm 2: BTD-gen($in : \mathcal{A}, E_i, V_{E_i}, NG_p, G_p, in/out : NG, G$)

```
if V_{E_i} = ∅ then
    Cons ← true ; F ← Sons(E_i)
    while F ≠ ∅ and Cons do
        Choose E_j ∈ F ; F ← F − {E_j}
        S_j ← E_i ∩ E_j ;
        if A[S_j] is a nogood into NG then Cons ← false
        else
            if A[S_j] is a nogood into NG_p then Cons ← false
            else
                if A[S_j] is a good into G then Cons ← true
                else
                    if A[S_j] is a good into G_p and
                    CheckGood(E_j, A[S_j]) then
                        Cons ← true
                    else
                        Cons ← BTD-gen(A, E_j, E_j\(E_j ∩
                        E_i), NG_p, G_p, NG, G)
                        if Cons then Save the good A[S_j] into G
                        else Save the nogood A[S_j] into NG
else
    Choose x_k ∈ V_{E_i} ; d_k ← D_k ; Cons ← false
    while d_k ≠ ∅ and ¬Cons do
        Choose w ∈ d_k ; d_k ← d_k − {w}
        if A ∪ {x_k ← w} satisfies each constraint then
            Cons ←BTD-gen(A ∪ {x_k ← w}, E_i, V_{E_i} − {x_k},
            NG_p, G_p, NG, G)
return Cons
```

Algorithm 3: CheckGood(E_i, g)

```
Let S be the assignment g and its recorded extension on E_i
forall y ∈ E_i do
    if S[y] ∉ d_y then return false
ValidGood ← true ; F ← Sons(E_i)
while F ≠ ∅ and ValidGood do
    Choose E_j ∈ F ; F ← F − {E_j}
    g_F ← good on E_j such that g_F[E_i ∩ E_j] = S[E_i ∩ E_j]
    ValidGood ←CheckGood(E_j, g_F)
return ValidGood
```

in assigning consistently y_2, a new call to BTD-gen is performed since the cutset is entirely assigned. If BTD-gen returns $true$ then the CSP is consistent. Otherwise CC-BTD-gen looks for a new assignment for y_2.

Theorem 3 *BTD-gen and CC-BTD-gen are sound, complete and finish.*

In the following theorem, n denotes the number of variables of CSP, m the number of constraints, d the size of the largest domain, k the size of the cutset, w the width of the considered tree-decomposition, and s the size of the largest intersection between two clusters.

Theorem 4 *BTD-gen has a time complexity in $O(n(n+m)d^{w+1})$ and a space complexity in $O(nwd^s)$. CC-BTD-gen has a time complexity in $O(n(n+m)d^{w+k+2})$ and a space complexity in $O(nwd^s)$.*

4 Conclusions and future works

We have proposed a new method for solving structured CSPs. This method generalizes and improves the Cyclic-Clustering approach [4]. More precisely, it exploits a cutset and a tree-decomposition whose computation is made independent of the notion of triangulated induced subgraph, what brings more freedom in a crucial step of the method. Then, CC-BTD-gen can check whether the current assignment on the cutset can be consistently extended on the tree-decomposition part, even if all the variables of the cutset are not assigned yet. By so doing, it has a more global view of the problem than CC-BTD$_i$. Finally, it exploits a dedicated version of BTD which implements some properties which make it possible to exploit some (no)goods recorded during previous calls to BTD and so to avoid more redundancies in the search. Our preliminary experiments (see [8]) show the practical interest of our approach. Namely, CC-BTD-gen often outperforms CC-BTD$_i$.

In the CSP framework, few works related to cutset have been achieved. In our knowledge, the computation of both relevant cutset and tree-decomposition with respect to CSP solving has not been studied yet. Such a work, like [5] for tree-decomposition, must be performed to improve the efficiency of such approaches. It could turn to be very useful for solving efficiently structured real-world instances. Finally, exploiting dynamic cutset and tree-decomposition could be promising.

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