

# **CMPSC 465**

## **Data Structures and Algorithms**

### **Spring 2022**

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Instructor: Chunhao Wang

**Flow network**  
**(Textbook, Section 7.2**  
**Kleinberg & Tardos Section 7.1)**

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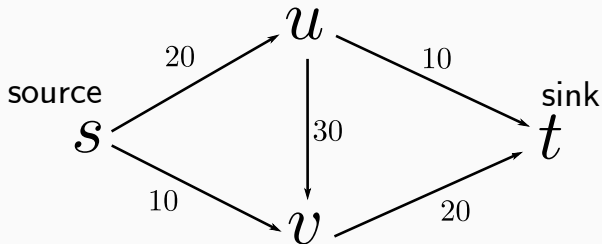
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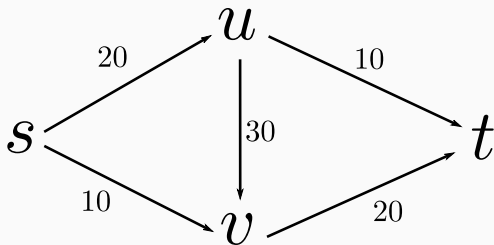
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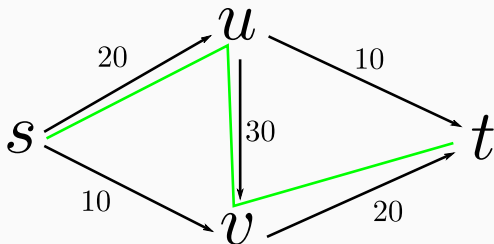
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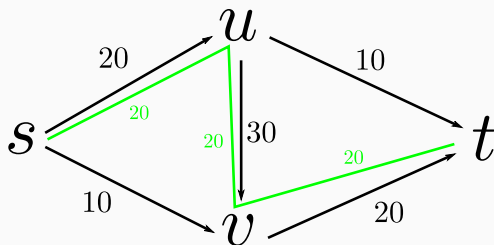
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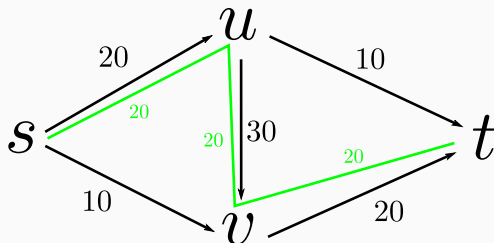
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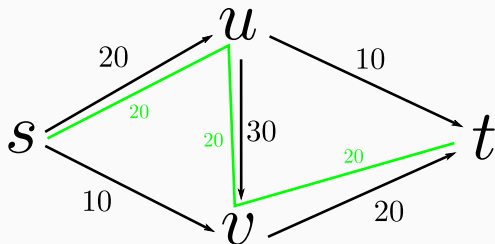
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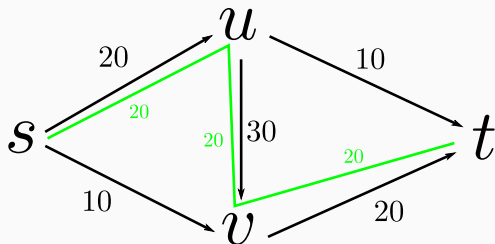
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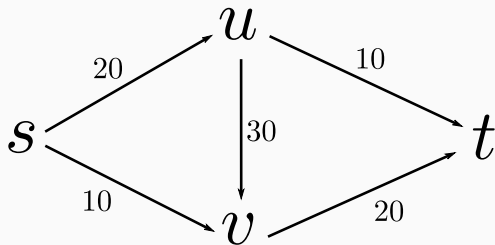
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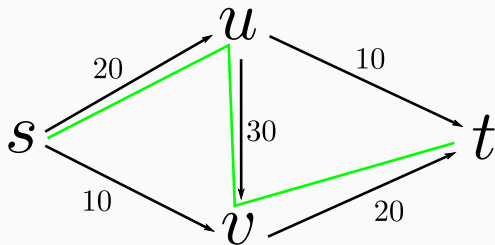
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$v(f) = 20$ . Can we do better?

