

# The Boost Graph Library

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- Header only C++ library



- **GNU/Linux:** (Almost certainly) already in the repositories of your distribution

```
sudo apt install libboost-graph-dev
```

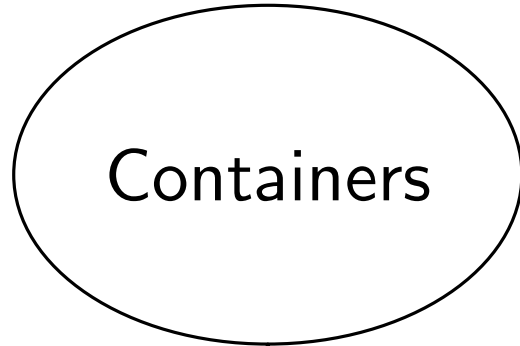
- **Windows:** follow official instructions.

[https://www.boost.org/doc/libs/release/more/getting\\_started/windows.html](https://www.boost.org/doc/libs/release/more/getting_started/windows.html)

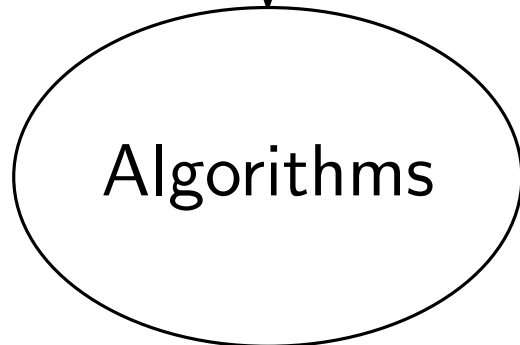
Essentially: download, unpack, and set the include path of your compiler

