

Package ‘prioriactions’

August 13, 2023

Type Package

Version 0.5.0

Title Multi-Action Conservation Planning

Description This uses a mixed integer mathematical programming (MIP) approach for building and solving multi-action planning problems, where the goal is to find an optimal combination of management actions that abate threats, in an efficient way while accounting for spatial aspects. Thus, optimizing the connectivity and conservation effectiveness of the prioritized units and of the deployed actions. The package is capable of handling different commercial (gurobi, CPLEX) and non-commercial (symphony, CBC) MIP solvers. Gurobi optimization solver can be installed using comprehensive instructions in the 'gurobi' installation vignette of the prioritizr package (available in https://prioritizr.net/articles/gurobi_installation_guide.html). Instead, 'CPLEX' optimization solver can be obtain from IBM CPLEX web page (available here <https://www.ibm.com/es-es/products/ilog-cplex-optimization-studio>). Additionally, the 'rcbc' R package (available at <https://github.com/dirkschumacher/rcbc>) can be used to obtain solutions using the CBC optimization software (<https://github.com/coin-or/Cbc>). Methods used in the package refers to Salgado-Rojas et al. (2020) [doi:10.1016/j.ecolmodel.2019.108901](https://doi.org/10.1016/j.ecolmodel.2019.108901), Beyer et al. (2016) [doi:10.1016/j.ecolmodel.2016.02.005](https://doi.org/10.1016/j.ecolmodel.2016.02.005), Cattarino et al. (2015) [doi:10.1371/journal.pone.0128027](https://doi.org/10.1371/journal.pone.0128027) and Watts et al. (2009) [doi:10.1016/j.envsoft.2009.06.005](https://doi.org/10.1016/j.envsoft.2009.06.005). See the prioriactions website for more information, documentations and examples.

Depends R (>= 3.5.0)

Imports assertthat (>= 0.2.0), Matrix, proto, magrittr, tidyr, dplyr, Rcpp, rlang

Suggests knitr, gurobi (>= 9.0), Rcplex, roxygen2, rcbc, Rsymphony (>= 0.1-31), rmarkdown, testthat (>= 3.0.0), raster, tmap, sp, viridis, markdown, data.table, purrr, readr, slam, tibble, methods, reshape2

LinkingTo Rcpp, RcppArmadillo (>= 0.10.1.0.0), BH

Encoding UTF-8

LazyData true

License GPL (>= 2)

Language en-US

RoxygenNote 7.2.3

URL <https://prioriactions.github.io/prioriactions/>,
<https://github.com/prioriactions/prioriactions>

BugReports <https://github.com/prioriactions/prioriactions/issues>

VignetteBuilder knitr

Collate 'RcppExports.R' 'internal.R' 'data-class.R' 'writeOutputs.R'
 'optimizationProblem-class.R' 'presolve.R' 'evalBlm.R'
 'problem_modifier.R' 'evalBudget.R' 'evalTarget.R'
 'getActions.R' 'getConnectivityPenalty.R' 'getCost.R'
 'getModelInfo.R' 'getPerformance.R' 'getPotentialBenefit.R'
 'getSolutionBenefit.R' 'inputData.R' 'package.R'
 'portfolio-class.R' 'print.R' 'problem.R' 'show.R' 'simData.R'
 'solution-class.R' 'solve.R' 'utils-pipe.R' 'zzz.R'

Config/testthat/edition 3

NeedsCompilation yes

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Repository CRAN

Date/Publication 2023-08-13 12:40:02 UTC

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|------------|-------------------|
| data-class | <i>Data class</i> |
|------------|-------------------|

Description

This class is used to represent data of the instances of the corresponding multi-action planning problem. It includes several methods for retrieving the information of the instance (such as the spatial allocation of threats and species, the cost of management actions or the structure of the spatial connectivity across the area where the planning is carried out. This class is created using the [inputData\(\)](#) function.

Value

No return value.

Fields

data list object containing data.

Methods

- getActionsAmount():** integer. Number of possible actions.
- getData(character name):** [data.frame\(\)](#). Object stored in the data field with the corresponding name. The argument name indicates the name of arguments of the problem function ("pu", "features", "dist_features", "threats", "dist_threats", "sensitivity" or "boundary").
- getFeatureAmount():** integer. Number of features.
- getFeatureNames():** character. Names of features.
- getMonitoringCosts():** numeric [vector\(\)](#). Cost of monitoring each planning unit.
- getPlanningUnitsAmount():** integer. Number of planning units.
- getActionCosts():** numeric [vector\(\)](#). Cost of actions each planning unit and threat.
- getThreatNames():** character. Names of threats.
- getThreatsAmount():** integer. Number of threats.
- print():** Print basic information of the data instance.
- show():** Call print method.

Examples

```
## set seed for reproducibility
set.seed(14)

## Set prioriactions path
prioriactions_path <- system.file("extdata/example_input/", package = "prioriactions")

## Load in planning unit data
pu_data <- data.table::fread(paste0(prioriactions_path, "/pu.dat"),
                             data.table = FALSE)
head(pu_data)

## Load in feature data
features_data <- data.table::fread(paste0(prioriactions_path, "/features.dat"),
                                   data.table = FALSE)
head(features_data)

## Load in planning unit vs feature data
dist_features_data <- data.table::fread(paste0(prioriactions_path, "/dist_features.dat"),
                                       data.table = FALSE)
head(dist_features_data)

## Load in the threats data
threats_data <- data.table::fread(paste0(prioriactions_path, "/threats.dat"),
                                 data.table = FALSE)
head(threats_data)

## Load in the threats distribution data
dist_threats_data <- data.table::fread(paste0(prioriactions_path, "/dist_threats.dat"),
                                       data.table = FALSE)
head(dist_threats_data)

## Load in the sensitivity data
sensitivity_data <- data.table::fread(paste0(prioriactions_path, "/sensitivity.dat"),
                                     data.table = FALSE)
head(sensitivity_data)

## Load in the boundary data
boundary_data <- data.table::fread(paste0(prioriactions_path, "/boundary.dat"),
                                  data.table = FALSE)
head(boundary_data)

## Create instance
problem_data <- inputData(
  pu = pu_data, features = features_data, dist_features = dist_features_data,
  dist_threats = dist_threats_data, threats = threats_data, sensitivity = sensitivity_data,
  boundary = boundary_data
)

## Summary
print(problem_data)
```

```

## Use class methods
problem_data$getData("features")

problem_data$getFeatureAmount()

problem_data$getFeatureNames()

problem_data$getMonitoringCosts()

problem_data$getPlanningUnitsAmount()

problem_data$getActionCosts()

problem_data$getThreatNames()

problem_data$getThreatsAmount()

problem_data$print()

