

Scheduling

Problem definition
Motivation

Parameterized
Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

Scheduling meets parameterized complexity

Maher Mallem, Claire Hanen, Alix Munier-Kordon

December 14th 2023



Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

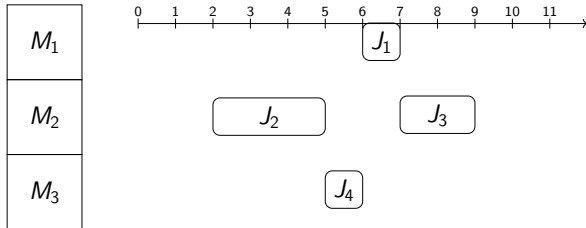
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

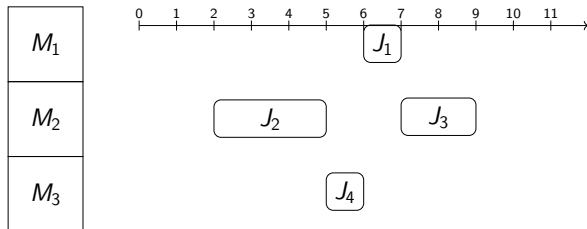
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



machines | job properties | optimization criterion

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

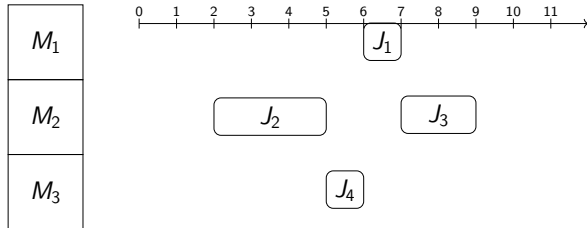
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



$P3|.|.$

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

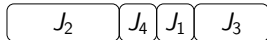
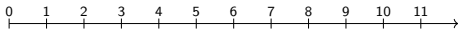
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



1|.|.

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

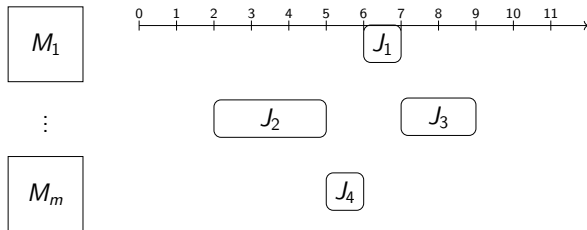
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



$P|.|.$

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

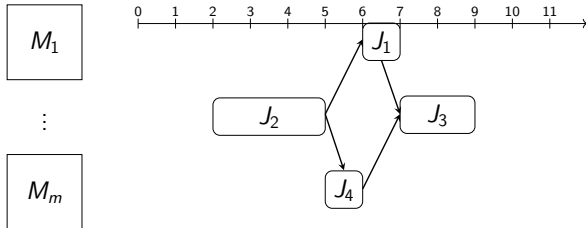
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



$$P|prec|.$$

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

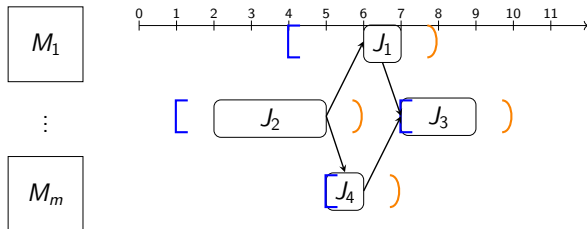
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



$$P|prec, r_j, d_j|.$$

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

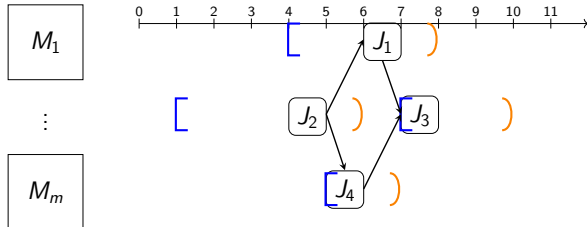
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



$$P|prec, p_j = 1, r_j, d_j|.$$

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

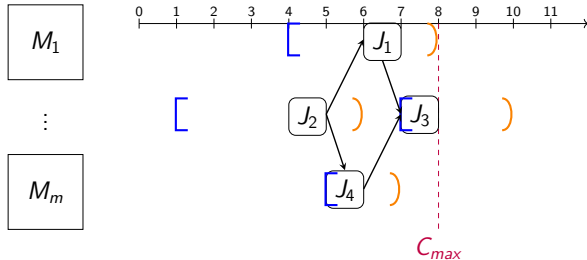
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



$$P|prec, p_j = 1, r_j, d_j|C_{max}$$

Parallel machine scheduling

Scheduling

Problem definition

Motivation

Parameterized

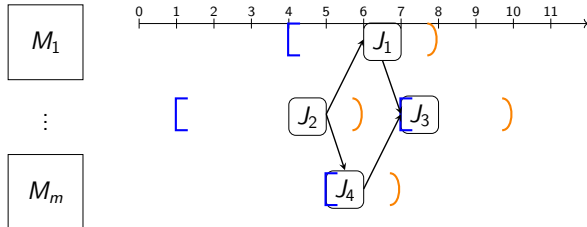
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



$$P|prec, p_j = 1, r_j, d_j| \star$$

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

From poly-time solvable problem $1|p_j = 1, r_j, d_j|*$

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

From poly-time solvable problem $1|p_j = 1, r_j, d_j|*$

- $1 \rightarrow P$

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

From poly-time solvable problem $1|p_j = 1, r_j, d_j|*$

- $1 \rightarrow P$
- $p_j = 1 \rightarrow \text{any } p_j$

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

From poly-time solvable problem $1|p_j = 1, r_j, d_j|*$

- $1 \rightarrow P$
- $p_j = 1 \rightarrow \text{any } p_j$
- Add precedence relations $prec$

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

From poly-time solvable problem $1|p_j = 1, r_j, d_j|*$

- $1 \rightarrow P$
- $p_j = 1 \rightarrow \text{any } p_j$
- Add precedence relations $prec$
- Add precedence delays $\ell_{i,j}$

