Applying Littlewood-Richardson Homotopies to Schubert Problems

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Outline

1. Numerical Schubert Calculus
   - Schubert varieties and Schubert problems
   - homotopies for enumerative geometry
2. The Moving Flag in Littlewood-Richardson Homotopies
   - specialization and generalization
   - encoding the moves by black checkers
3. 2 Lines meeting 4 given general Lines in 3-space
   - checker games encode moving flag and coordinates for solutions
   - coordinate transformations and moving coordinates in homotopy
4. Localization Patterns and Checker Movements
   - option -e of phc and Macaulay 2 interface LRhomotopies.m2

Schubert Varieties

A Schubert variety is defined by an n-dimensional flag F:

$$F = [\mathbf{f}_1 \mathbf{f}_2 \cdots \mathbf{f}_n] \in \mathbb{C}^{n \times n} \quad \langle \mathbf{f}_1 \rangle \subset \langle \mathbf{f}_1, \mathbf{f}_2 \rangle \subset \cdots \subset \langle \mathbf{f}_1, \mathbf{f}_2, \ldots, \mathbf{f}_n \rangle$$

and a k-dimensional bracket $\omega \in \mathbb{N}^k$, $1 \leq \omega_1 < \omega_2 < \cdots < \omega_k \leq n$:

$$\Omega_\omega(F) = \left\{ X \in \mathbb{C}^{n \times k} \mid \dim(X \cap \langle \mathbf{f}_1, \ldots, \mathbf{f}_{\omega_i} \rangle) = i, i = 1, 2, \ldots, k \right\}.$$

For example: for $F \in \mathbb{C}^{6 \times 6}$, $\Omega_{[2\ 4\ 6]}(F)$ contains

$$X = \begin{bmatrix} 1 & 0 & 0 \\ x_{21} & 1 & 0 \\ x_{31} & x_{32} & 1 \\ x_{41} & x_{42} & x_{43} \\ 0 & x_{52} & x_{53} \\ 0 & 0 & x_{63} \end{bmatrix}$$

$$\dim(X \cap \langle \mathbf{f}_1, \mathbf{f}_2 \rangle) = 1$$
$$\dim(X \cap \langle \mathbf{f}_1, \mathbf{f}_2, \mathbf{f}_3, \mathbf{f}_4 \rangle) = 2$$
$$\dim(X \cap \langle \mathbf{f}_1, \mathbf{f}_2, \mathbf{f}_3, \mathbf{f}_4, \mathbf{f}_5, \mathbf{f}_6 \rangle) = 3$$

expressed via conditions on minors $\rightarrow$
system of 13 polynomials in 9 variables

Schubert Problems

A triple intersection $[2\ 4\ 6]^3 = [2\ 4\ 6][2\ 4\ 6][2\ 4\ 6]$ means

$$\Omega_{[2\ 4\ 6]}(I) \cap \Omega_{[2\ 4\ 6]}(M) \cap \Omega_{[2\ 4\ 6]}(F)$$

where I : the identity matrix represents the standard flag,
M : a matrix represents the moving flag,
F : another matrix represents the fixed flag.

The Littlewood-Richardson rule computes the number of solutions:

$$\begin{aligned}
[2\ 4\ 6]^3 &= ([2\ 4\ 6][2\ 4\ 6])[2\ 4\ 6] \\
&= ([2\ 3\ 4] + 2[1\ 3\ 5] + [1\ 2\ 6])[2\ 4\ 6] \\
&= [2\ 3\ 4][2\ 4\ 6] + 2[1\ 3\ 5][2\ 4\ 6] + [1\ 2\ 6][2\ 4\ 6] \\
&= 0 + 2[1\ 2\ 3] + 0
\end{aligned}$$

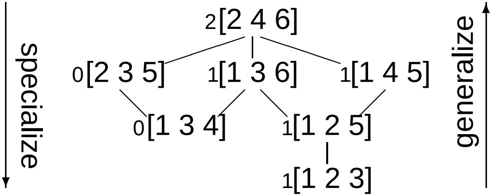
$\rightarrow$ there are 2 isolated 3-planes in $\Omega_{[2\ 4\ 6]}(I) \cap \Omega_{[2\ 4\ 6]}(M) \cap \Omega_{[2\ 4\ 6]}(F)$.

poset to resolve general problems

Resolving $[2\ 4\ 6][2\ 5\ 6]^3$:

$$\begin{aligned}[2\,4\,6][2\,5\,6]^3 &= (1[2\,3\,5]+1[1\,4\,5]+1[1\,3\,6])[2\,5\,6]^2 \\ &= (2[1\,3\,4]+2[1\,2\,5])[2\,5\,6] \\ &= 2[1\,2\,3].\end{aligned}$$

Using a poset:



a Geometric Littlewood-Richardson Rule

William Fulton: *Young Tableau. With Applications to Representation Theory and Geometry*. Cambridge University Press, 1997.
The first geometric proof and interpretation was given by
Ravi Vakil: *a geometric Littlewood-Richardson rule*. Ann of Math, 2006.

A combinatorial checker game for the Littlewood-Richardson coefficients gives homotopies to solve Schubert problems:
F. Sottile, R. Vakil, and J. Verschelde: *Solving Schubert problems with Littlewood-Richardson Homotopies.* In Proceedings of ISSAC 2010.

Motivation: experimental study of reality conjectures
`http://www.math.tamu.edu/~secant`
Christopher Hillar, Luis Garcia-Puente, Abraham Martin del Campo, James Ruffo, Zach Teitler, Stephen L. Johnson, Frank Sottile: *Experimentation at the Frontiers of Reality in Schubert Calculus.* Contemporary Math. AMS 2010.

