

Monte Carlo Tree Search in Finding Feasible Solutions for Course Timetabling Problem

Say Leng Goh[#], Graham Kendall^{*}, Nasser R. Sabar⁺

[#]*Decision Sciences Lab, ISRG, Faculty of Computing and Informatics, Universiti Malaysia Sabah Labuan International Campus, Labuan, 87000, Malaysia.
E-mail: gohsayleng@yahoo.com*

^{*}*School of Computer Science, The University of Nottingham Malaysia Campus, Semenyih, Malaysia.
E-mail: Graham.Kendall@nottingham.edu.my*

⁺*Department of Computer Science and Information Technology, La Trobe University, Melbourne, Australia.
E-mail: nasser.sabar@gmail.com*

Abstract— We are addressing the course timetabling problem in this work. In a university, students can select their favorite courses each semester. Thus, the general requirement is to allow them to attend lectures without clashing with other lectures. A feasible solution is a solution where this and other conditions are satisfied. Constructing reasonable solutions for course timetabling problem is a hard task. Most of the existing methods failed to generate reasonable solutions for all cases. This is since the problem is heavily constrained and an effective method is required to explore and exploit the search space. We utilize Monte Carlo Tree Search (MCTS) in finding feasible solutions for the first time. In MCTS, we build a tree incrementally in an asymmetric manner by sampling the decision space. It is traversed in the best-first manner. We propose several enhancements to MCTS like simulation and tree pruning based on a heuristic. The performance of MCTS is compared with the methods based on graph coloring heuristics and Tabu search. We test the solution methodologies on the three most studied publicly available datasets. Overall, MCTS performs better than the method based on graph coloring heuristic; however, it is inferior compared to the Tabu based method. Experimental results are discussed.

Keywords— combinatorial optimization; timetabling; monte carlo tree search; graph coloring heuristics; tabu search.

I. INTRODUCTION

Course timetabling problem (CTP) involves allocating courses to time slots and rooms to produce a satisfactory timetable satisfying several constraints. CTP is a variant of the combinatorial optimization problem (COP). It is a widely studied NP-complete problem due to its practical importance to universities. A feasible course timetable prevents clashes of courses allowing students to attend all the lectures for courses registered. As a result, lecturers are not required to conduct replacement classes for the clashing courses. A feasible timetable ensures that lecture rooms fulfill the requirements of courses by having enough seats and teaching equipment such as overhead projector, audio/video, Internet connection etc. By having a feasible timetable, it is possible to conduct courses (possibly related) in a specific sequence. For instance, some courses may require that lectures be conducted before tutorials or vice-versa. Finally, a feasible

course timetable allows busy lecturers to perform courses at certain preferred times.

MCTS is considered as a comparatively new search methodology. It has caught the attention of the Artificial Intelligence (AI) community because of its success in the games area. The impact of MCTS in the territory of the game has inspired us to figure out the performance of MCTS in CTP which are dominated by local search methods. We apply MCTS in finding feasible solutions (solutions that fulfill all the hard constraints) for the first time. We propose several enhancements to MCTS, such as simulation and tree pruning based on a heuristic. The performance of MCTS is compared with that of the classical graph coloring approach as well as Tabu Search.

A. Problem Description

We are utilizing publicly available datasets (standard benchmarks) in this research. The datasets are **Socha** consists of 11 cases, **ITC02** consists of 20 cases, and **ITC07** consists of 24 cases. All the datasets have hard constraints,

namely, student can only attend one course at one time, a room must fulfill the features required by a course, a room must provide enough seats for a course, and only one course is allowed in every time slot and room. ITC07 has two extra hard constraints consist of a course that must be assigned to one of the preset time slots and a course may be required to appear in a certain sequence.

B. Related Work

MCTS based programs are now comparable with the best human players [1], [2], [3]. MCTS is well known in games AI but it is seldom used for COP. Examples of the application of MCTS in COP are job shop scheduling [4], one player puzzle [5], reentrant scheduling problem [6] and production management problems [7]. To our knowledge, MCTS has never been utilized on CTP.

Various approaches have been developed in finding feasible solutions for CTP. One common approach is utilizing graph coloring heuristics. A hybrid of graph coloring heuristics was employed to construct an early solution by Sabar et al. where events were randomly assigned to time slots and rooms after sorting them by heuristics such as largest degree, largest enrolment and saturation degree [8]. Interested readers may refer to [9] and [10].

Another common approach is based on Tabu search. To find a feasible solution, Cambazard et al. performed a local search on randomly generated solutions [11]. In order to avoid an event from being repeatedly allocated the identical time slots, a Tabu list is maintained for certain number of iterations. They used neighborhood structures such as transferring a course to a vacant place, exchanging two courses, exchanging two-time slots, matching (courses are unassigned and reassigned within a time slot), transferring a course using matching and Hungarian move. Other examples of this approach can be found in [12] and [13]. Some authors are using methods based on the combination of graph coloring heuristics and Tabu search in finding feasible solutions. 100% feasibility is attained for all the cases of ITC07 by Lewis and Thompson using constructive heuristics and then PARTIALCOL algorithm [14]. Unassigned events were handled using a Tabu mechanism [15]. Refer to [16] and [17] for other similar methods.