```

| | |
|---------|-------------------------------------|
| evalBlm | <i>Evaluate multiple blm values</i> |
|---------|-------------------------------------|

Description

Return one solution per instance for different values of blm. Like `prioriactions()` function, it inherits all arguments from `inputData()`, `problem()` and `solve()`.

Usage

```
evalBlm(values = c(), ...)
```

Arguments

| | |
|---------------------|--|
| <code>values</code> | numeric. Values of blm to verify. More than one value is needed. |
| <code>...</code> | arguments inherited from <code>inputData()</code> , <code>problem()</code> and <code>solve()</code> functions. |

Details

`evalblm()` creates and solves multiple instances, of the corresponding multi-actions planning problem, for different values of blm. Alternatively, this could be obtained by executing function `prioriactions()` or by steps the `inputData()`, `problem()` and `solve()` functions; using, in each run, different blm values. However, the `evalblm()` function has two advantages with respect to this manual approach: 1) it is more efficient to create the models (this is because the model is created just once and, at each iteration, only the blm values are updated); and 2) the output is a portfolio object, which allows obtaining information about the group of solutions (including all *get* functions).

Value

An object of class `portfolio`.

Examples

```
# set seed for reproducibility
set.seed(14)

## Create model and solve
port <- evalBlm(pu = sim_pu_data, features = sim_features_data,
               dist_features = sim_dist_features_data,
               threats = sim_threats_data,
               dist_threats = sim_dist_threats_data,
               sensitivity = sim_sensitivity_data,
               boundary = sim_boundary_data,
               values = c(0.0, 0.01, 0.02, 0.03),
               model_type = "minimizeCosts",
               time_limit = 50,
               output_file = FALSE,
               cores = 2)

getConnectionityPenalty(port)
```

 evalBudget

Evaluate multiple budget values

Description

Return one solution per instance for different values of budgets. This function assumes that the *maximizeBenefits* option is being used (note that the *minimizeCosts* option does not require setting a maximum budget). Like `prioriactions()` function, it inherits all arguments from `inputData()`, `problem()` and `solve()`.

Usage

```
evalBudget(values = c(), ...)
```

Arguments

| | |
|--------|--|
| values | numeric. Values of budget to verify. More than one value is needed. |
| ... | arguments inherited from <code>inputData()</code> , <code>problem()</code> , and <code>solve()</code> functions. |

Details

`evalBudget()` creates and solves multiple instances, of the corresponding multi-actions planning problem, for different values of maximum budgets. Alternatively, this could be obtained by executing function `prioriactions()` or by steps the `inputData()`, `problem()` and `solve()` functions; using, in each run, different budgets values. However, the `evalBudget()` function has two advantages with respect to this manual approach: : 1) it is more efficient to create the models (this is

because the model is created just once and, at each iteration, only the budget values are updated); and 2) the output is a portfolio object, which allows obtaining information about the group of solutions (including all *get* functions).

Value

An object of class `portfolio`.

Examples

```
# set seed for reproducibility
set.seed(14)

## Create model and solve
port <- evalBudget(pu = sim_pu_data, features = sim_features_data,
                  dist_features = sim_dist_features_data,
                  threats = sim_threats_data,
                  dist_threats = sim_dist_threats_data,
                  sensitivity = sim_sensitivity_data,
                  boundary = sim_boundary_data,
                  values = c(1, 10, 50, 100),
                  time_limit = 50,
                  output_file = FALSE,
                  cores = 2)

getSolutionBenefit(port)
```

evalTarget

Evaluate multiple target values

Description

Return one solution per instance for different targets values. This function assumes that the *minimizeCosts* model is being used. As well as the `prioriactions()` function, it inherits all arguments from `inputData()`, `problem()` and `solve()`.

Usage

```
evalTarget(values = c(), ...)
```

Arguments

| | |
|--------|---|
| values | numeric. Proportion of maximum value of benefits to verify (both recovery and conservation benefits). This information can be obtained with <code>getPotentialBenefit()</code> function. More than one value is needed. |
| ... | arguments inherited from <code>inputData()</code> , <code>problem()</code> , and <code>solve()</code> functions. |

Details

evalTarget() creates and solves multiple instances, of the corresponding multi-actions planning problem, for different proportions of maximum benefit values as target values. It is assumed that the same proportion is applied for the maximum benefit in recovery and conservation. Alternatively, this could be obtained by executing function prioriactions() or by steps the inputData(), problem() and solve() functions; using, in each run, different targets values. However, the evalTarget() function has two advantages with respect to this manual approach: : 1) it is more efficient to create the models (this is because the model is created just once and, at each iteration, only the target values are updated); and 2) the output is a portfolio object, which allows obtaining information about the group of solutions (including all *get* functions).

Value

An object of class `portfolio`.