# The Boost Graph Library

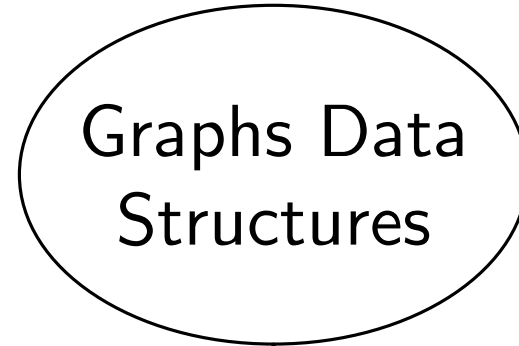
STL



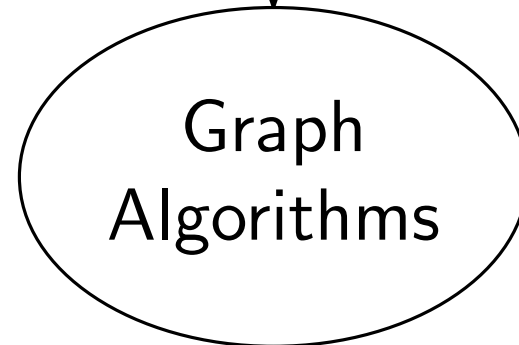
Element Iterators



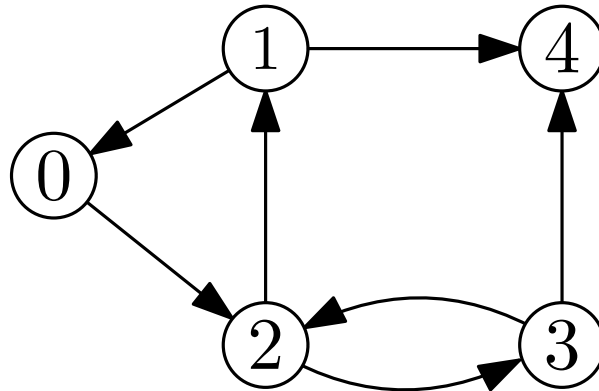
BGL



Vertex Iterators  
Adjacency Iterators  
Visitors  
Property Accessors



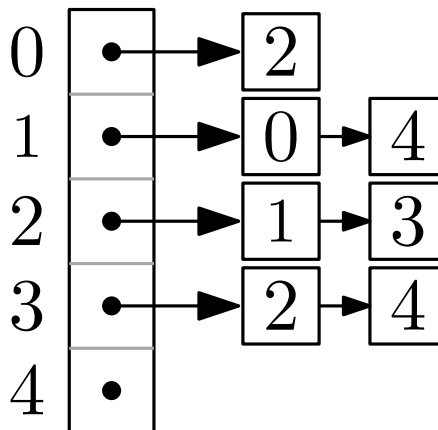
# Graph Representation



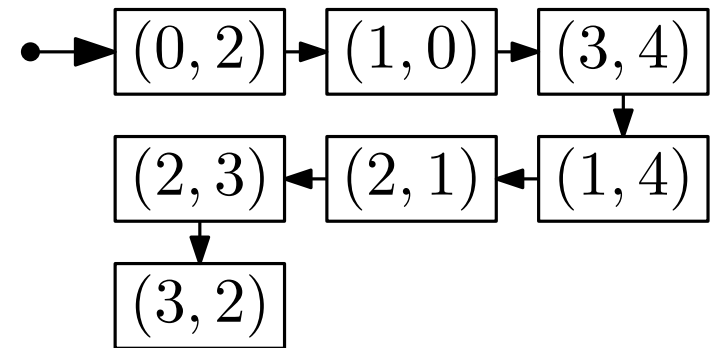
Adjacency Matrix

	0	1	2	3	4
0	0	0	1	0	0
1	1	0	0	0	1
2	0	1	0	1	0
3	0	0	1	0	1
4	0	0	0	0	0

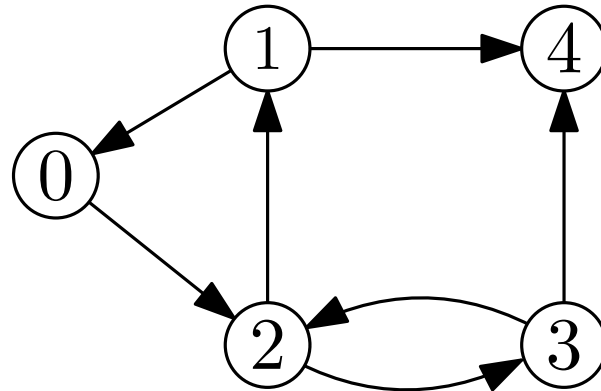
Adjacency List



Edge List



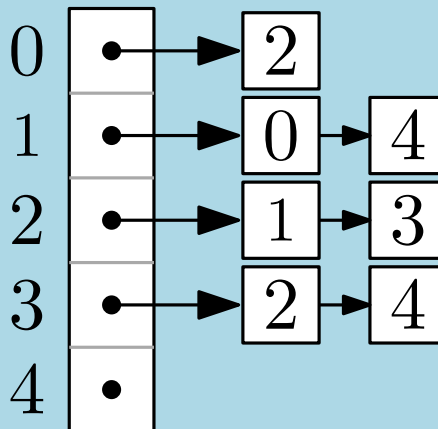
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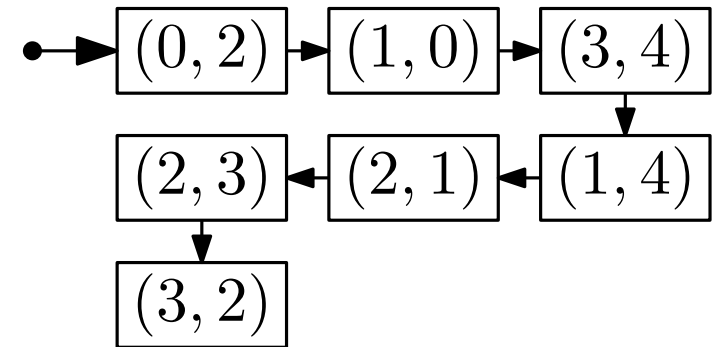
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0	0	0	1	0	0
1	1	0	0	0	1
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3	0	0	1	0	1
4	0	0	0	0	0

Adjacency List



Edge List



# Graph Representations

```
#include <boost/graph/adjacency_list.hpp>

// OutEdgeList type, VertexList type, Directivity
typedef boost::adjacency_list<boost::vecS, boost::vecS, boost::directedS> Graph;
```

# Graph Representations

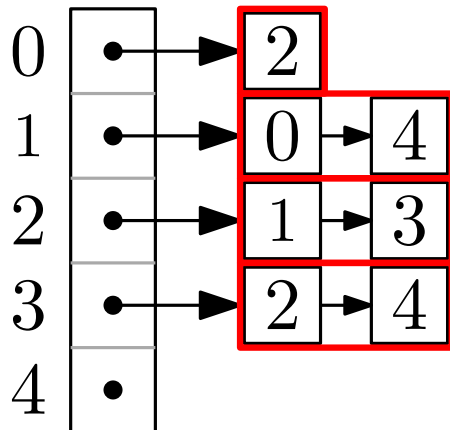
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```