II. MATERIALS AND METHOD

A. MCTS

In MCTS, every state is constituted by a node in the tree and a directed link constitutes every action (leading to the state). Every node contains a value and a visit count. MCTS comprises four key steps specifically selection, expansion, simulation and back-propagation. These steps are repeated within available computation resources. Inside the selection step, the tree is covered from the root until a non-terminal node (with unvisited action) arrives. Inside the expansion step, a new child node is appended for the unvisited action. Inside the simulation step, a playout is carried out from the child node to generate an outcome. Inside the backpropagation step, the covered nodes (plus the child node) are updated with values from the outcome. Finally, the best child (child node having the greatest average value or visit

count) of the root node is the selected move. The process is depicted in Fig. 1, from [18].

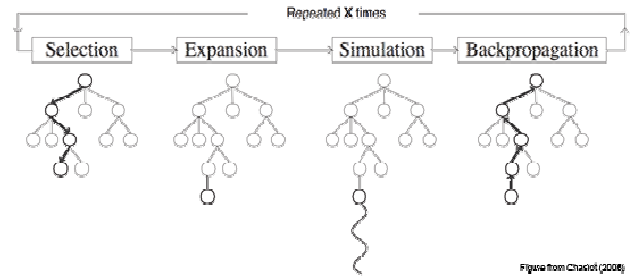


Fig. 1 MCTS

In our MCTS implementation, we assign events into time slots and use maximal matching for room assignment. The node and action classes are defined as shown in Fig. 2. Algorithm 1 shows the MCTS method. We set the initial solution $initSol$ to best solution $bestSol$, list of events E to unassigned events $unassigned$ and best cost $f(bestSol)$ to the number of events in E . We make a node as the root node $rootNode$. The iteration stops when the $terminationCondition$ is true (when either we found a feasible solution or the elapsed time passes execution time t). At the start of every iteration, we set the current solution $curSol$ to $initSol$, the list of remaining events $remaining$ to events in E and the list of visited nodes $visitedNode$ to vacant. We append the root node to $visitedNode$. Nodes visited during tree traversal are kept in the $visitedNode$.

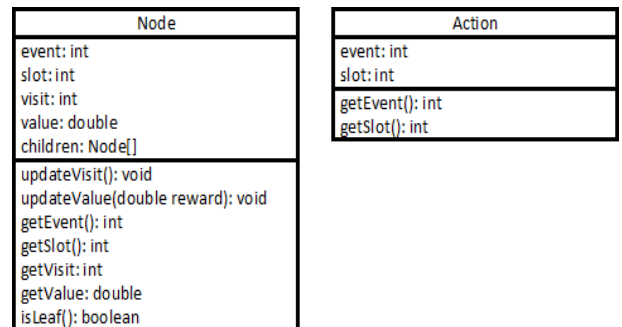


Fig. 2 Node and Action class definition

Algorithm 1

```

1: method MCTS ( $bestSol$ ,  $unassigned$ )
2:    $initSol \leftarrow bestSol$ 
3:    $E \leftarrow unassigned$ 
4:    $f(bestSol) \leftarrow |E|$ 
5:   make a node,  $rootNode$ 
6:   while  $terminationCondition = false$ 
7:      $curSol \leftarrow initSol$ 
8:      $remaining \leftarrow E$ 
9:      $visitedNode \leftarrow vacant$ 
10:     $visitedNode \leftarrow visitedNode \cup rootNode$ 
11:    TREEGROWTH ( $curSol$ ,  $rootNode$ ,  $visitedNode$ ,  $remaining$ )
12:     $reward \leftarrow SIMULATION(curSol, bestSol, f(bestSol), unassigned, remaining, E)$ 
13:    BACKPROPAGATION ( $reward$ ,  $visitedNode$ )
14:  end while
15: end method

```

TREEGROWTH method is given in Algorithm 2. We set the *currentNode* to *rootNode*. While *currentNode* is not a leaf node, we select one of the children of *currentNode* as the current node by using the SELECTION method in Algorithm 7. We then append the current node to *visitedNode*. The event of *currentNode* is assigned to *curSol* according to the time slot of *currentNode*. We then remove that event from *remaining*. We try to expand the tree from the leaf node if the *currentNode* is leaf node. All the possible actions are selected and stored in the list of actions *A* by the GETACTIONS method (Algorithm 8). If *A* is not vacant, we append all actions in *A* as the children of *currentNode* using the EXPANSION method (Algorithm 11). We randomly choose one of the children as the child node *childNode* and append it to *visitedNode*. The event of *childNode* is assigned to *curSol* according to the time slot of *childNode*. We then remove that event from *remaining*.