Homotopies for Enumerative Geometry

- B. Huber, F. Sottile, and B. Sturmfels: Numerical Schubert calculus. *J. of Symbolic Computation*, 26(6):767–788, 1998.
- J. Verschelde: Numerical evidence for a conjecture in real algebraic geometry. *Experimental Mathematics* 9(2): 183–196, 2000.
- B. Huber and J. Verschelde: Pieri homotopies for problems in enumerative geometry applied to pole placement in linear systems control. *SIAM J. Control Optim.* 38(4):1265–1287, 2000.
- F. Sottile and B. Sturmfels: A sagbi basis for the quantum Grassmannian. *J. Pure and Appl. Algebra* 158(2-3): 347–366, 2001.
- T.Y. Li, X. Wang, and M. Wu: Numerical Schubert calculus by the Pieri homotopy algorithm. *SIAM J. Numer. Anal.* 20(2):578–600, 2002.
- J. Verschelde and Y. Wang: Computing dynamic output feedback laws. *IEEE Trans. Automat. Control.* 49(8):1393–1397, 2004.
- A. Leykin and F. Sottile: Galois group of Schubert problems via homotopy continuation. *Math. Comp.* 78(267): 1749–1765, 2009.

Degenerating the moving Flag

Given	I	:	the identity matrix represents the standard flag,
	M	:	a matrix represents the moving flag,
	F	:	another matrix represents the fixed flag,

we consider a triple intersection for some bracket ω:

general problem: $\Omega_\omega(I) \cap \Omega_\omega(M) \cap \Omega_\omega(F)$

degeneration ↓↑ *generalization*

degenerate problem: $\Omega_\omega(I) \cap \Omega_\omega(I) \cap \Omega_\omega(F)$

The degeneration $M \to I$ allows to satisfy the intersection condition by solving some linear systems.

Littlewood-Richardson homotopies generalize I to M via invertible transformations involving a parameter t.

Generalizing the moving Flag

first three moves for $n = 4$, random $\gamma_{ij} \in \mathbb{C}$

$$\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & \gamma_{31}t & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & \gamma_{31}t & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix}$$

$$\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & \gamma_{31} & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \gamma_{21}t & 1 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \gamma_{21}t & 1 & 0 \\ 0 & \gamma_{31} & 0 & 1 \\ 0 & 1 & 0 & 0 \end{bmatrix}$$

$$\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \gamma_{21} & 1 & 0 \\ 0 & \gamma_{31} & 0 & 1 \\ 0 & 1 & 0 & 0 \end{bmatrix} \begin{bmatrix} \gamma_{11}t & 1 & 0 & 0 \\ 1 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} \gamma_{11}t & 1 & 0 & 0 \\ \gamma_{21} & 0 & 1 & 0 \\ \gamma_{31} & 0 & 0 & 1 \\ 1 & 0 & 0 & 0 \end{bmatrix}$$

Generalizing the moving Flag

last three moves for $n = 4$, random $\gamma_{ij} \in \mathbb{C}$

$$\begin{bmatrix} \gamma_{11} & 1 & 0 & 0 \\ \gamma_{21} & 0 & 1 & 0 \\ \gamma_{31} & 0 & 0 & 1 \\ 1 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & \gamma_{22}t & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix} = \begin{bmatrix} \gamma_{11} & 1 & 0 & 0 \\ \gamma_{21} & 0 & \gamma_{22}t & 1 \\ \gamma_{31} & 0 & 1 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix}$$

$$\begin{bmatrix} \gamma_{11} & 1 & 0 & 0 \\ \gamma_{21} & 0 & \gamma_{22} & 1 \\ \gamma_{31} & 0 & 1 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \gamma_{21}t & 1 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} = \begin{bmatrix} \gamma_{11} & \gamma_{21}t & 1 & 0 \\ \gamma_{21} & \gamma_{22} & 0 & 1 \\ \gamma_{31} & 1 & 0 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix}$$

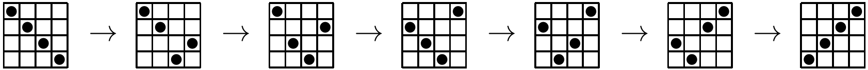
$$\begin{bmatrix} \gamma_{11} & \gamma_{21} & 1 & 0 \\ \gamma_{21} & \gamma_{22} & 0 & 1 \\ \gamma_{31} & 1 & 0 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & \gamma_{13}t & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix} = \begin{bmatrix} \gamma_{11} & \gamma_{21} & \gamma_{13}t & 1 \\ \gamma_{21} & \gamma_{22} & 1 & 0 \\ \gamma_{31} & 1 & 0 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix}$$

