



[https://github.com/  
martinchapman/BuildX\(.git\)](https://github.com/martinchapman/BuildX(.git))

# BUILD X: ALGORITHMS

MARTIN CHAPMAN

# GRAPHS

Yellow

Orange

Red

Magenta

Violet

Blue

Cyan

Green

# BUILD X: ALGORITHMS

MARTIN CHAPMAN

GRAPHS (sort of)

Yellow

Orange

Red

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Violet

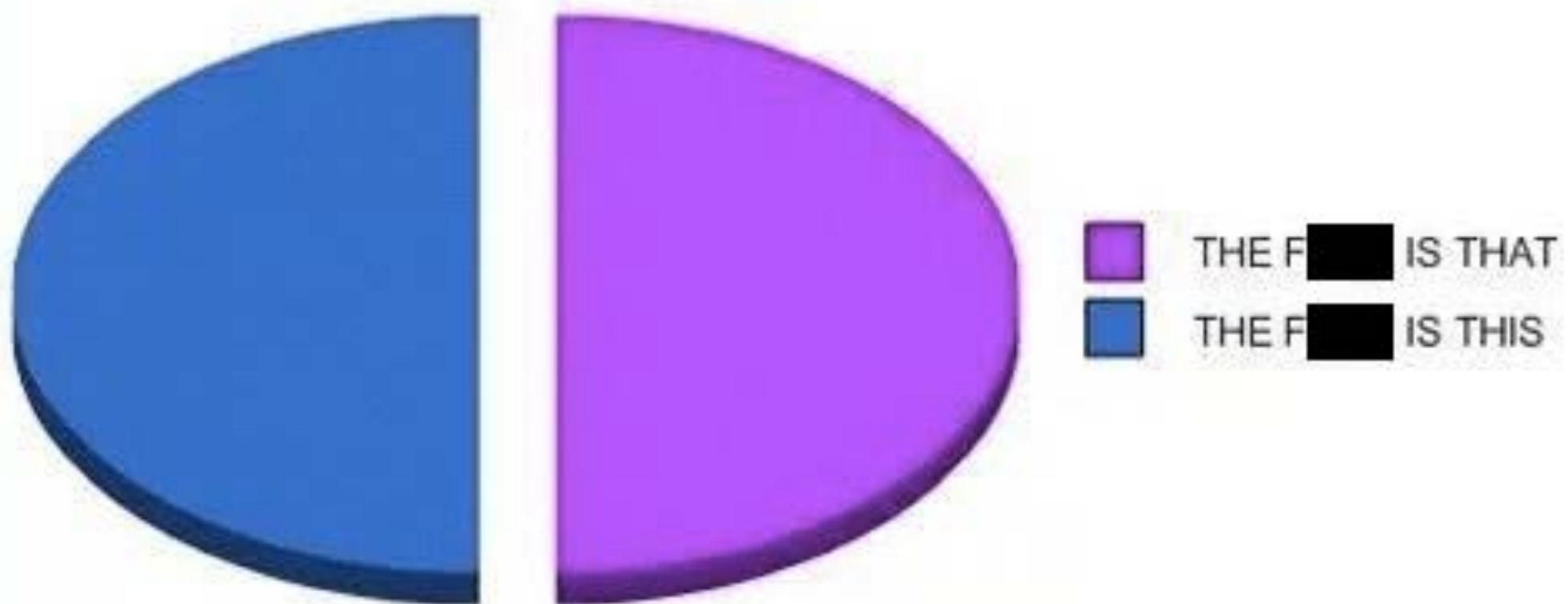
Blue

Cyan

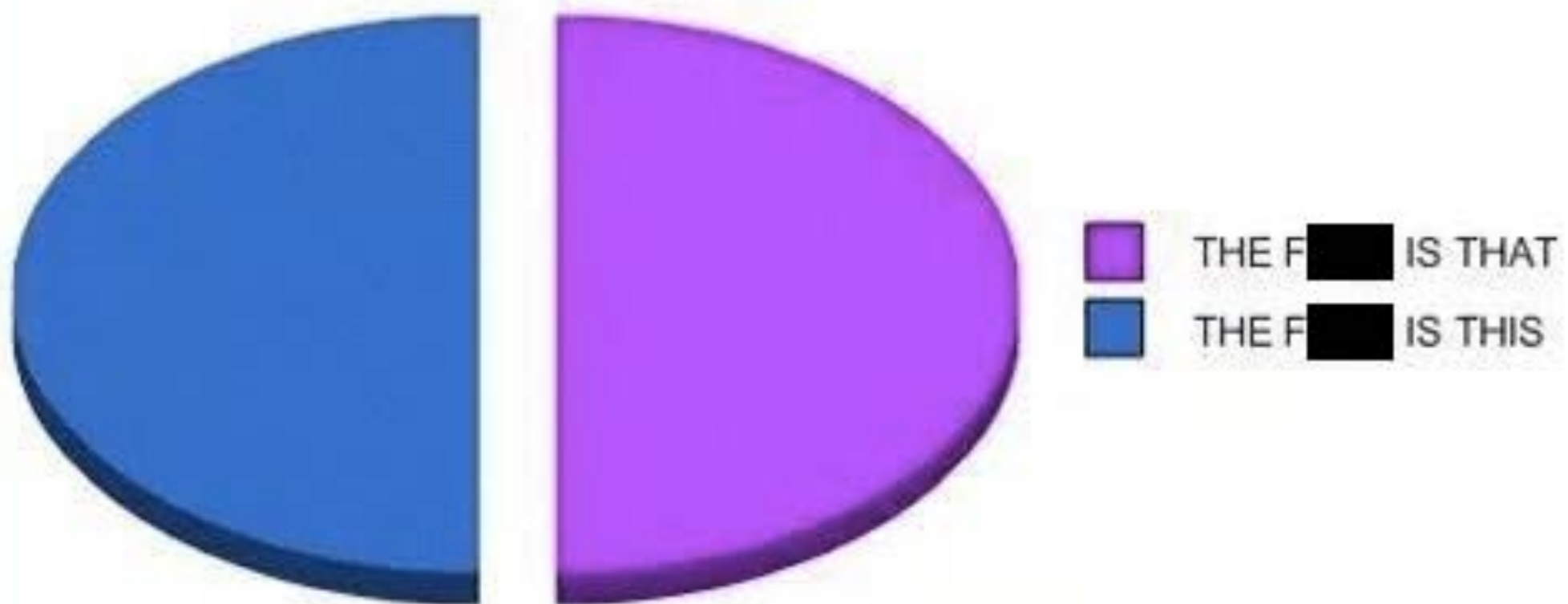
Green



# What I think about in math class



# What I think about in math class





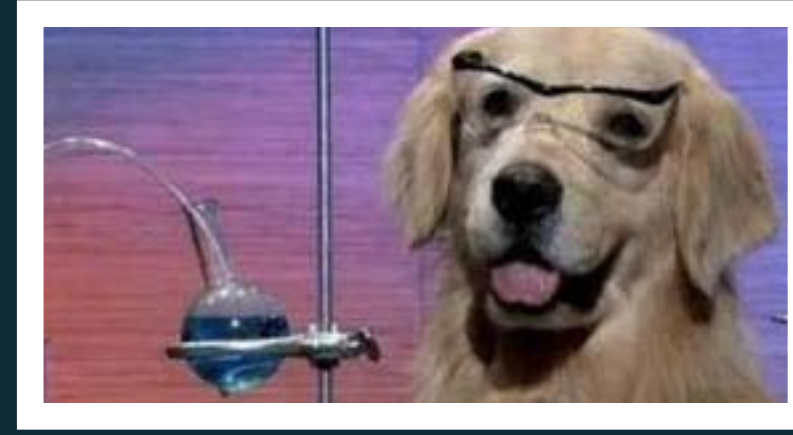
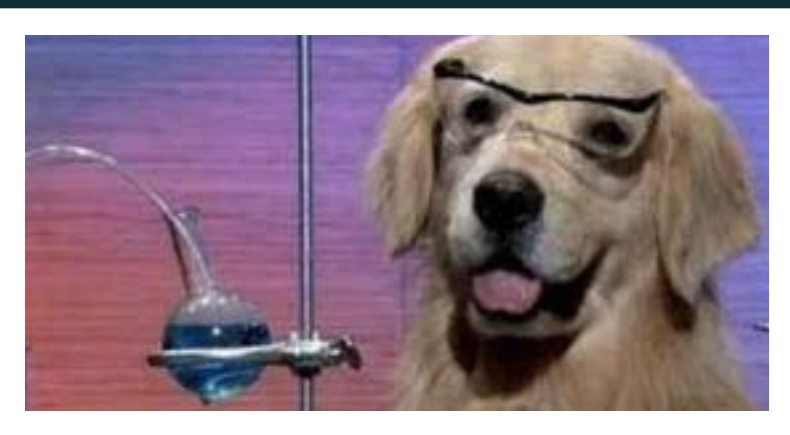
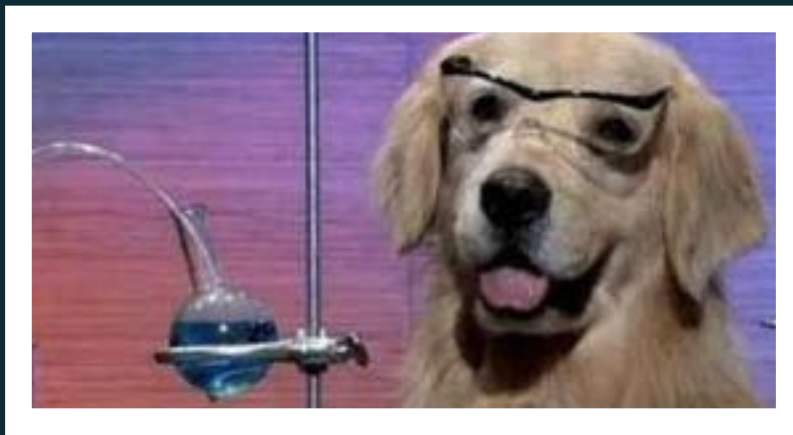
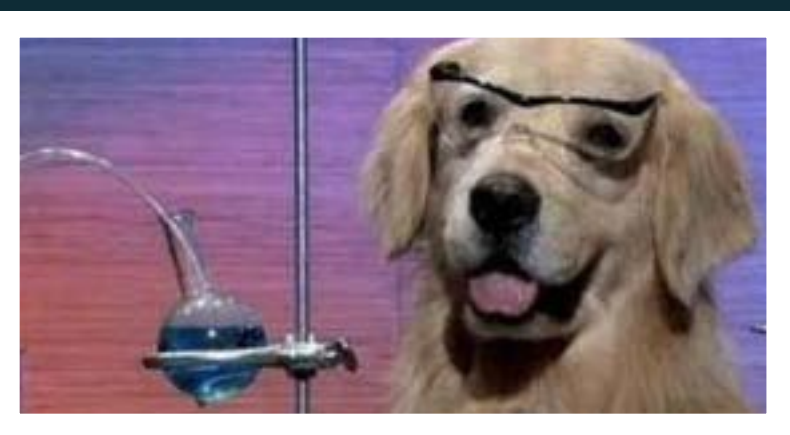
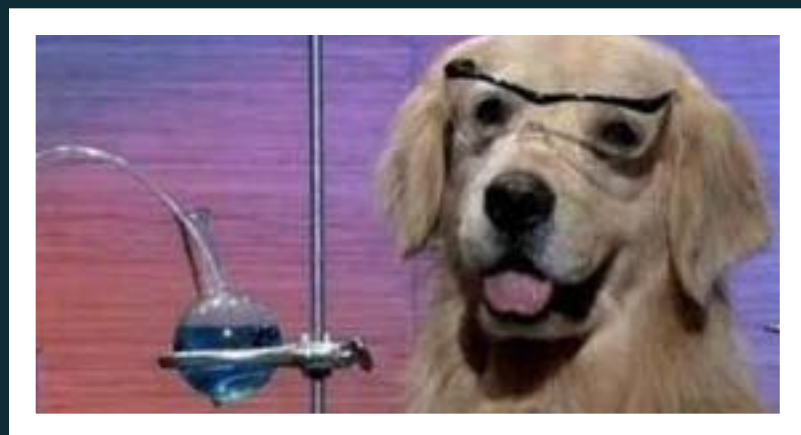
**I HAVE NO  
IDEA WHAT  
I'M DOING**











?



# BUILD X: ALGORITHMS

GRAPHS (sort of)

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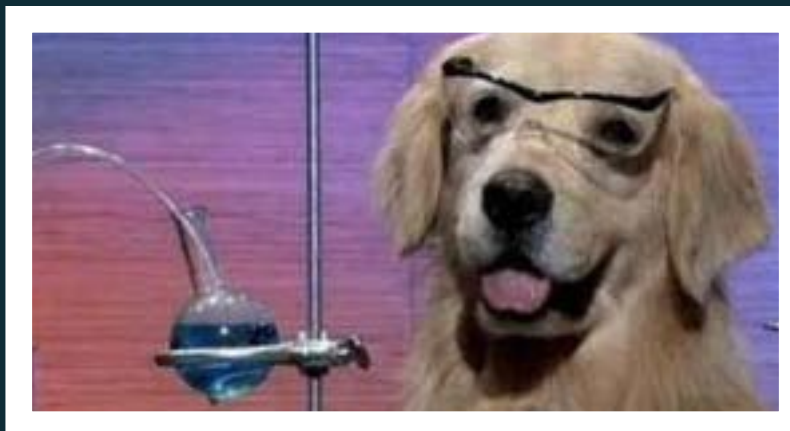
Blue