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

From poly-time solvable problem $1|p_j = 1, r_j, d_j|*$

- $1 \rightarrow P$
- $p_j = 1 \rightarrow \text{any } p_j$
- Add precedence relations $prec$
- Add precedence delays $\ell_{i,j}$

$1|r_j, d_j|*$ is strongly NP-hard. [Brucker, Kan, Lenstra 1977]

Classical complexity theory

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

$$1|p_j = 1, r_j, d_j|*$$

Classical complexity theory

Scheduling

Problem definition

Motivation

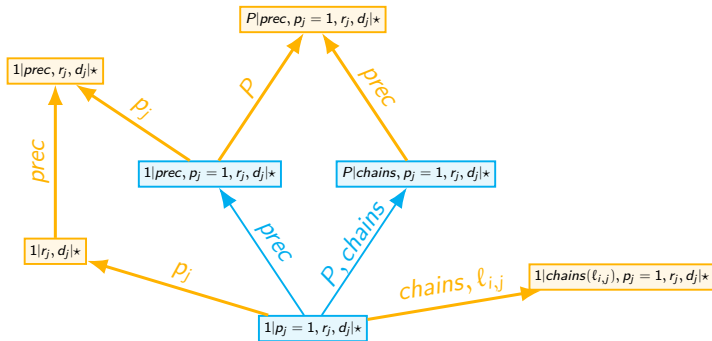
Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



Classical complexity theory

Scheduling

Problem definition

Motivation

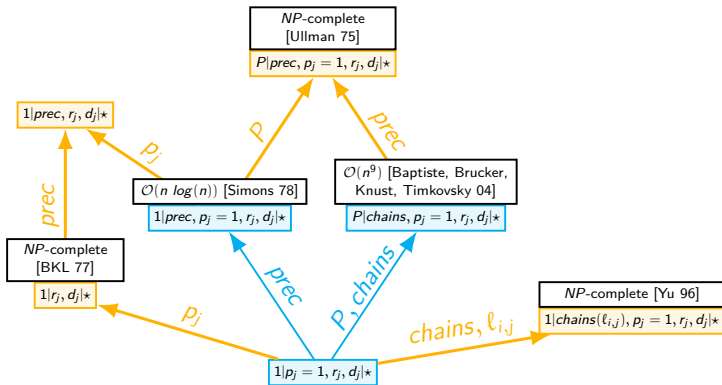
Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



Parameterized complexity classes

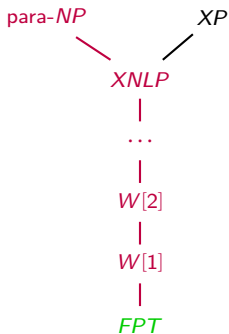
Scheduling

- Problem definition
- Motivation

Parameterized Complexity

- General**
- Pathwidth
- Pathwidth & maximum delay

Further work



Parameterized complexity classes

Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

nondet. time $f(k) \cdot \text{poly}(n)$

det. time $n^{f(k)}$

para-NP

XP

XNLP

nondet. time $f(k) \cdot \text{poly}(n)$
& space $f(k) \cdot \log(n)$

...

W[2]

W[1]

FPT

det. time $f(k) \cdot \text{poly}(n)$

Parameterized complexity in machine scheduling

Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- [Bodlaender, Fellows 1995]
 - #machines m : $P|prec, p_j = 1|C_{max}$ is $W[2]$ -hard.

Parameterized complexity in machine scheduling

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

- [Bodlaender, Fellows 1995]
 - #machines m : $P|prec, p_j = 1|C_{max}$ is $W[2]$ -hard.
- [Mnich, Wiese 2015]
 - Maximum processing time p_{max} : $P||C_{max} \in FPT$.

Parameterized complexity in machine scheduling

Scheduling

Problem definition

Motivation

Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

- [Bodlaender, Fellows 1995]
 - #machines m : $P|prec, p_j = 1|C_{max}$ is $W[2]$ -hard.
- [Mnich, Wiese 2015]
 - Maximum processing time p_{max} : $P||C_{max} \in FPT$.
- [Hermelin, Karhi, Pinedo, Shabtay 2018]
 - #distinct d_j , #distinct p_j , #distinct w_j : $1||\sum w_j U_j \in FPT$ with two of the three.

Pathwidth μ

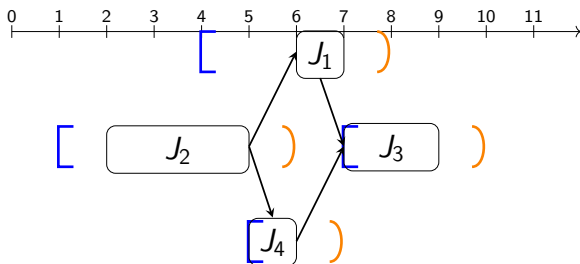
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Pathwidth μ

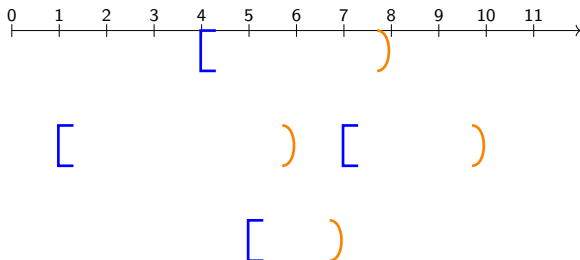
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Pathwidth μ

Scheduling

Problem definition

Motivation

Parameterized

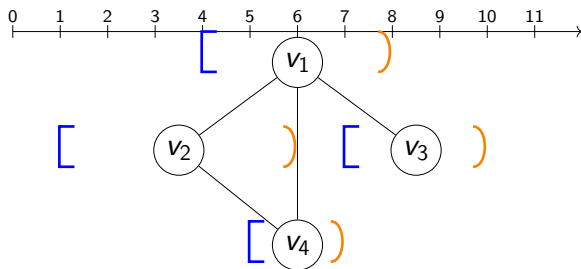
Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



