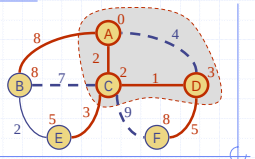
Shortest Path

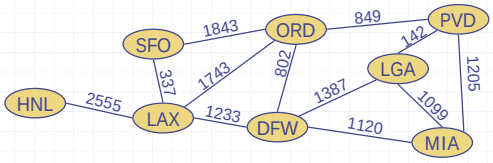


Outline and Reading

- Shortest path
  - Weighted graph
  - Shortest path problem
  - Shortest path properties
- Dijkstra's algorithm (§7.1.1)
  - Algorithm
  - Edge relaxation
  - Example
  - Analysis

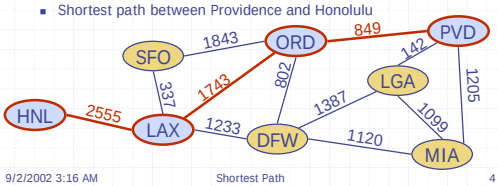
Weighted Graph

- In a weighted graph, each edge has an associated numerical value, called the weight of the edge
- Edge weights may represent, distances, costs, etc.
- Example:
  - In a flight route graph, the weight of an edge represents the distance in miles between the endpoint airports



Shortest Path Problem

- Given a weighted graph and two vertices u and v, we want to find a path of minimum total weight between u and v
- Applications
  - Flight reservations
  - Driving directions
  - Internet packet routing
- Example:
  - Shortest path between Providence and Honolulu

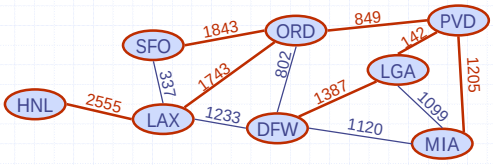


Shortest Path Properties

Property 1:
A subpath of a shortest path is itself a shortest path

Property 2:
There is a tree of shortest paths from a start vertex to all the other vertices

Example:
Tree of shortest paths from Providence



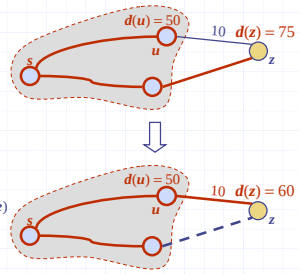
Dijkstra's Algorithm

- The distance of a vertex v from a vertex s is the length of a shortest path between s and v
- Dijkstra's algorithm computes the distances of all the vertices from a given start vertex s
- Assumptions:
  - the graph is connected
  - the edges are undirected
  - the edge weights are nonnegative
- We grow a "cloud" of vertices, beginning with s and eventually covering all the vertices
- We store with each vertex v a label $d(v)$ representing the distance of v from s in the subgraph consisting of the cloud and its adjacent vertices
- At each step
  - We add to the cloud the vertex u outside the cloud with the smallest distance label
  - We update the labels of the vertices adjacent to u

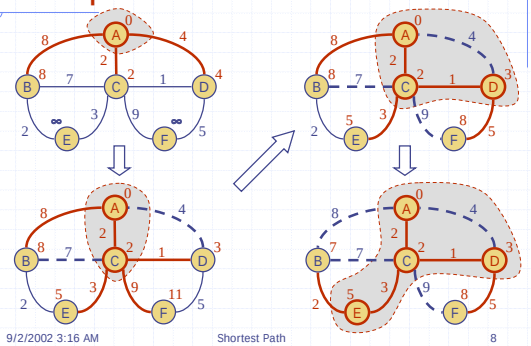
Edge Relaxation

- Consider an edge $e = (u,z)$ such that
  - u is the vertex most recently added to the cloud
  - z is not in the cloud
- The relaxation of edge e updates distance $d(z)$ as follows

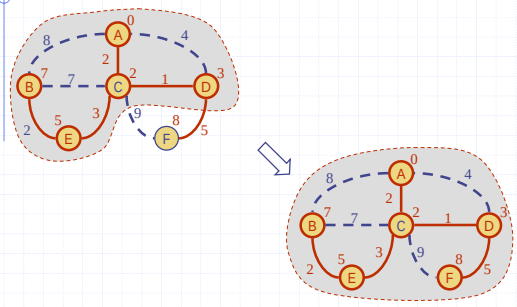
$d(z) \leftarrow \min(d(z), d(u) + weight(e))$



Example



Example (cont.)



Dijkstra's Algorithm

- A priority queue stores the vertices outside the cloud
  - Key: distance
  - Element: vertex
- Locator-based methods
  - *insert*(k,e) returns a locator
  - *replaceKey*(l,k) changes the key of an item
- We store two labels with each vertex:
  - distance
  - locator in priority queue

```
Algorithm DijkstraDistances(G, s)
  Q ← new heap-based priority queue
  for all v ∈ G.vertices()
    if v = s
      setDistance(v, 0)
    else
      setDistance(v, ∞)
    l ← Q.insert(getDistance(v), v)
    setLocator(v,l)
  while ¬Q.isEmpty()
    u ← Q.removeMin()
    for all e ∈ G.incidentEdges(u)
      { relax edge e }
      z ← G.opposite(u,e)
      r ← getDistance(u) + weight(e)
      if r < getDistance(z)
        setDistance(z,r)
        Q.replaceKey(getLocator(z),r)
```


Analysis

- Graph operations
  - Method incidentEdges is called once for each vertex
- Label operations
  - We set/get the distance and locator labels of vertex z $O(\deg(z))$ times
  - Setting/getting a label takes $O(1)$ time
- Priority queue operations
  - Each vertex is inserted once into and removed once from the priority queue, where each insertion or removal takes $O(\log n)$ time
  - The key of a vertex in the priority queue is modified at most $\deg(w)$ times, where each key change takes $O(\log n)$ time
- Dijkstra's algorithm runs in $O((n + m) \log n)$ time provided the graph is represented by the adjacency list structure
  - Recall that $\sum_v \deg(v) = 2m$
- The running time can also be expressed as $O(m \log n)$ since the graph is connected

Extension

- Using the template method pattern, we can extend Dijkstra's algorithm to return a tree of shortest paths from the start vertex to all other vertices
- We store with each vertex a third label:
  - parent edge in the shortest path tree
- In the edge relaxation step, we update the parent label

```
Algorithm DijkstraShortestPathsTree(G, s)
  …
  for all v ∈ G.vertices()
    …
    setParent(v, ∅)
    …
  for all e ∈ G.incidentEdges(u)
    { relax edge e }
    z ← G.opposite(u,e)
    r ← getDistance(u) + weight(e)
    if r < getDistance(z)
      setDistance(z,r)
      setParent(z,e)
      Q.replaceKey(getLocator(z),r)
```