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**CZ3005 Artificial Intelligence**

**Assignment 1**

Lab Group: TS4

**Team Members and Respective Contributions:**

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# 1.1 Introduction

Graph traversal and pathfinding are well studied problems with a large body of research. Standard algorithms such as BFS, UCS and A\* Search have good performance and are complete.

Given that the entire network has been parsed and will not change during our analysis, we can define the environment of this problem as having the following properties: *accessible* (fully observable), *deterministic*, *episodic* (non-sequential), *static* and *discrete*. Edges have two properties – distance and energy cost. The objective is to pathfind for the shortest overall distance, whilst checking to ensure that the energy cost constraint is not violated. This task is described in literature as a *resource constrained shortest path problem.*

# 1.2 Results

**Task 1**

S->1->1363->1358->1357->1356->1276->1273->1277->1269->1267->1268->1284->1283->1282->1255->1253->1260->1259->1249->1246->963->964->962->1002->952->1000->998->994->995->996->987->988->979->980->969->977->989->990->991->2369->2366->2340->2338->2339->2333->2334->2329->2029->2027->2019->2022->2000->1996->1997->1993->1992->1989->1984->2001->1900->1875->1874->1965->1963->1964->1923->1944->1945->1938->1937->1939->1935->1931->1934->1673->1675->1674->1837->1671->1828->1825->1817->1815->1634->1814->1813->1632->1631->1742->1741->1740->1739->1591->1689->1585->1584->1688->1579->1679->1677->104->5680->5418->5431->5425->5424->5422->5413->5412->5411->66->5392->5391->5388->5291->5278->5289->5290->5283->5284->5280->T

Distance: 148648.63

**Task 2**

S->1->1363->1358->1357->1356->1276->1273->1277->1269->1267->1268->1284->1283->1282->1255->1253->1260->1259->1249->1246->963->964->962->1002->952->1000->998->994->995->996->987->988->979->980->969->977->989->990->991->2465->2466->2384->2382->2385->2379->2380->2445->2444->2405->2406->2398->2395->2397->2142->2141->2125->2126->2082->2080->2071->1979->1975->1967->1966->1974->1973->1971->1970->1948->1937->1939->1935->1931->1934->1673->1675->1674->1837->1671->1828->1825->1817->1815->1634->1814->1813->1632->1631->1742->1741->1740->1739->1591->1689->1585->1584->1688->1579->1679->1677->104->5680->5418->5431->5425->5424->5422->5413->5412->5411->66->5392->5391->5388->5291->5278->5289->5290->5283->5284->5280->T

Distance: 150335.55

Energy Cost: 259087

**Task 3**

S->1->1363->1358->1357->1356->1276->1273->1277->1269->1267->1268->1284->1283->1282->1255->1253->1260->1259->1249->1246->963->964->962->1002->952->1000->998->994->995->996->987->988->979->980->969->977->989->990->991->2465->2466->2384->2382->2385->2379->2380->2445->2444->2405->2406->2398->2395->2397->2142->2141->2125->2126->2082->2080->2071->1979->1975->1967->1966->1974->1973->1971->1970->1948->1937->1939->1935->1931->1934->1673->1675->1674->1837->1671->1828->1825->1817->1815->1634->1814->1813->1632->1631->1742->1741->1740->1739->1591->1689->1585->1584->1688->1579->1679->1677->104->5680->5418->5431->5425->5424->5422->5413->5412->5411->66->5392->5391->5388->5291->5278->5289->5290->5283->5284->5280->T

Distance: 150335.55

Energy Cost: 259087

# 2.1 Uninformed Search

In tasks 1 and 2, uninformed search is used to determine the shortest path. For both tasks we can analyse the graph as a directed graph since moving in reverse along the same edge doubles both distance and energy cost with no benefit. The graph may contain cycles. We use UCS to explore the graph in task 1.

## Task 1

|  |  |
| --- | --- |
| **Time Complexity**  Number of nodes which have a shortest distance path to the target node than the starting node | **Space Complexity**  Same as time complexity |
| **Completeness**  Yes | **Optimality**  Yes |

**Empirical Analysis**

Number of nodes explored: 32514 nodes, V+E = 65028, Depth of answer: 131 nodes deep

Avg. branching factor of graph: b [1], Assuming b = 2,

Complexity of BFS for same depth = =

UCS performs ~ times better than BFS for this problem

## Task 2

When optimising only for shortest distance, UCS performs well because the nodes at the frontier are guaranteed to have the shortest distance from the starting node. Thus, only one path needs to be cached for each node and nodes are explored at most once, minimising both time and space complexity. In the worst case, all nodes (vertexes) and edges are traversed once, for complexity.