Examples

```
# set seed for reproducibility
set.seed(14)

## Create model and solve
port <- evalTarget(pu = sim_pu_data, features = sim_features_data,
                  dist_features = sim_dist_features_data,
                  threats = sim_threats_data,
                  dist_threats = sim_dist_threats_data,
                  sensitivity = sim_sensitivity_data,
                  boundary = sim_boundary_data,
                  values = c(0.1, 0.3, 0.5),
                  time_limit = 50,
                  output_file = FALSE,
                  cores = 2)

getCost(port)
```

getActions

Extract action information

Description

Returns the spatial deployment of the actions for each planning unit of the corresponding solution.

Usage

```
getActions(x, format = "wide")
```


Arguments

| | |
|--------|--|
| x | solution or portfolio object. |
| format | character. Output format of the action matrix; wide format shows one column per action, while large format shows four columns: solution_name, pu, action and solution. |

Details

getActions() function assumes that actions can be of three types:

1. **to abate specific threats:** these actions have the *id* corresponding to the threat to be abate.
2. **to conservation:** that indicates if the planning unit is selected to conservative any feature that is not threatened.
3. **to connectivity:** that indicates if the planning unit is selected only by connectivity (i.e. without performing conservation actions or actions against a threat in said unit).

Value

[data.frame](#).

Examples

```
# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
sim_boundary_data)

## Create instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data)

## Solve the optimization model
s <- solve(a = problem_model, time_limit = 2, output_file = FALSE, cores = 2)

# get actions information in large format
actions <- getActions(s, format = "large")
head(actions)

# get actions information in wide format
actions <- getActions(s, format = "wide")
```

```
head(actions)
```

```
getConnectivityPenalty
```

Extract connectivity penalty values

Description

Provides the connectivity penalty value for all actions and planning units in a solution.

Usage

```
getConnectivityPenalty(x)
```

Arguments

`x` [solution](#) or [portfolio](#) object.

Details

The connectivity penalty among is calculated as the sum of all connectivity penalties by each action and planning unit in the solution. This can be expressed mathematically for a set of planning units I indexed by i and j , and a set of threats K indexed by k as:

$$\sum_{k \in K} \sum_{i \in I_k} \sum_{j \in I_k} x_{ik}(1 - x_{jk})cv_{ij}$$

Where, x_{ik} is the decisions variable that specify whether an action has been selected to abate threat k in planning unit i (1) or not (0), cv_{ij} is the connectivity penalty that applies when a solution contains planning unit i but not j o viceversa.

Note that there is an action per threat, so it is assumed that the index of the threat coincides with the index of the action used to abate it.

Value

[data.frame](#).

Examples

```
# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
```

```

sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data, blm = 0.03)

## Solve the optimization model
s <- solve(a = problem_model, time_limit = 2, output_file = FALSE, cores = 2)

# get connectivity penalty values
getConnectivityPenalty(s)

```

getCost

Extract cost values

Description

Provides the sum of costs to actions and monitoring applied in a solution.

Usage

```
getCost(x)
```

Arguments

`x` [solution](#) or [portfolio](#) object.

Details

The cost value is calculated as the sum of all the individual costs of actions and monitoring carried out in each of the planning units. This can be expressed mathematically for a set of planning units I indexed by i , and a set of threats K indexed by k as:

$$actions = \sum_{i \in I} \sum_{k \in K_i} x_{ik} c_{ik}$$

$$monitoring = \sum_{i \in I} x_i \cdot c'_i$$

Where, x_{ik} is the decisions variable that specify whether an action has been selected to abate threat k in planning unit i (1) or not (0), c_{ik} is the action cost to abate threat k in planning unit i and c'_i is

the monitoring cost of planning unit i . The cost of monitoring is applied to all planning units where some type of action has been selected (conservation action, to abate threats or connectivity).

Note that there is an action per threat, so it is assumed that the index of the threat coincides with the index of the action used to abate it.

Value

[data.frame](#).

Examples

```
# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
     sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
     sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data)

## Solve the optimization model
s <- solve(a = problem_model, time_limit = 2, output_file = FALSE, cores = 2)

## Get costs
getCost(s)
```

getModelInfo

Extract general information about mathematical model

Description

Provides general information about the mathematical model.

Usage

```
getModelInfo(x)
```

Arguments

x [optimizationProblem](#), [solution](#) or [portfolio](#) object.

Details

getModelInfo() function returns five specific fields:

1. **solution_name**: indicates the name of the solution, by default is *sol*.
2. **model_sense**: returns the optimization sense (i.e., it indicates whether the objective function is minimized or maximize).
3. **n_constraints**: returns the number of constraints in the corresponding mathematical optimization model.
4. **n_variables**: returns the number of variables in the corresponding mathematical optimization model.
5. **size**: returns the size of the constraints' coefficients matrix A (number of constraints and number of variables).

Value

[data.frame](#).

Examples

```
# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
     sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
     sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data, blm = 1)

# get model information
getModelInfo(problem_model)
```

`getPerformance`*Extract general information about solution*

Description

Provides general information about the process of solving.

Usage

```
getPerformance(x)
```

Arguments

`x` [solution](#) or [portfolio](#) object.