Encoding the Moves

bubble sort on $n \; n-1 \; \cdots \; 2 \; 1$

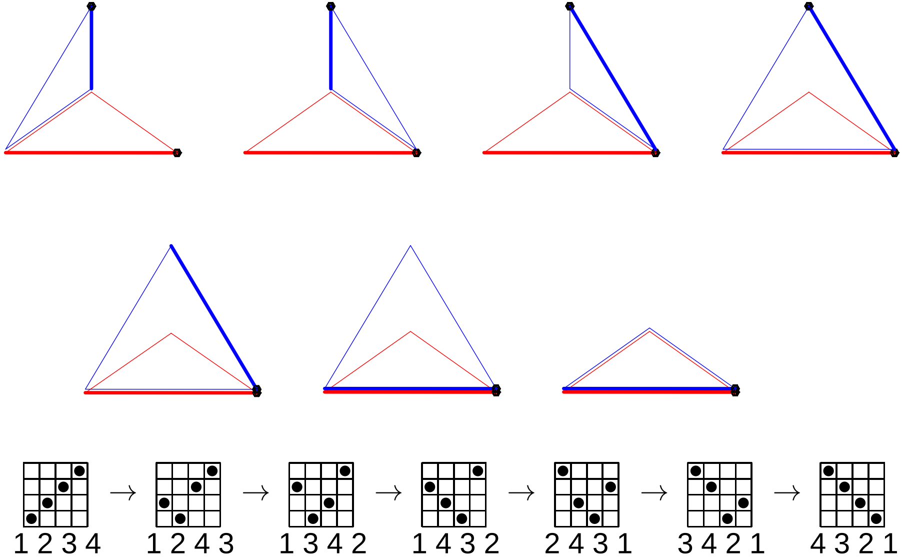
$$
I \rightarrow \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & \gamma_{31} & 1 \\ 0 & 0 & 1 & 0 \end{bmatrix} \rightarrow \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & \gamma_{21} & 1 & 0 \\ 0 & \gamma_{31} & 0 & 1 \\ 0 & 1 & 0 & 0 \end{bmatrix} \rightarrow \begin{bmatrix} \gamma_{11} & 1 & 0 & 0 \\ \gamma_{21} & 0 & 1 & 0 \\ \gamma_{31} & 0 & 0 & 1 \\ 1 & 0 & 0 & 0 \end{bmatrix}
$$

$$
\rightarrow \begin{bmatrix} \gamma_{11} & 1 & 0 & 0 \\ \gamma_{21} & 0 & \gamma_{22} & 1 \\ \gamma_{31} & 0 & 1 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix} \rightarrow \begin{bmatrix} \gamma_{11} & \gamma_{21} & 1 & 0 \\ \gamma_{21} & \gamma_{22} & 0 & 1 \\ \gamma_{31} & 1 & 0 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix} \rightarrow \begin{bmatrix} \gamma_{11} & \gamma_{21} & \gamma_{13} & 1 \\ \gamma_{21} & \gamma_{22} & 1 & 0 \\ \gamma_{31} & 1 & 0 & 0 \\ 1 & 0 & 0 & 0 \end{bmatrix}
$$



4 3 2 1 → 3 4 2 1 → 2 4 3 1 → 1 4 3 2 → 1 3 4 2 → 1 2 4 3 → 1 2 3 4

Specialization in $\mathbb{P}^3$



Littlewood-Richardson Homotopies

Degeneration of general flag from M to I in $\binom{n}{2}$ moves.

Three flag intersection condition $\Omega_\omega(I) \cap \Omega_\omega(M) \cap \Omega_\omega(F)$ is at the special position for $M = I$ reduced to the equations imposed on

$$X \in \Omega_\omega(F) : \quad P(X) = 0.$$

Generalizing the moving flag M leads to homotopies of the form

$$P(M(t)X) = 0, \quad t \in [0, 1].$$

The solution k-plane X is represented in this moving basis $M(t)$ in suitable local coordinates, via a localization pattern.

The Problem of Four General Lines

Classical problem in projective 3-space $\mathbb{P}^3$:

Given four general lines in $\mathbb{P}^3$ (no triplet is coplanar), find all lines that meet those four given lines nontrivially.

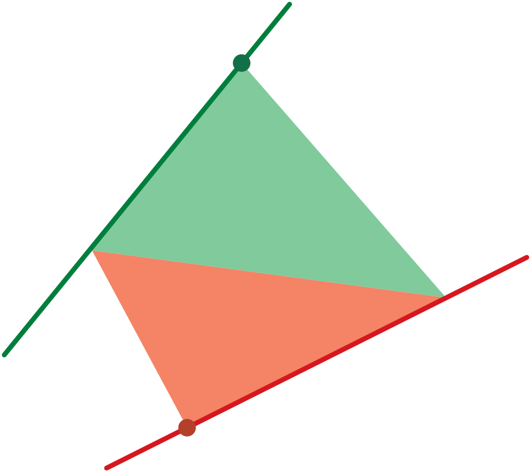
Identify $\mathbb{P}^3$ with $\mathbb{C}^4$ with natural basis $(\mathbf{e}_1, \mathbf{e}_2, \mathbf{e}_3, \mathbf{e}_4)$.
Let $L_1 = \mathrm{span}(\mathbf{e}_1, \mathbf{e}_2)$ and $L_2 = \mathrm{span}(\mathbf{e}_3, \mathbf{e}_4)$, consider

$$X = \begin{bmatrix} 1 & 0 \\ x_{2,1} & 0 \\ 0 & 1 \\ 0 & x_{4,2} \end{bmatrix} \quad P(X) = \begin{cases} \det([X | L_3]) = 0 \\ \det([X | L_4]) = 0 \end{cases}$$

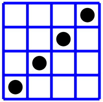
where X meets L_1 and L_2 by its pattern.

Specializing L_2 to coincide with L_1 makes X change pattern so $P(X) = \mathbf{0}$ becomes a linear system.