---

## OutEdgeList

Container used to store the outgoing edges from a vertex



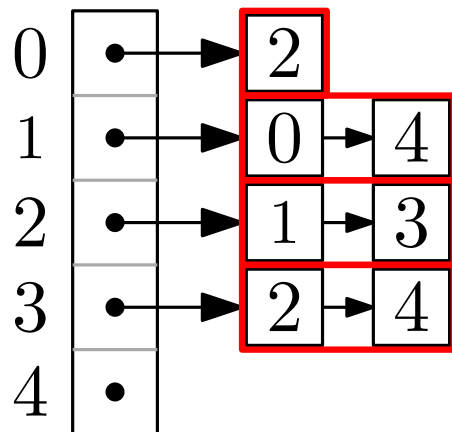
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## OutEdgeList

Container used to store the outgoing edges from a vertex



---

**vecS**: vector. Parallel edges allowed. Random acc. iterator. Insertions in amortized  $O(1)$  time.

**listS**: doubly-linked list. Parallel edges allowed. Insertions in constant worst-case time. Space overhead.

**slistS**: singly-linked list. Parallel edges allowed. Insertions in constant worst-case time. (Less) space overhead. Cannot iterate backwards.

**setS**: associative container. No parallel edges. Fast edge lookups, insertions in  $O(\log \Delta)$  time.



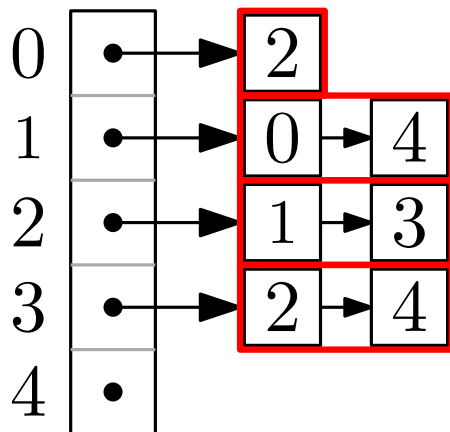
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## OutEdgeList

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Insertions in constant worst-case time. (Less) space overhead. Cannot iterate backwards.

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Do I need parallel edges?  
Do I need fast edge lookups?

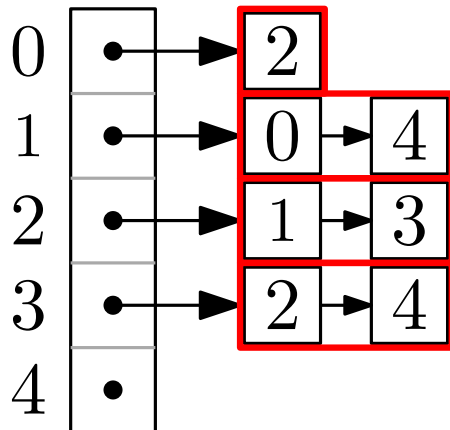
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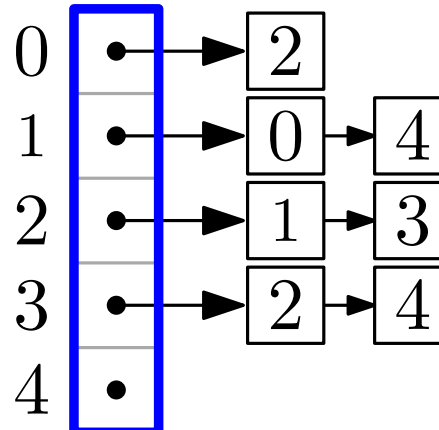
## OutEdgeList

Container used to store the outgoing edges from a vertex



## VertexList

Container used to store vertices



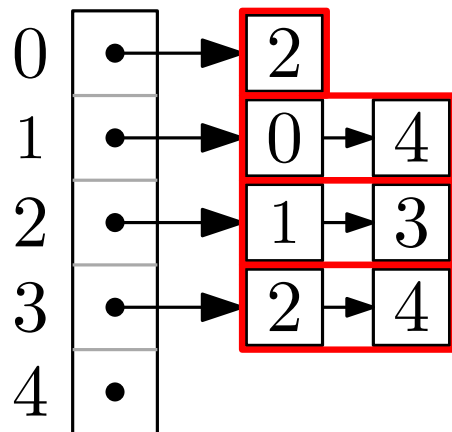
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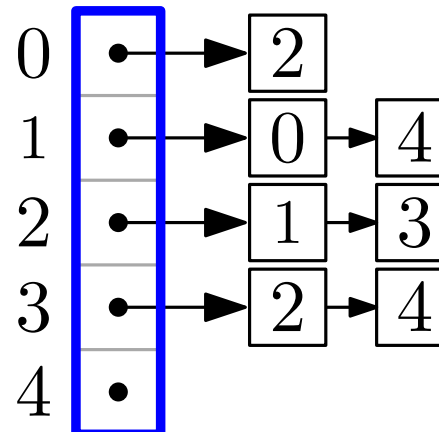
## OutEdgeList

Container used to store the outgoing edges from a vertex



## VertexList

Container used to store vertices



**vecS**: vector.

Amortized  $O(1)$ -time vertex insertion.