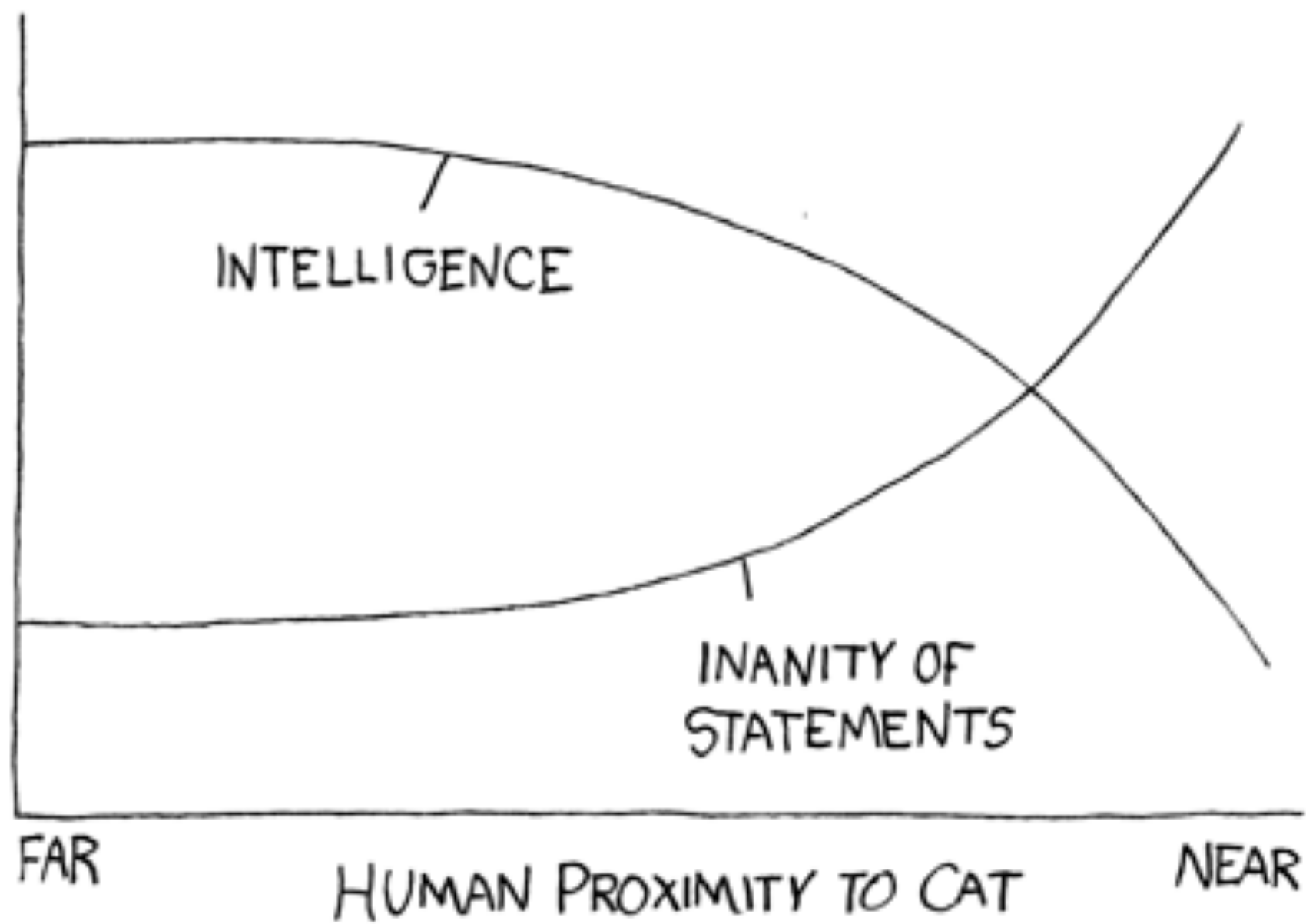
Cyan

Green

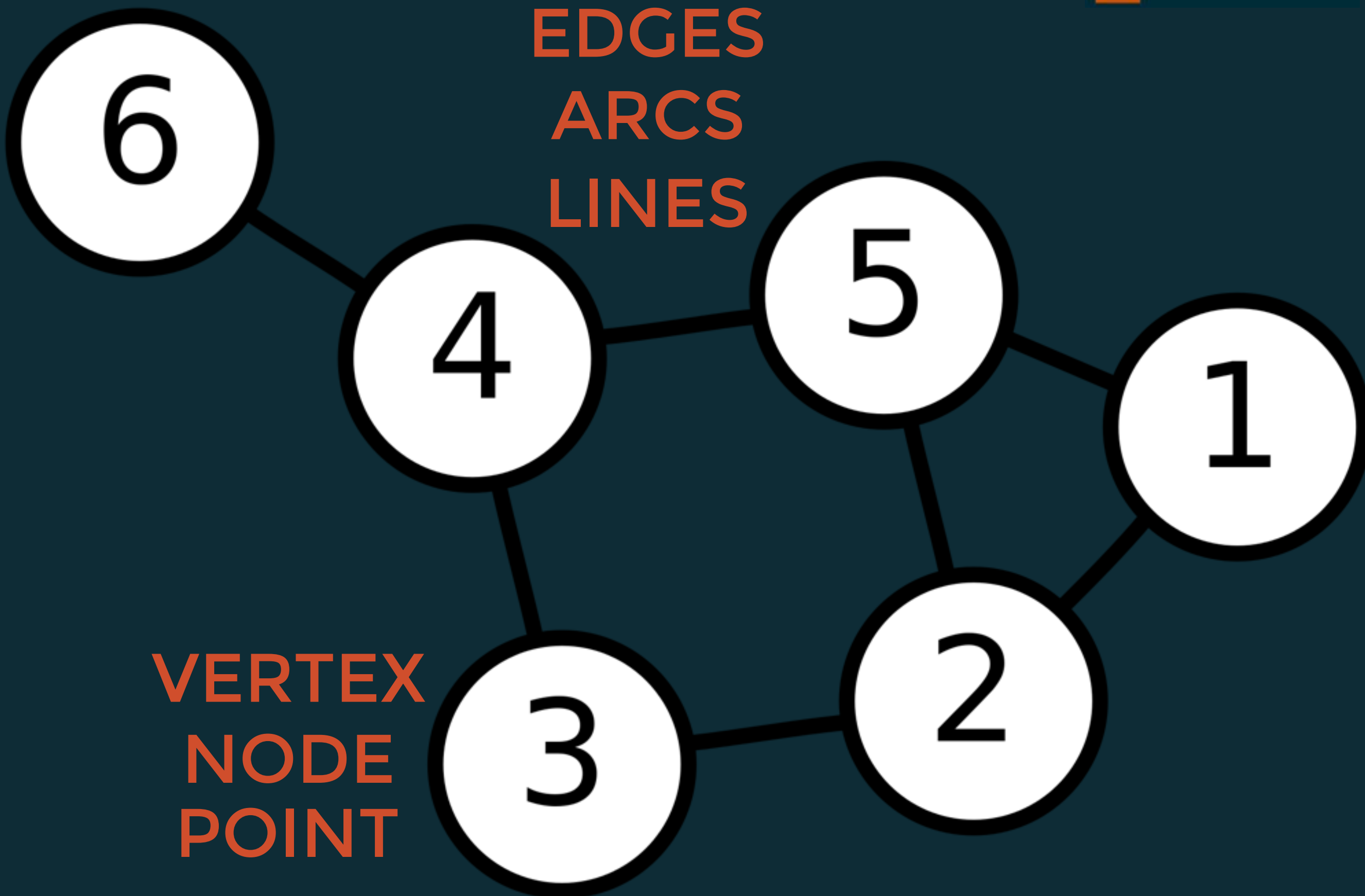
GRAPH





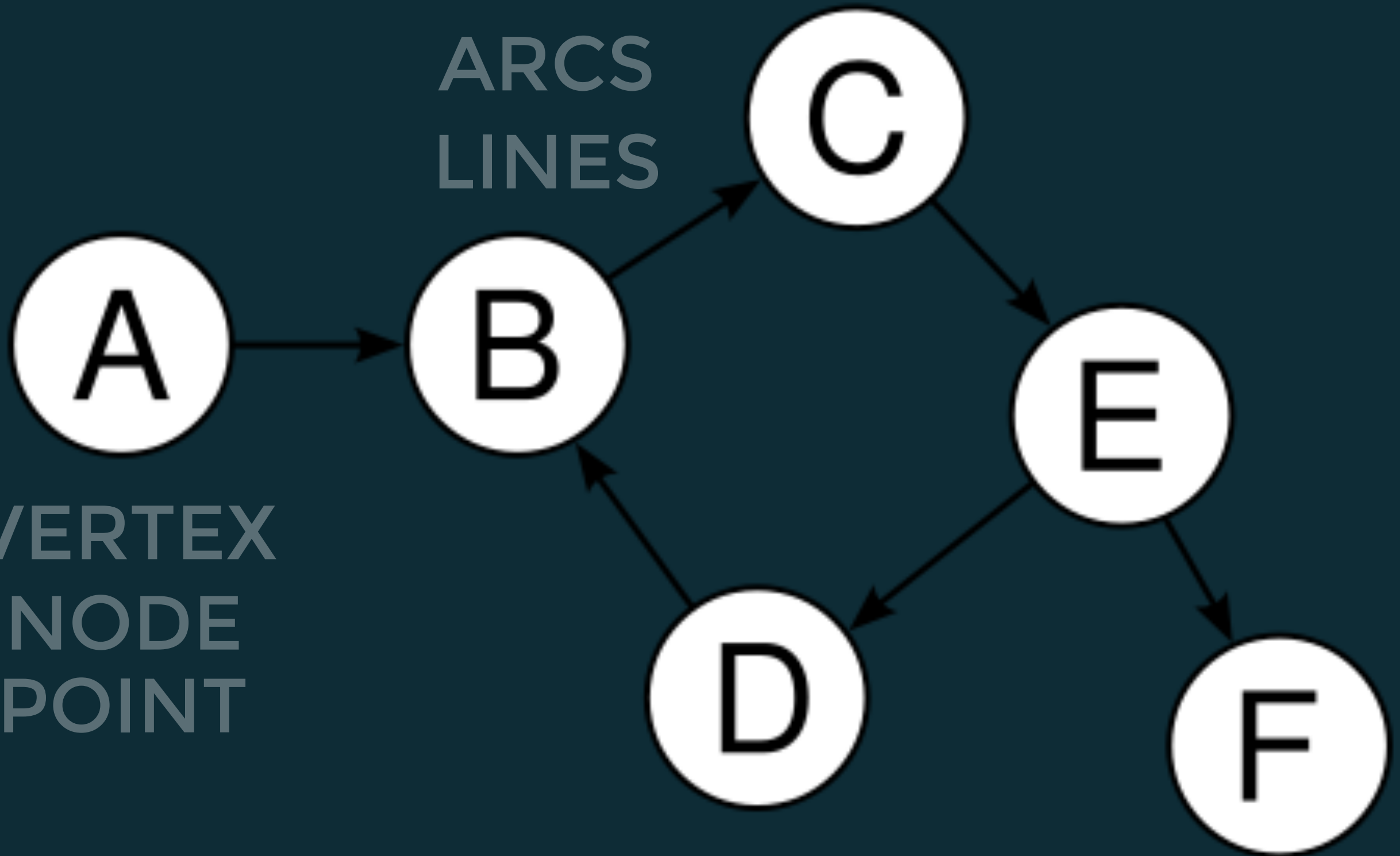


EDGES  
ARCS  
LINES



VERTEX  
NODE  
POINT

EDGES  
ARCS  
LINES



VERTEX  
NODE  
POINT

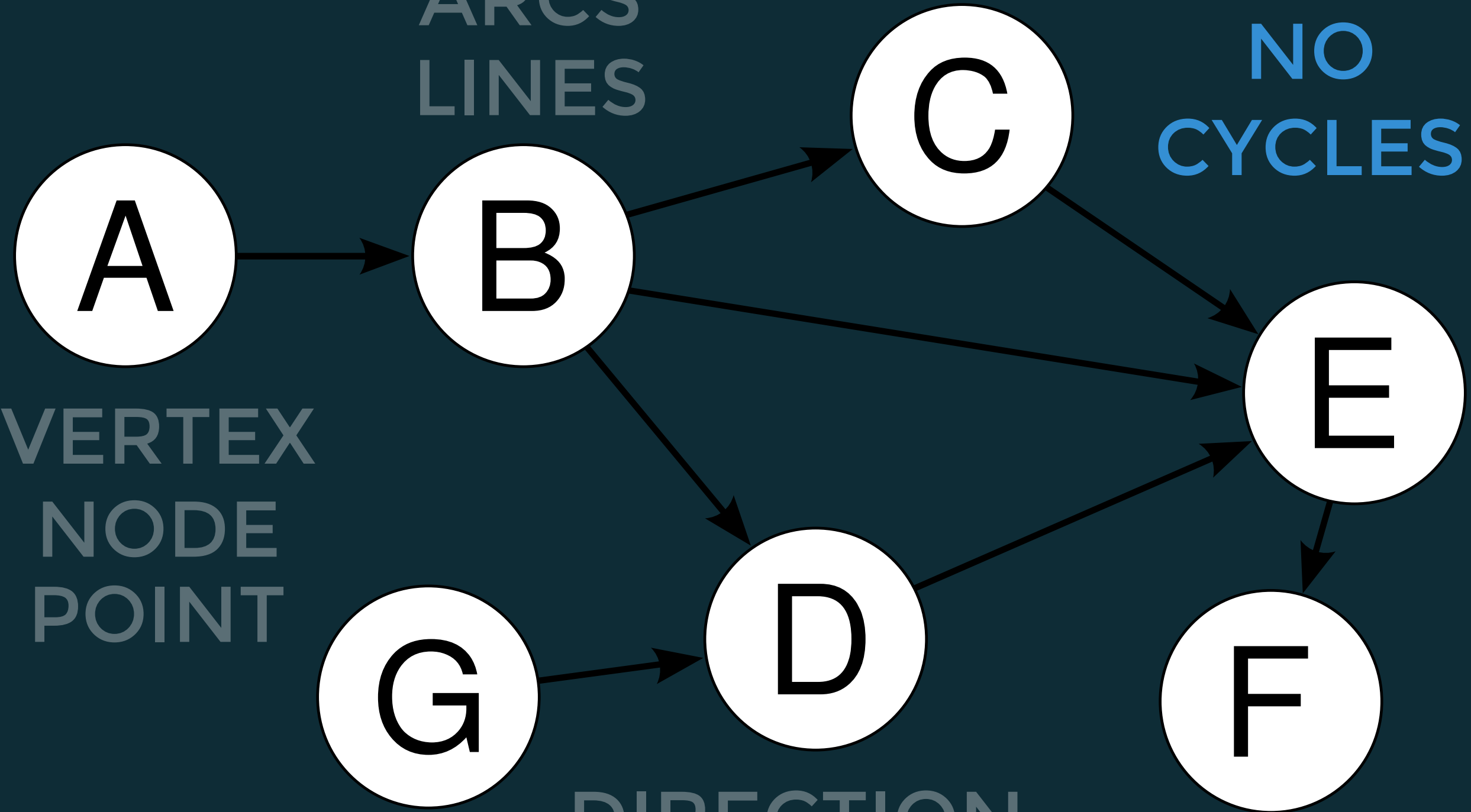
DIRECTION

EDGES  
ARCS  
LINES

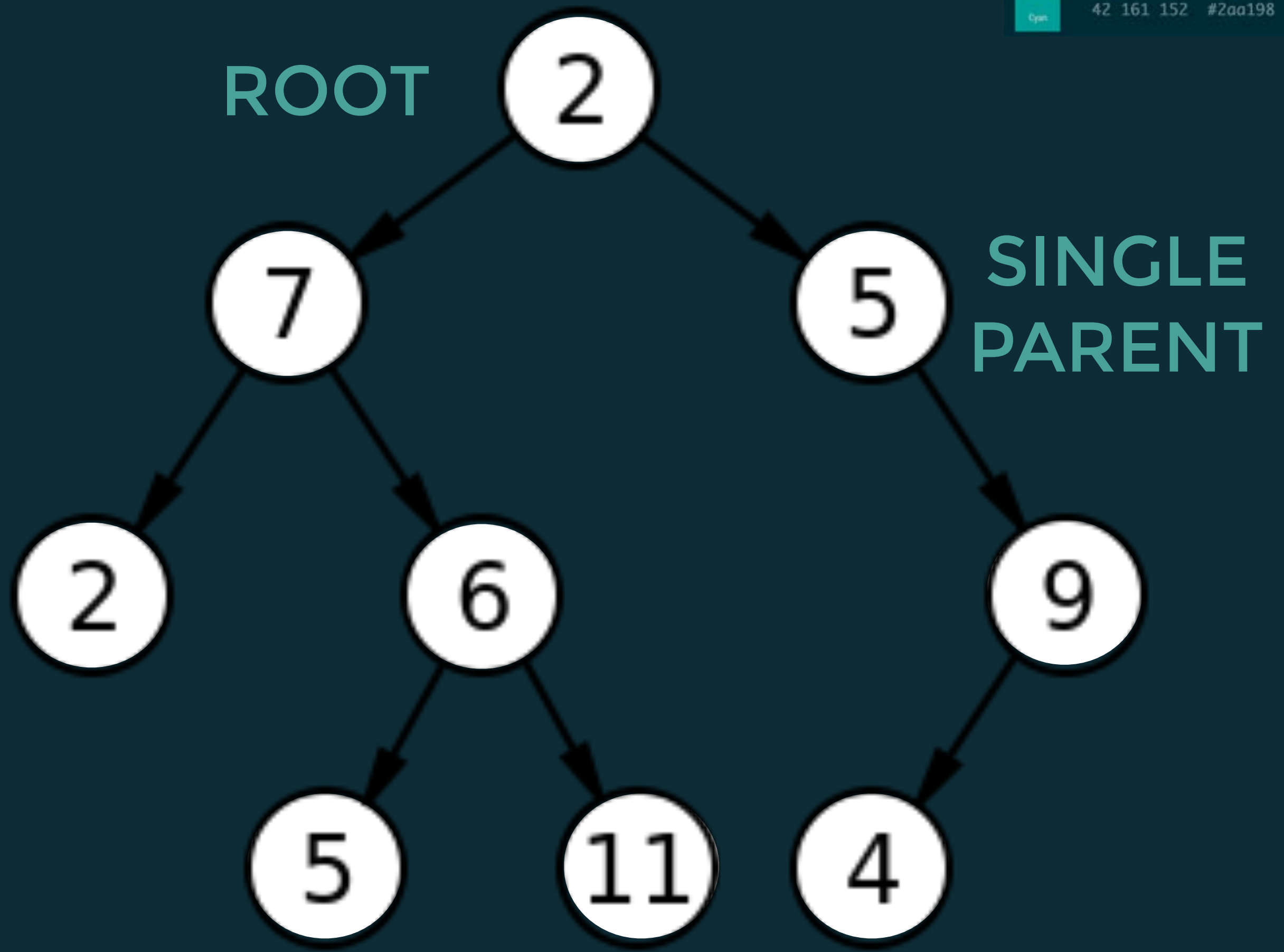
NO  
CYCLES

VERTEX  
NODE  
POINT

DIRECTION

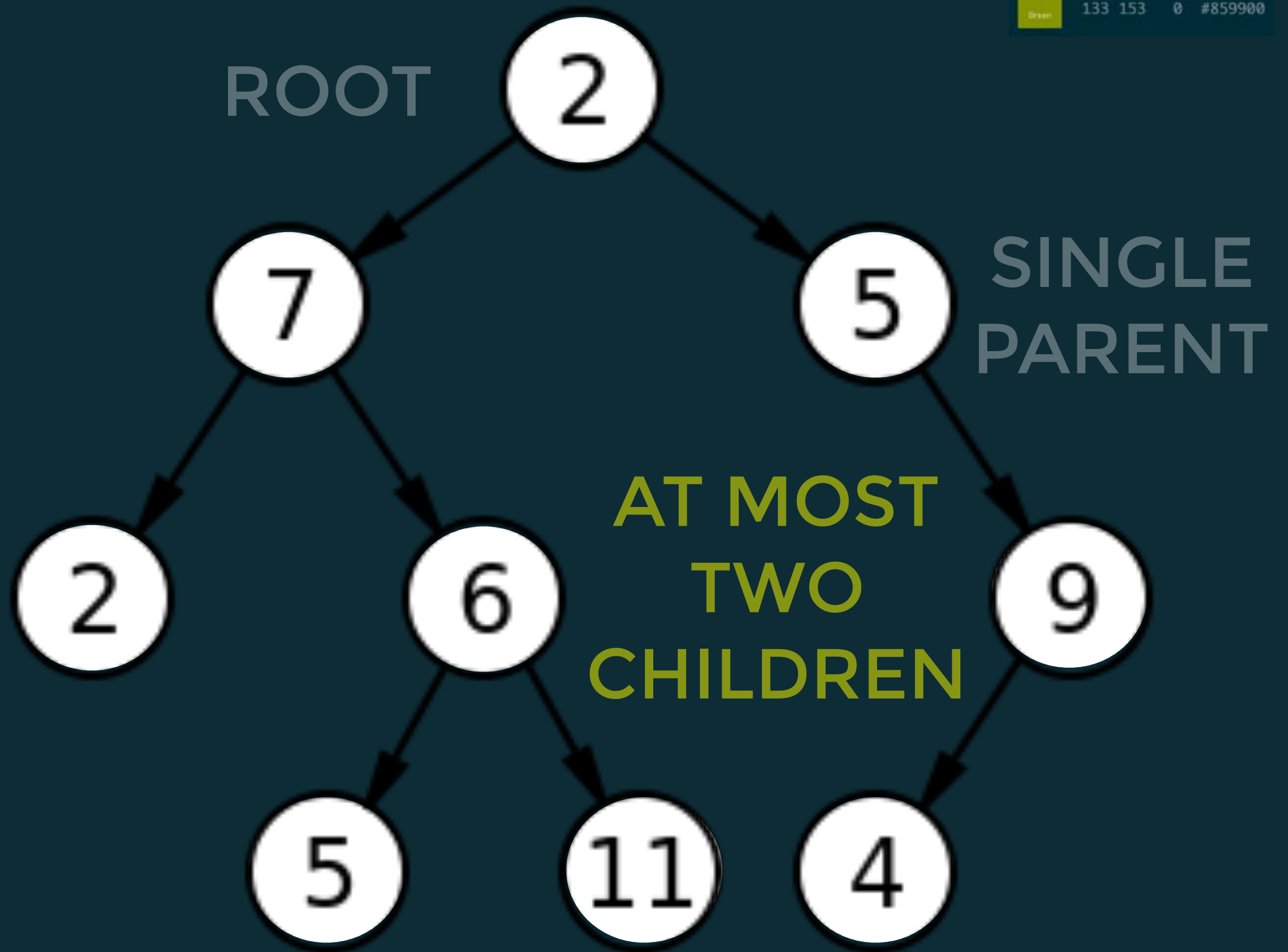


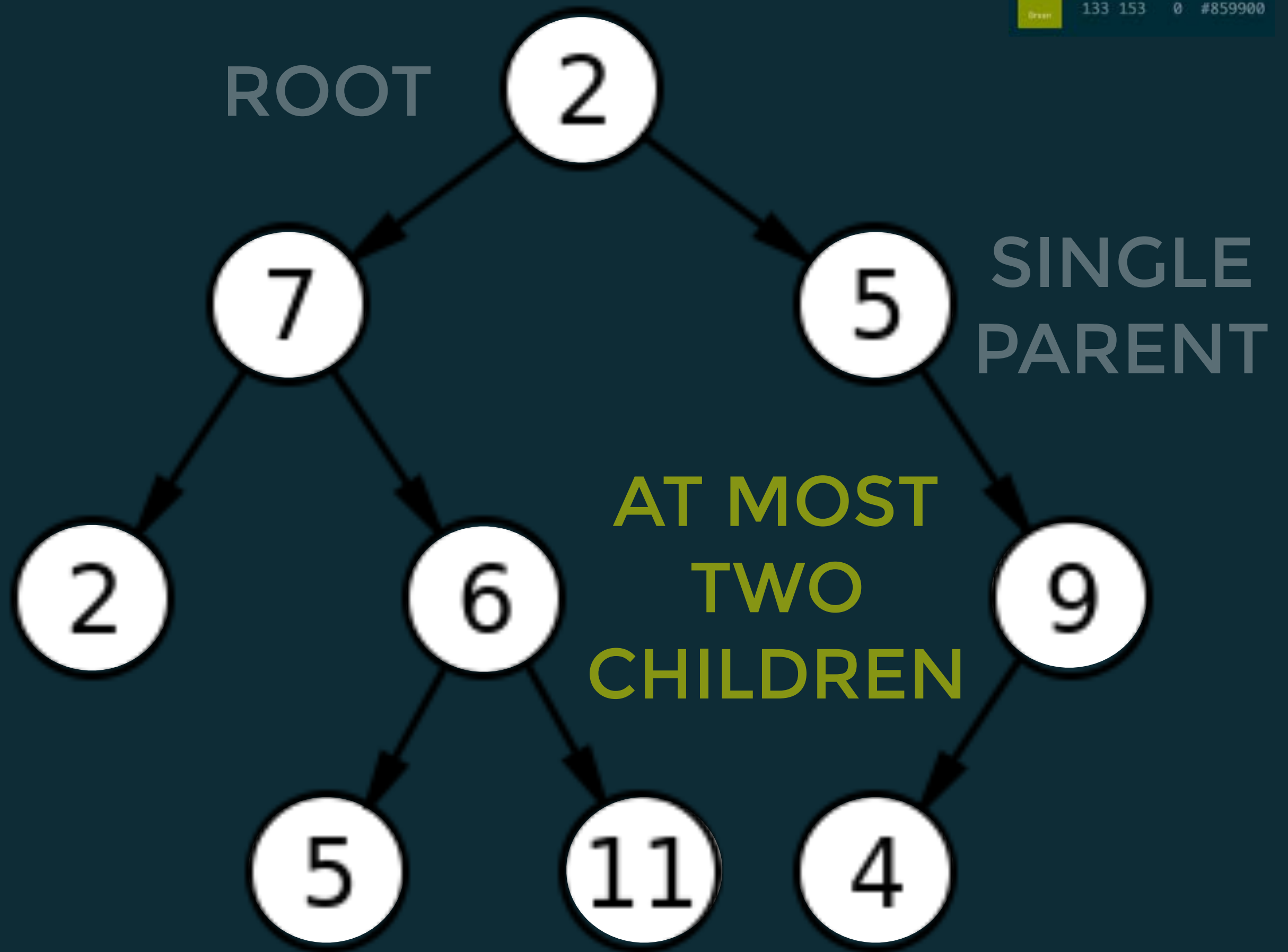




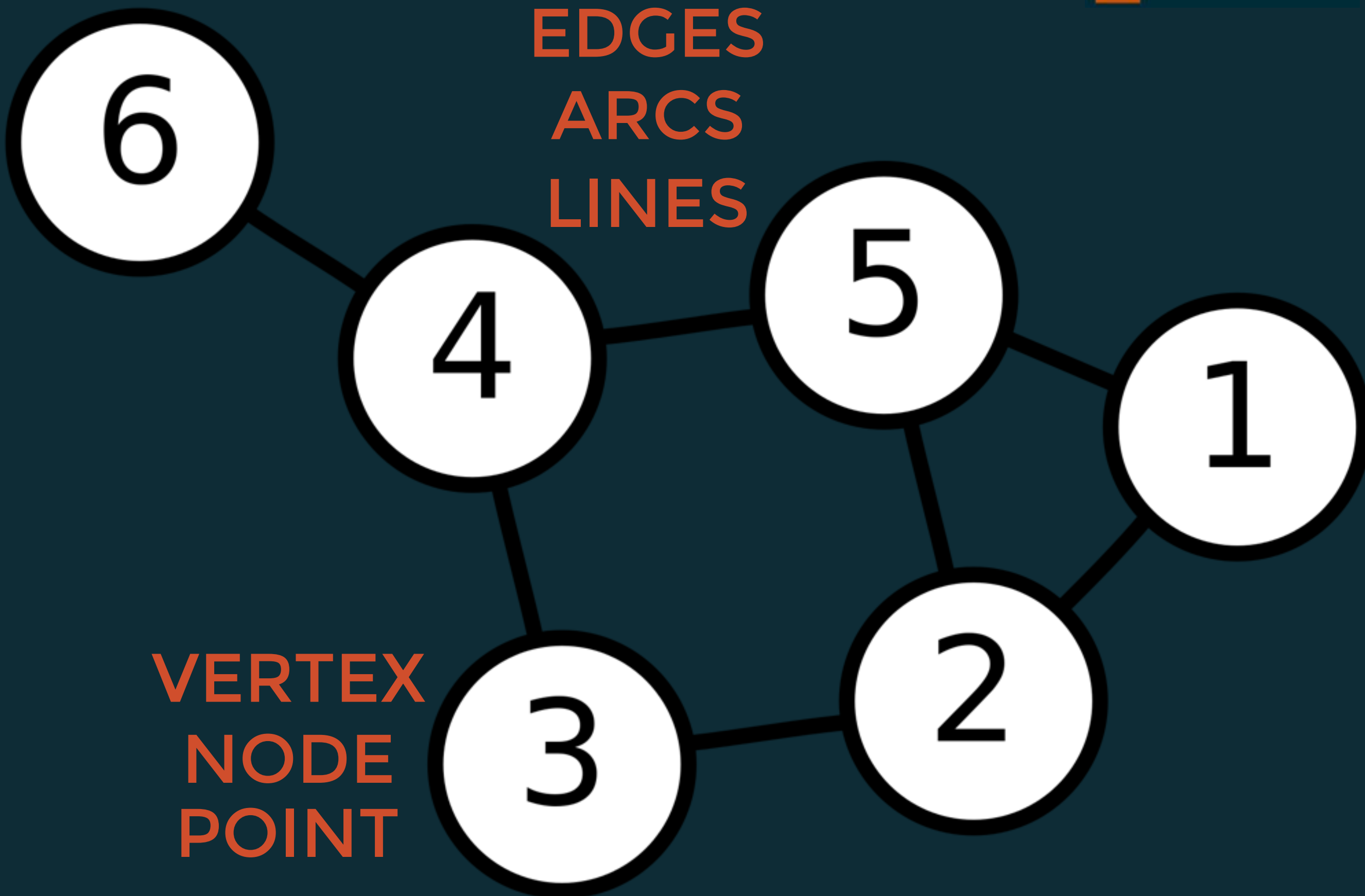
# TREE

(other definitions exist)





EDGES  
ARCS  
LINES



VERTEX  
NODE  
POINT





# HOW DO WE CONSTRUCT A GRAPH?



# TOPOLOGY AND GENERATORS

<http://graphstream-project.org/doc/Generators/>



# RANDOM

Béla Bollobás. Random Graphs. Springer, 1998.