Algorithm 2

```

1: method TREEGROWTH (curSol, rootNode, visitedNode,
remaining)
2:   currentNode  $\leftarrow$  rootNode
3:   while currentNode is not leaf
4:     currentNode  $\leftarrow$  SELECTION (currentNode)
5:     visitedNode  $\leftarrow$  visitedNode  $\cup$  currentNode
6:     curSol  $\leftarrow$  curSol  $\cup$  currentNode.event
7:     remaining  $\leftarrow$  remaining  $-$  currentNode.event
8:   end while
9:   A  $\leftarrow$  GETACTIONS (remaining, curSol)
10:  if A is not vacant
11:    EXPANSION (currentNode, A)
12:    childNode  $\leftarrow$  select one of currentNode.children
    randomly
13:    visitedNode  $\leftarrow$  visitedNode  $\cup$  childNode
14:    curSol  $\leftarrow$  curSol  $\cup$  childNode.event
15:    remaining  $\leftarrow$  remaining  $-$  childNode.event
16:  end if
17: end method

```

SIMULATION method is presented in Algorithm 3. We assign events to time slots in *curSol*. An event in *remaining* is returned according to heuristics by SELECTEVENT. SELECTTIMESLOT returns a time slot that is suitable for *event*. Dynamic Search Rearrangement (DSR) is used for event and time slot selection as it is the most effective heuristic based on experience. *unplaced* is a list of unplaced events that keeps events without any compatible time slot. We calculate $f(\text{curSol})$ as the number of events in *unplaced*. *bestSol*, $f(\text{bestSol})$ and *unassigned* are updated if $f(\text{curSol})$ is superior than $f(\text{bestSol})$. As reward is specified as the ratio of assigned events to the number of events, reward in the range of 0 to 1 is returned.

Algorithm 3

```

1: method SIMULATION (curSol, bestSol,  $f(\text{bestSol})$ ,
unassigned, remaining, E)
2:   unplaced  $\leftarrow$  vacant
3:   size  $\leftarrow$   $|$ remaining $|$ 
4:   for  $i = 1$  to size
5:     event  $\leftarrow$  SELECTEVENT (remaining, curSol)
6:     timeSlot  $\leftarrow$  SELECTTIMESLOT (event, remaining,
curSol)
7:     if timeSlot is not null
8:       curSol  $\leftarrow$  curSol  $\cup$  event //assign event to timeSlot

```

```

9:     else
10:       unplaced  $\leftarrow$  unplaced  $\cup$  event
11:     end if
12:     remaining  $\leftarrow$  remaining  $-$  event
13:   end for
14:    $f(\text{curSol}) \leftarrow |$ unplaced $|$ 
15:   if  $f(\text{curSol}) < f(\text{bestSol})$ 
16:     bestSol  $\leftarrow$  curSol
17:      $f(\text{bestSol}) \leftarrow f(\text{curSol})$ 
18:     unassigned  $\leftarrow$  unplaced
19:   end if
20:   return  $(|E| - |$ unplaced $|) / |E|$ 
21: end method

```

BACKPROPAGATION method is shown in Algorithm 4. We update the visit and value attribute of every node in *visitedNode*. We increment the visit count and update the value as a cumulative mean of reward.

Algorithm 4

```

1: method BACKPROPAGATION (reward, visitedNode)
2:   for all node in visitedNode
3:     node.updateVisit()
4:     node.updateValue(reward)
5:   end for
6: end method

```

We describe the SELECTION, GETACTIONS and EXPANSION methods stated earlier in detail below. In SELECTION method (Algorithm 5), we return a child with the highest UCB value among the children of *currentNode*. We balance the search exploration and exploitation by adjusting the constant *B*. More priority is given to the less frequently visited nodes when *B* is set higher. We set *B* as 0.0001.

Algorithm 5

```

1: method SELECTION (currentNode)
2:   return  $\arg \max_{i \in \text{children of } \text{currentNode}} \text{value}_i +$ 
 $B \sqrt{\frac{\ln \text{visit}_{\text{currentNode}}}{\text{visit}_i}}$ 
3: end method

```

GETACTIONS method is given Algorithm 6. To avoid the tree from getting too wide, we apply several heuristics used in graph coloring to filtrate the actions. Effectively, we prune the tree based on heuristics. Bear in mind that an action comprises of an event and a time slot. Events in *remaining* are returned based on heuristics by GETEVENTS. GETTIMESLOTS returns time slots that are suitable for *e*.

Algorithm 6

```

1: method GETACTIONS (remaining, curSol)
2:   A  $\leftarrow$  vacant
3:   E  $\leftarrow$  GETEVENTS (remaining, curSol)
4:   for all  $e$  in E
5:     TS  $\leftarrow$  GETTIMESLOTS ( $e$ , remaining, curSol)
6:     for all  $ts$  in TS
7:       A  $\leftarrow$   $A \cup \text{action}(e, ts)$ 
8:     end for
9:   end for
10:  return A
11: end method

```

EXPANSION method is shown in Algorithm 7. We append all actions in A as children of $currentNode$. Unlike the general implementation of MCTS (where a child node is appended whenever an unvisited action is encountered), we append multiple nodes at one time. Our intention is to save computation cost with the sacrifice of some memory.