**listS**: list. Insertions and removals in  $O(1)$  worst-case time. Space overhead.

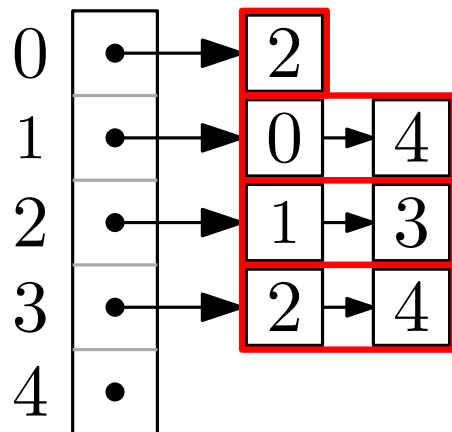
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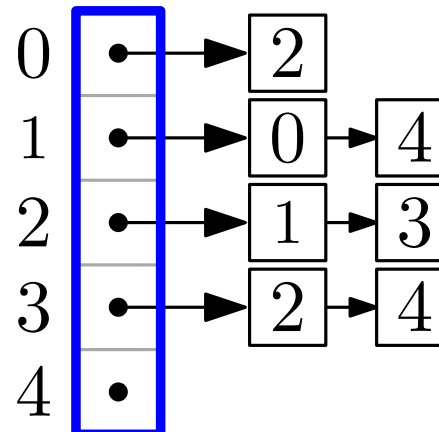
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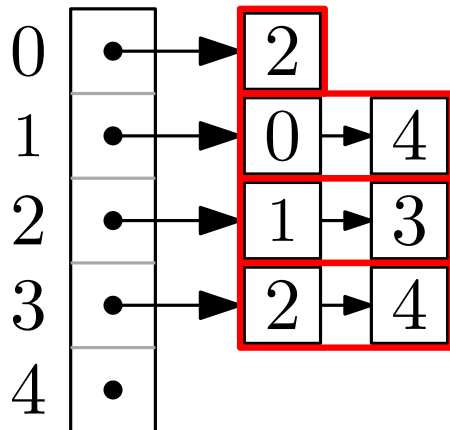
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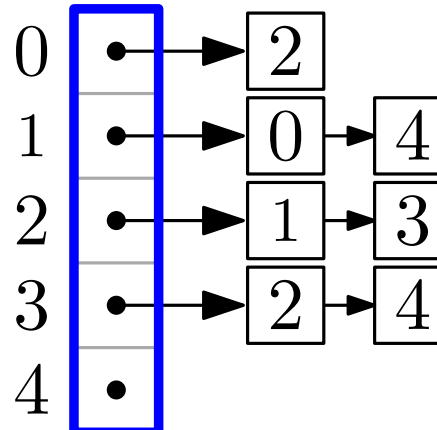
## OutEdgeList

Container used to store the outgoing edges from a vertex



## VertexList

Container used to store vertices



## Directivity

- directedS
- undirectedS
- bidirectionalS

(directed with efficient access to incoming edges. Twice the space.)

# Constructing a Graph

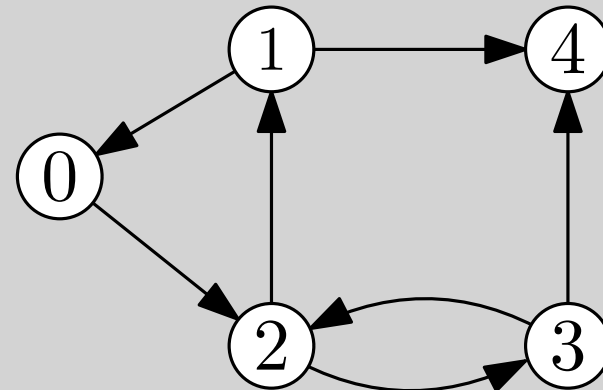
```
#include <boost/graph/adjacency_list.hpp>

typedef boost::adjacency_list<boost::vecS, boost::vecS,
                             boost::directedS> Graph;

int main()
{
    Graph G(5);

    boost::add_edge(0, 2, G);
    boost::add_edge(1, 0, G);
    boost::add_edge(1, 4, G);
    boost::add_edge(2, 1, G);
    boost::add_edge(2, 3, G);
    boost::add_edge(3, 2, G);
    boost::add_edge(3, 4, G);

    [...]
}
```



# Vertex and Edge descriptors

- Vertices and edges are accessed through handles, called vertex descriptors and edge descriptors.
  - They can be, e.g., iterators to the inner collections used by the implementation.
  - Descriptors are **opaque!** You should never explicitly access or manipulate their value!
- `boost::graph_traits<Graph>::edge_descriptor`
- `boost::graph_traits<Graph>::vertex_descriptor`
- **Exception:** If `VertexList` is of type `vecS`, the vertex descriptor is an integral type that stores indices from 0 to `boost::num_vertices(G)-1`.