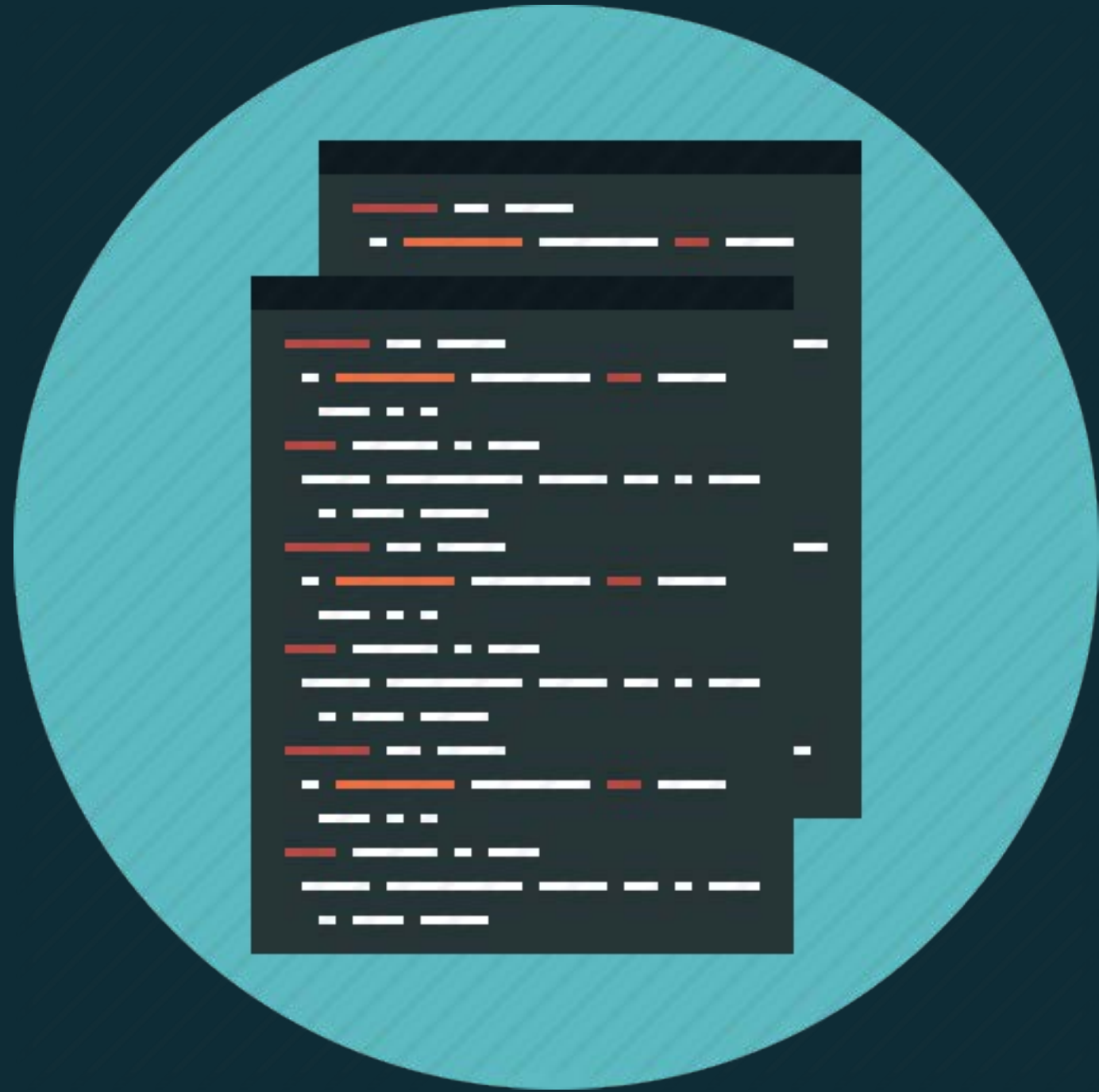
# SCALE-FREE

Albert-László BY Barabási and Eric Bonabeau.  
Scale-free Networks.  
Scientific American, 5(5):50–59, 2003.





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# SCALE-FREE

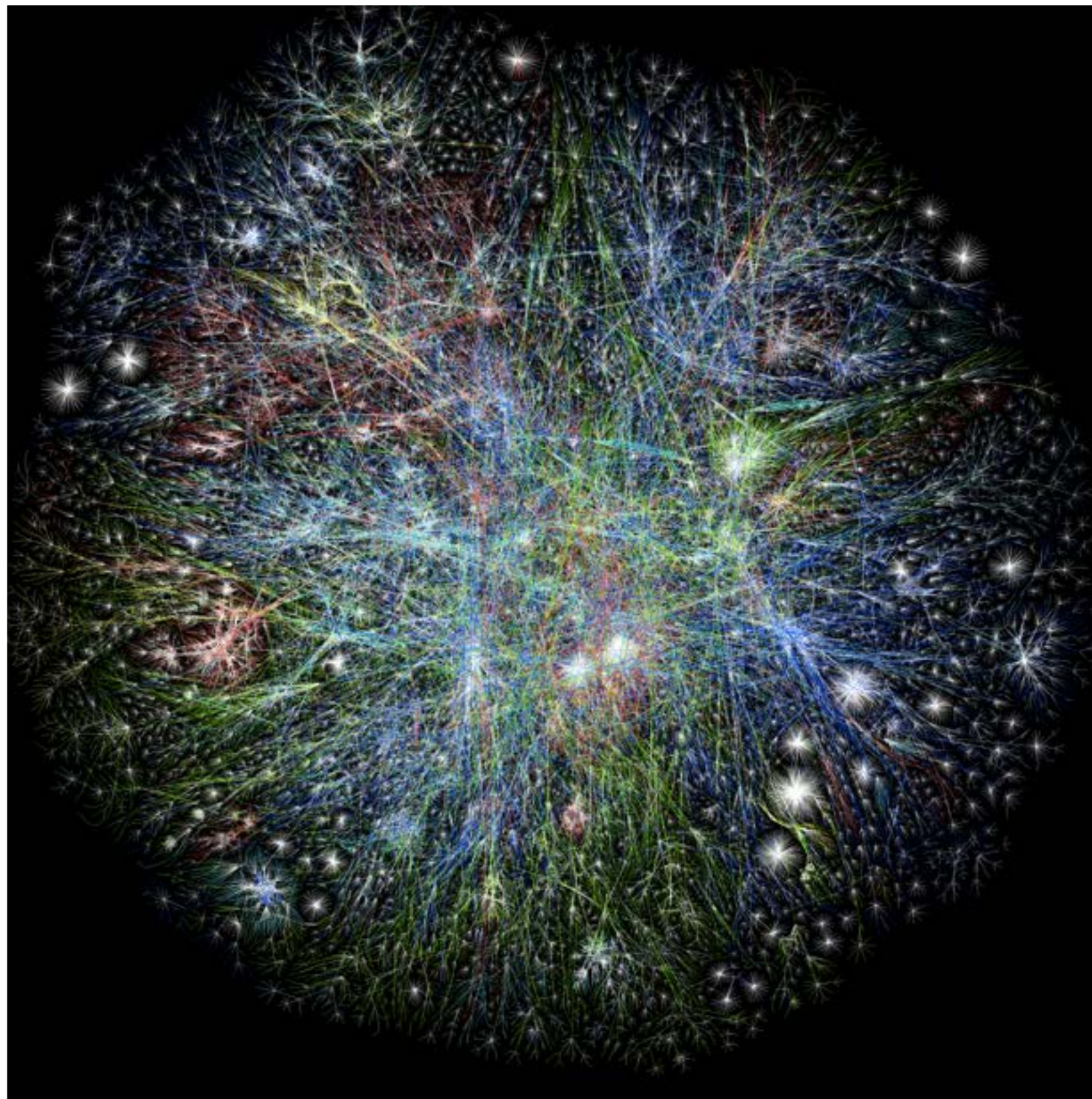
Michalis Faloutsos, Petros Faloutsos, and Christos Faloutsos.

On Power-law Relationships of the Internet Topology.

In Proceedings of

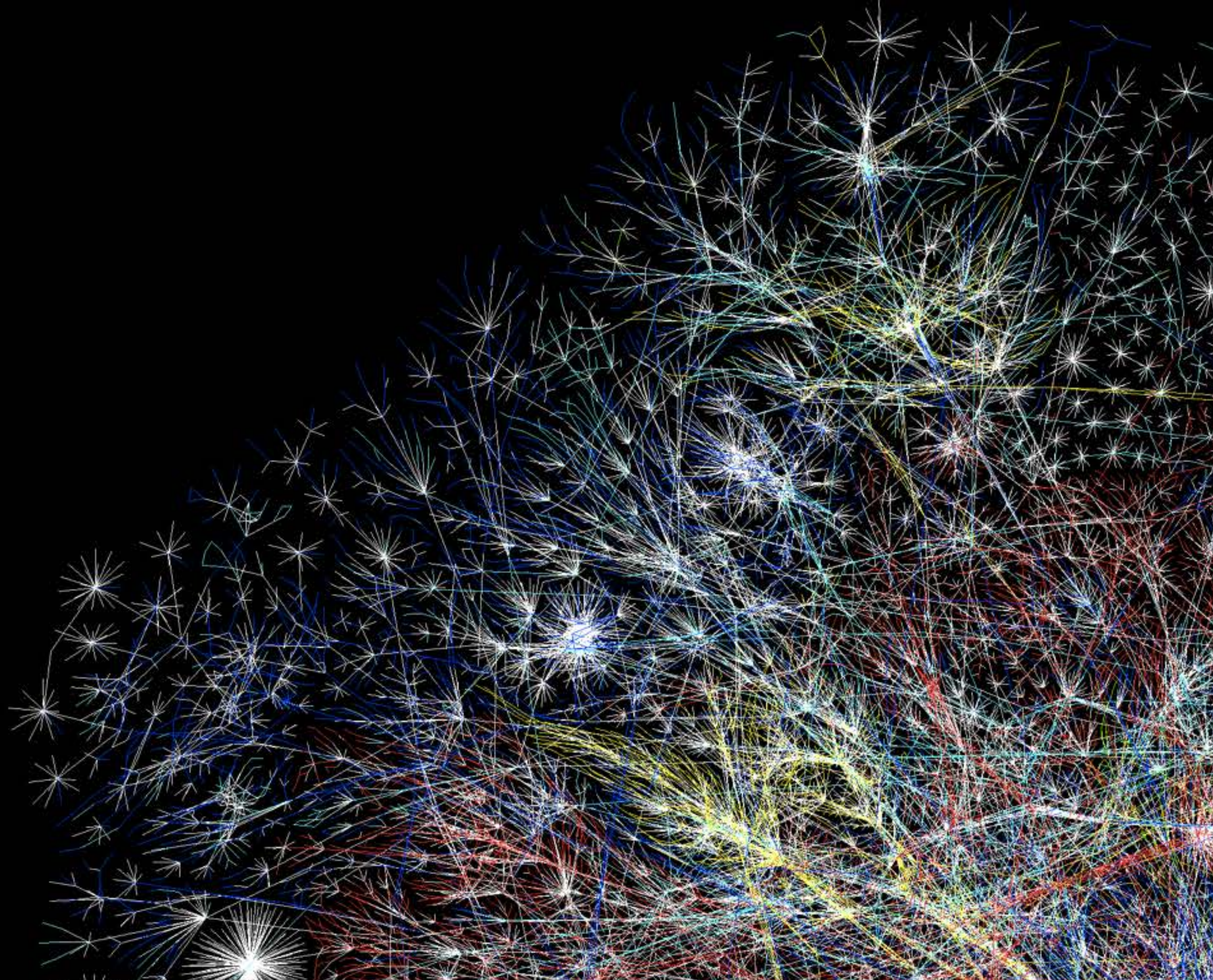
The 1999 Conference on Applications, Technologies, Architectures, and Protocols for  
Computer Communications  
(SIGCOMM99), pages 251-262, 1999.