Algorithm 7

```

1: method EXPANSION ( $currentNode, A$ )
2:   append all actions in  $A$  as children of  $currentNode$ 
3: end method

```

B. Benchmark: Graph Colouring Heuristic (GCH)

In the graph coloring problem, GCH is considered a classical approach. The heuristics derived from graph coloring problem are often utilized in CTP. Usually, difficult events are assigned first with the hope that easier events will be assigned later as the environment getting more restricted. Algorithm 8 presents the GCH method. At every iteration, an event is selected and assigned to a selected time slot. It is a one-pass method. In our experiments, Dynamic Search Rearrangement (DSR) [19] is utilized. DSR is a heuristic often used in constraint satisfaction problem. It is dynamic as the next selected event is determined at every iteration. In DSR, we select an event randomly from the set $E=\{\text{events with the least number of suitable time slots}\}$. Next, we select a $timeSlot$ randomly from the set $P=\{\text{time slots suitable for event and fit the least number of left events}\}$.

Algorithm 8

```

1: method GCH ( $bestSol, unassigned$ )
2:    $remaining \leftarrow unassigned$ 
3:    $unplaced \leftarrow \text{vacant}$ 
4:    $size \leftarrow |remaining|$ 
5:   for  $i = 1$  to  $size$ 
6:      $event \leftarrow \text{SELECTEVENT}(remaining)$ 
7:      $timeSlot \leftarrow \text{SELECTTIMESLOT}(event)$ 
8:     if  $timeSlot$  is not null
9:        $bestSol \leftarrow bestSol \cup event$  //assign event to timeSlot
10:    else
11:       $unplaced \leftarrow unplaced \cup event$ 
12:    end if
13:     $remaining = remaining - event$ 
14:  end for
15:   $unassigned \leftarrow unplaced$ 
16: end method

```

C. Benchmark: Tabu Search (TS)

PARTIALCOL [14] was originally utilized in addressing graph coloring problems. [16], [20] and [15] adapted the algorithm in solving CTP. The TS method we tested here is based on PARTIALCOL. A neighbor move is a move of one event from $unplaced$ to a time slot in $curSol$. At every iteration, we evaluate all the neighborhood moves by taking into consideration all suitable non-Tabu time slots for entire events in $unplaced$. All events conflicting with e (precedence or clash constraint) are temporarily shifted from $curSol$ to $unplaced$ in order to move an event e into a time slot feasibly. Maximal matching is used for room assignment sparingly as it is computationally expensive. A room is selected randomly among the suitable rooms and the relevant event is shifted from $curSol$ to $unplaced$ in case matching could not find a room for the specific event. We assess solutions

($curSol, canSol, bestSol$) utilizing the cost function f based on the number of unplaced events as given in Equation 1:

$$\sum_{e \in unplaced} 1 \quad (1)$$

We record the neighbor move with the lowest candidate cost $f(canSol)$ as $bestEvent$ and $bestSlot$. We move the events conflicting with $bestEvent$ from $curSol$ to $unplaced$. We applied the best neighbor move by moving the $bestEvent$ from $unplaced$ to the $bestSlot$ of $curSol$. If $f(curSol)$ is superior than $f(bestSol)$, $bestSol$, $f(bestSol)$ and $unassigned$ are updated. We prevent the events conflicting with $bestEvent$ from returning to their original time slots for some iterations by utilizing the Tabu tenure in Equation 2:

$$\text{RANDOM}[10) + |unplaced| \quad (2)$$

where $|unplaced|$ is the number of unplaced events. We use the value 10 for the random element as the same value was used in [14], [15] and [20] and more importantly, it works well for all the datasets that we are working on. The value of Tabu tenure determines the level of search exploration. Most of the available moves are not reachable thus restricting the search when the value of Tabu tenure is set too high. Meanwhile, cycling tends to occur which may stall the search when the value is set too low. The iteration stops when a feasible solution is found ($unplaced$ is vacant) or the elapsed time passes execution time t .

III. RESULTS AND DISCUSSION

We conducted the experiments on Intel Xeon (3.1GHz) with 4Gb RAM machines. We coded the algorithms utilizing Java language. The computation time limit (which is set by executing a benchmark program) for every execution is $T=190$ seconds.

A. Random Simulation vs. Heuristic Based Simulation

Domain knowledge is incorporated into playouts in order to make the simulation in MCTS more realistic [21], [22]. Here, the results of random simulation (random selection of events and time slots) and heuristic-based simulation (DSR) are compared. We attained 100% feasibility for Socha and ITC02 cases (as shown in Table I and II) when a heuristic is applied in the simulation phase of MCTS. As shown in Table III, MCTS with heuristic-based simulation is more effective than the one with random simulation for all the ITC07 cases. The algorithm encountered insufficient heap memory issue in the tree growth phase of MCTS, therefore no result is available as indicated by the dash symbols in Table II and III. In fact, we have extended the default heap memory size from 256Mb to 1.5Gb. However, the allotted 1.5Gb heap memory was worn out during the executions. An error message was prompted indicating this issue. Note that the tree is expanded by using all the possible actions (every action involves assigning an event to a time slot). Obviously, the results of random simulation are improved by heuristic based simulation for all the datasets considered.