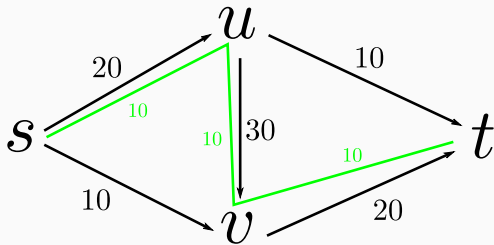
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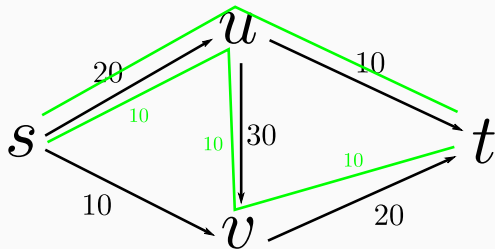
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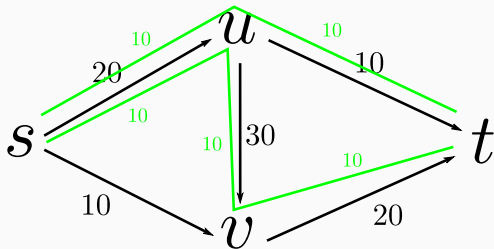
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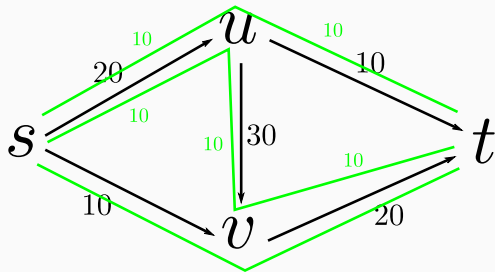
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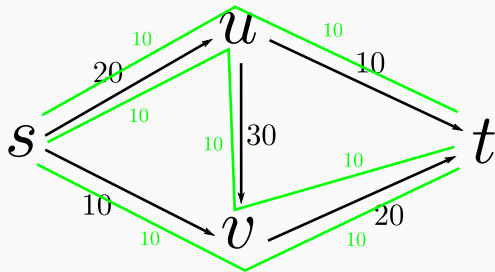
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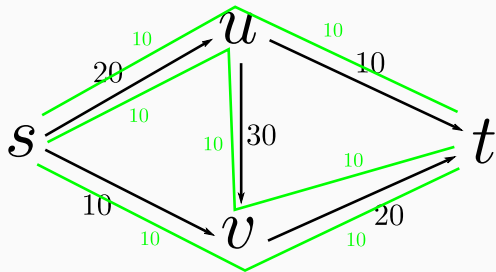


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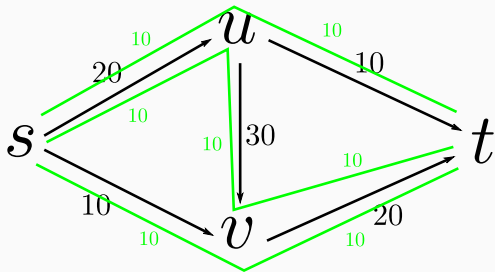
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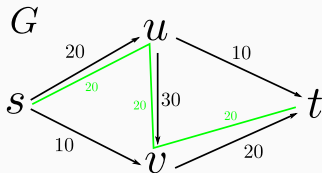
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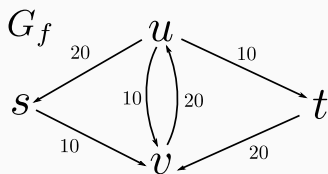
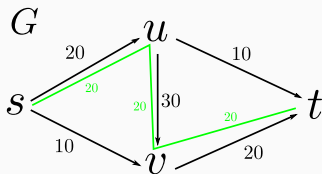
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Any  $s$ - $t$  path in  $G_f$  is called an **augmenting path**

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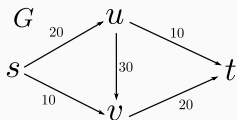
$f = f'$ ;