<http://opte.org/maps/>

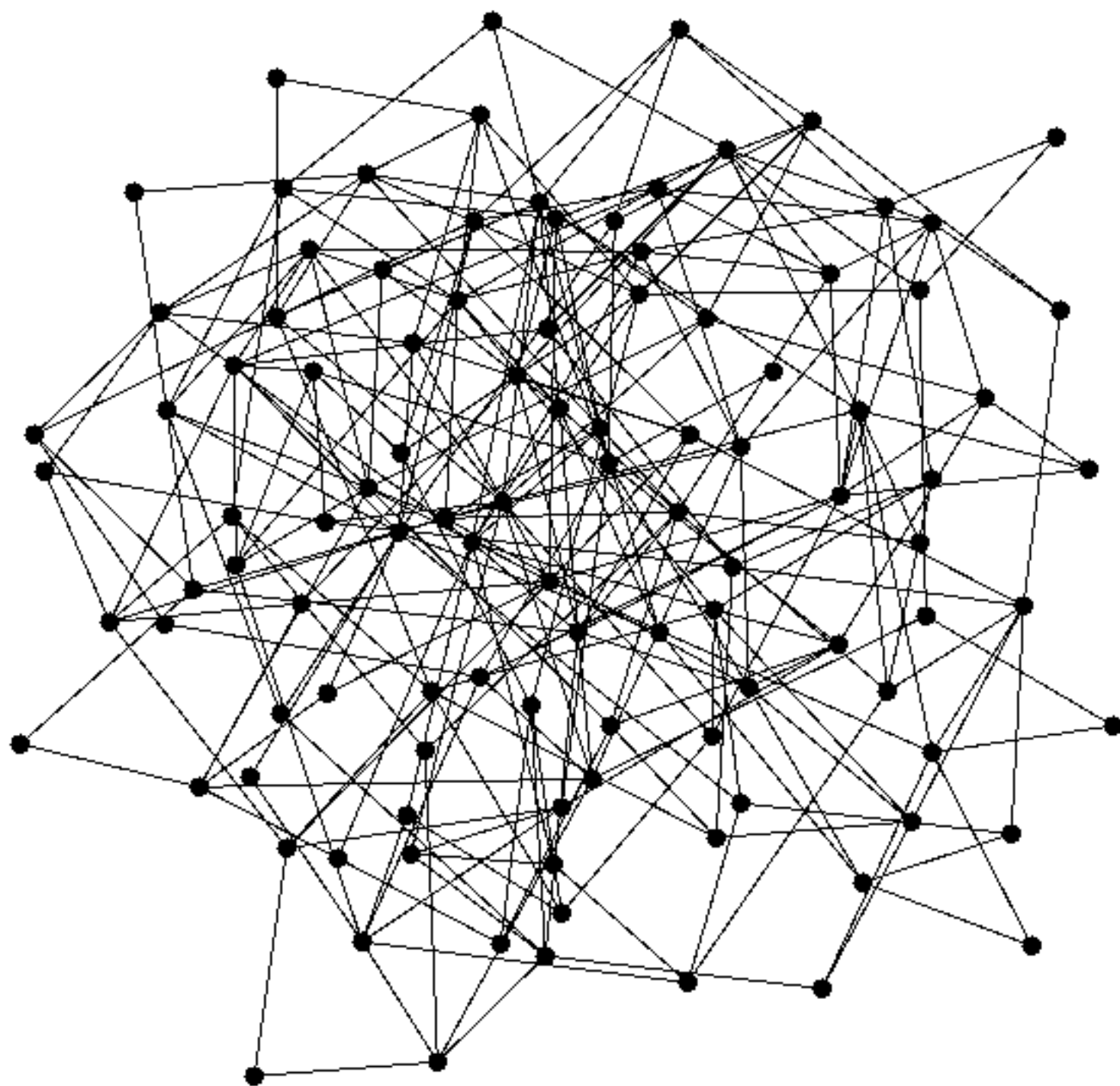




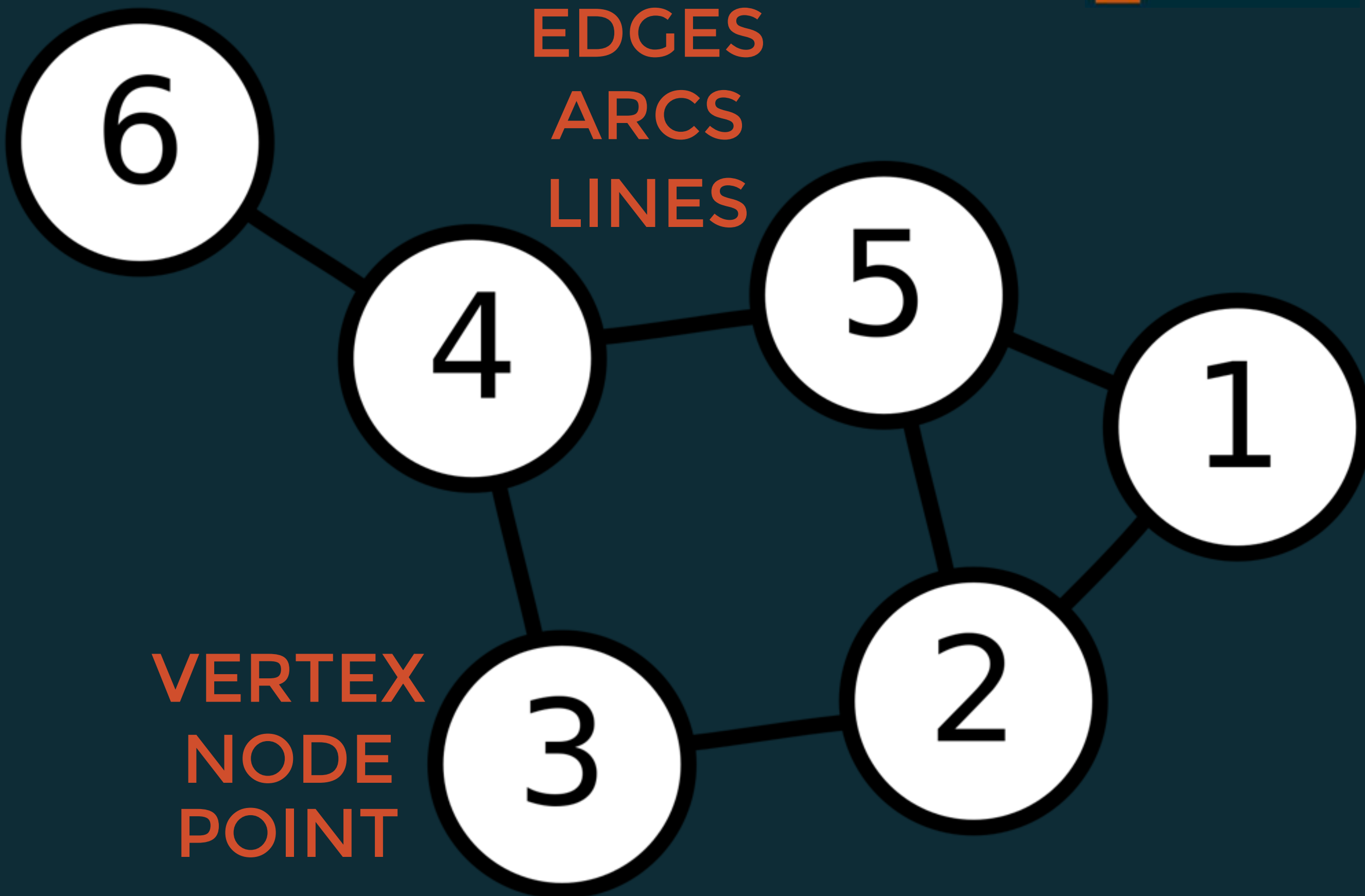




GraphStream



EDGES  
ARCS  
LINES

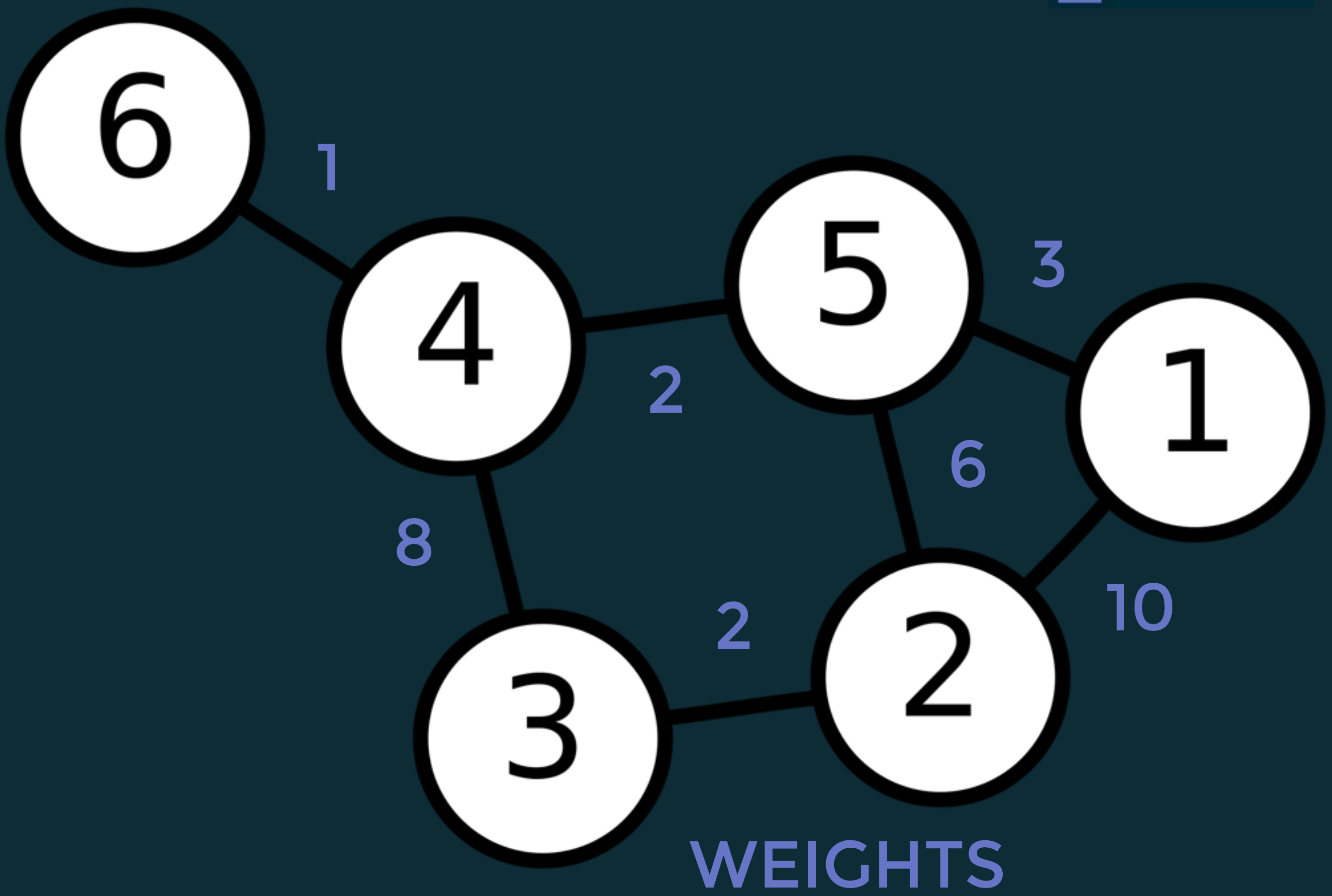


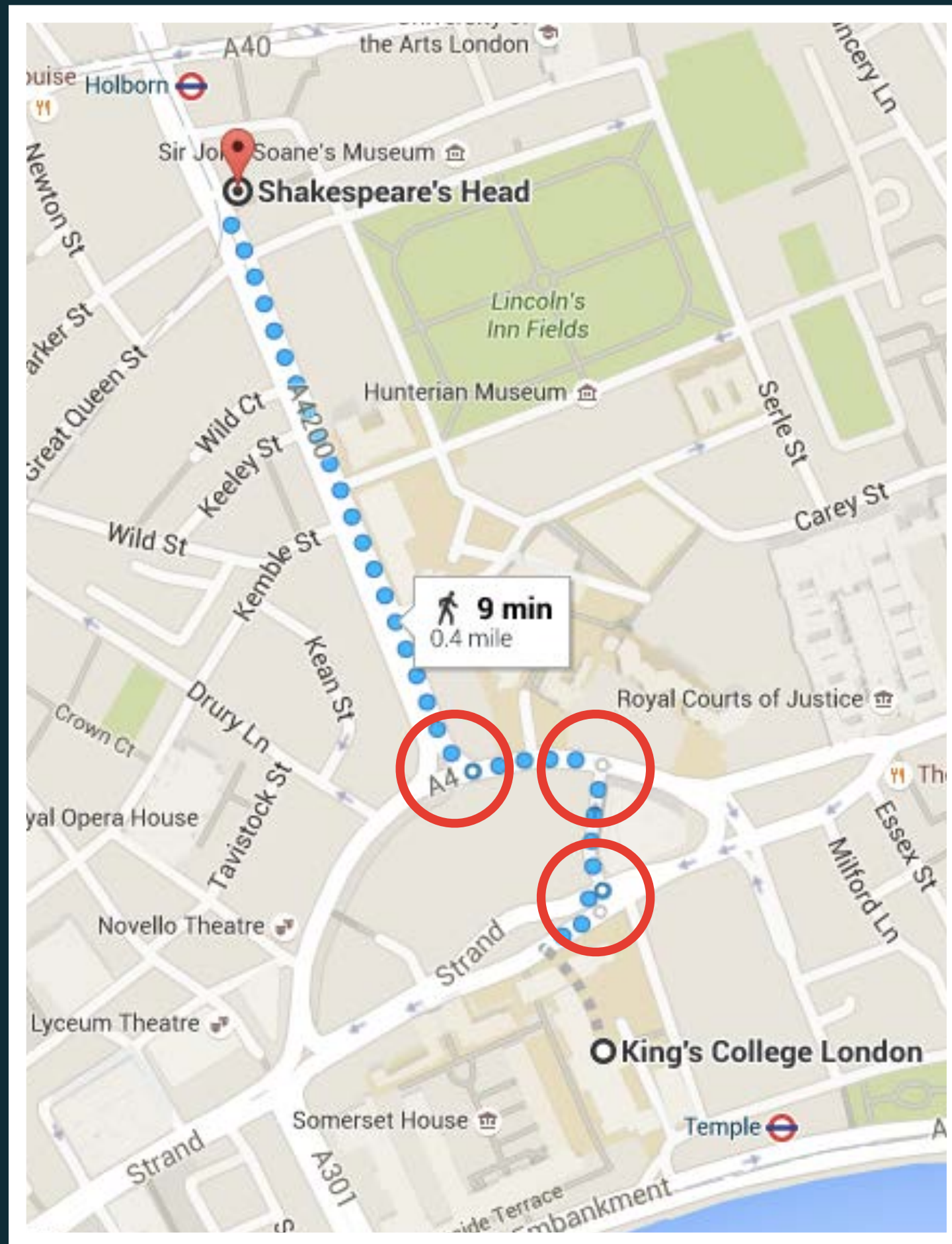
VERTEX  
NODE  
POINT



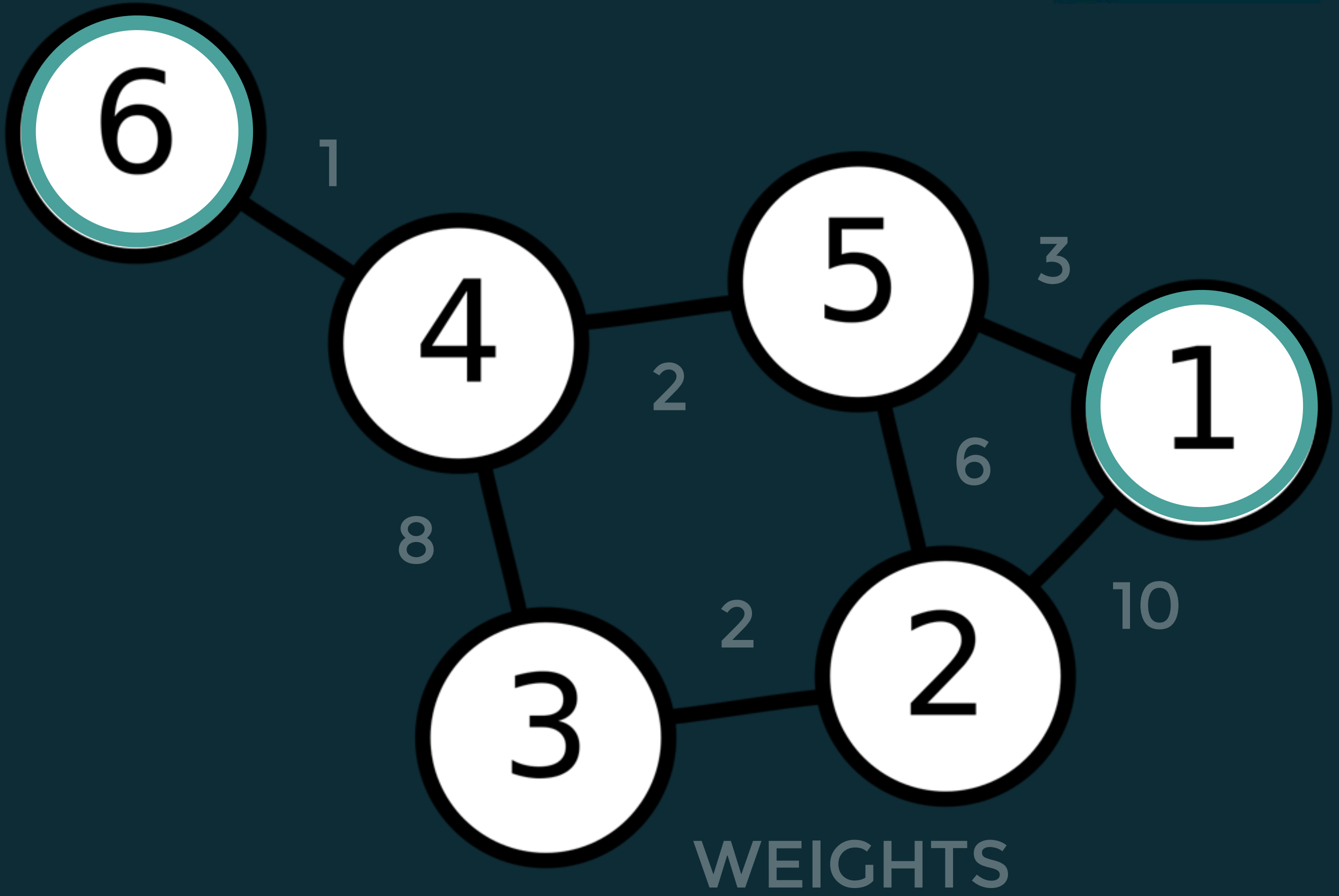
# WHAT CAN WE DO WITH THIS?





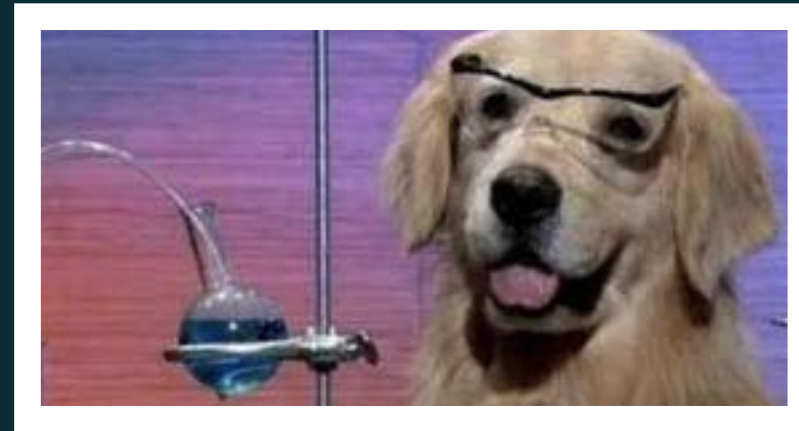
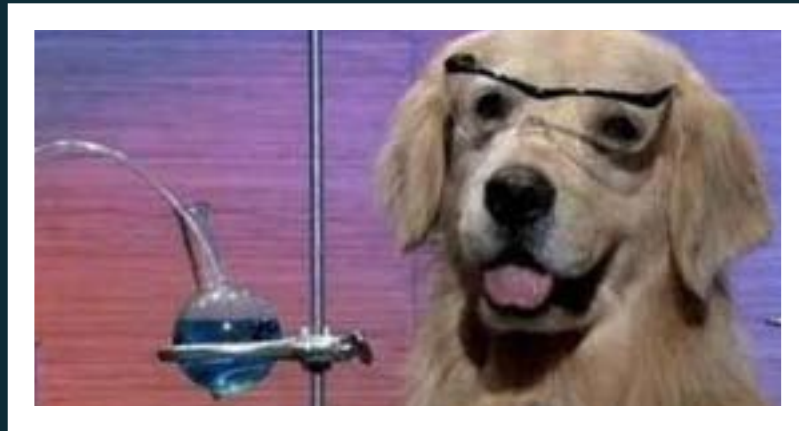