TABLE I
HEURISTIC BASED VS RANDOM SIMULATION ON SOCHA CASES. SHOWN IS (MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31 EXECUTIONS.

Case	Simulation	
	DSR	Random
Small01	(0.00, 0)	(0.00, 0)
Small02	(0.00, 0)	(0.00, 0)
Small03	(0.00, 0)	(0.00, 0)
Small04	(0.00, 0)	(0.00, 0)
Small05	(0.00, 0)	(0.00, 0)
Medium01	(0.00, 0)	(4.42, 3)
Medium02	(0.00, 0)	(6.06, 5)
Medium03	(0.00, 0)	(10.71, 8)
Medium04	(0.00, 0)	(3.71, 2)
Medium05	(0.00, 0)	(13.10, 10)
Large	(0.00, 0)	(35.94, 34)
Avg.	(0.00, -)	(6.72, -)

TABLE II
HEURISTIC BASED VS RANDOM SIMULATION ON ITC02 CASES. SHOWN IS (MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31 EXECUTIONS.

Case	Simulation	
	DSR	Random
01	(0.00, 0)	(14.52, 12)
02	(0.00, 0)	(10.74, 9)
03	(0.00, 0)	(11.48, 10)
04	(0.00, 0)	(20.16, 18)
05	(0.00, 0)	-
06	(0.00, 0)	-
07	(0.00, 0)	(10.68, 9)
08	(0.00, 0)	(12.71, 10)
09	(0.00, 0)	(10.35, 6)
10	(0.00, 0)	(17.13, 14)
11	(0.00, 0)	(15.29, 13)
12	(0.00, 0)	(19.26, 17)
13	(0.00, 0)	(15.26, 13)
14	(0.00, 0)	(16.06, 15)
15	(0.00, 0)	(14.52, 13)
16	(0.00, 0)	(5.68, 2)
17	(0.00, 0)	-
18	(0.00, 0)	(10.00, 7)
19	(0.00, 0)	(13.90, 12)
20	(0.00, 0)	(6.35, 5)
Avg.	(0.00, -)	(13.18, -)

TABLE III
HEURISTIC BASED VS RANDOM SIMULATION ON ITC07 CASES. SHOWN IS (MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31 EXECUTIONS.

Case	Simulation	
	DSR	Random
01	(15.90, 14)	(73.39, 67)
02	(25.19, 20)	-
03	(0.00, 0)	-
04	-	-
05	-	-
06	(5.55, 2)	-
07	-	-
08	(0.00, 0)	-
09	(24.77, 22)	(78.97, 76)
10	(32.58, 29)	(89.58, 86)
11	(0.00, 0)	-
12	-	-
13	(9.39, 7)	-
14	-	-
15	(0.00, 0)	-

16	(0.00, 0)	-
17	(0.00, 0)	-
18	-	-
19	-	-
20	(0.00, 0)	(36.58, 34)
21	(3.35, 2)	(67.23, 65)
22	(54.58, 52)	(131.39, 127)
23	-	-
24	-	-
Avg.	(11.42, -)	(79.52, -)

B. Heuristic Based Tree Pruning

We attempt to prune the tree in MCTS to address the memory issue faced earlier. We expand the tree by using a certain number of actions (an action involves assigning an event to a time slot) instead of all actions at one time (as in the previous section). Several heuristic-based pruning mechanisms is compared in this section. The idea is inspired by the work in [23], [24], [25] where the authors utilized domain knowledge for pruning. We present the descriptions of the heuristics based on Algorithm 8 in Table IV. Note that simulation based on DSR is used here due to its effectiveness, as shown in the previous section.

TABLE IV
TREE PRUNING HEURISTICS.

Heuristics	Description
DSR	All events having the least number of suitable time slots, $E=\{e_1, e_2, \dots, e_m\}$ is returned by GETEVENTS method. All-time slots suitable for e_m and fit the least number of remaining events, $S=\{s_1, s_2, \dots, s_n\}$ are returned by GETTIMESLOTS method.
LD-All	All events having the most number of clashes with other events, $E=\{e_1, e_2, \dots, e_m\}$ is returned by GETEVENTS method. All time slots suitable for e_m , $S=\{s_1, s_2, \dots, s_n\}$ are returned by GETTIMESLOTS method.
MV-All	All events having the least number of suitable time slots, $E=\{e_1, e_2, \dots, e_m\}$ is returned by GETEVENTS method. All time slots suitable for e_m , $S=\{s_1, s_2, \dots, s_n\}$ are returned by GETTIMESLOTS method.
SD-All	All events having the most number of clashes with other events, $E_2=\{e_1, e_2, \dots, e_m\}$ where $E_2 \subset E_1$ and E_1 ={events with the least number of suitable time slots} is returned by GETEVENTS method. All time slots suitable for e_m , $S=\{s_1, s_2, \dots, s_n\}$ are returned by GETTIMESLOTS method.