# Accessing the edges of $G$

```
#include <boost/graph/adjacency_list.hpp>
#include <boost/graph/graph_traits.hpp>

typedef boost::adjacency_list<boost::vecS, boost::vecS,
                             boost::directedS> Graph;
typedef boost::graph_traits<Graph> GT;

int main()
{
    Graph G(5);

    [...]

    std::pair<GT::edge_iterator, GT::edge_iterator> eit;
    for(eit = boost::edges(G); eit.first != eit.second; eit.first++)
    {
        std::cout << "Edge_from_" << boost::source(*eit.first, G)
                  << "_to_" << boost::target(*eit.first, G) << "\n";
    }

    [...]
}
```



# Accessing the edges of $G$

```
#include <boost/graph/adjacency_list.hpp>
#include <boost/graph/graph_traits.hpp>

typedef boost::adjacency_list<boost::vecS, boost::vecS,
                             boost::directedS> Graph;

int main()
{
    Graph G(5);

    [...]

    for(auto [eit, eend] = boost::edges(G); eit != eend; eit++)
    {
        std::cout << "Edge_from_" << boost::source(*eit, G)
                  << "_to_" << boost::target(*eit, G) << "\n";
    }

    [...]
}
```

# Accessing the edges of $G$

```
#include <boost/graph/adjacency_list.hpp>
```

```
#include <boost/graph/graph_traits.hpp>
```

```
typ
```

```
$ g++ -std=c++17 graph_example.cpp -o graph_example
```

```
$
```

```
$ ./graph_example
```

```
int
```

```
Edge from 0 to 2
```

```
{
```

```
Edge from 1 to 0
```

```
Edge from 1 to 4
```

```
Edge from 2 to 1
```

```
Edge from 2 to 3
```

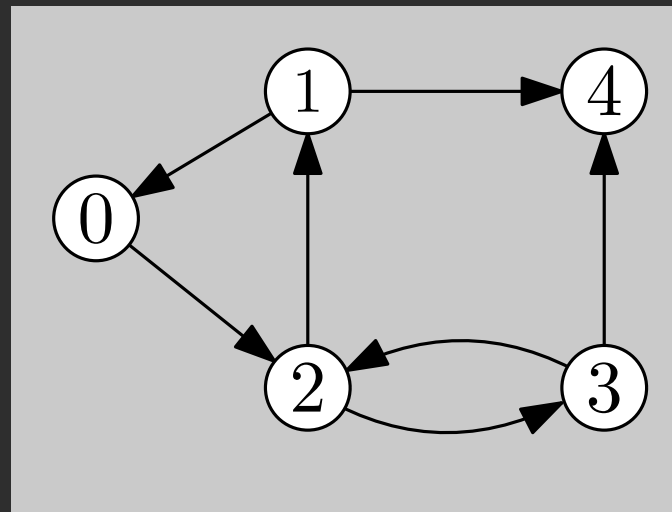
```
Edge from 3 to 2
```

```
Edge from 3 to 4
```

```
$
```

```
}
```

```
h;
```



# Accessing neighbors/out-edges

```
#include <boost/graph/adjacency_list.hpp>
#include <boost/graph/graph_traits.hpp>

typedef boost::adjacency_list<boost::vecS, boost::vecS,
                             boost::directedS> Graph;

int main()
{
    Graph G(5);

    [...]

    //boost::edges(vertex, G) returns a
    //std::pair<GT::out_edge_iterator, GT::out_edge_iterator>
    for(auto [eit, eend] = boost::out_edges(2, G); eit != eend; eit++)
    {
        std::cout << "Out_␣edge_␣from_␣" << boost::source(*eit, G)
                  << "␣to_␣" << boost::target(*eit, G) << "\n";
    }

    [...]
}
```

# Accessing neighbors/out-edges

```
#include <boost/graph/adjacency_list.hpp>
```

```
#include <boost/graph/graph_traits.hpp>
```

```
typ
```

```
$ g++ -std=c++17 graph_example.cpp -o graph_example
```

```
$
```

```
$ ./graph_example
```