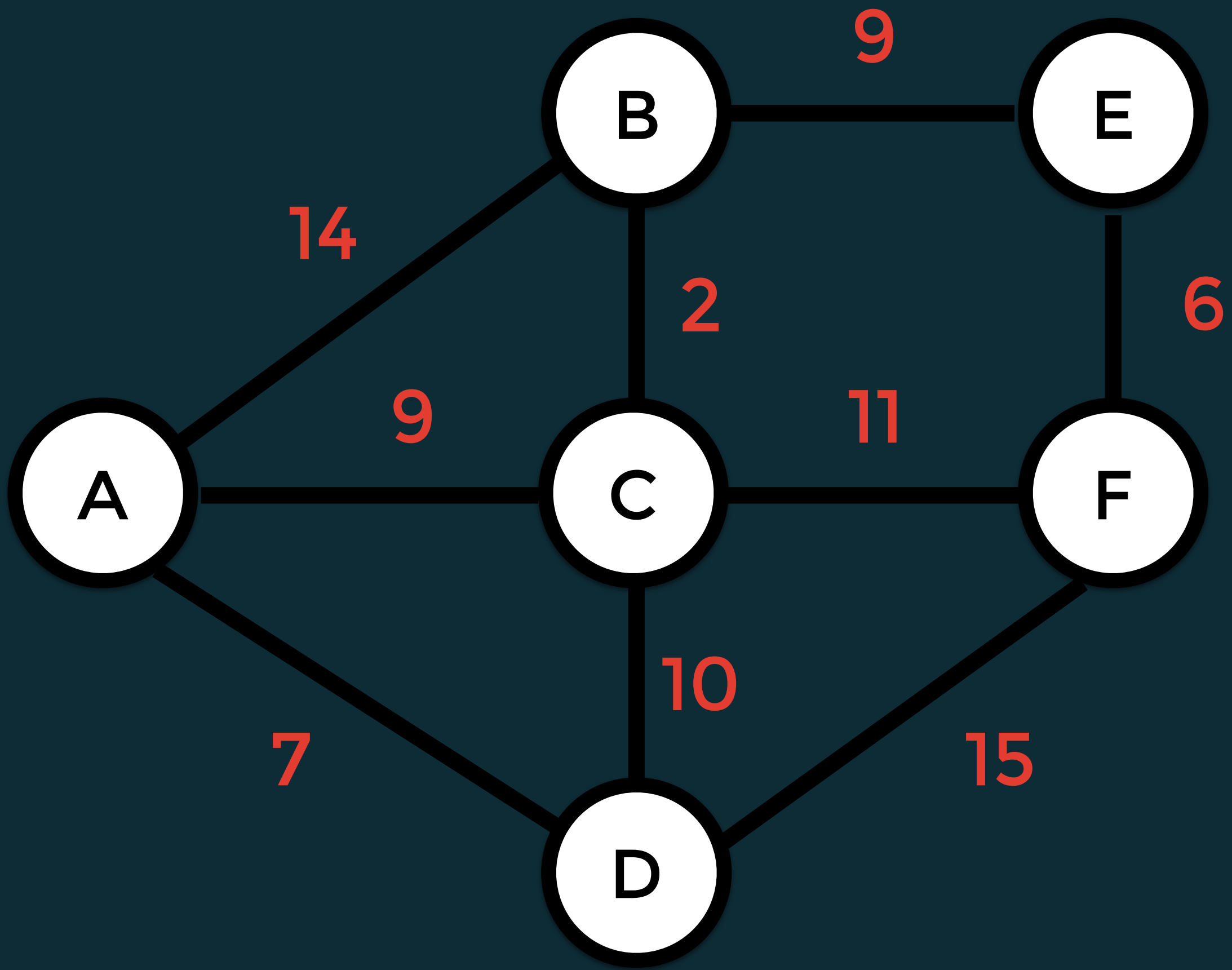
Decision points

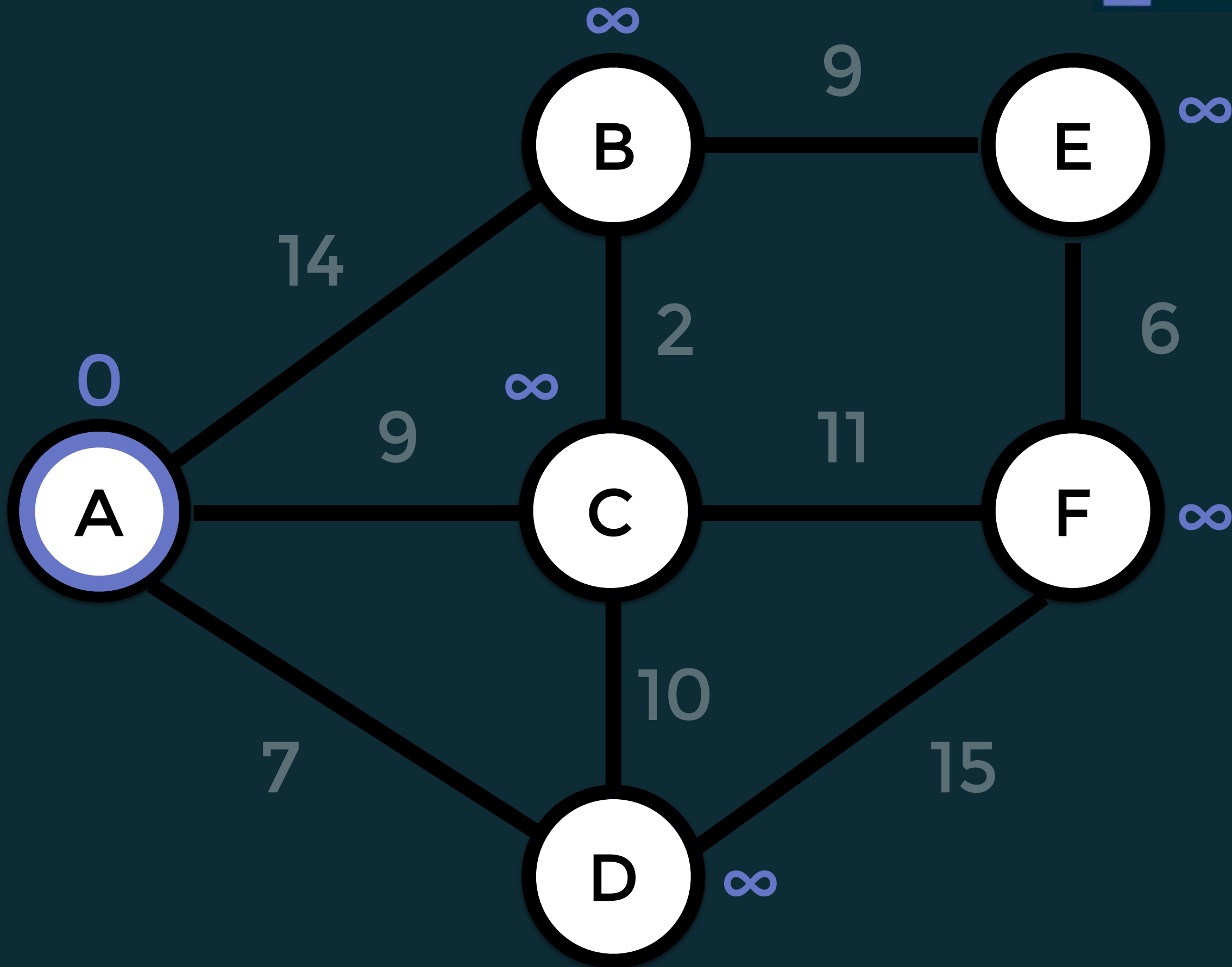


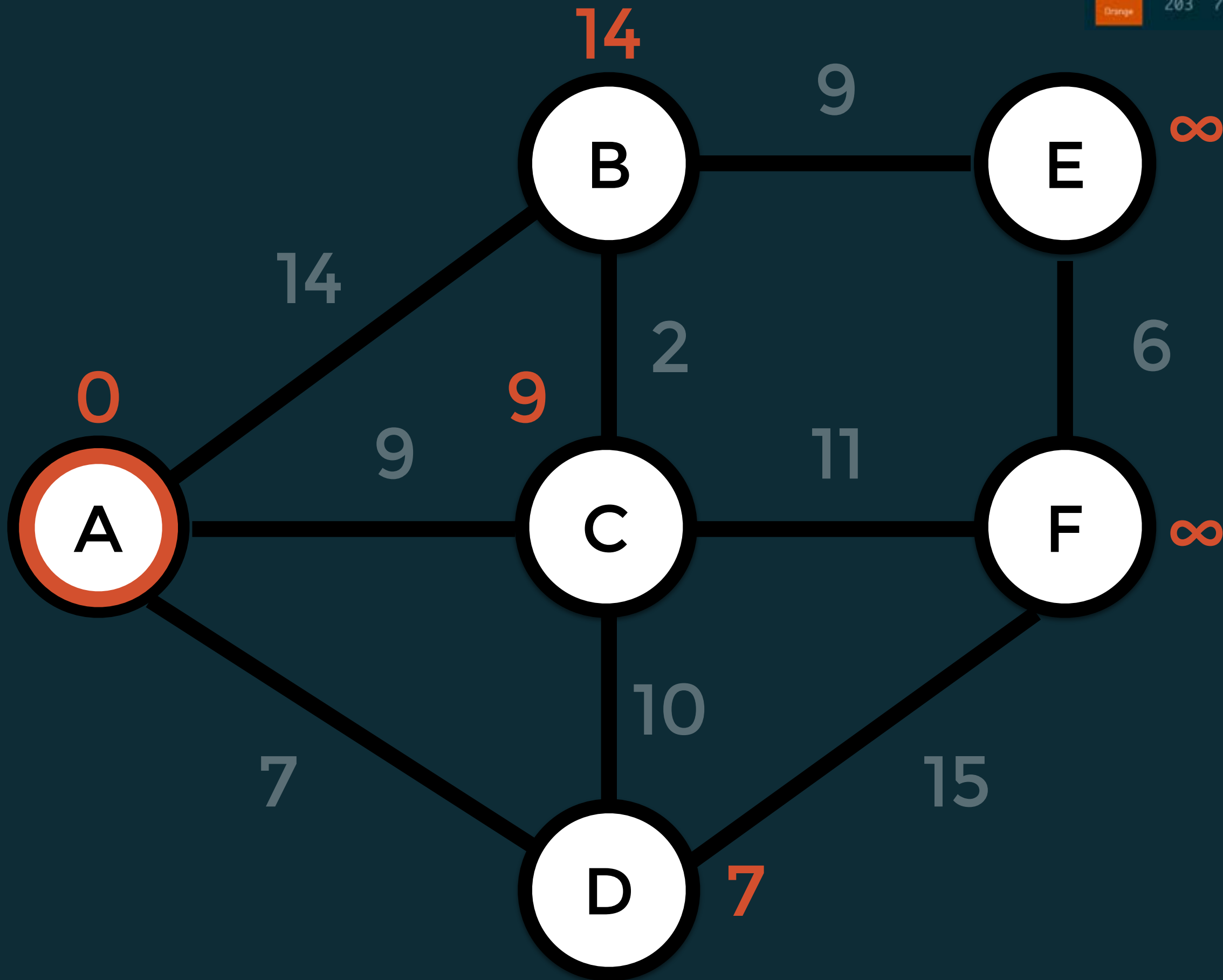
# SHORTEST PATH

<http://graphstream-project.org/doc/Algorithms/Shortest-path/>

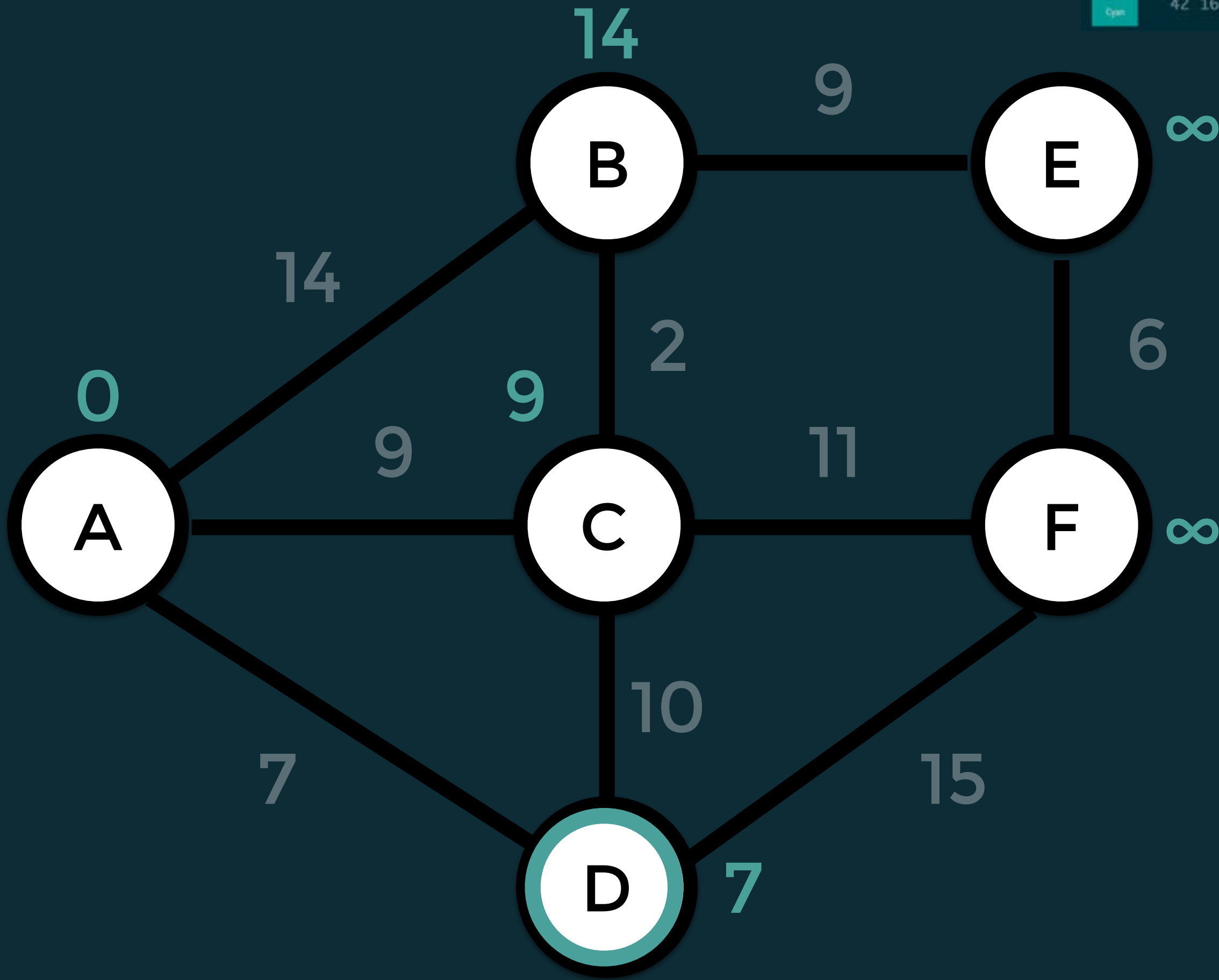


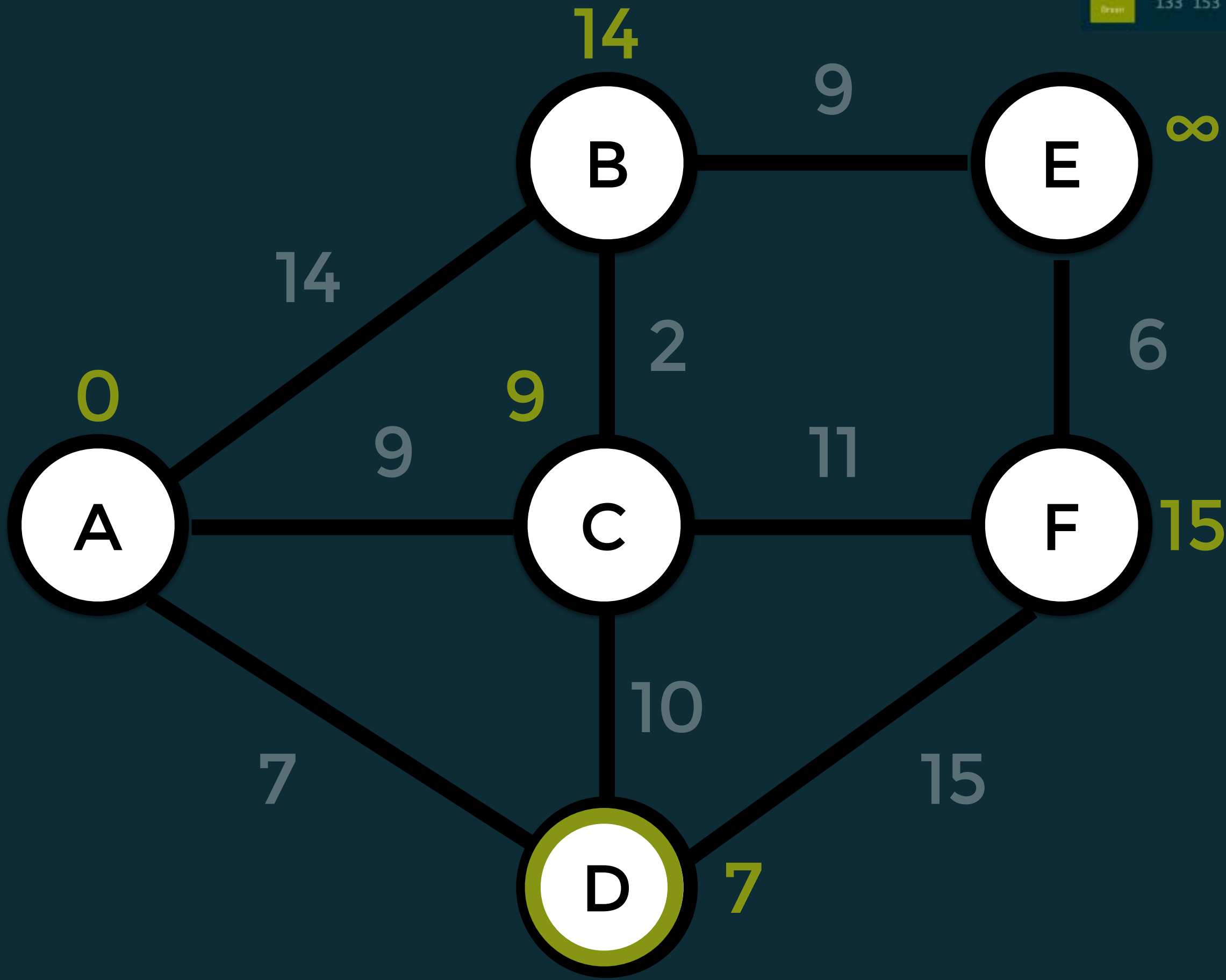


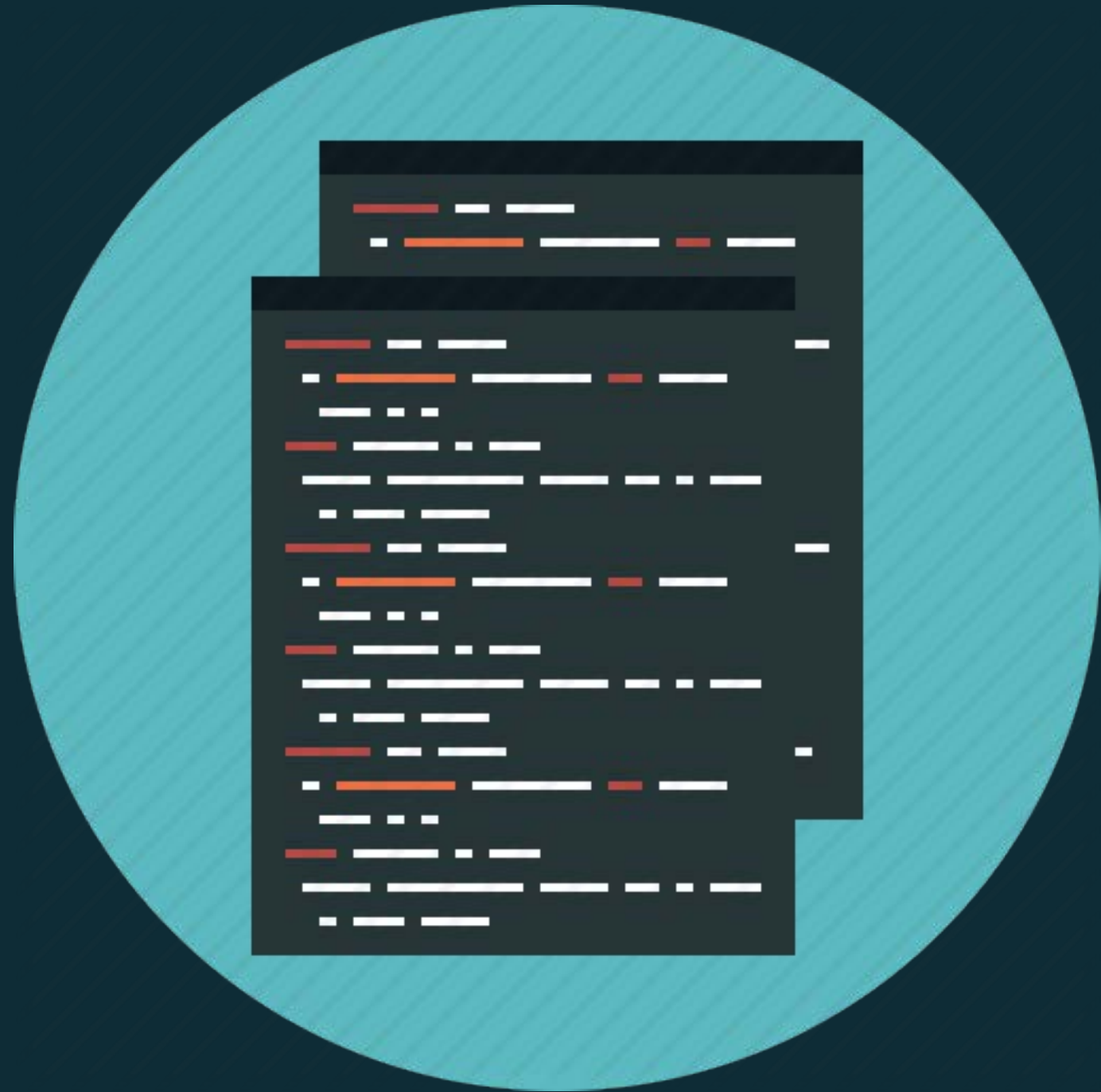












# COMPLEXITY

Running time as a function of the input





$$(V \times \text{LOG } V) + E$$

Many different permutations on this

<https://www.cs.cornell.edu/courses/cs312/2002sp/lectures/lec20/lec20.htm>

$$(V \times \text{LOG } V) + E$$



```

(* Dijkstra's Algorithm *)
let val q: queue = new_queue()
    val visited: vertexMap = create_vertexMap()
    fun expand(v: vertex) =
        let val neighbors: vertex list = Graph.outgoing(v)
            val dist: int = valOf(get(visited, v))
            fun handle_edge(v': vertex, weight: int) =
                case get(visited, v') of
                    SOME(d') =>
                        if dist+weight < d'
                        then ( add(visited, v', dist+weight);
                             incr_priority(q, v', dist+weight) )
                        else ()
                    | NONE => ( add(visited, v', dist+weight);
                               push(q, v', dist+weight) )
                in
                    app handle_edge neighbors
                end
        in
            add(visited, v0, 0);
            expand(v0);
            while (not (empty_queue(q))) do expand(pop(q))
        end
end

```



```

(* Dijkstra's Algorithm *)
let val q: queue = new_queue()
    val visited: vertexMap = create_vertexMap()
    fun expand(v: vertex) =
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                    app handle_edge neighbors
                end
        in
            add(visited, v0, 0);
            expand(v0);
            while (not (empty_queue(q))) do expand(pop(q))
        end
end

```

```
// Always deal with the next closest node first (via the estimate)
Node node = getClosestFromEstimate( unsettledNodes );

// expand(v: vertex)
let val neighbors: vertex list = Graph.outgoing(v)

if ( getDistanceEstimate( node ) < getDistanceEstimate( minimum ) ) {

    minimum = node;

}

// inc_priority(q, v', dist+weight)
else ()
    | NONE => ( add(visited, v', dist+weight);
               push(q, v', dist+weight) )
in
    app handle_edge neighbors
end
in
    add(visited, v0, 0);
    expand(v0);
    while (not (empty_queue(q)) do expand(pop(q))
end
```

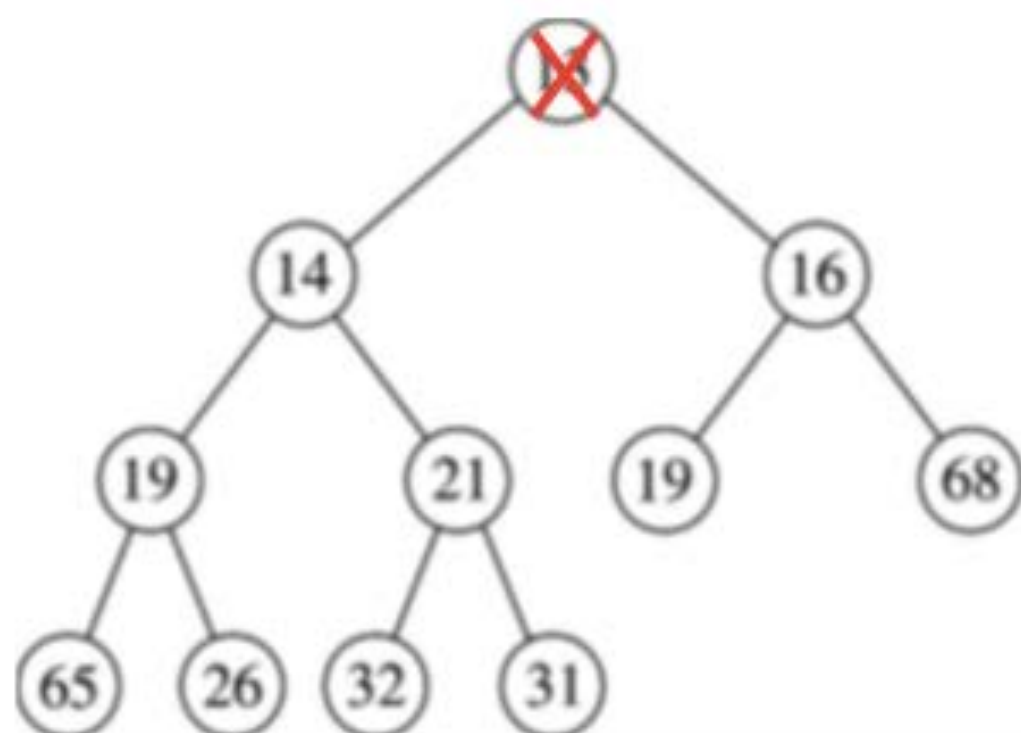
So, in reality, our intuitive Java implementation is likely to differ in complexity.



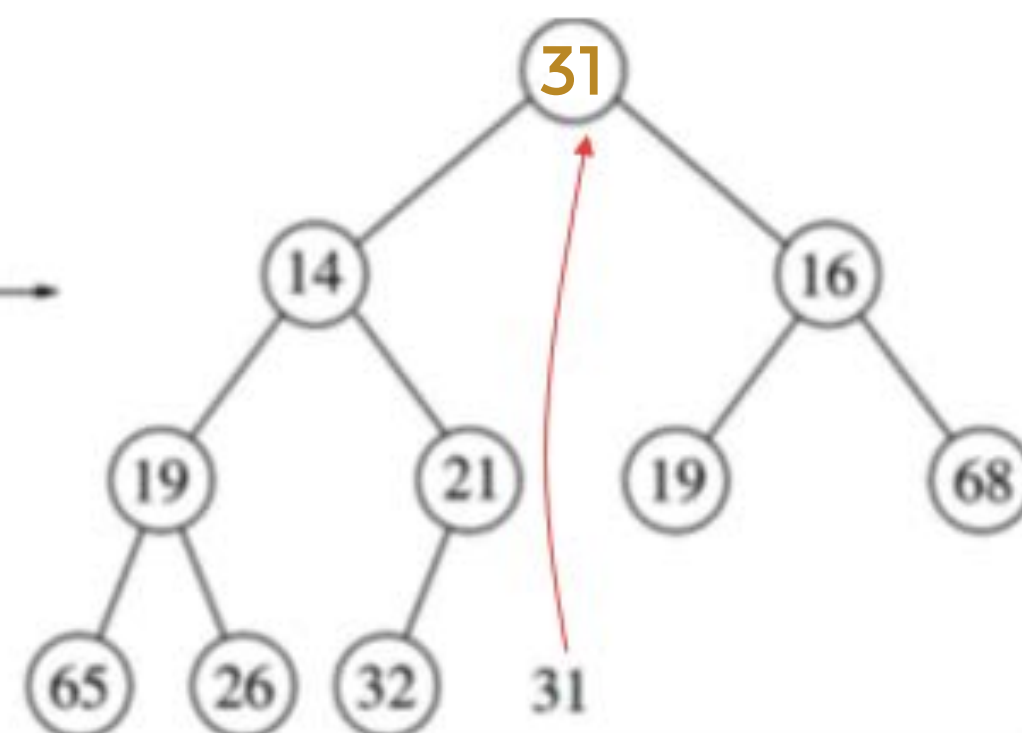
$$(V \times \text{LOG } V) + E$$

Reshuffling after a pop

Remove value at the root



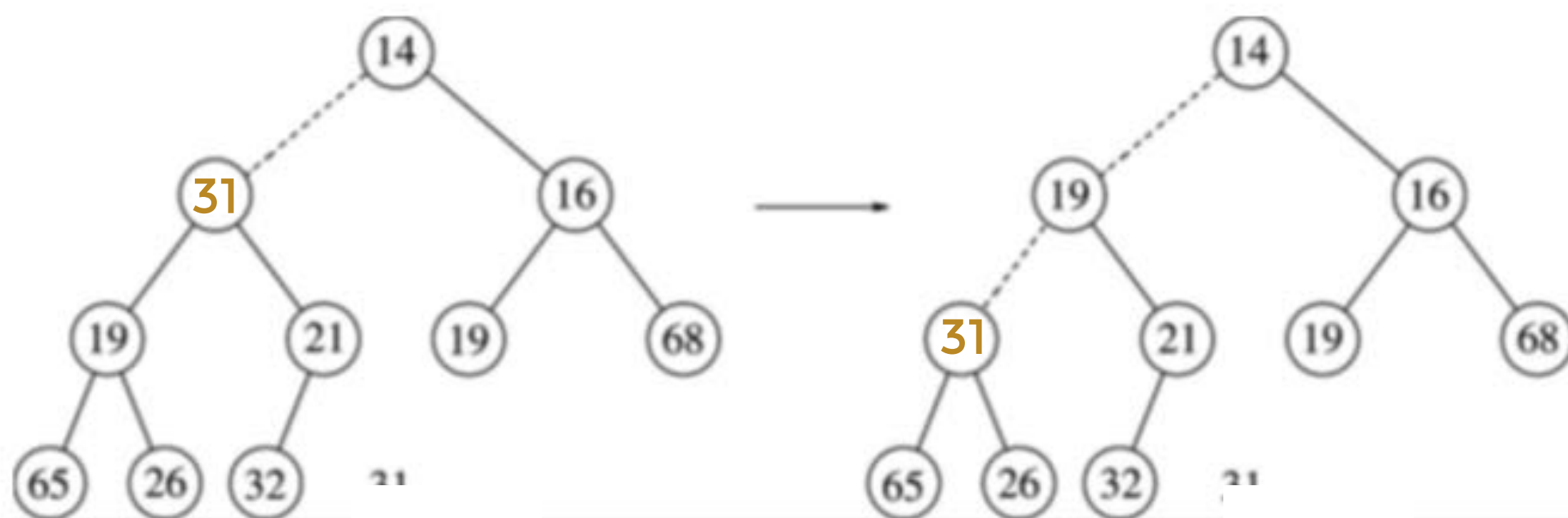
Move 31 (last element) to the root



Is  $31 > \min(14, 16)$ ?  
If yes, swap 31 with  $\min(14, 16)$   
If no, leave 31 in hole

Value in child is always greater than parent, and this is retained.  
I assume the initial removal and movement is an atomic action.

## Percolating down...

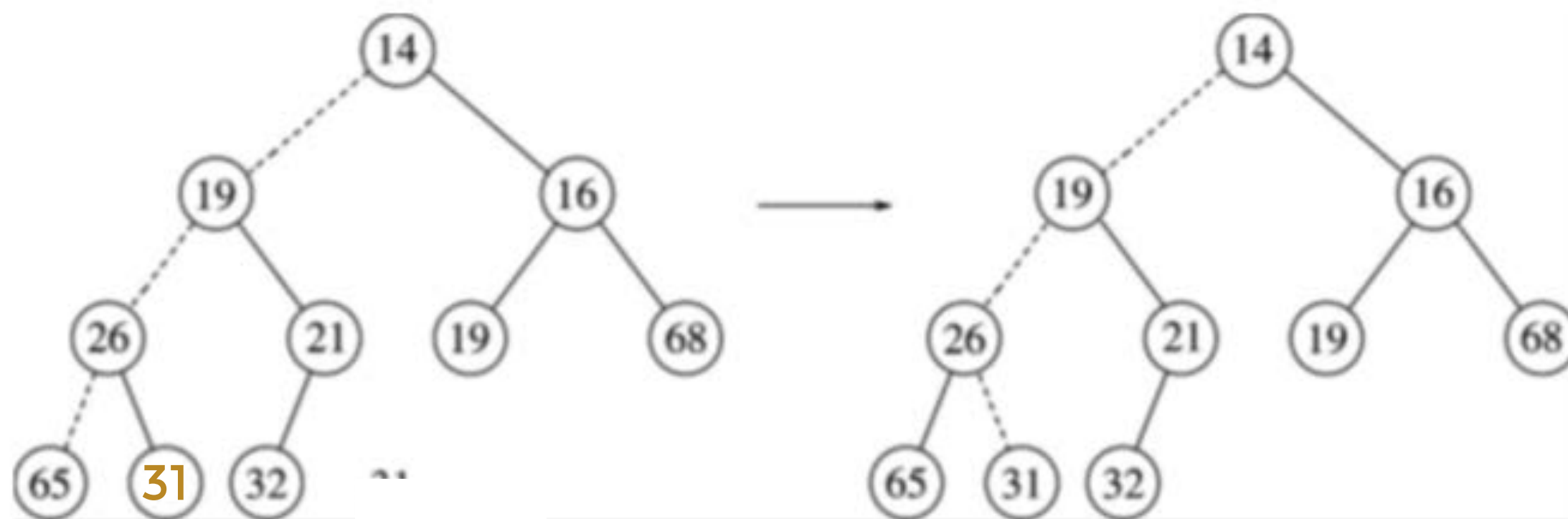


Is  $31 > \min(19, 21)$ ? **1 swap**  
If yes, swap 31 with  $\min(19, 21)$   
If no, leave 31 in hole

Is  $31 > \min(65, 26)$ ? **2 swaps**  
If yes, swap 31 with  $\min(65, 26)$   
If no, leave 31 in hole



## Percolating down...



3 swaps

Heap-order property okay;  
Structure okay;  
Done.