As shown in Table V and VI, 100% feasibility is attained for Socha and ITC02 cases regardless of heuristics applied for tree pruning. The same result is achieved even without pruning showing that these datasets are not challenging.

TABLE V
COMPARING TREE PRUNING HEURISTICS ON SOCHA CASES. SHOWN IS (MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31 EXECUTIONS.

Case	Tree Pruning Heuristics			
	MV-All	LD-All	SD-All	DSR
Small01	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Small02	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Small03	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Small04	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Small05	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Medium01	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Medium02	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Medium03	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Medium04	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Medium05	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)

Large	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Avg.	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)

TABLE VI
COMPARING TREE PRUNING HEURISTICS ON ITC02 CASES. SHOWN IS (MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31 EXECUTIONS.

Case	Tree Pruning Heuristics			
	MV-All	LD-All	SD-All	DSR
01	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
02	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
03	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
04	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
05	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
06	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
07	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
08	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
09	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
10	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
11	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
12	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
13	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
14	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
15	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
16	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
17	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
18	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
19	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
20	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
Avg.	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)

Memory issues are no longer faced when tree pruning is used in ITC07 cases. The maximum heap memory commitment during 31 executions for every problematic case in the previous section is presented in Table VII. Now, the maximum heap memory commitment is way below 1.5Gb (the allotted size). Note that we measured the heap memory sizes utilizing a tool supplied by Java Development Kit (JDK) called as Java Monitoring and Management Console.

TABLE VII
THE MAXIMUM MEMORY (Mb) COMMITTED DURING 31 EXECUTIONS FOR SELECTED ITC07 CASES.

Case	Maximum Heap Memory Commitment (Gb)
04	0.0272
05	0.1306
07	0.0241
12	0.0564
14	0.1471
18	0.0278
19	0.1587
23	0.1781
24	0.1343

Among the pruning heuristic tested, MV-All is the most promising one as feasible solutions were found for all cases exclude cases 1, 2, 9, 10 and 22 as evident in Table VIII. Excitingly, these results are compatible with those of a constraint programming approach [11] which also could not construct a feasible solutions for cases 1, 2, 9 and 10. The author did not consider case 22 in his experiment which is possibly hidden by the competition organizer at that point in time. From observation, we get better results when pruning is applied using any heuristic. With pruning, the tree size is considerably reduced. In effect, pruning eliminates poor

choices and guides the search to concentrate more time on finer options.

TABLE VIII
COMPARING TREE PRUNING HEURISTICS ON ITC07 CASES. SHOWN IS (MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31 EXECUTIONS.

Case	Tree Pruning Heuristics			
	MV-All	LD-All	SD-All	DSR
01	(6.39, 3)	(7.13, 3)	(6.87, 3)	(6.94, 3)
02	(11.19, 6)	(16.77, 11)	(12.13, 9)	(12.77, 7)
03	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
04	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
05	(0.03, 0)	(0.23, 0)	(0.16, 0)	(1.84, 0)
06	(0.29, 0)	(0.61, 0)	(0.42, 0)	(0.90, 0)
07	(0.00, 0)	(0.00, 0)	(0.03, 0)	(0.13, 0)
08	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
09	(16.97, 14)	(17.61, 13)	(15.16, 9)	(14.39, 10)
10	(19.71, 15)	(24.48, 17)	(21.77, 16)	(18.74, 14)
11	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
12	(0.00, 0)	(0.00, 0)	(0.06, 0)	(1.35, 0)
13	(1.13, 0)	(2.29, 1)	(1.26, 0)	(2.58, 0)
14	(0.84, 0)	(1.55, 0)	(2.19, 0)	(3.29, 1)
15	(0.00, 0)	(0.06, 0)	(0.00, 0)	(0.10, 0)
16	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
17	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
18	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.68, 0)
19	(2.77, 0)	(3.16, 1)	(8.26, 4)	(10.61, 6)
20	(0.00, 0)	(0.00, 0)	(0.00, 0)	(0.00, 0)
21	(1.10, 0)	(1.03, 0)	(0.39, 0)	(0.74, 0)
22	(44.68, 41)	(49.06, 46)	(40.45, 31)	(34.87, 28)
23	(6.16, 0)	(13.97, 7)	(9.23, 2)	(8.77, 2)
24	(0.06, 0)	(0.35, 0)	(1.61, 0)	(4.42, 1)
Avg.	(4.64, -)	(5.76, -)	(5.00, -)	(5.13, -)

C. Comparing MCTS with GCH and TS

The attainment of MCTS, GCH, and TS in finding feasible solutions is compared in this section. The GCH considered here is based on the DSR heuristic. While for the MCTS, MV-All and DSR heuristics are utilized for the tree pruning and simulation phase respectively. As shown in Table IX, all three methods found feasible solutions for all Socha cases. Both MCTS and TS attained 100% feasibility.

TABLE IX
COMPARING MCTS, GCH, AND TS ON SOCHA CASES. SHOWN IS (FEASIBILITY %, MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31 EXECUTIONS.