# The Ford-Fulkerson algorithm

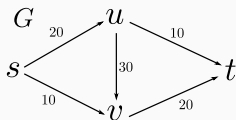
```
def FORD-FULKERSON( $G$ , capacities  $c$ ):  
    Set  $f(e) = 0$  for all  $e \in G$ ;  
    while  $\exists$   $s$ - $t$  path in the residual graph  $G_f$ :  
        Let  $P$  be a simple  $s$ - $t$  path in  $G_f$ ;  
         $f' = \text{AUGMENT}(f, P)$ ;  
         $G_f = G_{f'}$ ;  
         $f = f'$ ;  
    return  $f$ ;
```

# Running example



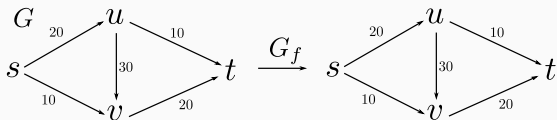
$e$			
$s \rightarrow u$			
$s \rightarrow v$			
$u \rightarrow v$			
$u \rightarrow t$			
$v \rightarrow t$			

# Running example



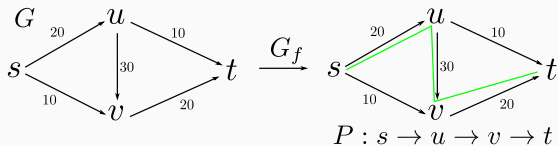
$e$	$f_1(e)$		
$s \rightarrow u$	0		
$s \rightarrow v$	0		
$u \rightarrow v$	0		
$u \rightarrow t$	0		
$v \rightarrow t$	0		

# Running example



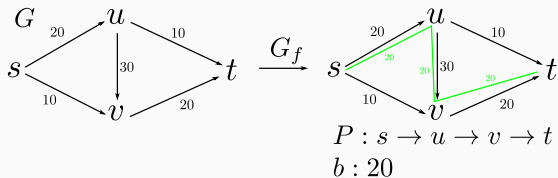
$e$	$f_1(e)$		
$s \rightarrow u$	0		
$s \rightarrow v$	0		
$u \rightarrow v$	0		
$u \rightarrow t$	0		
$v \rightarrow t$	0		

# Running example



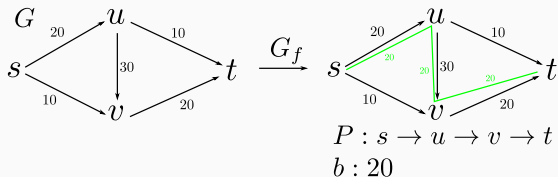
$e$	$f_1(e)$		
$s \rightarrow u$	0		
$s \rightarrow v$	0		
$u \rightarrow v$	0		
$u \rightarrow t$	0		
$v \rightarrow t$	0		

# Running example



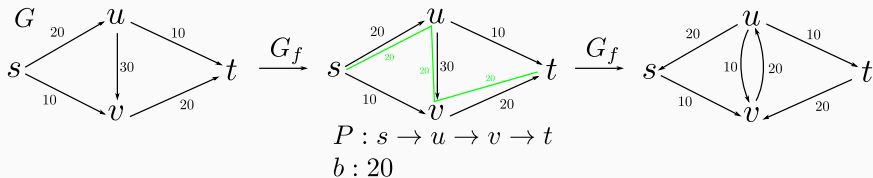
$e$	$f_1(e)$		
$s \rightarrow u$	0		
$s \rightarrow v$	0		
$u \rightarrow v$	0		
$u \rightarrow t$	0		
$v \rightarrow t$	0		

# Running example



$e$	$f_1(e)$	$f_2(e)$
$s \rightarrow u$	0	20
$s \rightarrow v$	0	0
$u \rightarrow v$	0	20
$u \rightarrow t$	0	0
$v \rightarrow t$	0	20

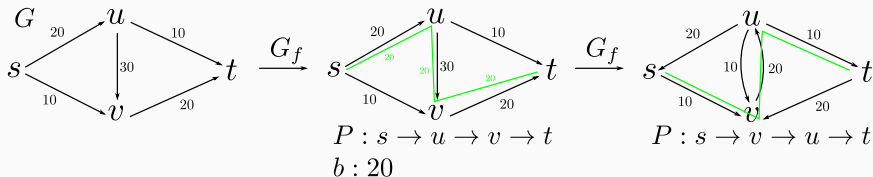
# Running example



$e$	$f_1(e)$	$f_2(e)$	
$s \rightarrow u$	0	20	
$s \rightarrow v$	0	0	
$u \rightarrow v$	0	20	
$u \rightarrow t$	0	0	
$v \rightarrow t$	0	20	