V = 11

$$V = 11$$

11 nodes = \_ levels?



$$V = 11$$

11 nodes = \_ levels?

$$\text{LOG } V = \text{LOG}(2) 11 = 3.4$$

$$V = 11$$

11 nodes = \_ levels?

$$\text{LOG } V = \text{LOG}(2) 11 = 3.4$$

WORST CASE =  
3 SWAPS

$$(V \times \text{LOG } V) + E$$

Popping every node in the graph

$$(V \times \text{LOG } V) + E$$

Updating distance estimates for everyone's neighbours

```

(* Dijkstra's Algorithm *)
let val q: queue = new_queue()
    val visited: vertexMap = create_vertexMap()
    fun expand(v: vertex) =
        let val neighbors: vertex list = Graph.outgoing(v)
            val dist: int = valOf(get(visited, v))
            fun handle_edge(v': vertex, weight: int) =
                case get(visited, v') of
                    SOME(d') =>
                        if dist+weight < d'
                        then ( add(visited, v', dist+weight);
                             incr_priority(q, v', dist+weight) )
                        else ()
                    | NONE => ( add(visited, v', dist+weight);

```

```

// Update the estimate to the neighbour, based on going through this node
distanceEstimate.put(neighbour, getDistanceEstimate(node) + getDistance(node, neighbour));

```

```

    app handle_edge neighbors
end
in
    add(visited, v0, 0);
    expand(v0);
    while (not (empty_queue(q)) do expand(pop(q))
end

```

# BELLMAN-FORD

# FLOYD-WARSHALL

$A^*$

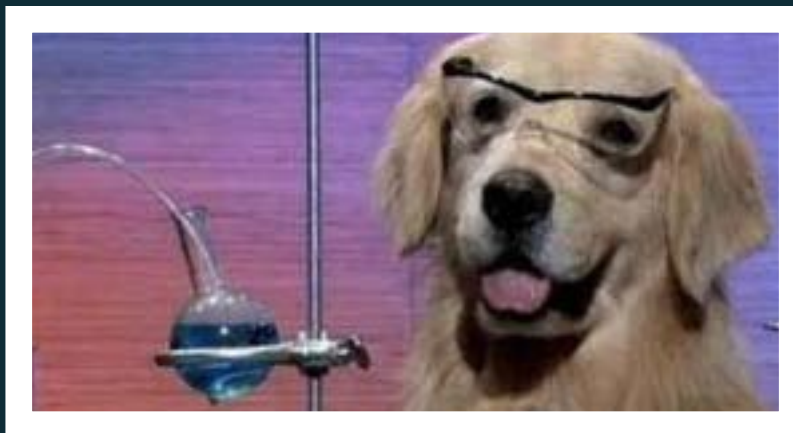
# BELLMAN-FORD

# FLOYD-WARSHALL

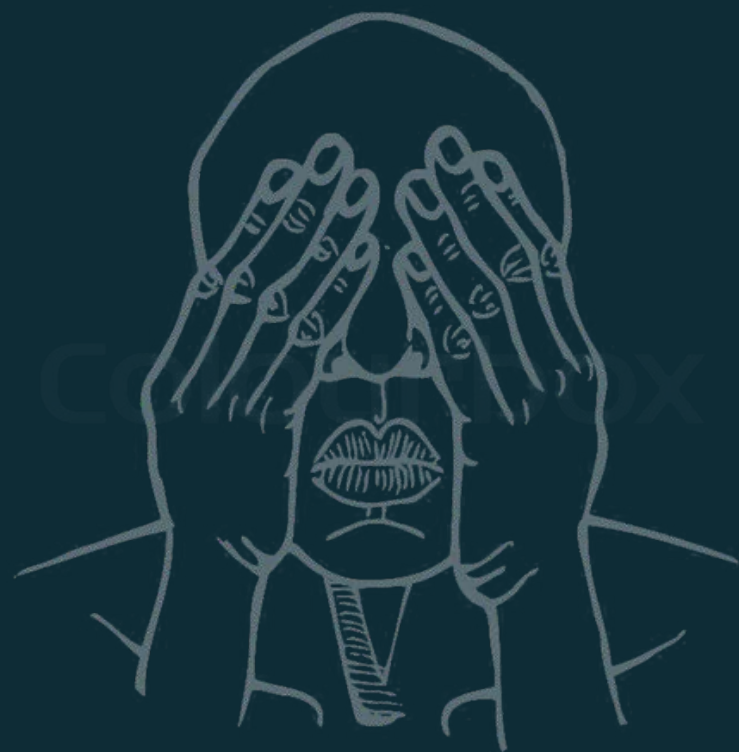
$A^*$



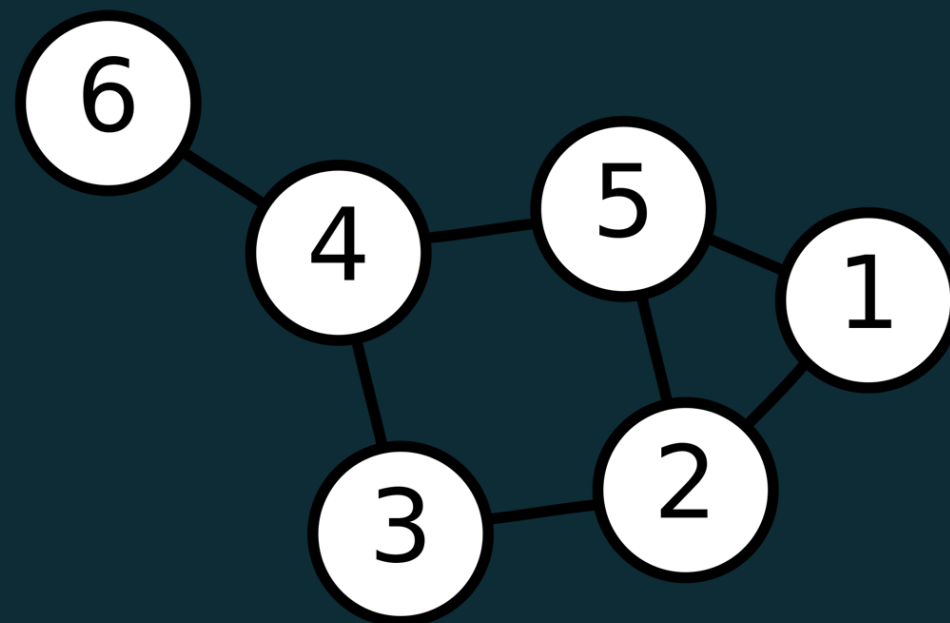
# LOOKING FOR HIDDEN THINGS





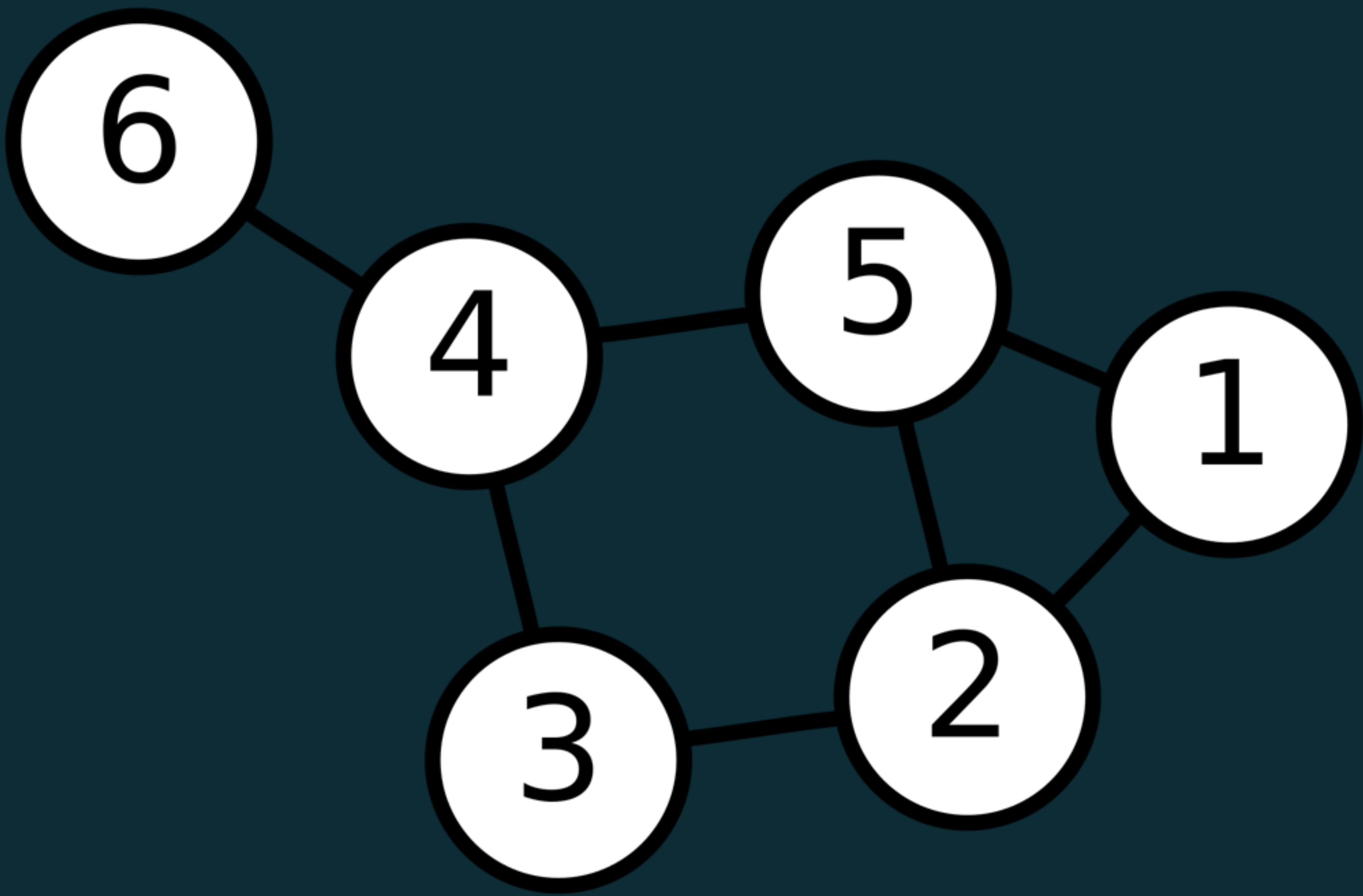


+



=



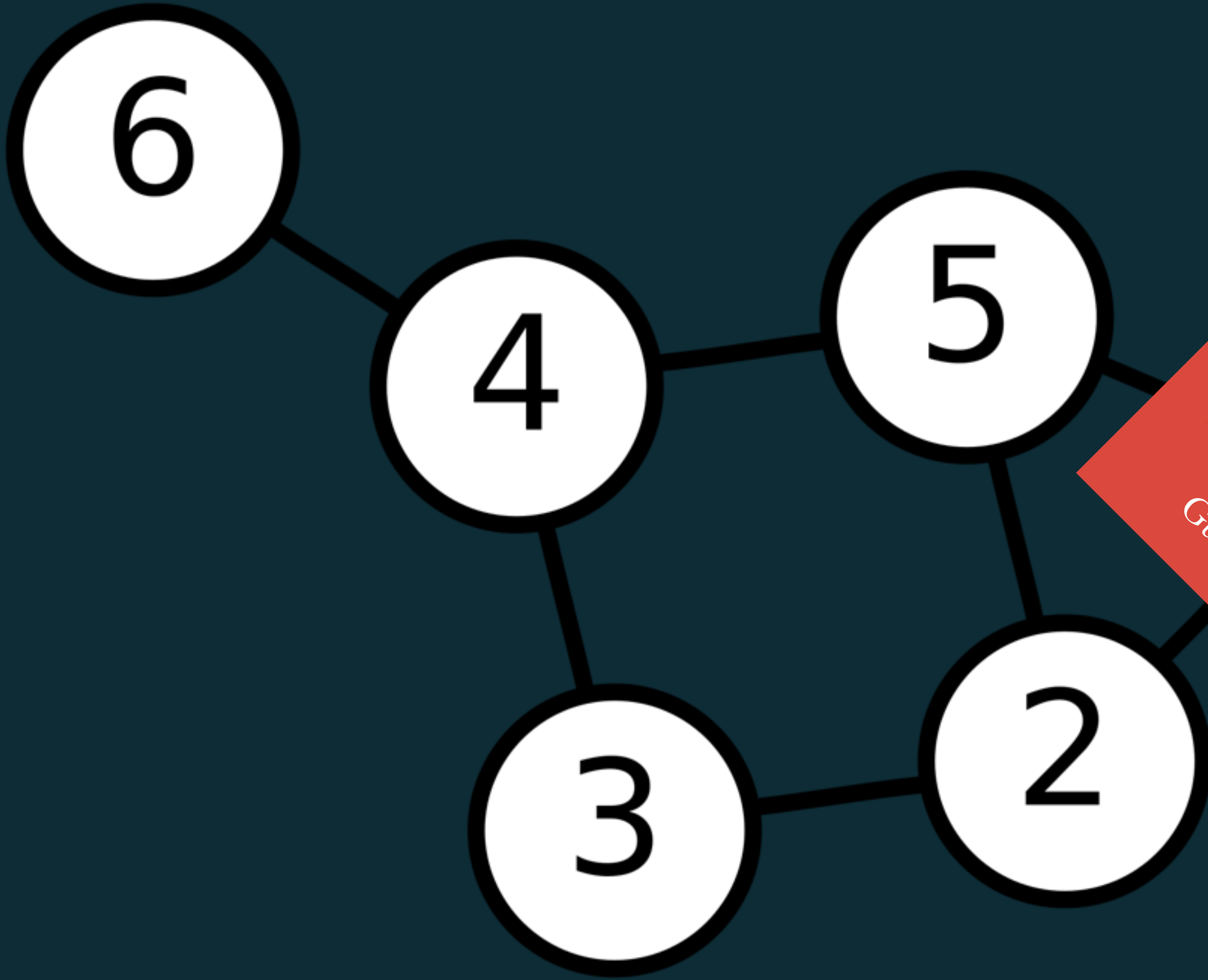


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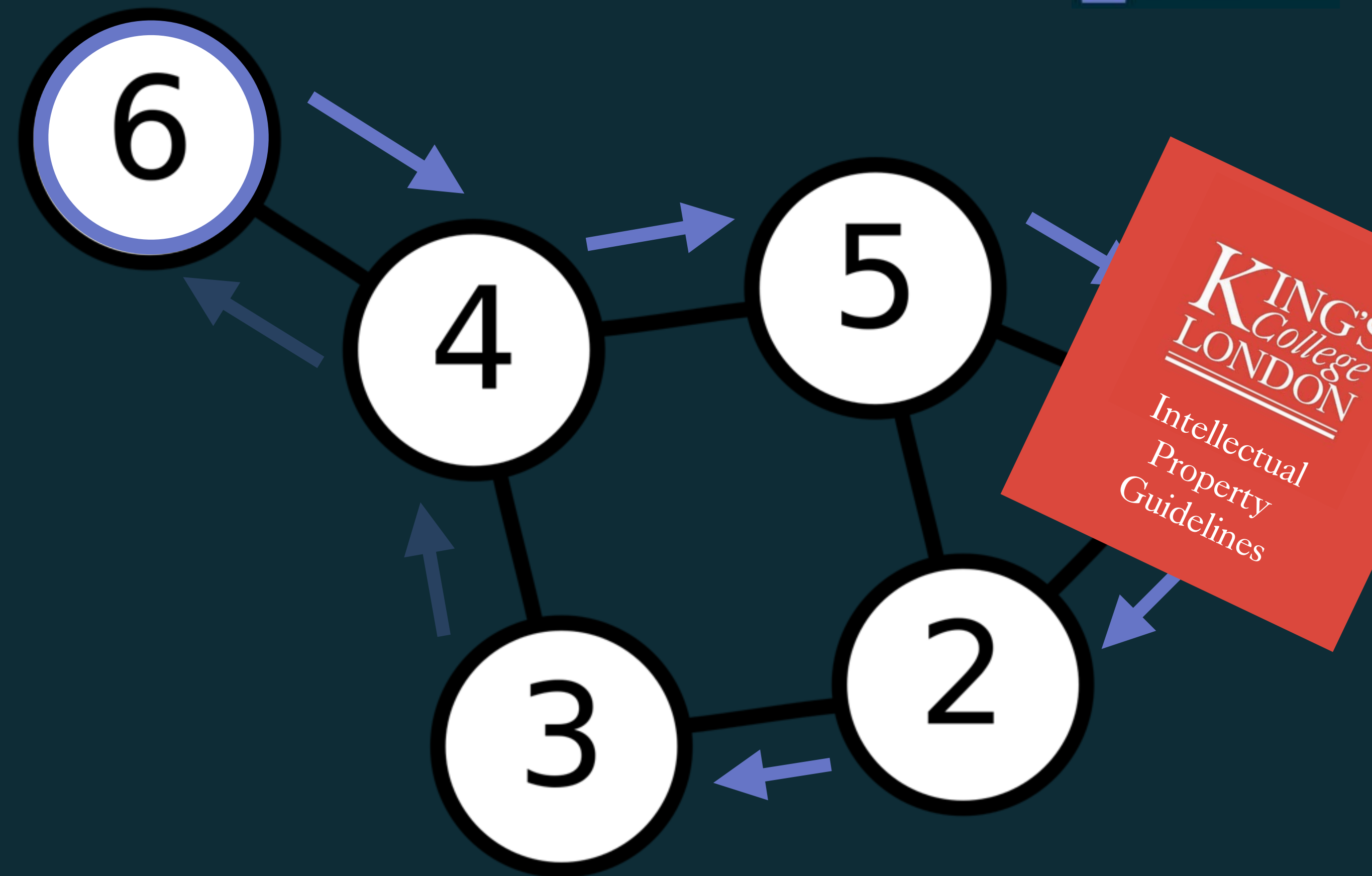


# Intellectual Property Guidelines

1

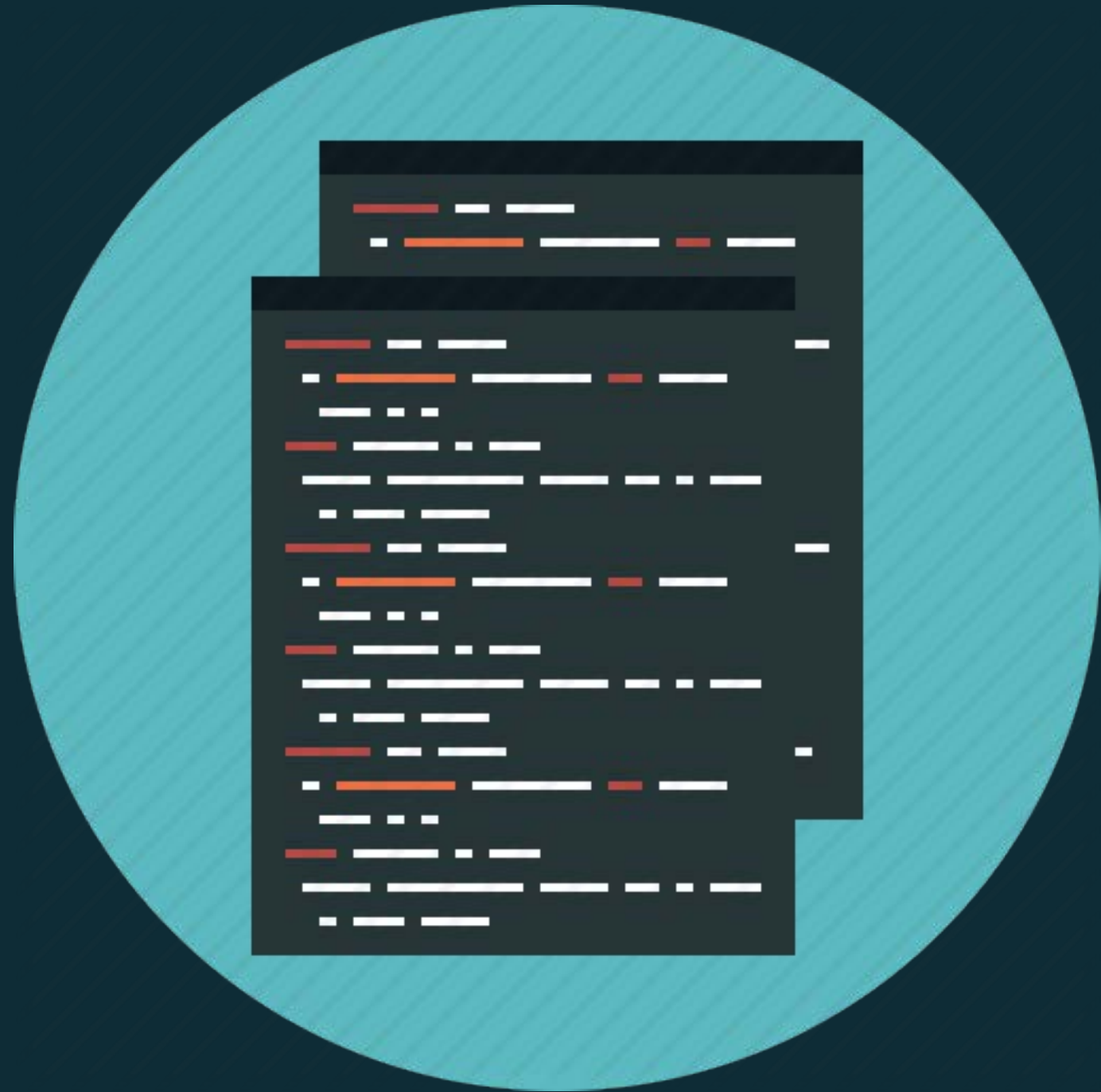






Notice that we've dropped the weights

# HAMILTONIAN PATH (CYCLE)





# COMPLEXITY







# QUADRATIC

# $N^2$

Seems a bit optimistic. Many different permutations on this classification depending on the implementation.



Notation	Name	Example
$O(1)$	constant	Determining if a binary number is even or odd; Calculating $(-1)^n$ ; Using a constant-size <a href="#">lookup table</a>
$O(\log \log n)$	double logarithmic	Number of comparisons spent finding an item using <a href="#">interpolation search</a> in a sorted array of uniformly distributed values
$O(\log n)$	logarithmic	Finding an item in a sorted array with a <a href="#">binary search</a> or a balanced search <a href="#">tree</a> as well as all operations in a <a href="#">Binomial heap</a>
$O(n^c)$ , $0 < c < 1$	fractional power	Searching in a <a href="#">kd-tree</a>
$O(n)$	linear	Finding an item in an unsorted list or a malformed tree (worst case) or in an unsorted array; adding two $n$ -bit integers by <a href="#">ripple carry</a>
$O(n \log^* n)$	$n \log\text{-star } n$	Performing <a href="#">triangulation</a> of a simple polygon using Seidel's algorithm, or the <a href="#">union-find algorithm</a> . Note that $\log^*(n) = \begin{cases} 0, & \text{if } n \leq 1 \\ 1 + \log^*(\log n), & \text{if } n > 1 \end{cases}$
$O(n \log n) = O(\log n!)$	linearithmic, loglinear, or	Performing a <a href="#">fast Fourier transform</a> ; <a href="#">heapsort</a> , <a href="#">quicksort</a> (best and average case), or <a href="#">merge sort</a>
$O(n^2)$	quadratic	Multiplying two $n$ -digit numbers by a simple algorithm; <a href="#">bubble sort</a> (worst case or naive implementation), <a href="#">Shell sort</a> , <a href="#">quicksort</a> (worst case), <a href="#">selection sort</a> or <a href="#">insertion sort</a>
$O(n^c)$ , $c > 1$	polynomial or algebraic	<a href="#">Tree-adjointing grammar</a> parsing; maximum <a href="#">matching</a> for bipartite graphs
$L_n[\alpha, c]$ , $0 < \alpha < 1 = e^{(c+o(1))(\ln n)^\alpha (\ln \ln n)^{1-\alpha}}$	L-notation or sub-exponential	Factoring a number using the <a href="#">quadratic sieve</a> or <a href="#">number field sieve</a>
$O(c^n)$ , $c > 1$	exponential	Finding the (exact) solution to the <a href="#">travelling salesman problem</a> using <a href="#">dynamic programming</a> ; determining if two logical statements are equivalent using <a href="#">brute-force search</a>
$O(n!)$	factorial	Solving the traveling salesman problem via brute-force search; generating all unrestricted permutations of a <a href="#">poset</a> ; finding the <a href="#">determinant</a> with <a href="#">expansion by minors</a> ; enumerating all <a href="#">partitions of a set</a>



# NP-Complete



## What is NP?

NP is the set of all **decision problems** (questions with a yes-or-no answer) for which the 'yes'-answers can be **verified** in polynomial time ( $O(n^k)$  where  $n$  is the problem size, and  $k$  is a constant) by a **deterministic Turing machine**. Polynomial time is sometimes used as the definition of *fast* or *quickly*.