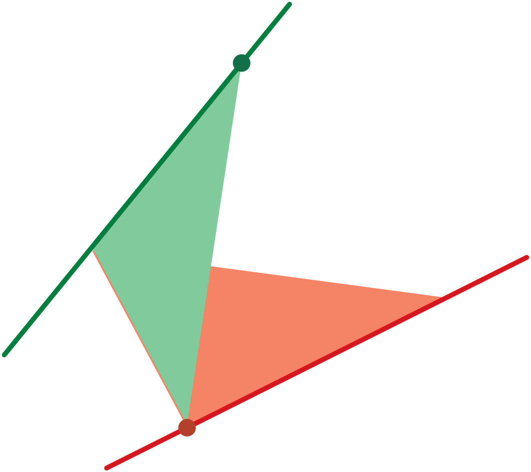
Specializing Moving Flag to Fixed Flag – stage 0



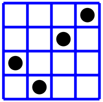
1	1	1	1
1	1	1	0
1	1	0	0
1	0	0	0



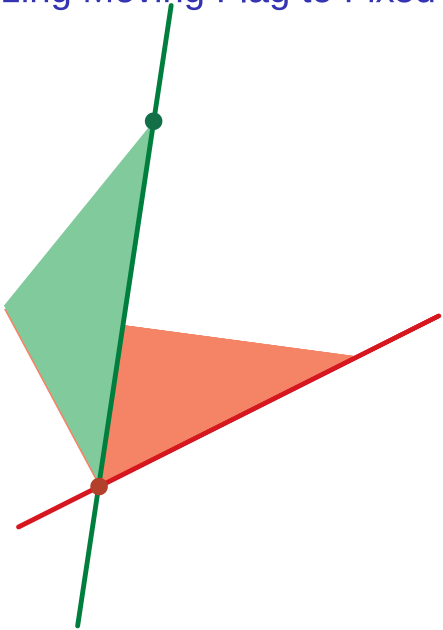
Specializing Moving Flag to Fixed Flag – stage 1



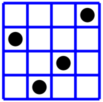
1	1	1	0
1	1	0	1
1	1	0	0
1	0	0	0



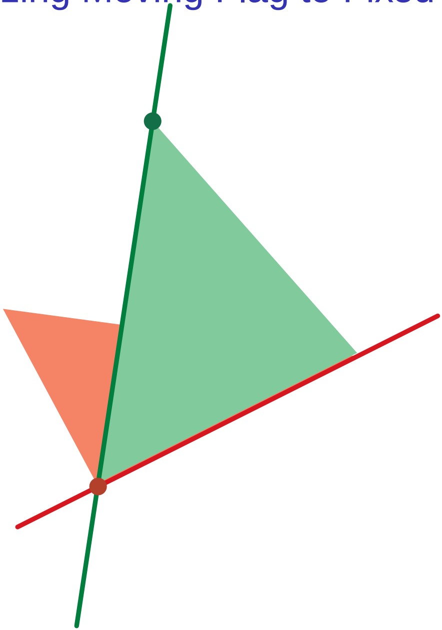
Specializing Moving Flag to Fixed Flag – stage 2



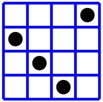
1	1	0	0
1	0	1	1
1	0	1	0
1	0	0	0



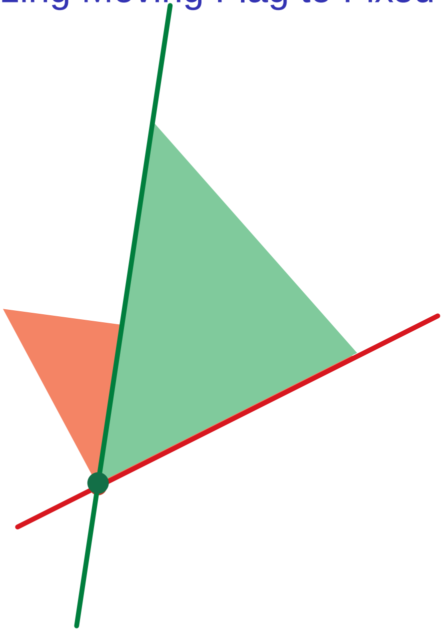
Specializing Moving Flag to Fixed Flag – stage 3



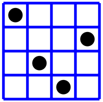
1	1	0	0
1	0	1	0
1	0	0	1
1	0	0	0



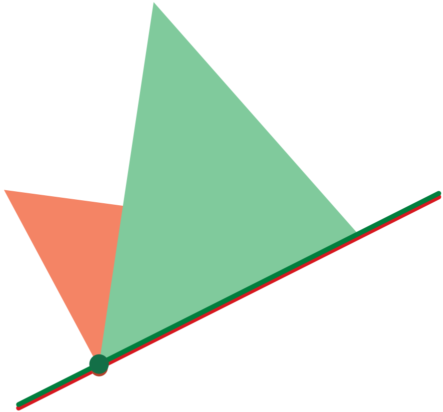
Specializing Moving Flag to Fixed Flag – stage 4



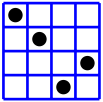
$$\begin{matrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 1 & 0 \\ 0 & 1 & 0 & 1 \\ 0 & 1 & 0 & 0 \end{matrix}$$



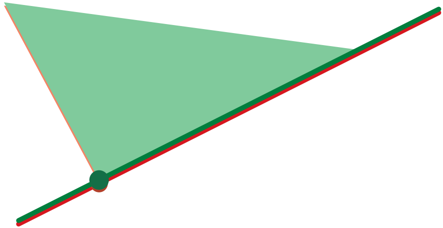
Specializing Moving Flag to Fixed Flag – stage 5



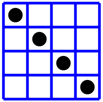
$$\begin{matrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 1 \\ 0 & 0 & 1 & 0 \end{matrix}$$



