Problem Set No. 5

1. Construct an example of a directed graph with a distinguished vertex s whose minimum spanning tree rooted at s is different from its shortest path tree rooted at s.

2. For a connected undirected graph, a *bottleneck minimum spanning tree* is a spanning tree whose maximum edge cost is minimum.

   (a) Show that any minimum spanning tree is a bottleneck minimum spanning tree, but a bottleneck spanning tree need not be a minimum spanning tree.

   (b) Describe and analyze an $O(m)$-time algorithm to find a bottleneck minimum spanning tree. Hint: Use median-finding and graph contraction.

3. (CLR 23.1-6, p. 468) When an adjacency-matrix representation is used, most graph algorithms require time $\Theta(V^2)$, but there are some exceptions. Show that determining whether a directed graph contains a **sink**–a vertex with in-degree $|V| - 1$ and out-degree 0–can be determined in time $O(V)$, even if an adjacency-matrix representation is used.

4. (CLR 23.5-7, p. 494) A directed graph $G = (V, E)$ is said to be **semiconnected** if, for any two vertices $u, v \in V$, we have $u \rightsquigarrow v$ or $v \rightsquigarrow u$. Give an efficient algorithm to determine whether or not G is semiconnected. Prove that your algorithm is correct, and analyze its running time.

5. (Heuristic Search) Let G be a graph with two distinguished vertices s and t and an edge cost $c(v, w)$ for each edge (v, w). Assume that G has no negative cycles (though it may have negative edge costs). We wish to find a shortest path from s to t by **heuristic search**, using a **distance estimate** $e(v)$ which is intended to be an easy-to-compute approximation to the actual distance from v to the destination t. We use the labeling and scanning algorithm as described in class. To choose the next vertex to scan, we pick a vertex $v \in L$ with minimum $d(v) + e(v)$. Specifically, the algorithm is as follows:

   Initialize $L = \{s\}, d(s) = 0, d(v) = \infty$ for $v \neq s$.
   while $L \neq \phi$ *do begin*
       delete from L a vertex v with $d(v) + e(v)$ minimum;
       if $v = t$ *then stop else*

for (v, w) an edge *do begin if* $d(v) + c(v, w) < d(w)$ *then begin*

$d(w) = d(v) + c(v, w); p(w) = v;$

if $w \notin L$ then insert w into L

end end end

We call an estimate e **safe** if $e(t) = 0$ and $e(v) \leq c(v, w) + e(w)$ for every edge (v, w).

(a) Prove that if e is a safe estimate, then $e(v)$ is a lower bound on the distance from v to t, for every vertex v.

(b) Prove that if e is a safe estimate, the heuristic search algorithm will delete each vertex from L at most once, and will terminate with $d(t)$ equal to the correct distance from s to t, with the parent pointers from t indicating a shortest path from s to t (backwards).

(c) Prove that if e and f are two safe estimates such that $e(v) \leq f(v)$ for every v, then heuristic search run with f will delete no more vertices from L than heuristic search run with e.

(d) Describe how to implement heuristic search so that the total running time is $O(k \log k + l)$, where k is the number of vertices inserted into L and l is the total number of edges leading out of such vertices. (Assume $e(v)$ is computable in $O(1)$ time for any v.) Hint: Use an F-heap. You will also need to **avoid** explicitly initializing $d(v) = \infty$ for all vertices $v \neq s$, since the number of such vertices may be much larger than k. How can you do this?

6. (extra credit) Give a family of graphs (with some negative-cost edges) on which Dijkstra's shortest path algorithm (shortest-first scanning) runs in exponential time.