However, this task requires the consideration of two resources. In this case, the first exploration of a node might provide shortest overall distance but large energy cost. Therefore, nodes may have to be explored more than once, greatly increasing overall complexity.

Without consulting the literature, two possible solutions can be conceived heuristically. BFS to explore all possible paths to the target, or a UCS using an evaluation function (otherwise called best-first search). For this variation, instead of using solely distance to measure cost several cost functions can be combined to provide an overall cost, with weights assigned to each cost function (e.g., distance might be judged to be 2x as important as cost).

**Best-First Search**

By tuning the weights of the cost functions, we can optimise for either the best distance or best energy cost result.

|  |  |
| --- | --- |
| **Time Complexity**  Number of nodes with cost <= starting node | **Space Complexity**  Same as time complexity |
| **Completeness**  No.  For some graph with only one path , where are vertexes in the graph, if there are two paths that include – the correct path with lower energy cost and a path that will exceed the overall energy cost (wrong path), given a cost function that penalizes distance, the wrong path will be chosen. Since all nodes are explored only once, the only valid path under the constraints will be discarded. | **Optimality**  No. Optimal algorithms exist as a subset of complete algorithms. Since the algorithm is not complete, it is not optimal. |

Number of nodes explored: 12616/26084 nodes, depending on parameter

**Breadth-First Search**

As analysed in Task 1, the complexity of BFS for this graph would make a complete traversal of the graph infeasible. By providing some conditions for the traversal, we can limit the number of nodes explored.

Number of nodes explored: 16600000 nodes

# 2.2 Informed Search

In task 3, A\* Search is used to determine the shortest path. A\* is guaranteed to return the least-cost path from the start to the goal if the heuristic used is admissible, whereby the heuristic will not overestimate the true cost (energy cost or distance) to the target.

The coordinates of each vertex is given, as well as the distance of an edge. Therefore, we can create a heuristic to calculate the estimated distance cost of path to the target. However, as no other energy information is given, we cannot estimate the energy cost.

We calculate the estimated distance to the target vertex with the equation

To derive a heuristic function, we can take the straight-line distance between two points. For some vertices , where is the next vertex and is the goal,

The actual distance is equal to where number of nodes on the shortest path to the goal and is their true distance as given by the data.

For A\* to return the least-cost path, the heuristic function must never overestimate the actual distance (must be admissible). Given that the heuristic calculates straight-line distance (the shortest path between two points) while the actual path must follow along the edges and therefore covers a circuitous route, the actual distance will always be larger than the estimated distance.

Furthermore, when comparing the calculated straight-line distance between two vertices against the actual distances given for each edge, the given distance is always equal to or larger than the calculated straight-line distance. (*Mean difference: 92.31, Std Dev: 100.80, n=40.5%*. [n] This discrepancy could be due to winding/curved roads, great-circle distance or other factors). However, the given distance is never smaller than the calculated distance. This is significant because if the calculated distance was larger than the actual distance, then could be larger than the actual straight-line distance for some routes.

Therefore, we can conclude that is admissible, and A\* will return the shortest distance path.

In the event that the shortest distance path exceeds the energy cost, we must perform backtracking search. For least distance path , we begin uninformed search from a previous node to completely search the space for a path minimises distance and satisfies the energy cost constraint.

|  |  |
| --- | --- |
| *Fig 1. Backtracking Search*  *The red path is the original least distance path, and the green path is the constraint satisfactory path* | By beginning uninformed search from (the second last node), and propagating backwards if there is no solution, (start from the etc.), we can iteratively propagate backwards until a valid solution is found.  Since this solution retraces the same paths many times, memoising traversed paths will reduce the complexity of the overall solution. |

TIME COMPLEXITY

SPACE COMPLEXITY

**TODO**

**TODO add the references here**

[1] – Average branching factor of graph

[2] – Average number of node references, given in verify.py

[n] – Comparison between calculated distance and given distance is done in investigate\_distance.py