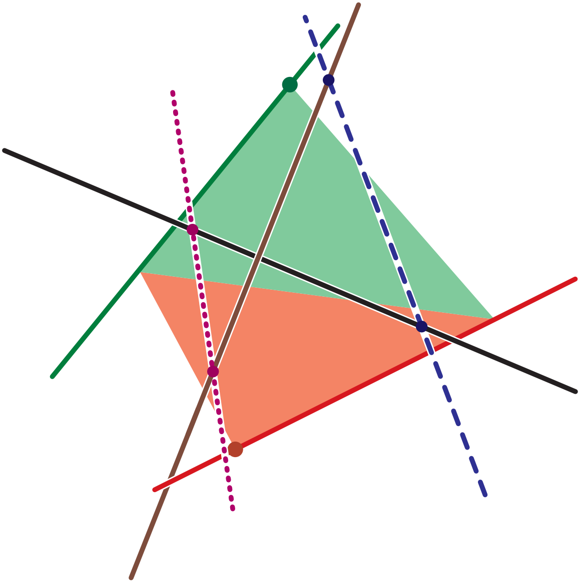
Specializing Moving Flag to Fixed Flag – stage 6



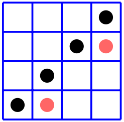
$$\begin{matrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{matrix}$$



Resolving the Problem of Four Lines – stage 0

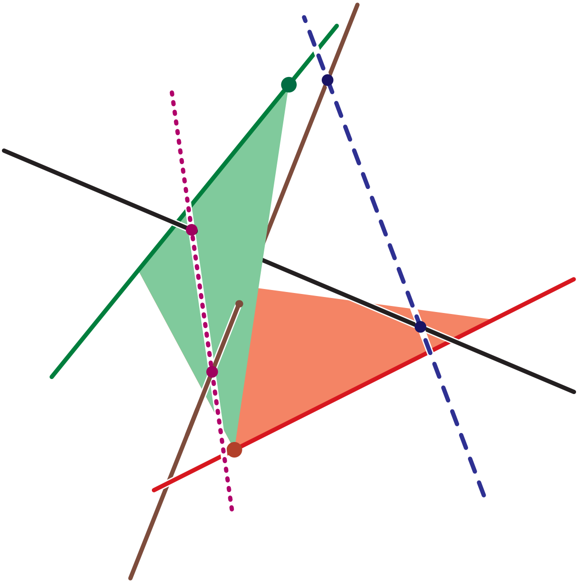


∗ 0
1 0
0 ∗
0 1

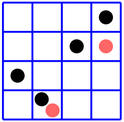


∗ 0
1 0
0 ∗
0 1

Resolving the Problem of Four Lines – stage 1

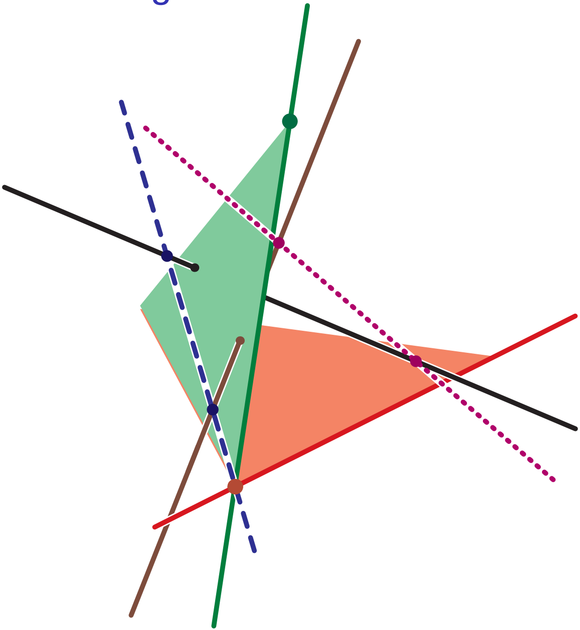


$$\begin{matrix} * & 0 \\ 1 & 0 \\ 0 & * \\ 0 & 1 \end{matrix}$$

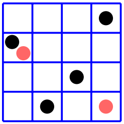


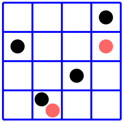
$$\begin{matrix} * & 0 \\ 1 & 0 \\ 0 & * \\ 0 & 1 \end{matrix}$$

Resolving the Problem of Four Lines – stage 2



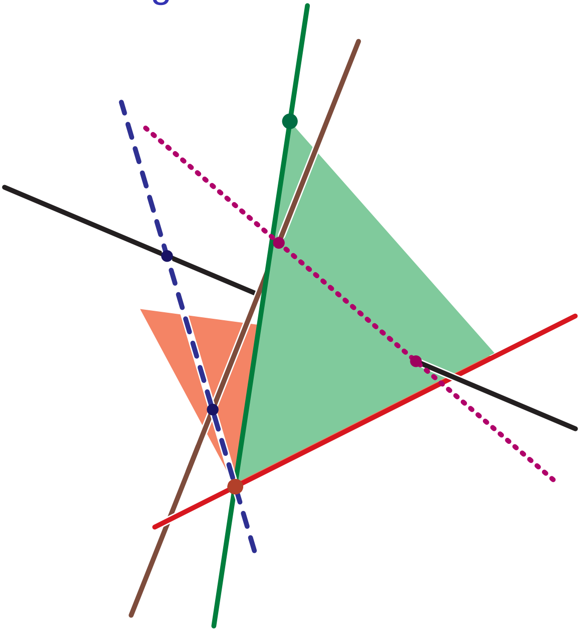
$$\begin{matrix} 0 & * \\ 1 & 0 \\ 0 & * \\ 0 & 1 \end{matrix}$$