Details

`getPerformance()` function returns five specific fields:

1. **solution_name**: indicates the name of the solution, by default is *sol*.
2. **objective_value**: indicates the value of the objective function of a given solution. This value depends on the type of model solved (more information in the `problem()` function).
3. **gap**: returns the relative MIP optimality gap of a solution. It is measured as the ratio between the objective function induced by the best known (primal solution) integer solution and the objective function induced by the best node in the search tree (dual solution).
4. **solving_time**: indicates the solving time of mathematical model.
5. **status**: provides the status of solver at the end of the optimization period. This can have six states:
 - *Optimal solution (according to gap tolerance)* : When the resolution of the model stop when the quality of the solution (gap) is less than or equal to `gap_limit` (parameter of the `solve()` function).
 - *No solution (model was proven to be infeasible or unbounded)*: When the model is infeasible.
 - *Feasible solution (according to time limit)*: When the resolution of the model stops when a `time_limit` has been reached finding a feasible solution (parameter of the `solve()` function).
 - *No solution (according to time limit)*: When the resolution of the model stops when a `time_limit` has been reached without finding a feasible solution (parameter of the `solve()` function).
 - *First feasible solution*: When the resolution of the model stops when it has found the first feasible solution (`solution_limit = TRUE` parameter in `solve()` function).
 - *No solution information is available*: For any other case.

Value

[data.frame](#).

Examples

```

# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
     sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
     sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data, blm = 1)

## Solve the optimization model
s <- solve(a = problem_model, time_limit = 2, output_file = FALSE, cores = 2)

# get solution gap
getPerformance(s)

```

getPotentialBenefit *Extract potential benefit of features*

Description

Provides the maximum values of benefits to achieve for each feature given a set of data inputs.

Usage

```
getPotentialBenefit(x)
```

Arguments

x data-class object.

Details

For a given feature s , let I_s be the set of planning units associated with s , let r_{is} is the amount of feature s in planning unit i , let K_s be the set of threats associated with s , and let K_i be the set of threats associated with i . The local benefit associated with s in a unit i is given by:

$$b_{is} = p_{is} r_{is} b_{is} = \frac{\sum_{k \in K_i \cap K_s} x_{ik}}{|K_i \cap K_s|} r_{is}$$

Where x_{ik} is a decision variable such that $x_{ik} = 1$ if an action against threat k is applied in unit i , and $x_{ik} = 0$, otherwise. This expression for the probability of persistence of the feature (p_{is}) is defined only for the cases where we work with values of binary intensities (presence or absence of threats). See the [sensitivities](#) vignette to know the work with continuous intensities.

While the total benefit is calculated as the sum of the local benefits per feature:

$$b_s = \sum_{i \in I_s} \frac{\sum_{k \in K_i \cap K_s} x_{ik}}{|K_i \cap K_s|} r_{is}$$

Since the potential benefit is being calculated, all variables x_{ik} are assumed to be equal to 1; that is, all possible actions are carried out, and only those that have a **lock-out** status are kept out of the planning (see `inputData()` function for more information).

Value

[data.frame](#).

Examples

```
# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
     sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
     sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Get maximum benefits to obtain
getPotentialBenefit(problem_data)
```

getSolutionBenefit *Extract benefit values*

Description

Returns the total benefit induced by the corresponding solution. The total benefit is computed as the sum of the benefits obtained, for all features, across all the units in the planning area.

Usage

```
getSolutionBenefit(x, type = "total")
```

Arguments

x Solution-class or Portfolio-class.

type character. Output format of the benefits matrix; total shows the total benefit by feature, while local format shows the benefit achieved per feature and planning unit.

Details

For a given feature s , let I_s be the set of planning units associated with s , let r_{is} is the amount of feature s in planning unit i , let K_s be the set of threats associated with s , and let K_i be the set of threats associated with i . The local benefit associated with s in a unit i is given by:

$$b_{is} = p_{is} r_{is} b_{is} = \frac{\sum_{k \in K_i \cap K_s} x_{ik}}{|K_i \cap K_s|} r_{is}$$

Where x_{ik} is a decision variable such that $x_{ik} = 1$ if an action against threat k is applied in unit i , and $x_{ik} = 0$, otherwise. This expression for the probability of persistence of the feature (p_{is}) is defined only for the cases where we work with values of binary intensities (presence or absence of threats). See the [sensitivities](#) vignette to know the work with continuous intensities.

While the total benefit is calculated as the sum of the local benefits per feature:

$$b_s = \sum_{i \in I_s} \frac{\sum_{k \in K_i \cap K_s} x_{ik}}{|K_i \cap K_s|} r_{is}$$

Value

[data.frame](#).

Examples

```
# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)
```

```

## Get maximum benefits to obtain
getPotentialBenefit(problem_data)

## Create optimization model
problem_model <- problem(x = problem_data)

## Solve the optimization model
s <- solve(a = problem_model, time_limit = 2, output_file = FALSE, cores = 2)

# get local benefits of solution
local_benefit <- getSolutionBenefit(s, type = "local")
head(local_benefit)

# get total benefits of solution
total_benefit <- getSolutionBenefit(s, type = "total")
head(total_benefit)

```

inputData

Creates the multi-action planning problem

Description

Create the [data](#) object with information about the multi-action conservation planning problem. This function is used to specify all the data that defines the spatial prioritization problem (planning units data, feature data, threats data, and their spatial distributions.)

Usage

```
inputData(pu, features, dist_features, threats, dist_threats, ...)
```

```

## S4 method for signature
## 'data.frame,data.frame,data.frame,data.frame,data.frame'
inputData(
  pu,
  features,
  dist_features,
  threats,
  dist_threats,
  sensitivity = NULL,
  boundary = NULL
)