Case	MCTS	GCH	TS
Small01	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
Small02	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
Small03	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
Small04	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
Small05	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
Medium01	(100, 0.00, 0)	(6, 5.00, 0)	(100, 0.00, 0)
Medium02	(100, 0.00, 0)	(29, 2.55, 0)	(100, 0.00, 0)
Medium03	(100, 0.00, 0)	(74, 0.48, 0)	(100, 0.00, 0)
Medium04	(100, 0.00, 0)	(10, 3.52, 0)	(100, 0.00, 0)
Medium05	(100, 0.00, 0)	(71, 0.68, 0)	(100, 0.00, 0)
Large	(100, 0.00, 0)	(3, 6.48, 0)	(100, 0.00, 0)

As shown in Table X, feasible solutions are found by all the three methods for all the ITC02 cases. However, only MCTS can attain 100% feasibility for all the circumstances. TS obtains 100% feasibility for the entire cases excluding claim 7 (87%).

TABLE X
COMPARING MCTS, GCH, AND TS ON ITC02 CASES. SHOWN IS
(FEASIBILITY %, MEAN UNASSIGNED, BEST UNASSIGNED,) FOR N=31
EXECUTIONS.

Case	MCTS	GCH	TS
01	(100, 0.00, 0)	(84, 0.23, 0)	(100, 0.00, 0)
02	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
03	(100, 0.00, 0)	(81, 0.39, 0)	(100, 0.00, 0)
04	(100, 0.00, 0)	(10, 7.26, 0)	(100, 0.00, 0)
05	(100, 0.00, 0)	(97, 0.03, 0)	(100, 0.00, 0)
06	(100, 0.00, 0)	(74, 0.74, 0)	(100, 0.00, 0)
07	(100, 0.00, 0)	(100, 0.00, 0)	(87, 0.13, 0)
08	(100, 0.00, 0)	(90, 0.29, 0)	(100, 0.00, 0)
09	(100, 0.00, 0)	(81, 0.42, 0)	(100, 0.00, 0)
10	(100, 0.00, 0)	(42, 1.16, 0)	(100, 0.00, 0)
11	(100, 0.00, 0)	(10, 4.68, 0)	(100, 0.00, 0)
12	(100, 0.00, 0)	(87, 0.19, 0)	(100, 0.00, 0)
13	(100, 0.00, 0)	(60, 0.77, 0)	(100, 0.00, 0)
14	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
15	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)
16	(100, 0.00, 0)	(32, 2.48, 0)	(100, 0.00, 0)
17	(100, 0.00, 0)	(71, 0.65, 0)	(100, 0.00, 0)
18	(100, 0.00, 0)	(97, 0.03, 0)	(100, 0.00, 0)
19	(100, 0.00, 0)	(65, 0.94, 0)	(100, 0.00, 0)
20	(100, 0.00, 0)	(100, 0.00, 0)	(100, 0.00, 0)

Table XI presents the result comparison of the three methods applied to ITC07 cases. TS is the only methodology that can find feasible solutions for the entire cases. GCH obtained feasible solutions for 5 (cases 3, 8, 16, 17 and 20) out of the 24 cases. Meantime, MCTS obtained feasible solutions for all the cases exclude cases 1, 2, 9, 10 and 22. In truth, none of the methods could accomplish 100% feasibility for all the cases. TS performed competently with 100% feasibility for all the cases excluding cases 11, 19 and 23.

TABLE XI
COMPARING MCTS, GCH, AND TS ON ITC07 CASES. SHOWN IS
(FEASIBILITY %, MEAN UNASSIGNED, BEST UNASSIGNED) FOR N=31
EXECUTIONS.

Case	MCTS	GCH	TS
01	(0, 6.39, 3)	(0, 34.29, 26)	(100, 0.00, 0)
02	(0, 11.19, 6)	(0, 45.03, 36)	(100, 0.00, 0)
03	(100, 0.00, 0)	(10, 4.35, 0)	(100, 0.00, 0)
04	(100, 0.00, 0)	(0, 9.94, 4)	(100, 0.00, 0)
05	(97, 0.03, 0)	(0, 20.42, 13)	(100, 0.00, 0)
06	(72, 0.29, 0)	(0, 20.26, 11)	(100, 0.00, 0)
07	(100, 0.00, 0)	(0, 11.87, 6)	(100, 0.00, 0)
08	(100, 0.00, 0)	(3, 4.97, 0)	(100, 0.00, 0)
09	(0, 16.97, 14)	(0, 43.26, 32)	(100, 0.00, 0)
10	(0, 19.71, 15)	(0, 53.29, 43)	(100, 0.00, 0)
11	(100, 0.00, 0)	(0, 7.10, 1)	(87, 0.26, 0)
12	(100, 0, 0.00)	(0, 14.26, 4)	(100, 0.00, 0)
13	(23, 1.13, 0)	(0, 25.26, 17)	(100, 0.00, 0)
14	(42, 0.84, 0)	(0, 24.81, 16)	(100, 0.00, 0)
15	(100, 0.00, 0)	(0, 9.97, 5)	(100, 0.00, 0)
16	(100, 0.00, 0)	(10, 2.39, 0)	(100, 0.00, 0)
17	(100, 0.00, 0)	(42, 1.26, 0)	(100, 0.00, 0)
18	(100, 0.00, 0)	(0, 17.61, 10)	(100, 0.00, 0)
19	(6, 2.77, 0)	(0, 30.23, 23)	(81, 0.29, 0)
20	(100, 0.00, 0)	(13, 2.52, 0)	(100, 0.00, 0)
21	(13, 1.10, 0)	(0, 14.65, 10)	(100, 0.00, 0)
22	(0, 44.68, 41)	(0, 74.16, 63)	(100, 0.00, 0)
23	(3, 6.16, 0)	(0, 52.81, 40)	(94, 0.06, 0)
24	(94, 0.06, 0)	(0, 21.94, 13)	(100, 0.00, 0)