Pathwidth μ

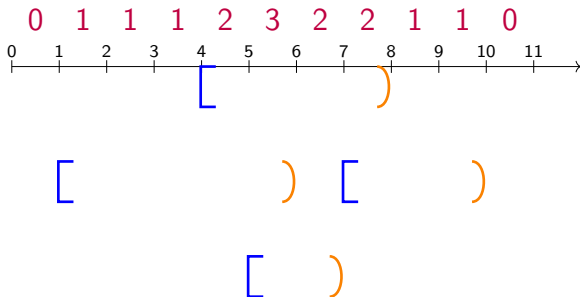
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Pathwidth μ

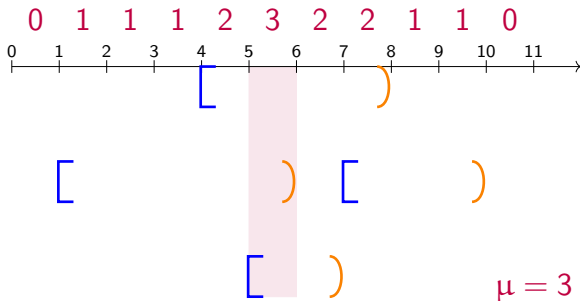
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Pathwidth μ

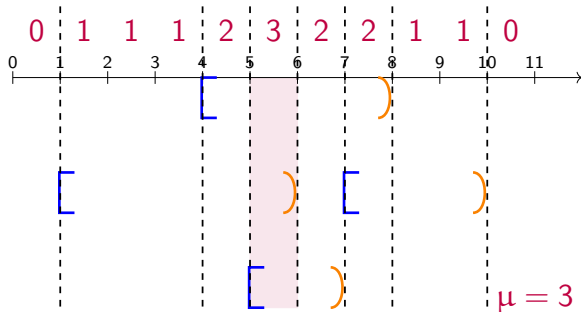
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Pathwidth μ

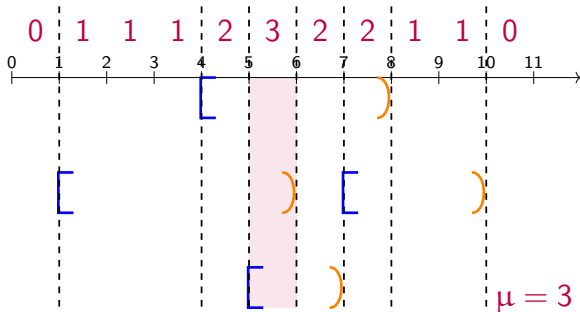
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



- [Munier 2021] $P|_{prec, p_j = 1, r_j, d_j} C_{max}$ is FPT parameterized by μ .

Pathwidth μ

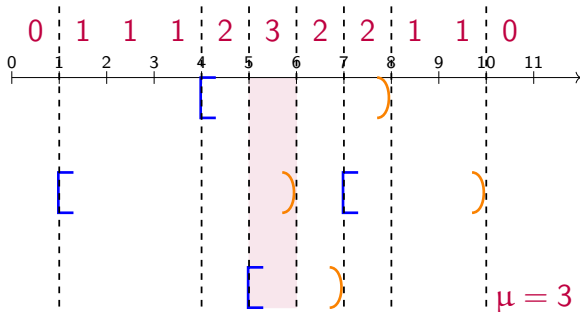
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



- [Munier 2021] $P|prec, p_j = 1, r_j, d_j|C_{max}$ is FPT parameterized by μ .
- [Bodlaender, Groenland, Jacob, Jaffke, Lima 2022]
 $P|prec, p_j = 1|C_{max}$ is XNLP-complete parameterized by $m + w$.

Parameter μ

Scheduling

Problem definition
Motivation

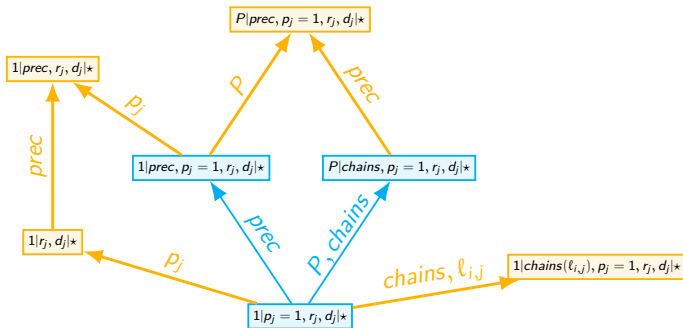
Parameterized Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work



Parameter μ

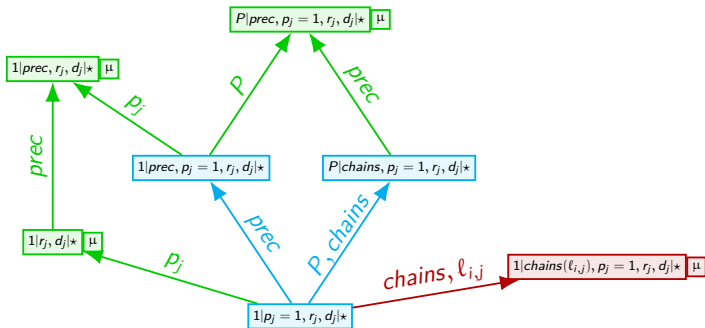
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Parameter μ

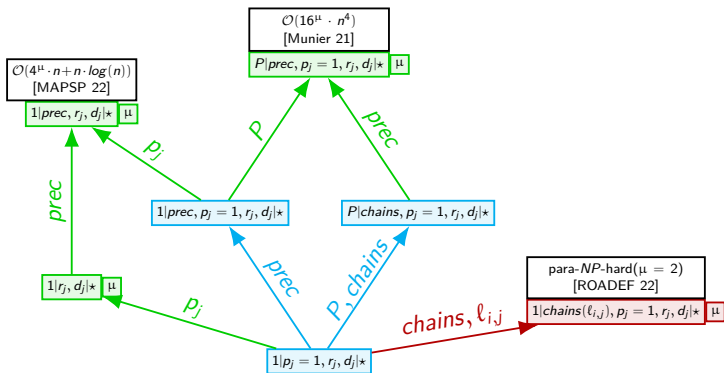
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Proving para- NP -hardness

