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of the dual constraint graph, we can solve a nonbinary CSP using methods developed for binary CSPs. In particular, if the dual constraint graph is a tree, the problem can be solved in time linear in the number of c-variables, using the tree algorithm described by Dechter [71]. Since trees are desirable structures, we want to transform any constraint

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model then is solved by commercial software using branch-and-bound approach. Skocdopolova (2012) proposed integer goal programming to solve the real timetabling problem at department of econometrics at University of Economics, Prague. A sequential three-stage goal programming model is introduced. This approach involves three stages.

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