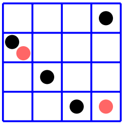


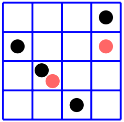
$$\begin{matrix} * & 0 \\ 1 & * \\ 0 & 0 \\ 0 & 1 \end{matrix}$$

Resolving the Problem of Four Lines – stage 3



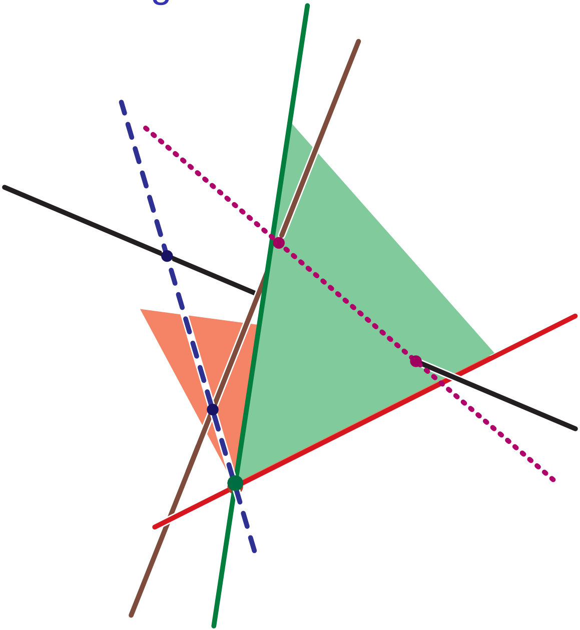
0	$\ast$
1	0
0	$\ast$
0	1



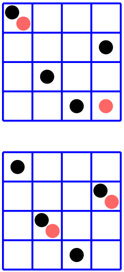


$\ast$	0
1	$\ast$
0	1
0	0

Resolving the Problem of Four Lines – stage 4

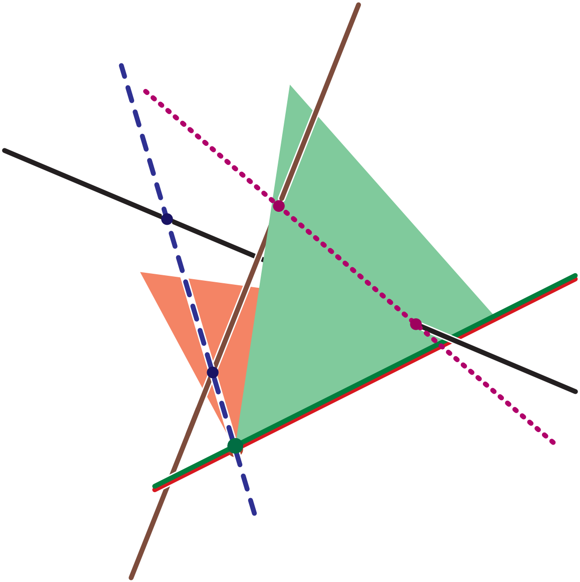


1 0
0 $\ast$
0 $\ast$
0 1

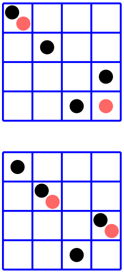


$\ast$ $\ast$
1 0
0 1
0 0

Resolving the Problem of Four Lines – stage 5

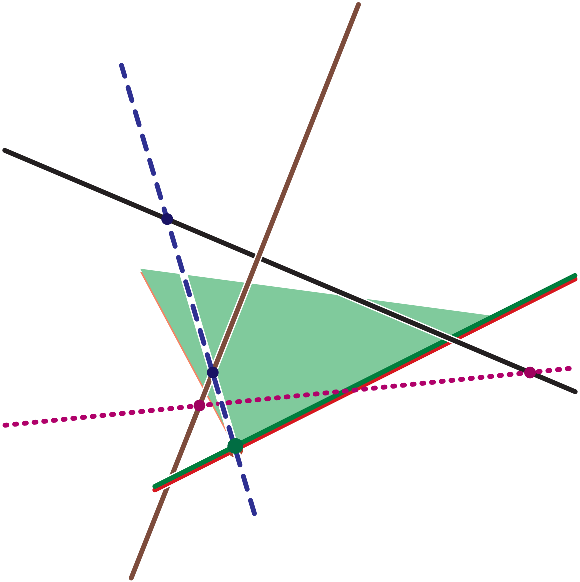


1 0
0 $*$
0 $*$
0 1

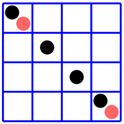


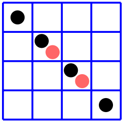
$*$ $*$
1 0
0 1
0 0

Resolving the Problem of Four Lines – stage 6



$$\begin{matrix} 1 & 0 \\ 0 & * \\ 0 & * \\ 0 & 1 \end{matrix}$$

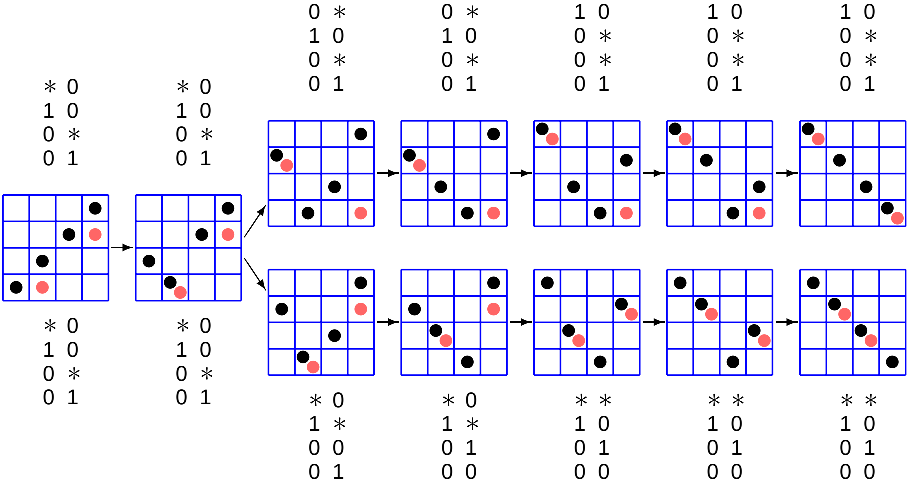




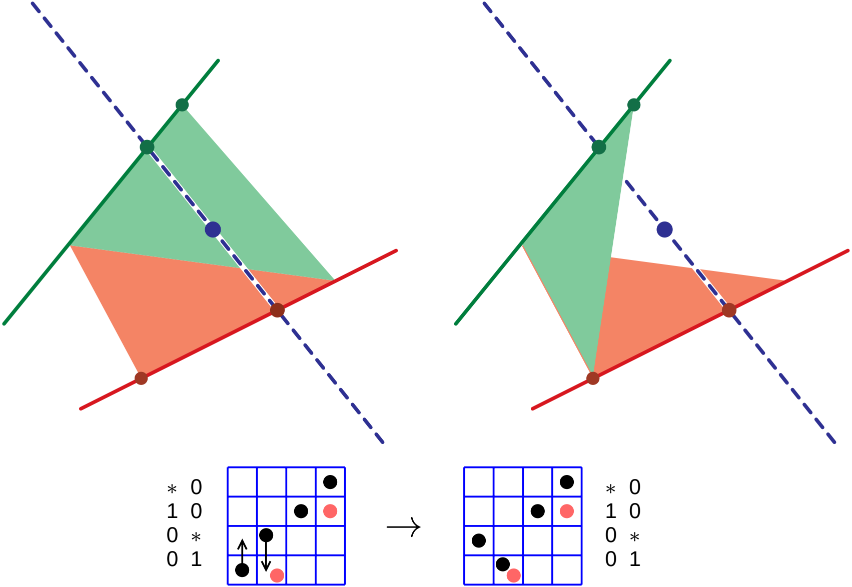