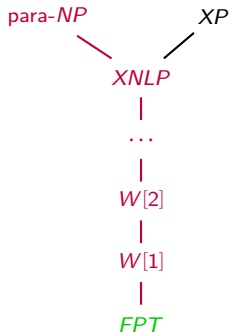
Scheduling

- Problem definition
- Motivation

Parameterized Complexity

- General
- Pathwidth**
- Pathwidth & maximum delay

Further work



Proving para- NP -hardness

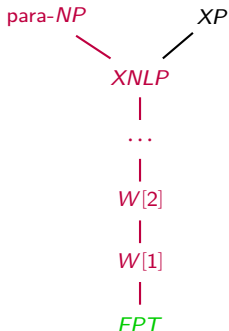
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



- [Flum, Grohe 1999] $(\mathcal{P}, k)$ is para- NP -complete iff $\mathcal{P}$ is NP -complete for some fixed value of k .

$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition

Motivation

Parameterized

Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

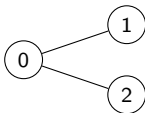
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

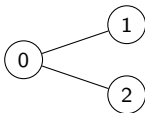
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



Vertex chain C_0

Vertex chain C_1

Vertex chain C_2

$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

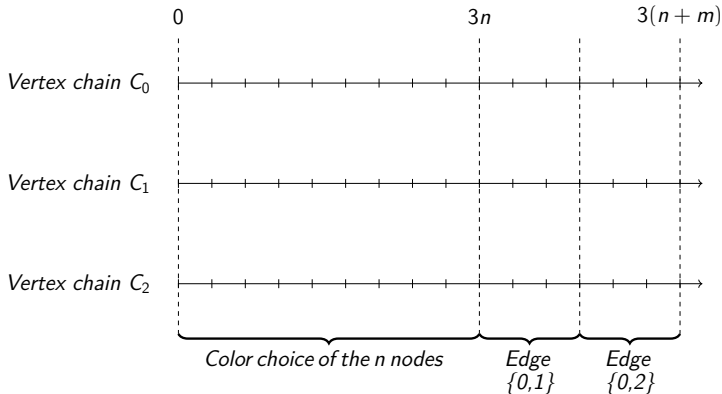
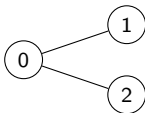
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E), n = |V|, m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

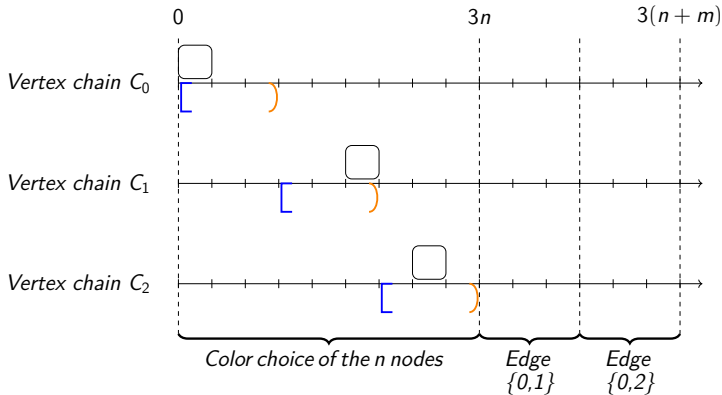
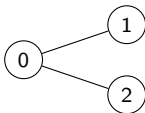
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

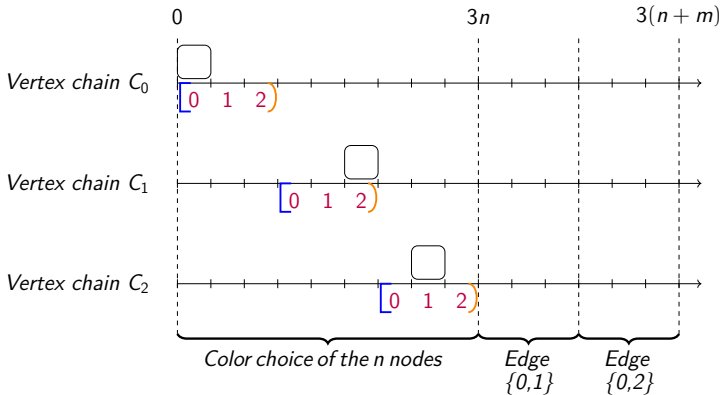
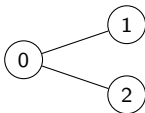
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

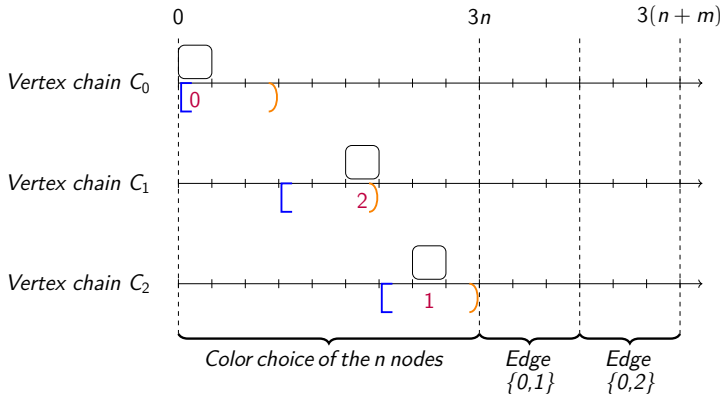
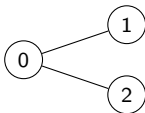
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