```

Arguments

pu Object of class [data.frame\(\)](#) that specifies the planning units (PU) of the corresponding instance and their corresponding monitoring cost and status. Each row

| | |
|---------------|--|
| | <p>corresponds to a different planning unit. This file is inherited from the <i>pu.dat</i> in <i>Marxan</i>. It must contain the following columns:</p> <p><code>id</code> integer unique identifier for each planning unit.</p> <p><code>monitoring_cost</code> numeric cost of including each planning unit in the reserve system.</p> <p><code>status</code> integer (optional) value that indicate if each planning unit should be available to be selected (0), <i>locked-in</i> (2) as part of the solution, or <i>locked-out</i> (3) and excluded from the solution.</p> |
| features | <p>Object of class <code>data.frame()</code> that specifies the conservation features to consider in the optimization problem. Each row corresponds to a different feature. This file is inherited from marxan's <i>spec.dat</i>.</p> <p>The <code>prioriactions</code> package supports two types of purposes when optimizing: focus on recovery of features threatened (through the recovery target), where only take into account benefits when taking action against threats and there is no benefit when selecting planning units where the features are not threatened; or include the benefits of the features sites where they are not threatened (through the conservation target).</p> <p>Note that by default only information on recovery targets is necessary, while conservation targets equal to zero are assumed. The maximum values of benefits to achieve both recovery and conservation per feature can be verified with the <code>getPotentialBenefit()</code> function. For more information on the implications of these targets in the solutions see the recovery vignette.</p> <p>This file must contain the following columns:</p> <p><code>id</code> integer unique identifier for each conservation feature.</p> <p><code>target_recovery</code> numeric amount of recovery target to achieve for each conservation feature. This field is required if a <code>minimizeCosts</code> model is used.</p> <p><code>target_conservation</code> numeric (optional) amount of conservation target to achieve for each conservation feature. This field is used only if a model of the type <code>minimizeCosts</code> is applied.</p> <p><code>name</code> character (optional) name for each conservation feature.</p> |
| dist_features | <p>Object of class <code>data.frame()</code> that specifies the spatial distribution of conservation features across planning units. Each row corresponds to a combination of planning unit and feature. This file is inherited from marxan's <i>puvspr.dat</i>. It must contain the following columns:</p> <p><code>pu</code> integer <i>id</i> of a planning unit where the conservation feature listed on the same row occurs.</p> <p><code>feature</code> integer <i>id</i> of each conservation feature.</p> <p><code>amount</code> numeric amount of the feature in the planning unit. Set to 1 to work with presence/absence.</p> |
| threats | <p>Object of class <code>data.frame()</code> that specifies the threats to consider in the optimization exercise. Each row corresponds to a different threats. It must contain the following columns:</p> <p><code>id</code> integer unique identifier for each threat.</p> <p><code>blm_actions</code> numeric (optional) penalty of connectivity between threats. Default is 0.</p> |

| | |
|--------------|--|
| | name character (optional) name for each threat. |
| dist_threats | Object of class <code>data.frame()</code> that specifies the spatial distribution of threats across planning units. Each row corresponds to a combination of planning unit and threat. It must contain the following columns: pu integer <i>id</i> of a planning unit where the threat listed on the same row occurs. threat integer <i>id</i> of each threat. amount numeric amount of the threat in the planning unit. Set to 1 to work with presence/absence. Continuous amount values require that feature sensitivities to threats be established (more info in sensitivities vignette). action_cost numeric cost of an action to abate the threat in each planning unit. status integer (optional) value that indicates if each action to abate the threat is available to be selected (0), <i>locked-in</i> (2) as part of the solution, or <i>locked-out</i> (3) and therefore excluded from the solution. |
| ... | Unused arguments, reserved for future expansion. |
| sensitivity | (optional) Object of class <code>data.frame()</code> that specifies the sensitivity of each feature to each threat. Each row corresponds to a combination of feature and threat. If not informed, all features are assumed to be sensitive to all threats. Sensitivity can be parameterized in two ways: binary ; the feature is sensitive or not, or continuous ; with response curves of the probability of persistence of the features to threats. For the first case, it is only necessary to indicate the ids of the threats and the respective features sensitive to them. In the second case, the response can be parameterized through four values: δ_1 , δ_2 , δ_3 and δ_4 . See sensitivities vignette for more information on continuous sensitivities. Then, the sensitivity input must contain the following columns: feature integer <i>id</i> of each conservation feature. threat integer <i>id</i> of each threat. delta1 numeric (optional) the minimum intensity of the threat at which the features probability of persistence starts to decline. The more sensitive the feature is to the threat, the lowest this value will be. Default is 0. delta2 numeric (optional) the value of intensity of the threat over which the feature has a probability of persistence of 0. If it is not established, it is assumed as the maximum value of the threat across all planning units in the study area. Note that this might overestimate the sensitivity of features to threats, as they will only be assumed to disappear from planning units if the threats reach the maximum intensity value in the study area. delta3 numeric (optional) minimum probability of persistence of a features when a threat reaches its maximum intensity value. Default is 0. delta4 numeric (optional) maximum probability of persistence of a features in absence threats. Default is 1. Note that optional parameters <i>delta1</i> , <i>delta2</i> , <i>delta3</i> and <i>delta4</i> can be provided independently. |
| boundary | (optional) Object of class <code>data.frame()</code> that specifies the spatial relationship between pair of planning units. Each row corresponds to a combination of planning unit. This file is inherited from marxan's <i>bound.dat</i> . It must contain the following columns: |

id1 integer *id* of each planning unit.
id2 integer *id* of each planning unit.
boundary numeric penalty applied in the objective function when only one of the planning units is present in the solution.

Value

An object of class `data`.

References

- Ball I, Possingham H, Watts, M. *Marxan and relatives: software for spatial conservation prioritization*. Spatial conservation prioritisation: quantitative methods and computational tools 2009.

See Also

For more information on the correct format for *Marxan* input data, see the [official *Marxan* website](#) and Ball *et al.* (2009).