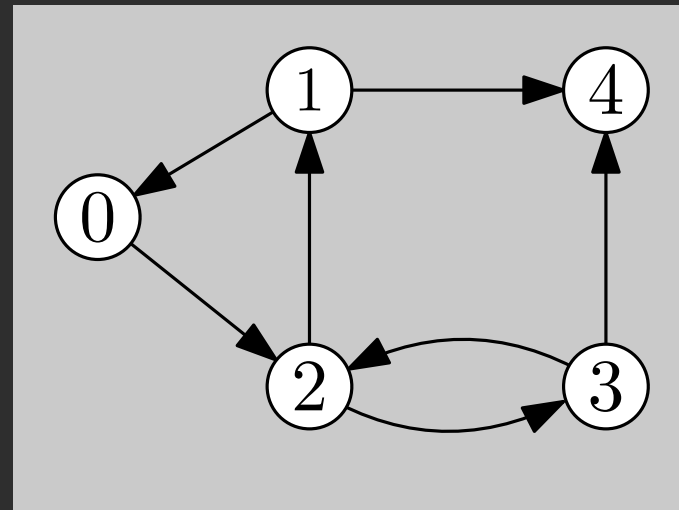
```
int
```

```
Out edge from 2 to 1
```

```
{
```

```
Out edge from 2 to 3
```

```
$
```



```
[...]
```

```
}
```

# Attaching information to edges/vertices

Internal properties:

```
typedef boost::adjacency_list<boost::vecS, boost::vecS, boost::directedS,  
    boost::no_property, boost::no_property> Graph;
```

Vertex properties

Edge properties

A graph with edge weights

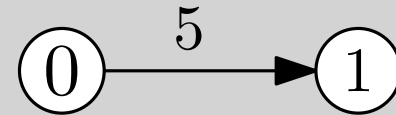
```
typedef boost::adjacency_list<boost::vecS, boost::vecS, boost::directedS,  
    boost::no_property, boost::property<boost::edge_weight_t, int>>  
    Graph;
```

- `edge_weight_t` is a “property tag”: it is one of several predefined property “names”, and is used to access the property values.
- `int` is the type of our property: in our example we are going to use integer weights.

# Accessing edge/vertex properties

```
typedef boost::adjacency_list<boost::vecS, boost::vecS, boost::directedS,  
    boost::no_property, boost::property<boost::edge_weight_t, int>>  
    Graph;  
typedef boost::graph_traits<Graph> GT;  
typedef boost::property_map<Graph, boost::edge_weight_t>::type weight_map;
```

```
int main()  
{  
    Graph G(2);  
  
    weight_map weights = boost::get(boost::edge_weight, G);  
  
    std::pair<GT::edge_descriptor, bool> e = boost::add_edge(0,1,G);  
    weights[e.first] = 5;  
}
```



# Accessing edge/vertex properties

```
int main()
{
    Graph G(5);
    weight_map weights = boost::get(edge_weight, G);

    [...]

    for(auto [eit, eend] = boost::edges(G); eit != eend; eit++)
    {
        std::cout << "Edge_from_" << boost::source(*eit, G)
                  << "_to_" << boost::target(*eit, G)
                  << "_with_weight_" << weights[*eit] << "\n";
    }

    [...]
}
```

# (Some) BGL Algorithms



# Topological Sort

```
void topological_sort(G, result);
```

- result is an output iterator.
- Vertices will be written to result in **reverse** topological order.

```
#include <boost/graph/topological_sort.hpp>
```

```
Graph G; [...]
```

```
std::vector<GT::vertex_descriptor> rev_order;
```

```
boost::topological_sort(G, std::back_inserter(rev_order));
```

```
for(auto it = rev_order.rbegin(); it!=rev_order.rend(); it++)
```

```
    std::cout << *it << "␣";
```

Time:  $O(n + m)$

# Topological Sort

```
void topological_sort(G, result);
```

- `$ g++ -std=c++17 ts.cpp -o ts`
  - `$`
  - `$ ./ts`
- ```
#in 1 0 2 3 4  
$
```

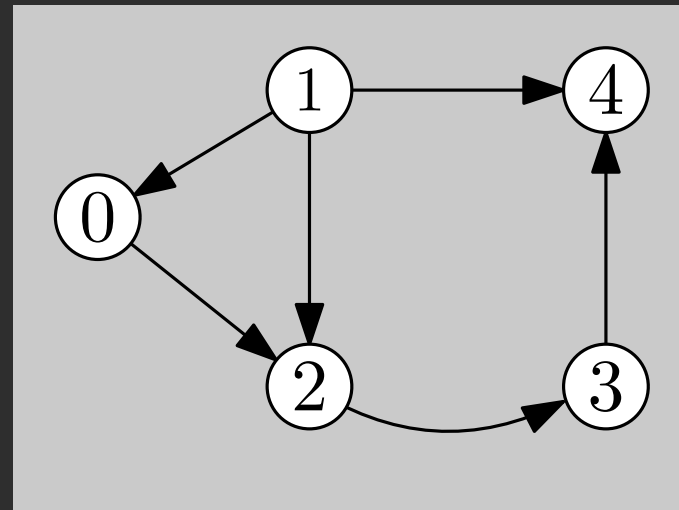
#in

Gr

std

boo

for



Time:  $O(n + m)$

# External Properties

It is also possible to store vertex/edge properties in external collections.