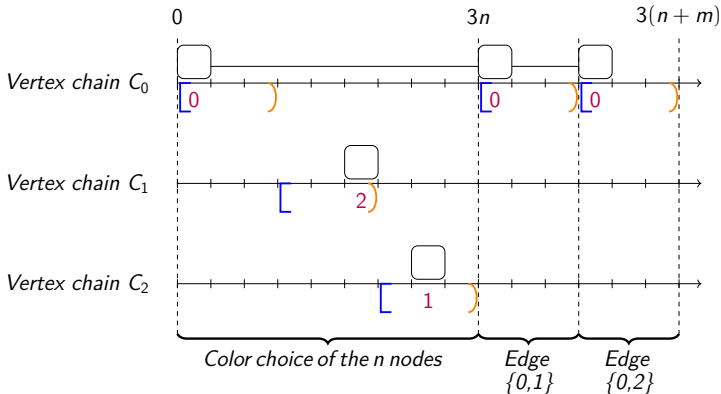
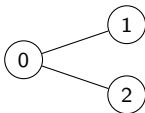
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

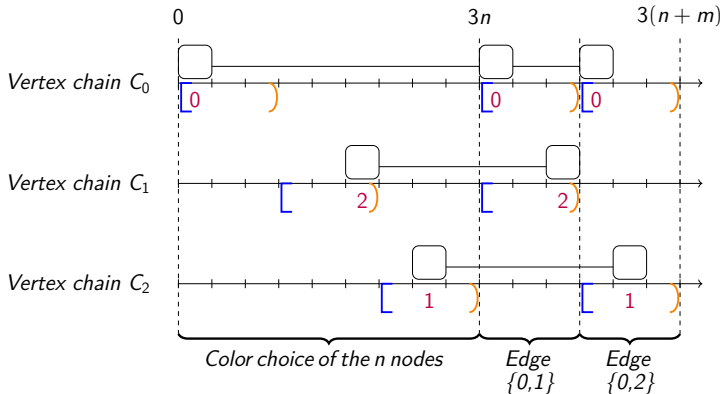
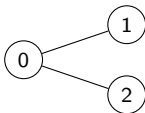
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E), n = |V|, m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

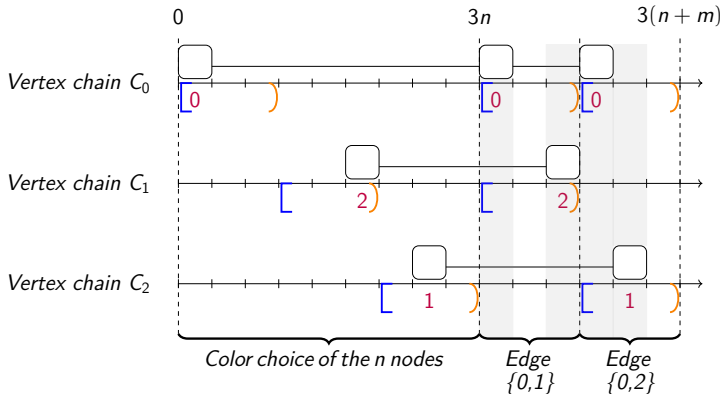
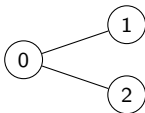
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



$1|chains(\ell_{i,j}^{ex}), p_j = 1, r_j, d_j| \star$, parameter $\mu = 2$

Scheduling

Problem definition
Motivation

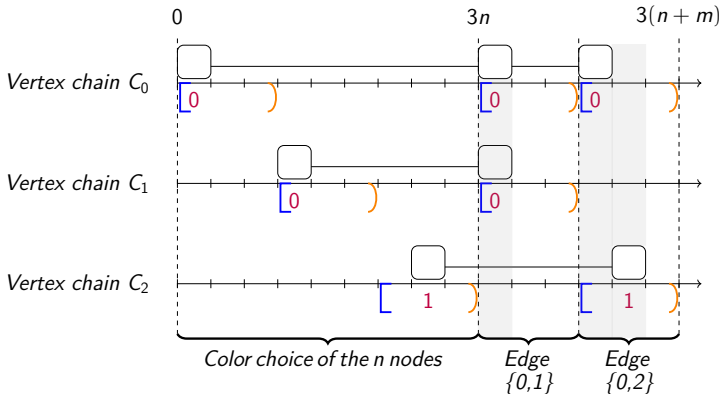
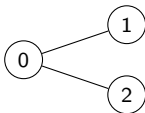
Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Reduction from 3-COLORING: $G = (V, E)$, $n = |V|$, $m = |E|$

Example:



Parameter μ

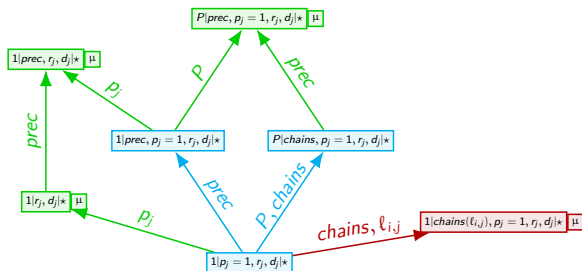
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Parameter μ

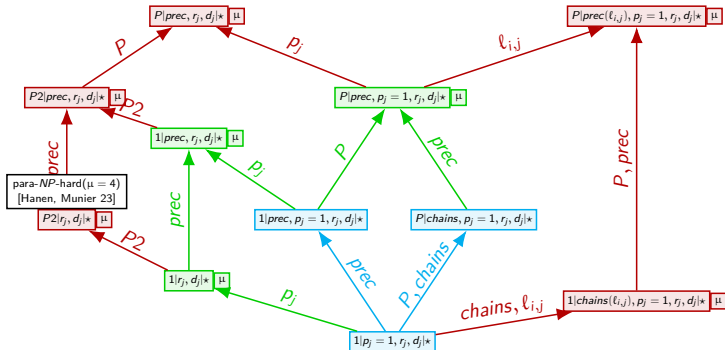
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Parameter μ

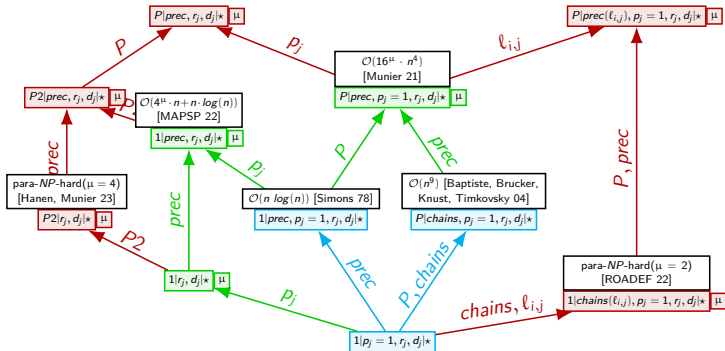
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Scheduling