Examples

```
## set seed for reproducibility
set.seed(14)

## Set prioriactions path
prioriactions_path <- system.file("extdata/example_input/", package = "prioriactions")

## Load in planning unit data
pu_data <- data.table::fread(paste0(prioriactions_path, "/pu.dat"),
                             data.table = FALSE)

head(pu_data)

## Load in feature data
features_data <- data.table::fread(paste0(prioriactions_path, "/features.dat"),
                                   data.table = FALSE)

head(features_data)

## Load in planning unit vs feature data
dist_features_data <- data.table::fread(paste0(prioriactions_path, "/dist_features.dat"),
                                         data.table = FALSE)

head(dist_features_data)

## Load in the threats data
threats_data <- data.table::fread(paste0(prioriactions_path, "/threats.dat"),
                                  data.table = FALSE)

head(threats_data)

## Load in the threats distribution data
dist_threats_data <- data.table::fread(paste0(prioriactions_path, "/dist_threats.dat"),
                                       data.table = FALSE)

head(dist_threats_data)
```

```

## Load in the sensitivity data
sensitivity_data <- data.table::fread(paste0(prioriactions_path, "/sensitivity.dat"),
                                     data.table = FALSE)

head(sensitivity_data)

## Load in the boundary data
boundary_data <- data.table::fread(paste0(prioriactions_path, "/boundary.dat"),
                                   data.table = FALSE)

head(boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Summary
print(problem_data)

```

optimizationProblem-class

Optimization problem class

Description

This class encodes the corresponding optimization model. It is created using `problem()` function.

Value

No return value.

Fields

\$data list object containing data of the mathematical model.

\$ConservationClass object of class `data-class()` that contains the data input.

Methods

getData(character name) vector(). Object stored in the data field with the corresponding name. The data correspond to the different parts of the mathematical model. The argument name can be made to the following: "obj", "rhs", "sense", "vtype", "A", "bounds" or "modelsense".

getDataList() list() of vector(). Object stored in the data. It contains all information relative to the mathematical model, such as "obj", "rhs", etc.

print() Print basic information of the optimization model.

show() Call print method.

Examples

```

# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data, blm = 1)

## Use class methods
head(problem_model$getData("obj"))

problem_model$print()

```

portfolio-class

Portfolio class

Description

This class encodes for the solutions obtained when solving multiple instances. This includes several methods to obtain information about both the optimization process and the solution associated with the planning units and conservation actions. It is created using the *eval* functions (e.g. `evalTarget()` or `evalBudget()`).

Value

No return value.

Fields

\$data list. Object containing data on the results of the optimization process.

Methods

getNames() character. Label indicating the name of solutions.

print() Print basic information of the model solution.

show() Call print method.

Examples

```
# set seed for reproducibility
set.seed(14)

## Create model and solve
port <- evalBlm(pu = sim_pu_data, features = sim_features_data,
               dist_features = sim_dist_features_data,
               threats = sim_threats_data,
               dist_threats = sim_dist_threats_data,
               sensitivity = sim_sensitivity_data,
               boundary = sim_boundary_data,
               values = c(0.0, 0.01, 0.02, 0.03),
               model_type = "minimizeCosts",
               time_limit = 50,
               output_file = FALSE, cores = 2)

## Use class methods
port$getName()

port$print()
```

print

Print

Description

Displays information about an object.

Usage

```
## S3 method for class 'Data'
print(x, ...)

## S3 method for class 'OptimizationProblem'
print(x, ...)

## S3 method for class 'Solution'
print(x, ...)

## S3 method for class 'Portfolio'
print(x, ...)
```

Arguments

| | |
|-----|-------------|
| x | Any object. |
| ... | Not used. |

Value

None.

See Also

[base::print\(\)](#).

prioriactions

Create and solve multi-actions planning problems

Description

Create and solve a multi-actions planning problem. It can be used instead of following the sequence of the `inputData()`, `problem()` and `solve()` functions.

Usage

```
prioriactions(...)
```

Arguments

... arguments inherited from `inputData()`, `problem()` and `solve()` functions.

Value

An object of class [solution](#).

Examples

```
## This example uses input files included into package.

## set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
     sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
     sim_boundary_data)

## Create data instance
s <- prioriactions(pu = sim_pu_data, features = sim_features_data,
                  dist_features = sim_dist_features_data,
                  threats = sim_threats_data,
                  dist_threats = sim_dist_threats_data,
                  sensitivity = sim_sensitivity_data,
                  boundary = sim_boundary_data,
                  model_type = "minimizeCosts",
                  time_limit = 50,
```

```

        output_file = FALSE,
        cores = 2)

print(s)

```

problem *Create mathematical model*

Description

Create an optimization model for the multi-action conservation planning problem, following the mathematical formulations used in Salgado-Rojas *et al.* (2020).

Usage

```

problem(
  x,
  model_type = "minimizeCosts",
  budget = 0,
  blm = 0,
  curve = 1,
  segments = 3
)

```

Arguments

| | |
|------------|---|
| x | data object. Data used in a problem of prioritization of multiple conservation actions. This object must be created using the problem() function. |
| model_type | character. Name of the type of model to create. With two possible values: <code>minimizeCosts</code> and <code>maximizeBenefits</code> . |
| budget | numeric. Maximum budget allowed. This field is used only if a model of the type <code>maximizeBenefits</code> is applied. |
| blm | numeric. Weight factor applied to the sum of connectivity penalties for missed connections in a solution, similar to Boundary Length Modifier (BLM) in <i>Marxan</i> . This argument only has an effect when the boundary is available. |
| curve | integer. Type of continuous curve used to represent benefit expression. It can be a linear (1), quadratic (2) or cubic (3) function. See Details for more information. |
| segments | integer. Number of segments (1, 2, 3, 4 or 5) used to approximate the non-linear expression (curve) in the calculate benefits. See Details for more information. |

Details

Currently the problem function allows you to create two types of mathematical programming models:

minimize cost (minimizeCosts): This model seeks to find the set of actions that minimizes the overall planning costs, while meeting a set of representation targets for the conservation features.