D. Expanded Execution Time for MCTS

Out of curiosity, the execution time is expanded for MCTS on chosen ITC07 cases with no feasible solution can be found previously. Different values for B (in Algorithm 7) are tested. The results improve on when the execution time is expanded regardless of B value as evident in Table XII. The suitable B value for MCTS to work vigorously is subject to the allotted execution time t . For the shorter execution time, the value of 0.00001 seems to be more fitting whereas, for the longer execution time, 0.0001 is more suitable. MCTS found feasible solutions for cases 1, 2 and 9 with expanded execution time of $5T$ and $B=0.0001$. However, no feasible solution could be found for cases 10 and 22.

TABLE XII
COMPARING MCTS WITH EXECUTION TIME OF T AND $5T$ FOR CHOSEN
ITC07 CASES. SHOWN ARE (MEAN UNASSIGNED, BEST UNASSIGNED)
FOR N=31 EXECUTIONS.

Case	$B=0.0001$		$B=0.00001$	
	$t=T$	$t=5T$	$t=T$	$t=5T$
01	(6.39, 3)	(1.10, 0)	(6.52, 3)	(1.10, 0)
02	(11.19, 6)	(2.97, 0)	(11.32, 7)	(3.52, 0)
09	(16.97, 14)	(5.87, 0)	(16.26, 8)	(7.13, 2)
10	(19.71, 15)	(9.81, 5)	(19.52, 16)	(10.13, 6)
22	(44.68, 41)	(28.23, 19)	(44.74, 39)	(29.29, 21)
Avg.	(19.79, -)	(9.59, -)	(19.67, -)	(10.23, -)

E. Discussion

We were faced with a heap memory issue when all possible actions expand the tree at one time. It was intentional as expanding the tree by one action at a time is computationally expensive. This decision is necessary as the CTP that we are working on, is restrained by an execution time limit because of competition rules. The heap memory issue was addressed by pruning the tree based on heuristics. The number of nodes appended to the tree (and therefore heap memory commitment) was greatly reduced by tree pruning. However paths to good solutions may also be cut off. Computational experience shows that results are affected by the value of B (selection part of MCTS). For longer execution times, a higher value of B allows MCTS to explore the search space. For shorter execution time, a lower value of B is preferred so that MCTS can exploit the search space.

Unlike games like Go, MCTS did not work well for CTP. MCTS is lacking the flexibility provided by local search methodologies (e.g. TS). In every iteration of MCTS, events are constructively assigned. In other words, moves made cannot be changed. This suits perfectly for Go however not for timetabling as events can be unassigned and reassigned at any time. As a result, the search space connectivity offered by MCTS is lacking compared to that of a local search. The effort to hybridize the algorithm with local search is also hampered by the rigid tree structure of MCTS. In fact, local search is the key for a similar learning-based algorithms such as Ant Colony Optimization (ACO) in obtaining good results. The use of learning-based algorithms (MCTS) is restricted by the time limit imposed on the CTP. Usually, reasonable computational resources are required for this type of algorithm to perform effectively.

IV. CONCLUSION

Random and heuristic simulation (DSR) for MCTS were compared. Heuristic-based simulation seems to be superior to a random simulation. We believe simulation is made more practical by heuristics in comparison to random simulation. Several types of tree pruning heuristics such as MV-All, LD-All, SD-All and DSR were also tested. The efficacy of MCTS in constructing feasible solutions is vastly improved by tree pruning regarding the average number of unassigned events. MV-All performed the best out of the heuristics as shown by the empirical results presented. Effectively, heuristic-based simulation and tree pruning improved the performance of the basic MCTS for the CTP.

MCTS, GCH and TS were compared in finding feasible solutions. In terms of performance, MCTS was useful for Socha and ITC02 cases but lacking for ITC07 cases. Even with expanded execution time, MCTS was unable to construct a feasible solution for cases 10 and 22 of ITC07. Overall, MCTS performed superior to GCH but worse than TS in finding feasible solutions. MCTS requires time to perform competently and well suited for games like Go but not for the competitive and time-restricted CTP (competitions). Meanwhile, TS shows excellent potential in finding feasible solutions for the CTP.

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