Problem definition

Motivation

Parameterized
Complexity

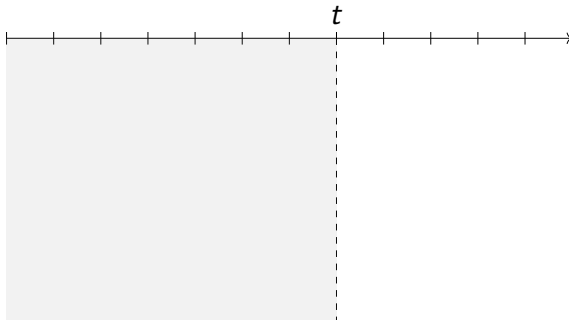
General

Pathwidth

Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



Scheduling

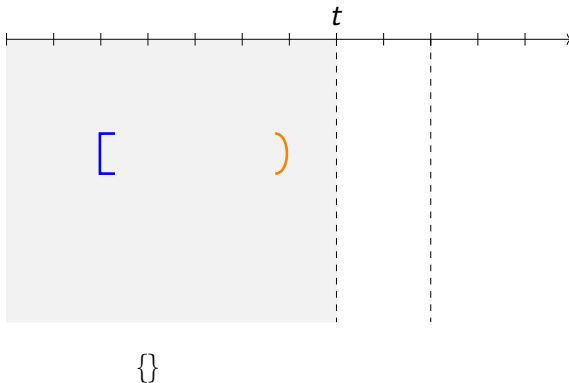
Problem definition
Motivation

Parameterized
Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



Scheduling

Problem definition

Motivation

Parameterized

Complexity

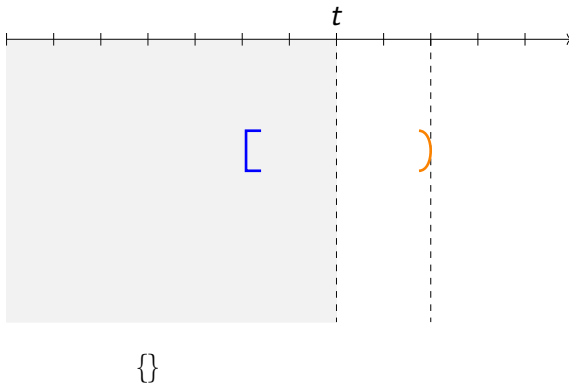
General

Pathwidth

Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



Scheduling

Problem definition

Motivation

Parameterized

Complexity

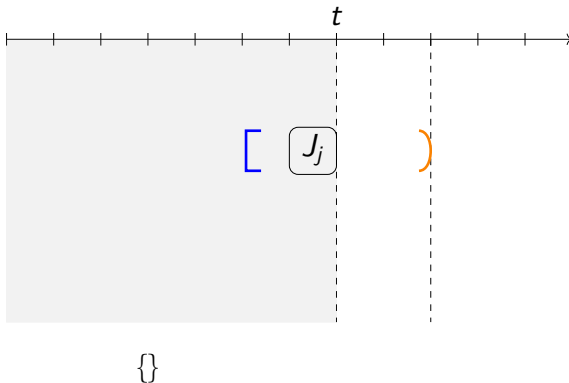
General

Pathwidth

Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



Scheduling

Problem definition

Motivation

Parameterized

Complexity

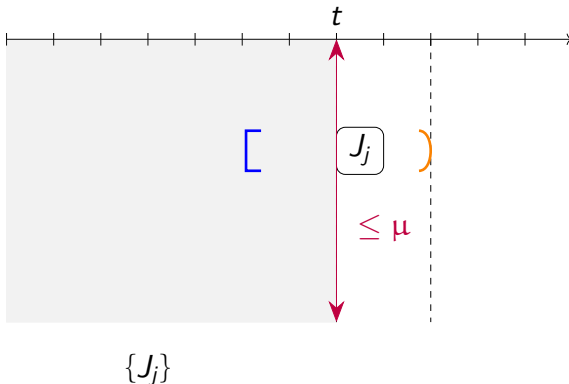
General

Pathwidth

Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



Scheduling

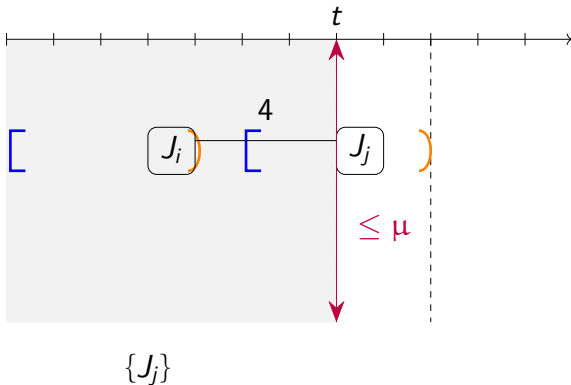
Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



Scheduling

Problem definition

Motivation

Parameterized

Complexity

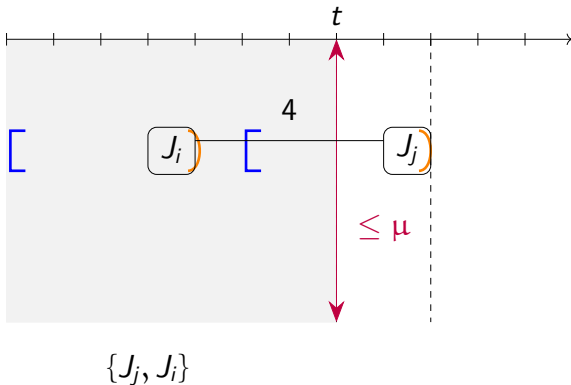
General

Pathwidth

Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



Scheduling

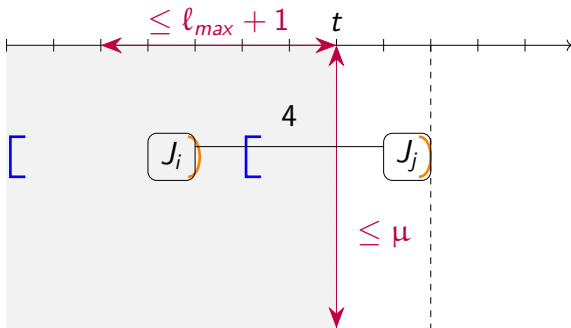
Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work