$$\begin{matrix} * & * \\ 1 & 0 \\ 0 & 1 \\ 0 & 0 \end{matrix}$$

Checker Games

resolving [2 4][2 4][2 4][2 4]



no homotopy, only change of coordinates

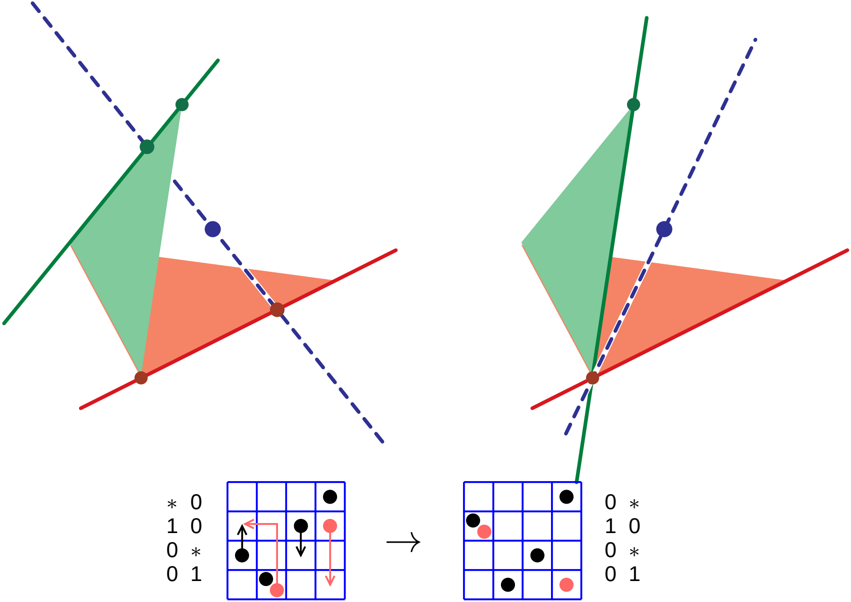


corresponding coordinate transformation

$$\begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 1 \\ 0 & 0 & 1 & -1 \end{bmatrix} \begin{bmatrix} x_{11} & 0 \\ 1 & 0 \\ 0 & x_{32} \\ 0 & 1 \end{bmatrix} = \begin{bmatrix} x_{11} & 0 \\ 1 & 0 \\ 0 & 1 \\ 0 & x_{32}-1 \end{bmatrix}$$

$$\equiv \begin{bmatrix} x_{11} & 0 \\ 1 & 0 \\ 0 & 1/(x_{32}-1) \\ 0 & 1 \end{bmatrix}$$

homotopy, as red checkers swap rows



homotopy as red checkers swap

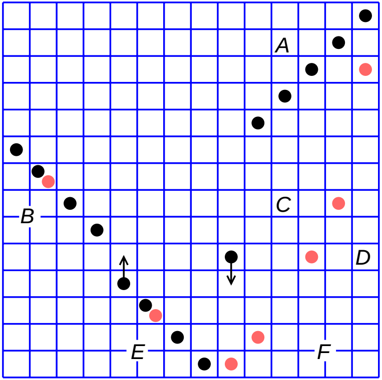
Similar to the case of a line meeting two lines and a fixed point, we use a homotopy:

$$X(t) = \begin{bmatrix} x_{12}t & x_{12} \\ x_{32} & 0 \\ x_{32}t & x_{32} \\ 0 & 1 \end{bmatrix}.$$

At $t = 0$, $X(0)$ fits the pattern.