**Example:** Associate an integer to each vertex.

```
std::vector<int> my_prop(boost::num_vertices(G));
```

Tell boost that `my_property` can be indexed with using vertices' indices.

```
make_iterator_property_map(my_prop.begin(), get(boost::vertex_index, G));
```

- The graph has a default interval property with tag `vertex_index_t`.
- It maps vertex descriptors to a vertex index from 0 to `boost::num_vertices(G)-1`.

# Connected Components

```
connected_components(G, comp);
```

- Each component will be indexed with a distinct integer.
- The return value is the number of components.
- comp maps each vertex to the index of its component.

```
#include <boost/graph/connected_components.hpp>
```

```
Graph G; [...]
```

```
std::vector<GT::vertices_size_type> comp(boost::num_vertices(G));  
boost::connected_components(G,  
    make_iterator_property_map(comp.begin(),  
    get(boost::vertex_index, G)));
```

```
for(int i=0; i<boost::num_vertices(G); i++)  
    std::cout << "Vertex_" << i  
        << "_is_in_component_" << comp[i] << "\n";
```

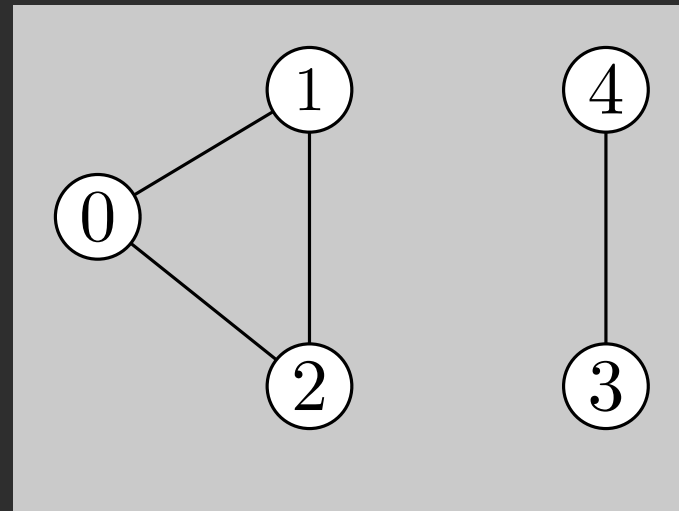
Time:  $O(n + m)$

# Connected Components

```
connected_components(G, comp);
```

- ```
$ g++ -std=c++17 cc.cpp -o cc
```
- ```
$
```
- ```
$ ./cc
```

```
#include <graph>
using namespace graph;
int main() {
    std::vector<int> comp;
    for (int i = 0; i < 5; i++) {
        Vertex i is in component 0
    }
    for (int i = 0; i < 5; i++) {
        Vertex 1 is in component 0
    }
    for (int i = 0; i < 5; i++) {
        Vertex 2 is in component 0
    }
    for (int i = 0; i < 5; i++) {
        Vertex 3 is in component 1
    }
    for (int i = 0; i < 5; i++) {
        Vertex 4 is in component 1
    }
}
```



Time:  $O(n + m)$

# Strongly Connected Components

```
strong_components(G, comp);
```

- Each component will be indexed with a distinct integer.
- The return value is the number of components.
- comp maps each vertex to the index of its component.

```
#include <boost/graph/strong_components.hpp>
```

```
Graph G; [...]
```

```
std::vector<GT::vertices_size_type> comp(boost::num_vertices(G));  
boost::strong_components(G,  
    make_iterator_property_map(comp.begin(),  
    get(boost::vertex_index, G)));
```

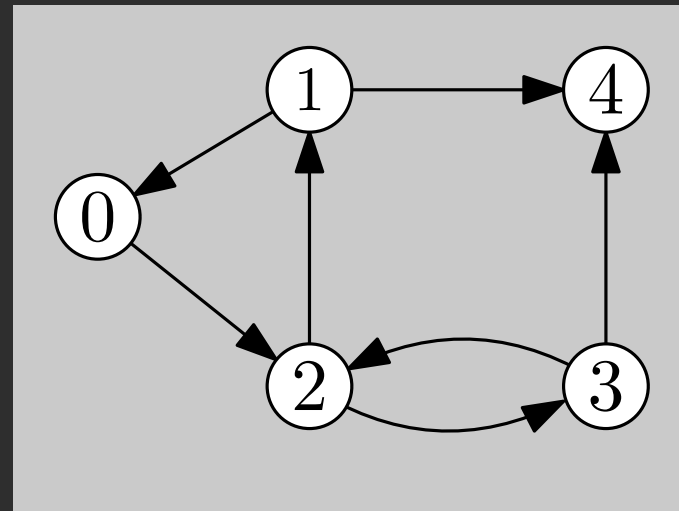
```
for(int i=0; i<boost::num_vertices(G); i++)  
    std::cout << "Vertex_" << i  
        << "_is_in_component_" << comp[i] << "\n";
```