## What is P?

P is the set of all decision problems which can be **solved** in *polynomial time* by a *deterministic Turing machine*. Since they can be solved in polynomial time, they can also be verified in polynomial time. Therefore P is a subset of NP.

## What is NP-Complete?

A problem  $x$  that is in NP is also in NP-Complete *if and only if* every other problem in NP can be quickly (ie. in polynomial time) transformed into  $x$ .

In other words:

1.  $x$  is in NP, and
2. Every problem in NP is **reducible** to  $x$

So, what makes *NP-Complete* so interesting is that if any one of the NP-Complete problems was to be solved quickly, then all *NP* problems can be solved quickly.

See also the post [What's "P=NP?", and why is it such a famous question?](#)

## What is NP-Hard?

NP-Hard are problems that are at least as hard as the hardest problems in NP. Note that NP-Complete problems are also NP-hard. However not all NP-hard problems are NP (or even a decision problem), despite having **NP** as a prefix. That is the NP in NP-hard does not mean *non-deterministic polynomial time*. Yes, this is confusing, but its usage is entrenched and unlikely to change.



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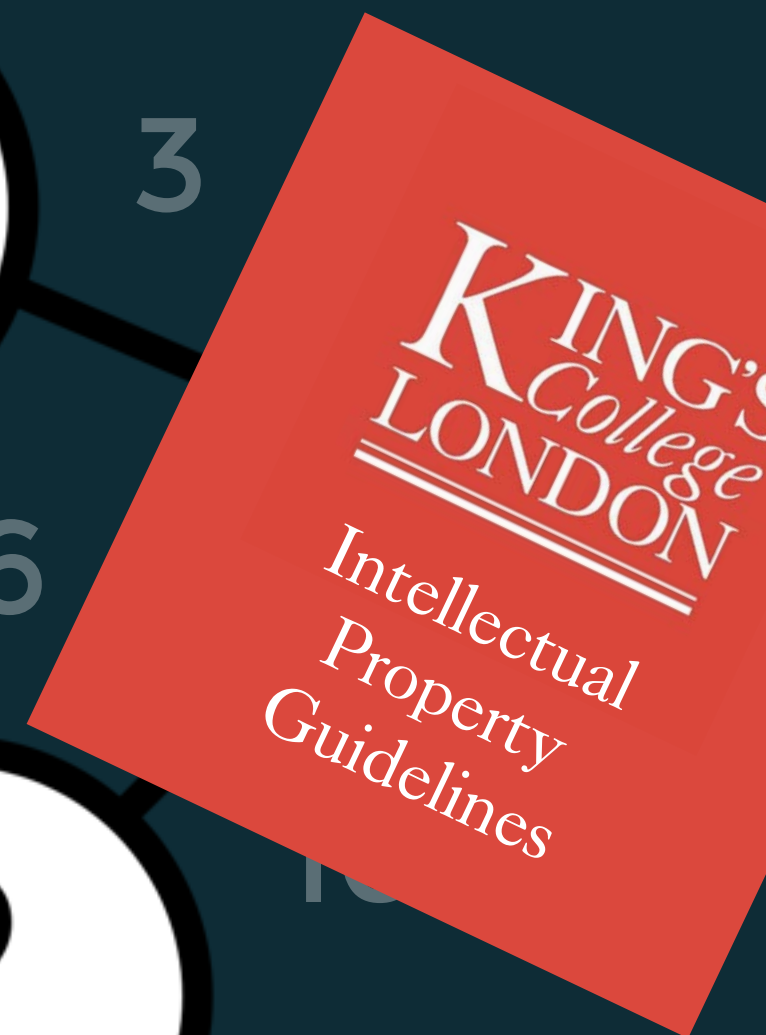
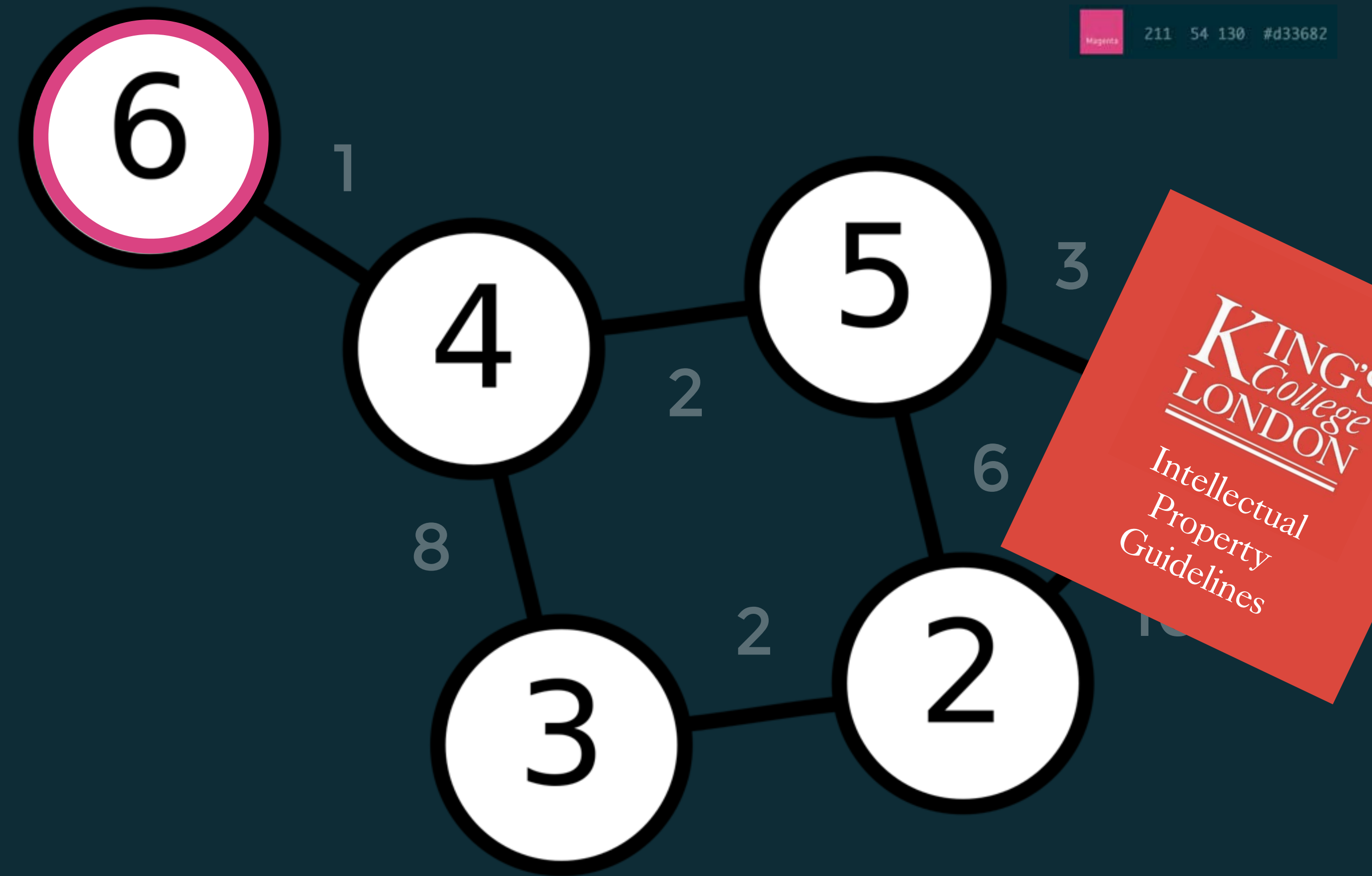
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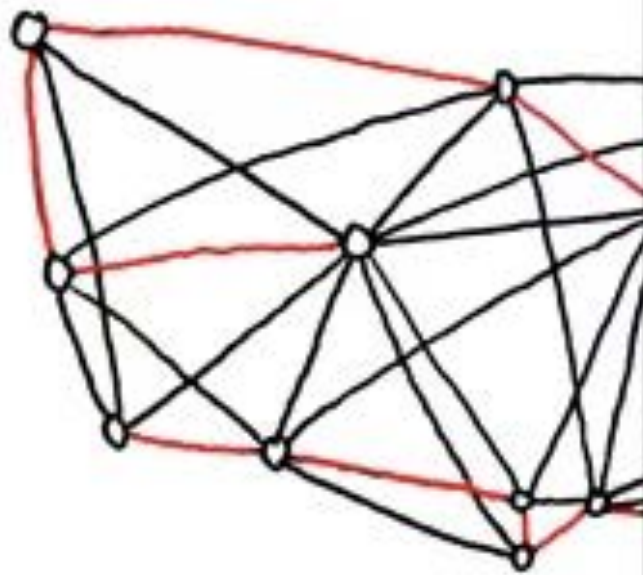
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Weights are back, so need to think about efficiency: Exponential and NP-hard

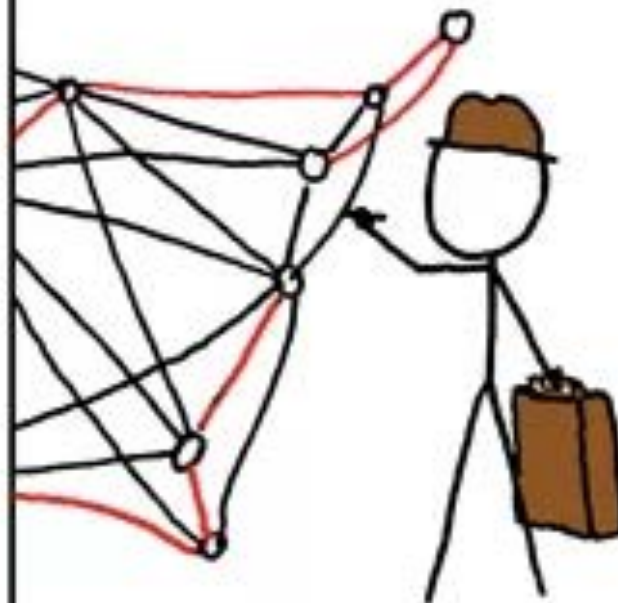
BRUTE-FORCE  
SOLUTION:

$$O(n!)$$



DYNAMIC  
PROGRAMMING  
ALGORITHMS:

$$O(n^2 2^n)$$



SELLING ON EBAY:  
 $O(1)$

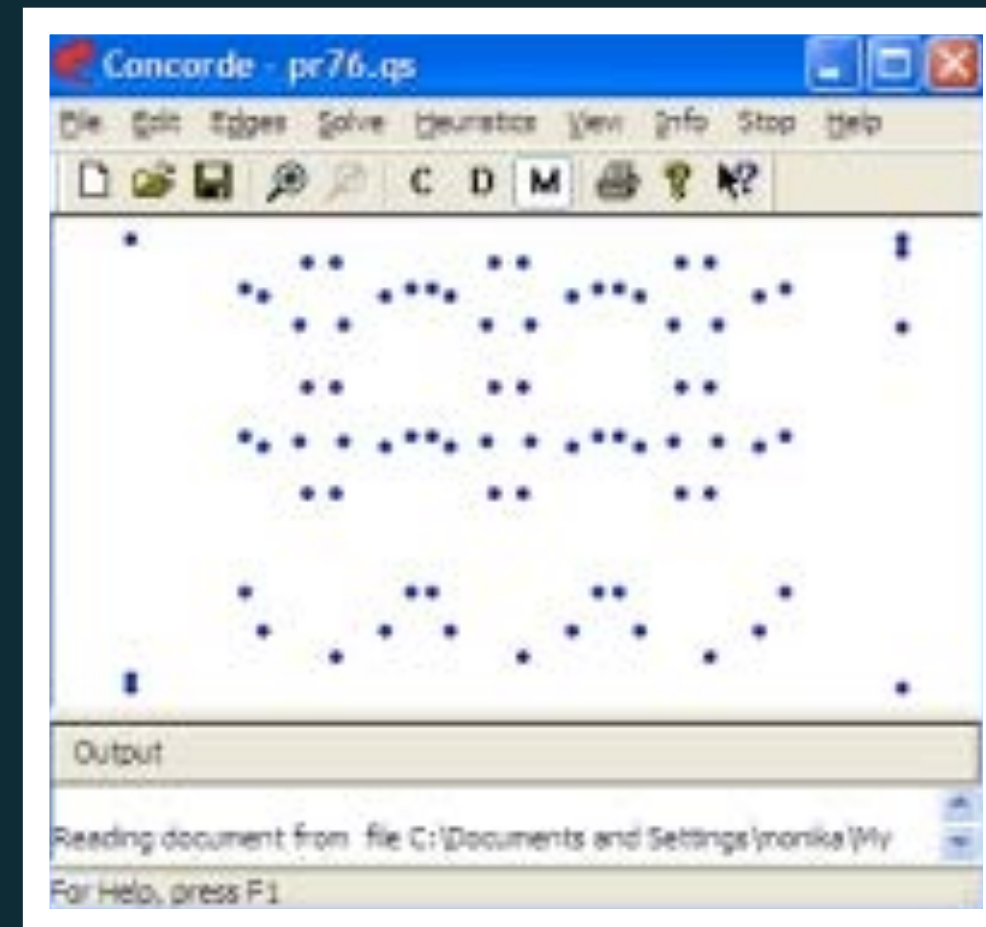
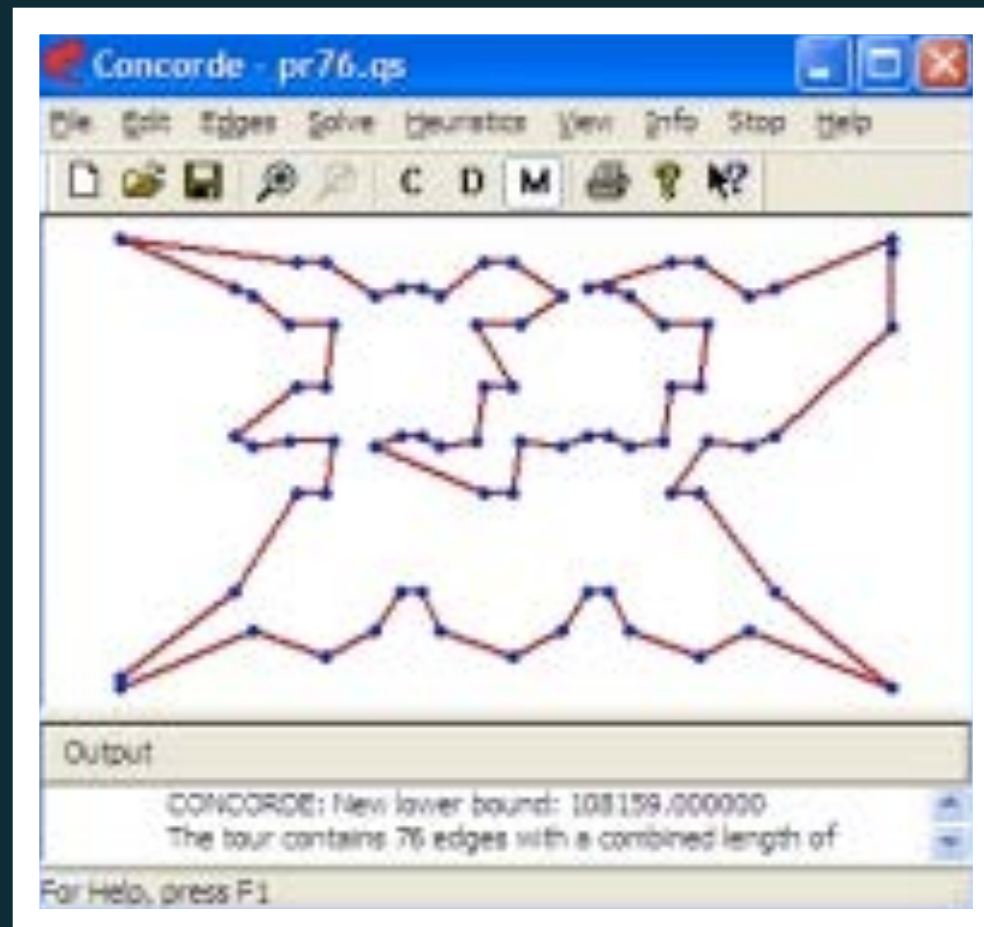
STILL WORKING  
ON YOUR ROUTE?

SHUT THE  
HELL UP.

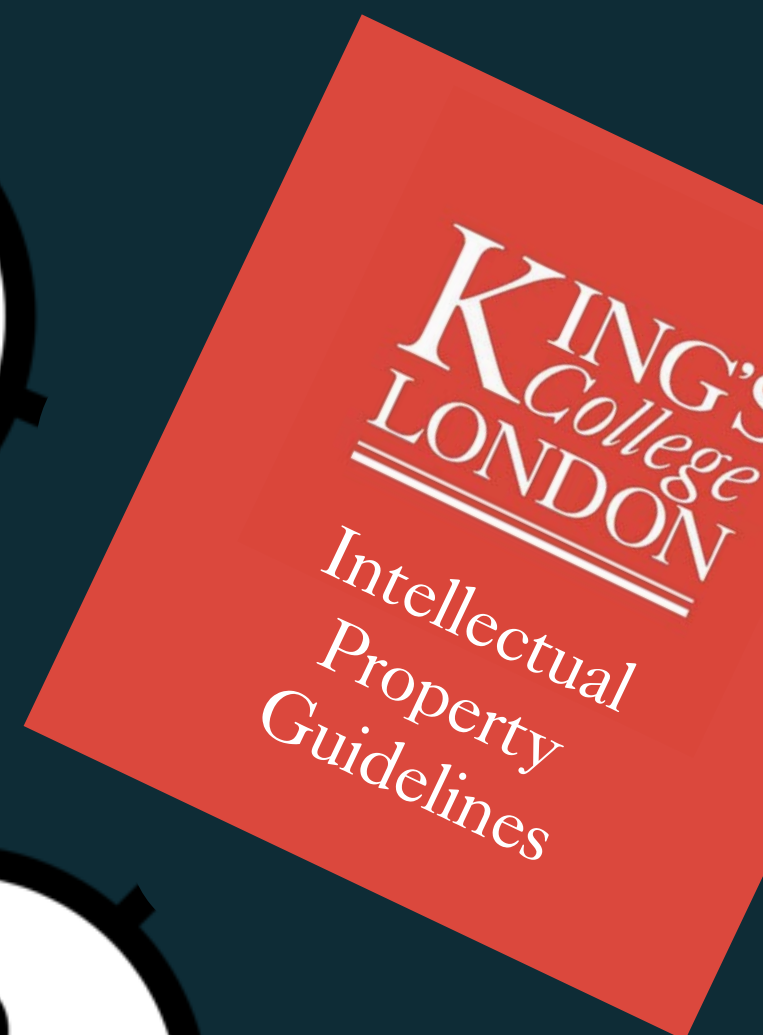
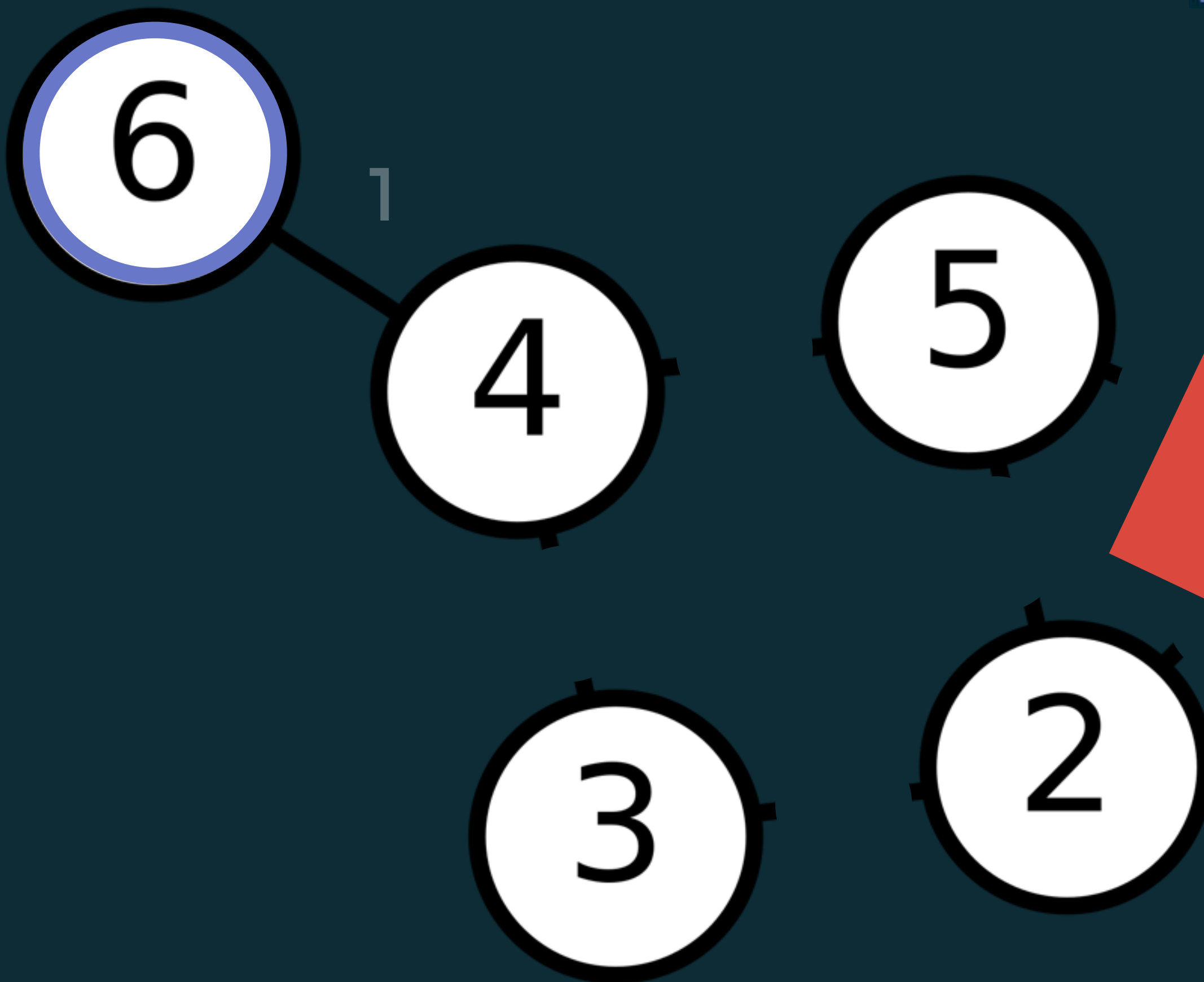


An intuitive analogy for the relationship between running times (complexity)





David Applegate, Ribert Bixby, Vasek Chvatal, and William Cook. Concorde TSP Solver. Available at <http://www.math.uwaterloo.ca/tsp/concorde/>, 2006.