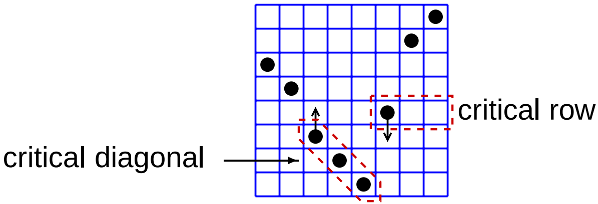
At $t = 1$, a coordinate change makes $X(1)$ to fit the pattern.

Localization Patterns



$$\begin{bmatrix}
x_{1,1} & \cdot & \cdot & \cdot & \cdot & \cdot & \cdot \\
x_{2,1} & \cdot & x_{2,3} & \cdot & \cdot & \cdot & \cdot \\
1 & \cdot & x_{3,3} & x_{3,4} & \cdot & \cdot & \cdot \\
\cdot & \cdot & x_{4,3} & x_{4,4} & \cdot & \cdot & \cdot \\
\cdot & \cdot & x_{5,3} & x_{5,4} & \cdot & x_{5,6} & \cdot \\
\cdot & x_{6,2} & x_{6,3} & x_{6,4} & x_{6,5} & x_{6,6} & x_{6,7} \\
\cdot & 1 & \cdot & \cdot & \cdot & \cdot & \cdot \\
\cdot & \cdot & 1 & x_{8,4} & x_{8,5} & x_{8,6} & x_{8,7} \\
\cdot & \cdot & \cdot & x_{9,4} & x_{9,5} & x_{9,6} & x_{9,7} \\
\cdot & \cdot & \cdot & 1 & \cdot & x_{10,6} & x_{10,7} \\
\cdot & \cdot & \cdot & \cdot & x_{11,5} & x_{11,6} & x_{11,7} \\
\cdot & \cdot & \cdot & \cdot & 1 & \cdot & \cdot \\
\cdot & \cdot & \cdot & \cdot & \cdot & 1 & x_{13,7} \\
\cdot & \cdot & \cdot & \cdot & \cdot & \cdot & 1
\end{bmatrix}$$

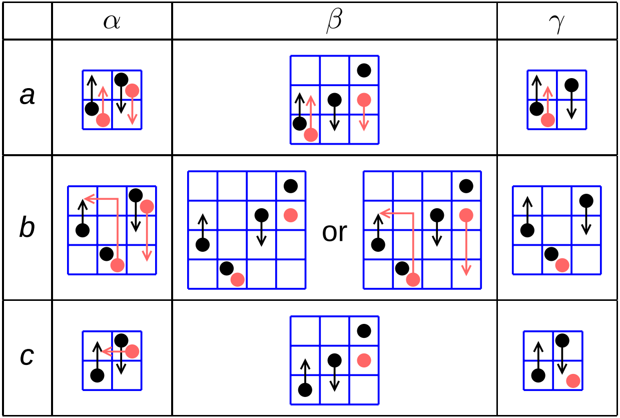
Rising and Falling Checkers



To resolve $\Omega_\omega(F) \cap \Omega_\tau(M)$, 9 cases to consider:

1. Where is the top red checker in the critical diagonal?
   - (*a*) In the rising checker's square.
   - (*b*) Elsewhere in the critical diagonal.
   - (*c*) There is no red checker in the critical diagonal.
2. Where is the red checker in the critical row?
   - (α) In the descending checker's square.
   - (β) Elsewhere in the critical row.
   - (γ) There is no red checker in the critical row.

Movement of Red Checkers



An Implementation in PHCpack

Since v2.3.46 Littlewood-Richardson homotopies are in PHCpack, at `http://www.math.uic.edu/~jan/download.html`

`phc -e` option #4 allows to resolve intersection conditions,

e.g.: in $\mathbb{C}^{10}$: $[6\ 8\ 10]^7 = 720[1\ 2\ 3]$,
in $\mathbb{C}^{11}$: $[7\ 9\ 11]^8 = 3598[1\ 2\ 3]$,
in $\mathbb{C}^{12}$: $[9\ 11\ 12][8\ 11\ 12]^{13} = 860574[1\ 2\ 3]$, etc...

Solving small Schubert problems on a Mac OS X 2.2 Ghz:

- $[2\ 4]^4 = 2$ takes 5 milliseconds,
- $[2\ 4\ 6]^3 = 2$ takes 169 milliseconds,
- $[2\ 5\ 8]^2[4\ 6\ 8] = 2$ takes 2.556 seconds,
- $[2\ 4\ 6\ 8]^2[2\ 5\ 7\ 8] = 3$ takes 8.595 seconds.

Macaulay 2 package LRhomotopies.m2

The example below computes all 3-planes that satisfy $[2\ 4\ 6]^3$.

```
i1 : R := ZZ;

i2 : n := 6;

i3 : m := matrix{{3, 2, 4, 6}};

                1        4
o3 : Matrix ZZ  <--- ZZ

i4 : result := LRtriple(n,m);
the input data for phc -e :
5
6
[ 2 4 6 ]^3;
0
/tmp/M2-296-2PHCoutput
0
0

writing data to file /tmp/M2-296-1PHCinput
running phc -e, session output to /tmp/M2-296-3PHCsession
                writing output to /tmp/M2-296-2PHCoutput
opening output file /tmp/M2-296-4PHCsolutions

extracting fixed flags, polynomial system, solutions
```