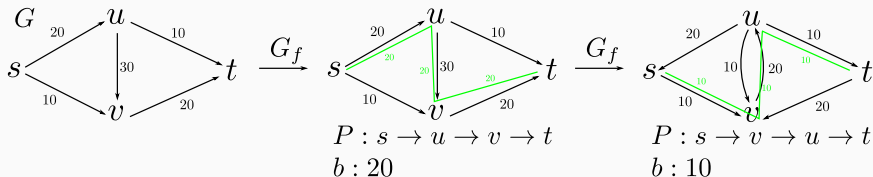


# Running example



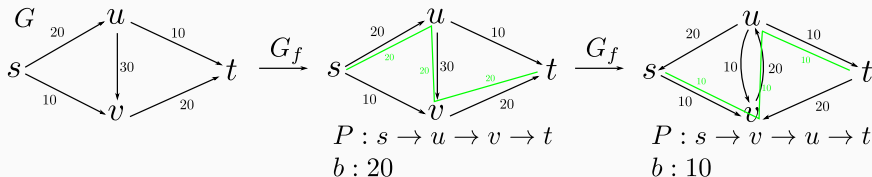
$e$	$f_1(e)$	$f_2(e)$	
$s \rightarrow u$	0	20	
$s \rightarrow v$	0	0	
$u \rightarrow v$	0	20	
$u \rightarrow t$	0	0	
$v \rightarrow t$	0	20	

# Running example



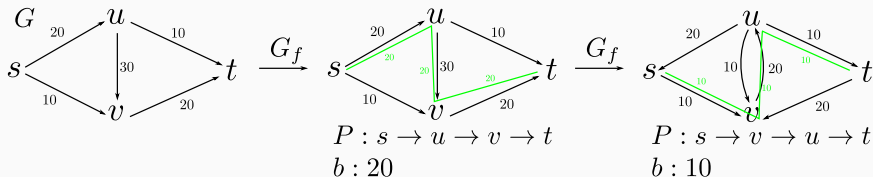
$e$	$f_1(e)$	$f_2(e)$	
$s \rightarrow u$	0	20	
$s \rightarrow v$	0	0	
$u \rightarrow v$	0	20	
$u \rightarrow t$	0	0	
$v \rightarrow t$	0	20	

# Running example

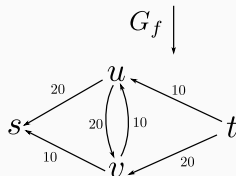


$e$	$f_1(e)$	$f_2(e)$	$f_3(e)$
$s \rightarrow u$	0	20	20
$s \rightarrow v$	0	0	10
$u \rightarrow v$	0	20	10
$u \rightarrow t$	0	0	10
$v \rightarrow t$	0	20	20

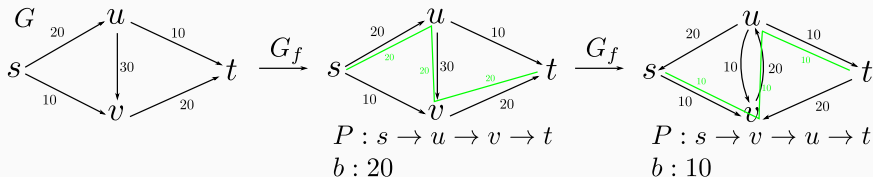
# Running example



$e$	$f_1(e)$	$f_2(e)$	$f_3(e)$
$s \rightarrow u$	0	20	20
$s \rightarrow v$	0	0	10
$u \rightarrow v$	0	20	10
$u \rightarrow t$	0	0	10
$v \rightarrow t$	0	20	20



# Running example



$e$	$f_1(e)$	$f_2(e)$	$f_3(e)$
$s \rightarrow u$	0	20	20
$s \rightarrow v$	0	0	10
$u \rightarrow v$	0	20	10
$u \rightarrow t$	0	0	10
$v \rightarrow t$	0	20	20