This model can be expressed mathematically for a set of planning units I indexed by i a set of features S indexed by s , and a set of threats K indexed by k as:

$$\min \sum_{i \in I} \sum_{k \in K_i} x_{ik} c_{ik} + \sum_{i \in I} x_i \cdot c'_i + blm \cdot connectivity.s.t. \sum_{i \in I_s} p_{is} r_{is} \geq t_s \forall s \in S$$

Where, x_{ik} is a decisions variable that specifies whether an action to abate threat k in planning unit i has been selected (1) or not (0), c_{ik} is the cost of the action to abate the threat k in the planning unit i , c'_i is the monitoring cost of planning unit i , p_{is} is the probability of persistence of the feature s in the planning unit i (ranging between 0 and 1), r_{is} is the amount of feature s in planning unit i . t_s is the **recovery target** for feature s . In the case of working with **conservation target**, the following constraint is necessary:

$$\sum_{i \in I_s: |K_s \cap K_i| \neq 0} z_{is} r_{is} \geq t'_s \forall s \in S$$

With, z_{is} as the probability of persistence by conservation of the feature s in the planning unit i (ranging between 0 and 1). It is only present when there is no spatial co-occurrence between a feature and its threats (i.e. $|K_s \cap K_i| \neq 0$). In the case of binary threat intensities it is assumed as 1. t'_s is the **conservation target** for feature s .

maximize benefits (maximizeBenefits): The maximize benefits model seeks to find the set of actions that maximizes the sum of benefits of all features, while the cost of performing actions and monitoring does not exceed a certain budget. Using the terminology presented above, this model can be expressed mathematically as:

$$\max \sum_{i \in I} \sum_{s \in S_i} b_{is} - blm \cdot connectivity.s.t. \sum_{i \in I} \sum_{k \in K_i} x_{ik} c_{ik} + \sum_{i \in I} x_i \cdot c'_i \leq budget$$

Where b_{is} is the benefit of the feature s in a planning unit i and it is calculated by multiplying the probability of persistence of the feature in the unit by its corresponding amount, i.e., $b_{is} = p_{is} r_{is}$. When we talk about recovering, the probability of persistence is a measure of the number of actions taken against the threats that affect said feature. For more information on its calculation, see the `getSolutionBenefit()` or `getPotentialBenefit()` functions references.

As a way of including the risk associated with calculating our probability of persistence of the features and in turn, avoiding that many low probabilities of persistence end up reaching the proposed targets, is that we add the curve parameter. That incorporates an exponent (values of 1: linear, 2: quadratic or 3: cubic) to the calculation of the probability of persistence. Thus penalizing the low probabilities in the sum of the benefits achieved. Since `prioriactions` works with linear models, we use a piecewise linearization strategy to work with non-linear curves in b_{is} . The `segments` parameter indicates how well the expression approximates the curved used in b_{is} . A higher number implies a better approximation but increases the resolution complexity. Note that for a linear curve (curve = 1) it is not necessary to set a `segment` parameter.

Parameters `blm` and `blm_actions` allow controlling the spatial connectivity of the selected units and of the deployed actions, respectively (similar to BLM in Marxan).

Value

An object of class `optimizationProblem`.

See Also

For more information regarding the arguments `curve` and `segments`, see the supplementary material of Salgado-Rojas *et al.* (2020)..

Examples

```
## This example uses input files included into package.

## set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create minimizeCosts model
model_min <- problem(x = problem_data, blm = 1, model_type = "minimizeCosts")

#' ## Create maximizeBenefits model
model_max <- problem(x = problem_data, model_type = "maximizeBenefits", budget = 100)
```

show

Show

Description

Display information about an object.

Usage

```
## S4 method for signature 'Data'
show(x)

## S4 method for signature 'OptimizationProblem'
```

```
show(x)

## S4 method for signature 'Portfolio'
show(x)
```

Arguments

x Any object.

See Also

[methods::show\(\)](#).

| | |
|---------|---|
| simData | <i>Simulated multi-action planning data</i> |
|---------|---|

Description

Simulated data for making prioritizations.

sim_pu_data Planning units are represented as tabular data.

sim_features_data Features are represented as tabular data.

sim_dist_features_data The simulated distribution of four features.

sim_threats_data Threats are represented as tabular data.

sim_dist_threats_data The simulated threats of two threats.

sim_sensitivity_data Sensitivity of features to threats as tabular data.

sim_boundary_data Boundary data between one hundred planning units.

Usage

```
data(sim_pu_data)
```

```
data(sim_features_data)
```

```
data(sim_dist_features_data)
```

```
data(sim_threats_data)
```

```
data(sim_dist_threats_data)
```

```
data(sim_sensitivity_data)
```

```
data(sim_boundary_data)
```

Format

sim_pu_data `data.frame` object.
sim_features_data `data.frame` object.
sim_dist_features_data `data.frame` object.
sim_threats_data `data.frame` object.
sim_dist_threats_data `data.frame` object.
sim_sensitivity_data `data.frame` object.
sim_boundary_data `data.frame` object.

Examples

```

## Not run:
# load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
      sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
      sim_boundary_data)

# plot examples
library(raster)
r <- raster::raster(ncol=10, nrow=10, xmn=0, xmx=10, ymn=0, ymx=10)

# plot cost of pu's
values(r) <- sim_pu_data$monitoring_cost
plot(r)

# plot feature distribution of feature 1
features <- tidyr::spread(data = sim_dist_features_data, key = feature, value = amount, fill = 0)
values(r) <- features$'1'
plot(r)

## End(Not run)

```

 solution-class

Solution class

Description

This class is used to represent the solution of the MIP (Mixed-Integer Programming) model. This includes several methods to obtain information about both the optimization process and the solution associated with the planning units and actions. It is created using the `solve()` function.