- Dynamic programming algorithm on active schedules



$$|\{J_j, J_i\}| = \mathcal{O}(\mu \times \ell_{\max})$$

Parameter $\mu + \ell_{max}$

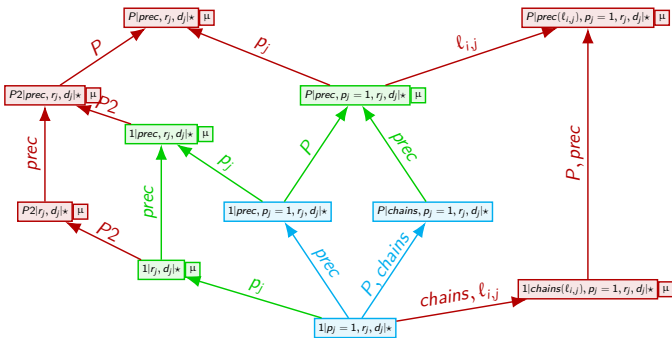
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



Parameter $\mu + \ell_{max}$

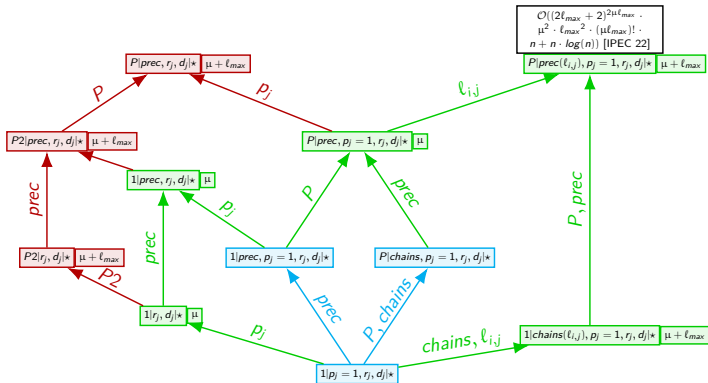
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



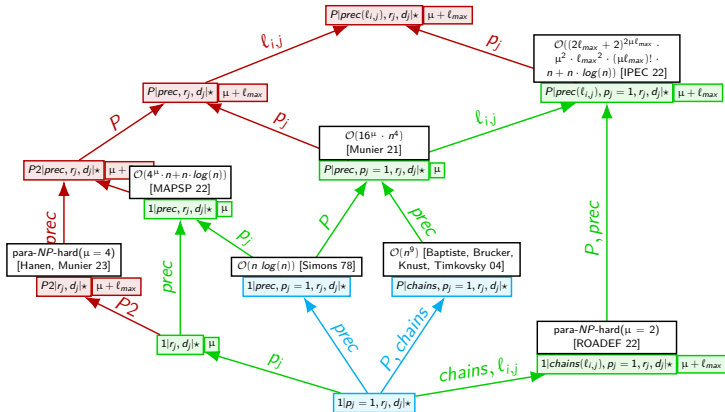
Parameter $\mu + \ell_{max}$

Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay
Further work



Scheduling

Problem definition

Motivation

Parameterized

Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

- *FPT* approximation results

Scheduling

Problem definition

Motivation

Parameterized

Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

- *FPT* approximation results
- New temporal-based structural parameters

Scheduling

Problem definition

Motivation

Parameterized

Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

- *FPT* approximation results
- New temporal-based structural parameters
- Find relations between parameters

Scheduling

Problem definition

Motivation

Parameterized

Complexity

General

Pathwidth

Pathwidth & maximum delay

Further work

- *FPT* approximation results
- New temporal-based structural parameters
- Find relations between parameters
 - Parallel machines: $m \leq \mu$
 - m : $P|prec, p_j = 1|C_{max}$ is *XNLP-hard*.
 - μ : $P|prec, p_j = 1, r_j, d_j|C_{max}$ is *FPT*.

$1|chains(\ell_{i,j}^{min}), p_j = 1, r_j, d_j|*, \text{ parameter } \mu = 3$

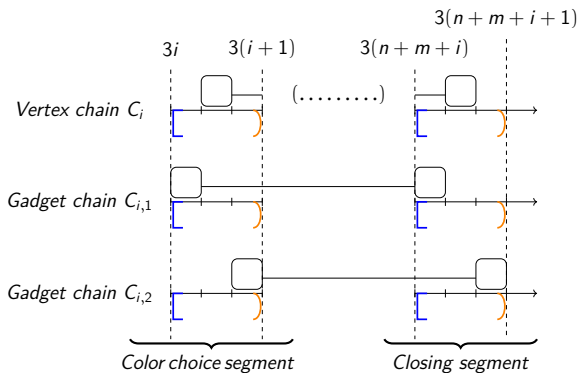
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



$1|chains(\ell_{i,j}^{min}), p_j = 1, r_j, d_j|*, \text{ parameter } \mu = 3$

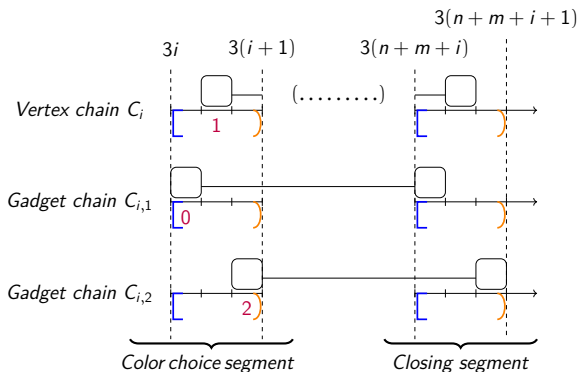
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