MORE GENERAL  
EXPLORATION  
STRATEGIES  
ARE NEEDED



Experimentation is needed.





## Constructor Summary

### Constructors

#### Constructor and Description

**EncapsulatedGraph**(`java.lang.String yourName`)  
Create a new graph that will communicate with my server.

## Method Summary

### All Methods

### Instance Methods

### Concrete Methods

#### Modifier and Type

#### Method and Description

`java.util.ArrayList<org.graphstream.graph.Edge>`

**edgesOfCurrentNode**( )

Gets the edges associated with the current node

`boolean`

**found**( )

Whether the desired object, hidden within this graph, has been found.

`org.graphstream.graph.Node`

**getCurrentNode**( )

The most important piece of encapsulated graph state is the current node, upon which a `searcher' currently exists.

`java.util.ArrayList<org.graphstream.graph.Node>`

**getPath**( )

Get the path you have created so far with your search.

`boolean`

**moveToNewNode**(`org.graphstream.graph.Node node`)

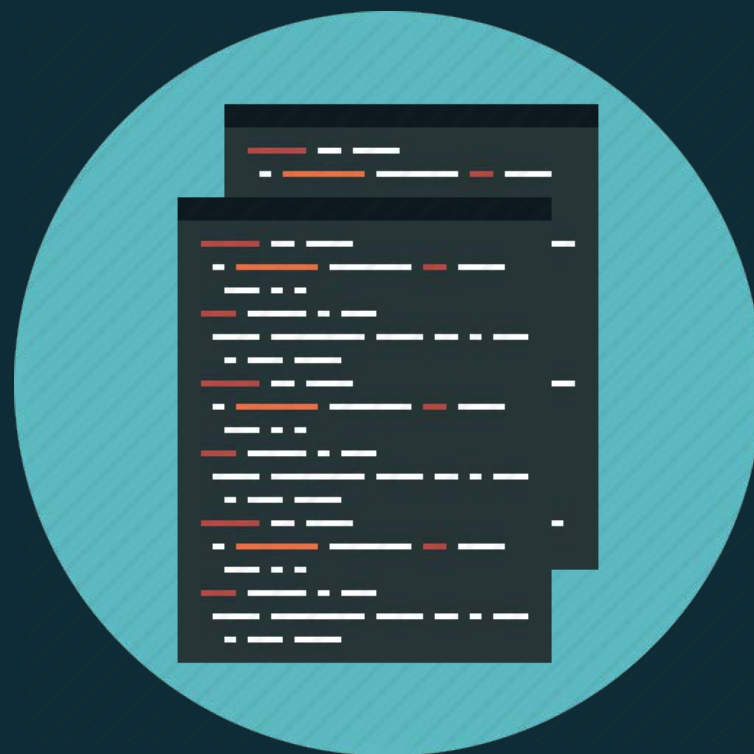
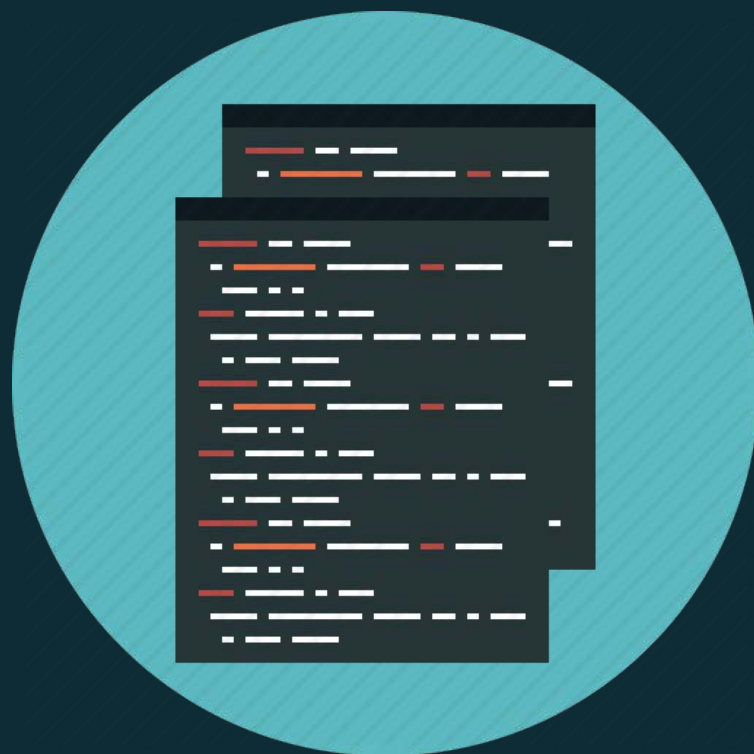
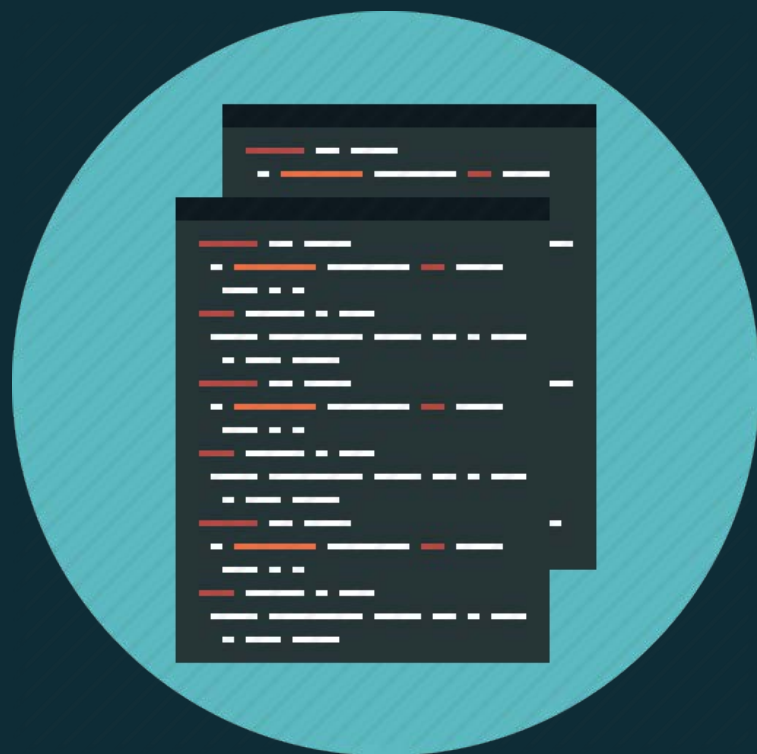
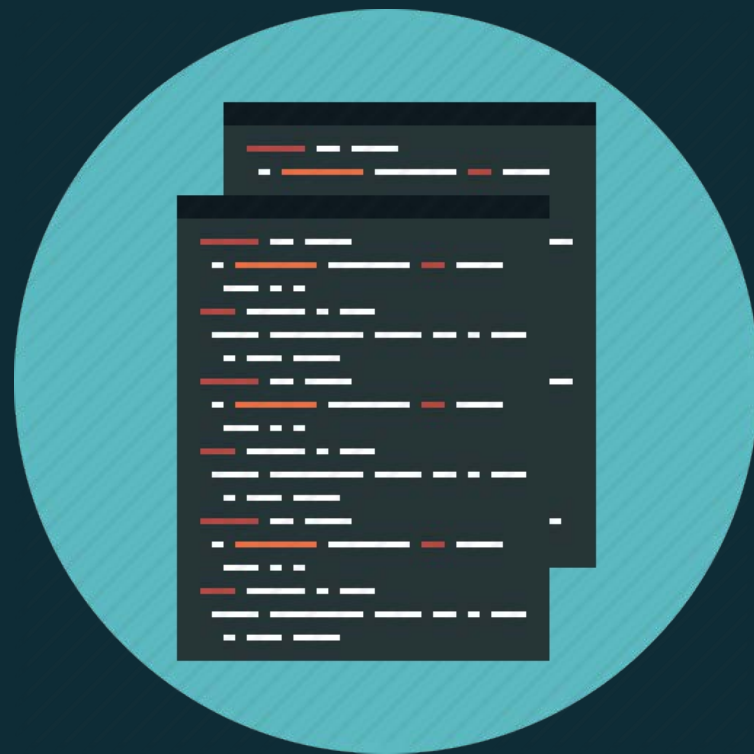
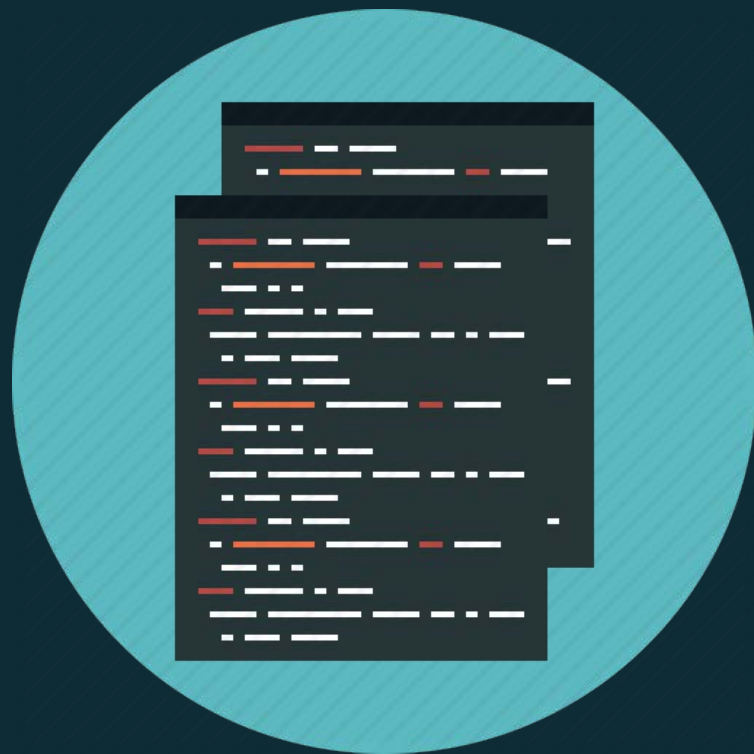
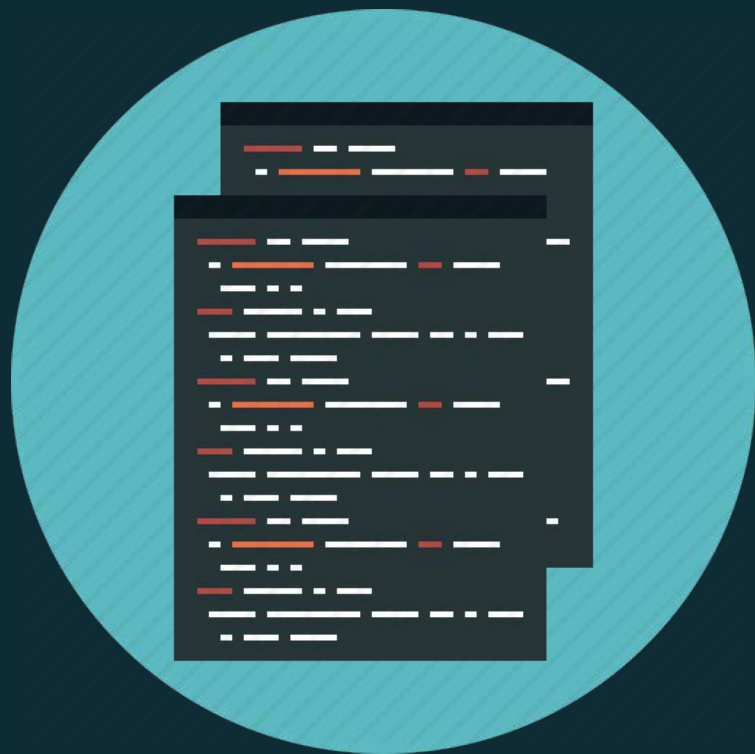
Move the `pointer' within the encapsulated graph to a new node.

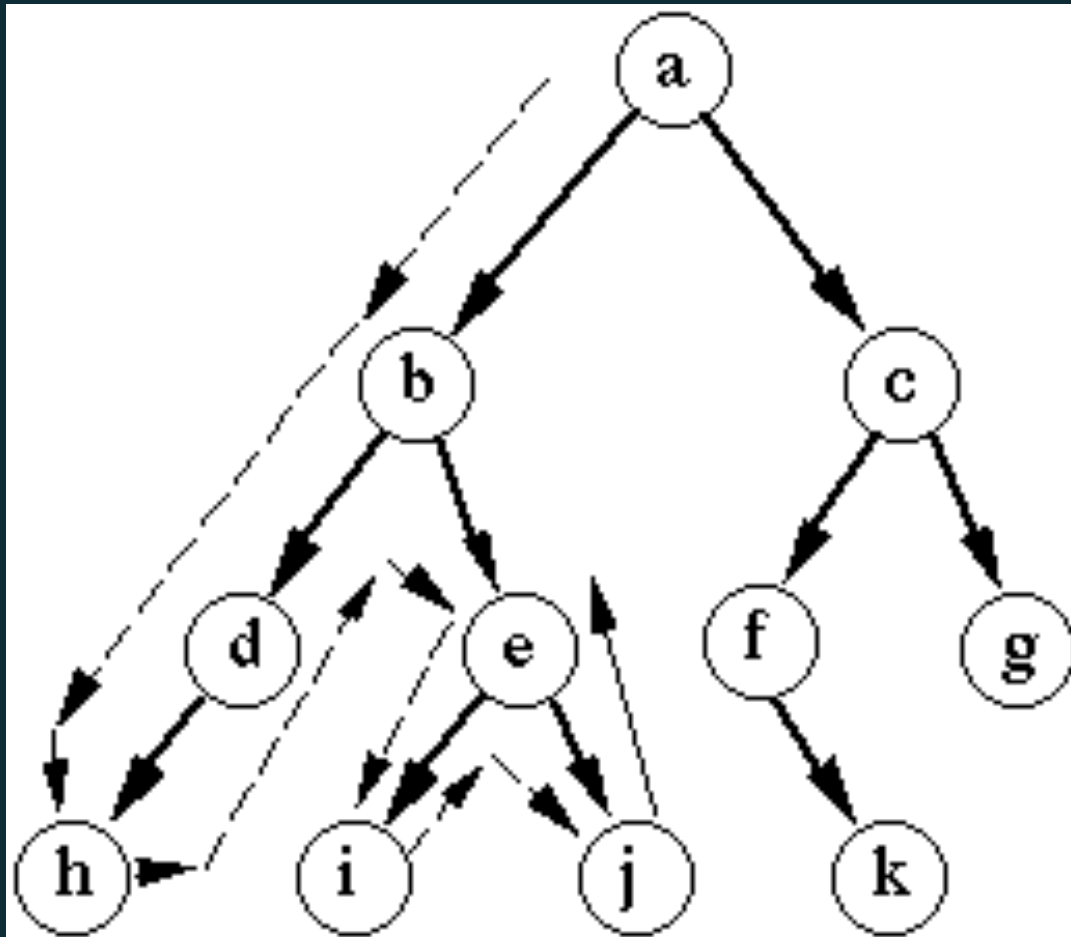
`void`

**sendPath**( )

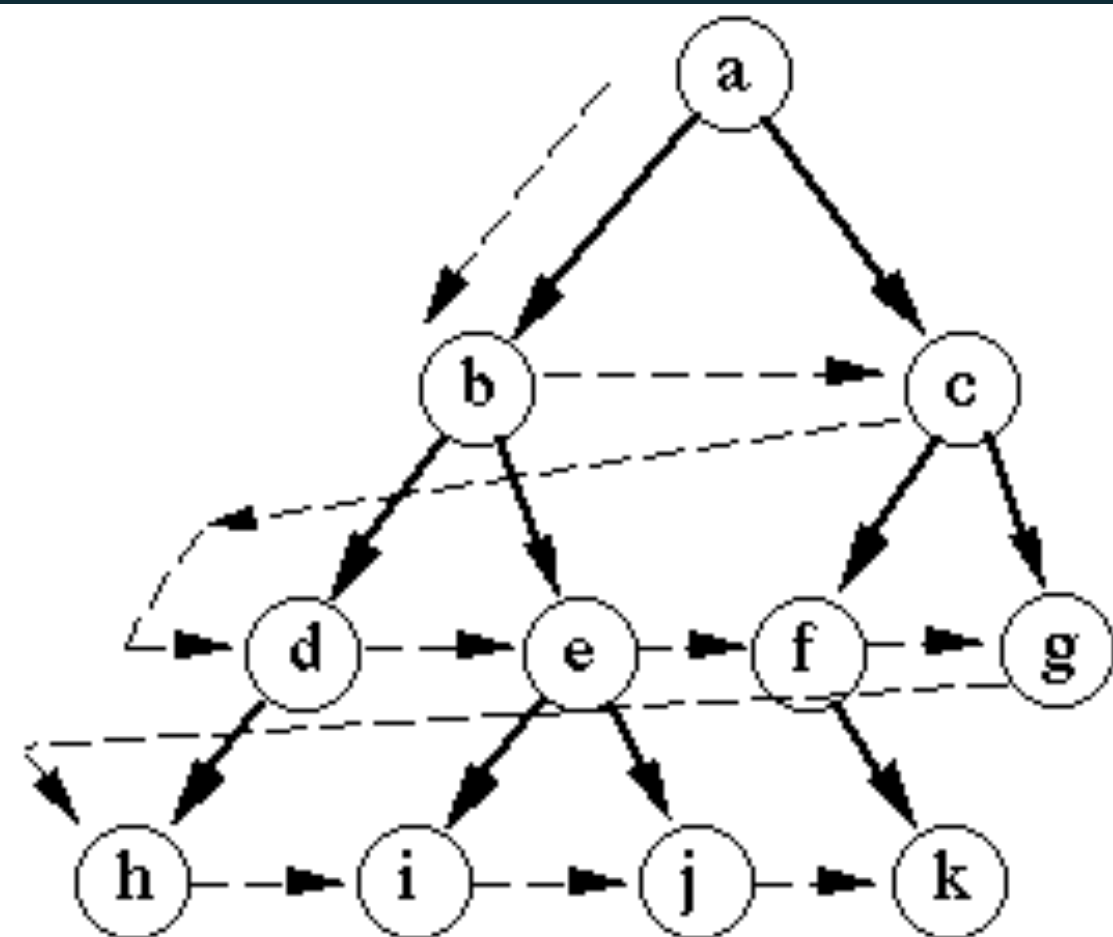
Upload your path to the server for scoring!







Depth-first search



Breadth-first search

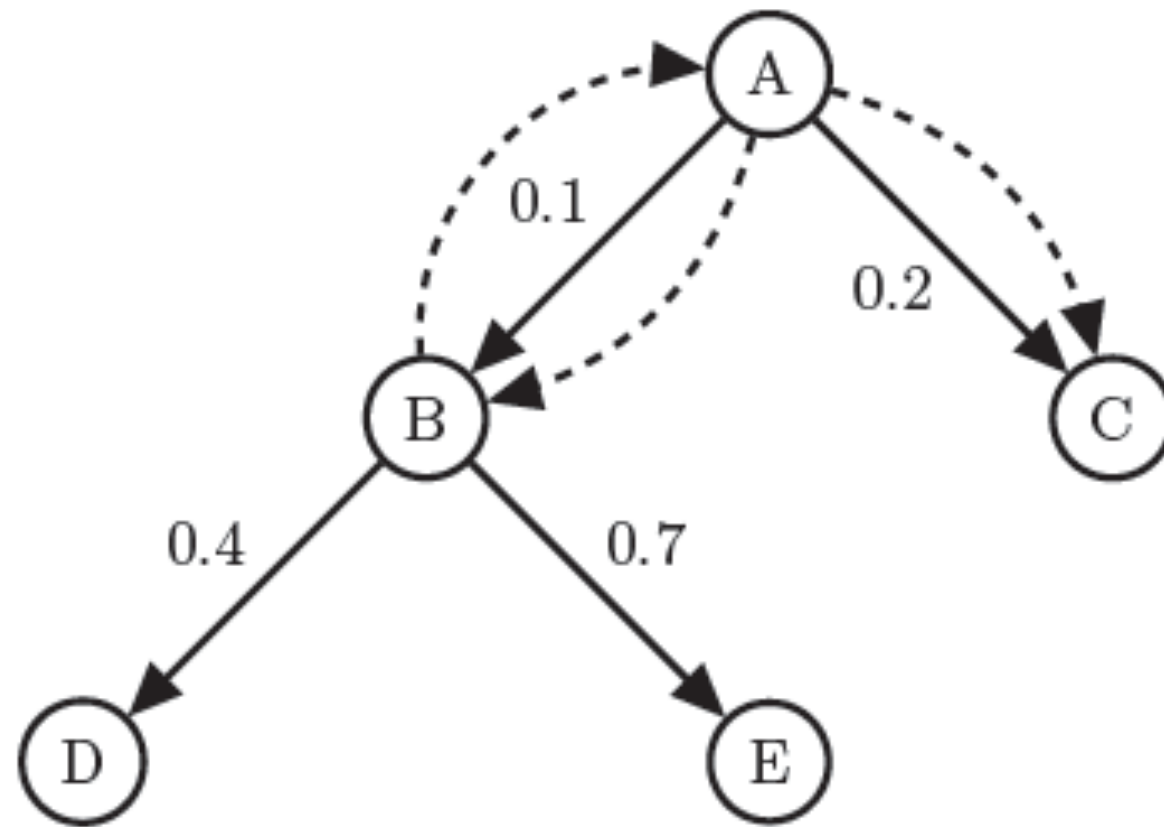


Figure 4.1: An example of how sBacktrackGreedy may backtrack to save cost: this strategy starts at node A, and then proceeds to node B, after recording the distance to node C. At vertex B, sBacktrackGreedy calculates that it will cost strictly less to move to node C *via* node A, where it has already been, than to take the single hop to nodes D or E, so it makes this move.

Base03	0	43	54	#002b36	Yellow	181	137	0	#b58900
Base02	7	54	66	#073642	Orange	203	75	22	#cb4b16
Base01	88	110	117	#586e75	Red	220	50	47	#dc322f
Base00	101	123	131	#657b83	Magenta	211	54	130	#d33682
Base0	131	148	150	#839496	Violet	108	113	196	#6c71c4
Base1	147	161	161	#93a1a1	Blue	38	139	210	#268bd2
Base2	238	232	213	#eee8d5	Cyan	42	161	152	#2aa198
Base3	253	246	227	#fdf6e3	Green	133	153	0	#859900