Value

No return value.

Fields

\$data list. Object containing data on the results of the optimization process.

Methods

print() Print basic information of the model solution.

show() Call print method.

Examples

```
# set seed for reproducibility
set.seed(14)

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
     sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
     sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data, blm = 1)

## Solve the optimization model
s <- solve(a = problem_model, time_limit = 5, output_file = FALSE, cores = 2)

## Use class methods

s$print()
```

solve

Solve mathematical models

Description

Solves the optimization model associated with the multi-action conservation planning problem. This function is used to solve the mathematical model created by the `problem()` function.

Usage

```
solve(
  a,
  solver = "",
  gap_limit = 0,
  time_limit = .Machine$integer.max,
```

```

solution_limit = FALSE,
cores = 2,
verbose = TRUE,
name_output_file = "output",
output_file = TRUE
)

```

Arguments

| | |
|------------------|--|
| a | optimizationProblem object. Optimization model created for the problem of prioritization of multiple conservation actions. This object must be created using the <code>problem()</code> function. |
| solver | string. Name of solver to use to solve the model. The following solvers are supported: <code>"gurobi"</code> (requires the gurobi package), <code>"cplex"</code> (requires the Rcplex package), <code>"cbc"</code> (requires the rcbc package) and <code>"symphony"</code> (requires the Rsymphony package). We recommend using gurobi (for more information on how to obtain an academic license here). |
| gap_limit | numeric. Value between 0 and 1 that represents the gap to optimality, i.e., a relative number that cause the optimizer to terminate when the difference between the upper and lower objective function bounds is less than the gap times the upper bound. For example, a value of 0.01 will result in the optimizer stopping when the difference between the bounds is 1 percent of the upper bound. Default is 0.0. |
| time_limit | numeric. Time limit to run the optimizer (in seconds). The solver will return the current best solution when this time limit is exceeded. Default is the maximum integer number of your machine. |
| solution_limit | logical. Indicates if the solution process should be stopped after the first feasible solution is found (TRUE), or not (FALSE). |
| cores | integer. Number of parallel cores to use in the machine to solve the problem. |
| verbose | logical. Indicates if the solver information is displayed while solving the optimization model (TRUE), or if it is not displayed (FALSE). |
| name_output_file | string. Prefix of all output names. |
| output_file | logical. Indicates if the outputs are exported as .csv files (TRUE), or they are not exported (FALSE). Currently, 5 files are exported. The distribution of actions in the solution, the distribution of the selected planning units, the benefits achieved by the features, the parameters used, and the optimization engine log. |

Details

The solvers supported by the `solve()` function are described below.

Gurobi solver *Gurobi* is a state-of-the-art commercial optimization software with an R package interface. It is by far the fastest of the solvers available in this package, however, also this solver is not freely available. That said, licenses are available to academics at no cost. The **gurobi** package is distributed with the *Gurobi* software suite. This solver uses the **gurobi** package to solve problems.

CPLEX solver *cplex* is a state-of-the-art commercial optimization software with an R package interface. Like Gurobi, it is not freely accessible, but we can obtain academic licenses. We recommend using this solver if the Gurobi solver is not available. Licenses are available for the IBM CPLEX software to academics at no cost [here](#). This solver uses the **Rcplex** package to solve problems.

CBC solver *CBC* is an open-source mixed integer linear programming solver written in C++. It is part of the Computational Infrastructure for Operations Research (COIN-OR) project interface. **rcbc** package to solve problems is now available only on Github. Please ensure that you closely adhere to the detailed installation instructions provided [here](#) for proper setup.

Symphony solver *SYMPHONY* is an open-source integer programming solver that is part of the Computational Infrastructure for Operations Research (COIN-OR) project, an initiative to promote development of open-source tools for operations research (a field that includes linear programming). The **Rsymphony** package provides an interface to COIN-OR and is available on CRAN. This solver uses the **Rsymphony** package to solve problems.

Value

An object of class [solution](#).

See Also

For more information on how to install and obtain an academic license of the Gurobi solver, see the *Gurobi installation guide*, which can be found online at [prioritizr vignette](#). Just like Gurobi, cplex needs an academic licence to work. Details about how to install the cplex solver, see the [webpage IBM CPLEX](#). Once installed, see the *Rcplex installation guide*, which can be found online at [Rcplex package](#).

Examples

```
## Not run:
## This example uses input files included into package.

## Load data
data(sim_pu_data, sim_features_data, sim_dist_features_data,
     sim_threats_data, sim_dist_threats_data, sim_sensitivity_data,
     sim_boundary_data)

## Create data instance
problem_data <- inputData(
  pu = sim_pu_data, features = sim_features_data, dist_features = sim_dist_features_data,
  threats = sim_threats_data, dist_threats = sim_dist_threats_data,
  sensitivity = sim_sensitivity_data, boundary = sim_boundary_data
)

## Create optimization model
problem_model <- problem(x = problem_data, blm = 1)

## Solve the optimization model using a gap_limit and gurobi solver
## NOTE: The Gurobi solver must be previously installed and must have a valid license!
s1 <- solve(a = problem_model, solver = "gurobi", gap_limit = 0.01, output_file = FALSE, cores = 2)
```

```
print(s1)

## Solve the optimization model using a gap_limit and symphony solver
s2 <- solve(a = problem_model,
           solver = "symphony",
           gap_limit = 0.01,
           output_file = FALSE,
           cores = 2)

print(s2)

## Solve the optimization model using a time_limit and gurobi solver
s3 <- solve(a = problem_model, solver = "gurobi", time_limit = 10, output_file = FALSE, cores = 2)

print(s3)

## End(Not run)
```

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