$1|chains(\ell_{i,j}^{min}), p_j = 1, r_j, d_j|*, \text{ parameter } \mu = 3$

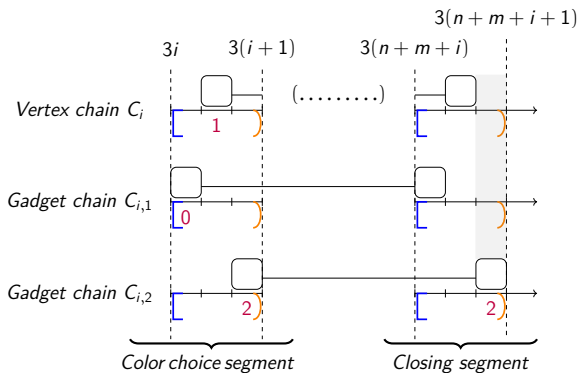
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



$1|chains(\ell_{i,j}^{min}), p_j = 1, r_j, d_j|*, \text{ parameter } \mu = 3$

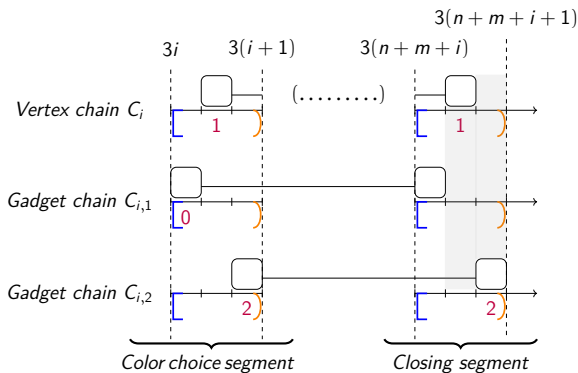
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work



$1|chains(\ell_{i,j}^{min}), p_j = 1, r_j, d_j|*, \text{ parameter } \mu = 3$

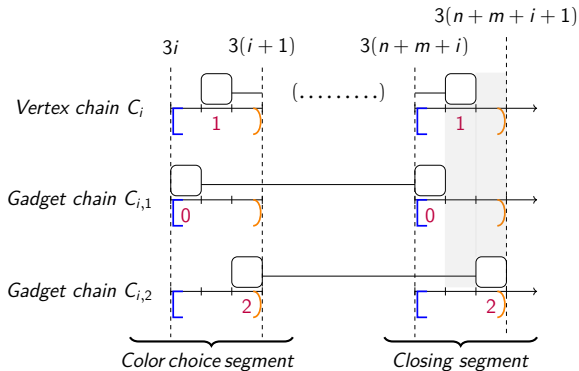
Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

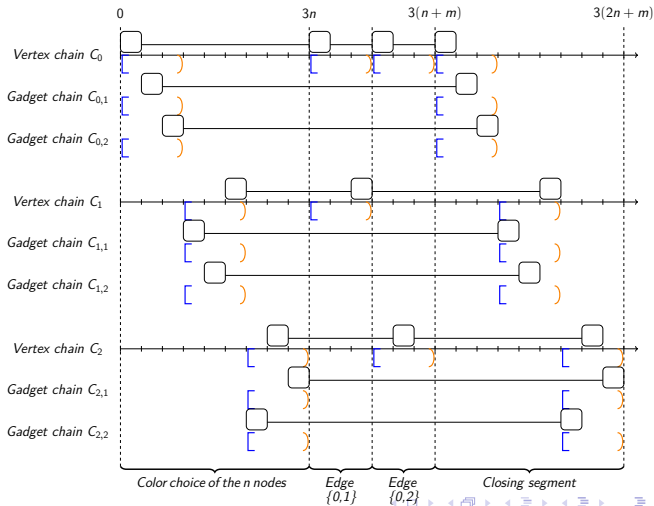
Further work



$1|chains(\ell_{i,j}^{min}), p_j = 1, r_j, d_j|*, \text{pathwidth } 3 \text{ (cont.)}$

- Reduction from 3-COLORING: $G = (V, E), n = |V|, m = |E|$

Example: $V = \{0, 1, 2\}, E = (\{0, 1\}, \{0, 2\})$



Scheduling

Problem definition
Motivation

Parameterized Complexity

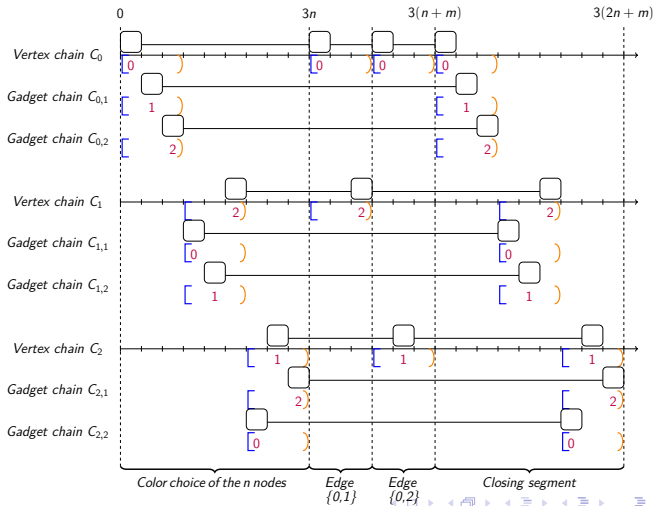
General
Pathwidth
Pathwidth & maximum delay

Further work

$1|chains(\ell_{i,j}^{min}), p_j = 1, r_j, d_j|*, \text{pathwidth } 3 \text{ (cont.)}$

- Reduction from 3-COLORING: $G = (V, E), n = |V|, m = |E|$

Example: $V = \{0, 1, 2\}, E = (\{0, 1\}, \{0, 2\})$



Scheduling

Problem definition
Motivation

Parameterized Complexity

General
Pathwidth
Pathwidth & maximum delay

Further work