Time:  $O(n + m)$

# Strongly Connected Components

```
strong_components(G, comp);
```

```
• $ g++ -std=c++17 scc.cpp -o scc  
• $  
• $ ./scc  
#include <vector>  
#include <string>  
using namespace std;  
vector<int> comp;  
for (int i = 0; i < n; i++)  
    comp[i] = 0;  
void strong_components(int u, int c) {  
    comp[u] = c;  
    for (int v : G[u])  
        strong_components(v, c);  
}
```



Time:  $O(n + m)$

# Named parameters

To avoid long list of positional parameters to functions, BGL uses *named parameters*.

It uses wrapper classes to match arguments to parameters based on names

Arguments can be passed in any order

Arguments are concatenated using a dot . instead of a comma (formally this is a call to a method).

A made-up example:

```
graph_algo(G, root_vertex(v).color(c).weight(w));
```



# Strongly Connected Components

```
strong_components(G, comp, named_params...);
```

- One of the named parameters `strong_components` is `root_map`
- For each SCC  $C$ , the algorithm picks a unique representative vertex  $v_C \in C$

Named parameters:

- `root_map` maps each vertex  $u$  of  $G$  to the representative vertex  $v_C$  of the SCC  $C$  containing  $u$ .

# Strongly Connected Components

```
strong_components(G, comp, named_params...);
```

```
#include <boost/graph/strong_components.hpp>
```

```
Graph G; [...]
```

```
std::vector<GT::vertices_size_type> comp(boost::num_vertices(G));
```

```
std::vector<GT::vertex_descriptor> roots(boost::num_vertices(G));
```

```
boost::strong_components(G,  
    make_iterator_property_map(comp.begin(),  
        get(boost::vertex_index, G)),  
    root_map(make_iterator_property_map(roots.begin(),  
        get(boost::vertex_index, G))));
```

```
for(int i=0; i<boost::num_vertices(G); i++)  
    std::cout << "The representative of the SCC of vertex "  
        << i  
        << " is " << roots[i] << "\n";
```

# Strongly Connected Components

```
strong_components(G, comp, named_params...);
```

```
#include <string>
using namespace std;
int main() {
    Graph G(5);
    G.addEdge(0, 1);
    G.addEdge(1, 4);
    G.addEdge(4, 3);
    G.addEdge(3, 2);
    G.addEdge(2, 0);
    G.addEdge(2, 3);
    G.addEdge(3, 2);
    for (int i = 0; i < G.V(); i++) {
        cout << "The representative of the SCC of vertex " << i << " is ";
        int r = strong_components(G, comp, {"named_params"});
        cout << r << endl;
    }
}
```

```
Graph G(5);
```

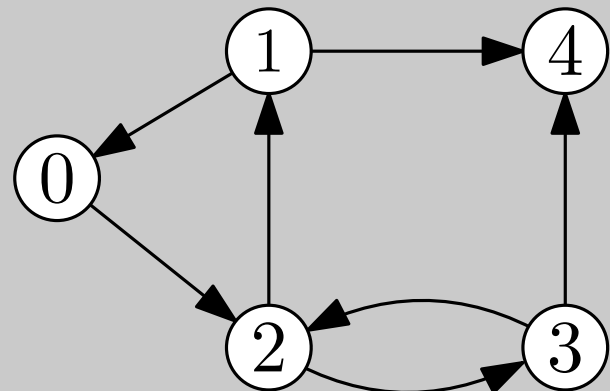
```
cout << "The representative of the SCC of vertex 0 is 0
```

```
cout << "The representative of the SCC of vertex 1 is 0
```

```
cout << "The representative of the SCC of vertex 2 is 0
```

```
cout << "The representative of the SCC of vertex 3 is 0
```

```
cout << "The representative of the SCC of vertex 4 is 4
```



# Example: 2-SAT

$$\phi = (x_1 \vee \overline{x_2}) \wedge (x_2 \vee x_4) \wedge (\overline{x_1} \vee \overline{x_3}) \wedge (x_3 \vee x_4) \wedge (\overline{x_1} \vee \overline{x_4})$$

## Input:

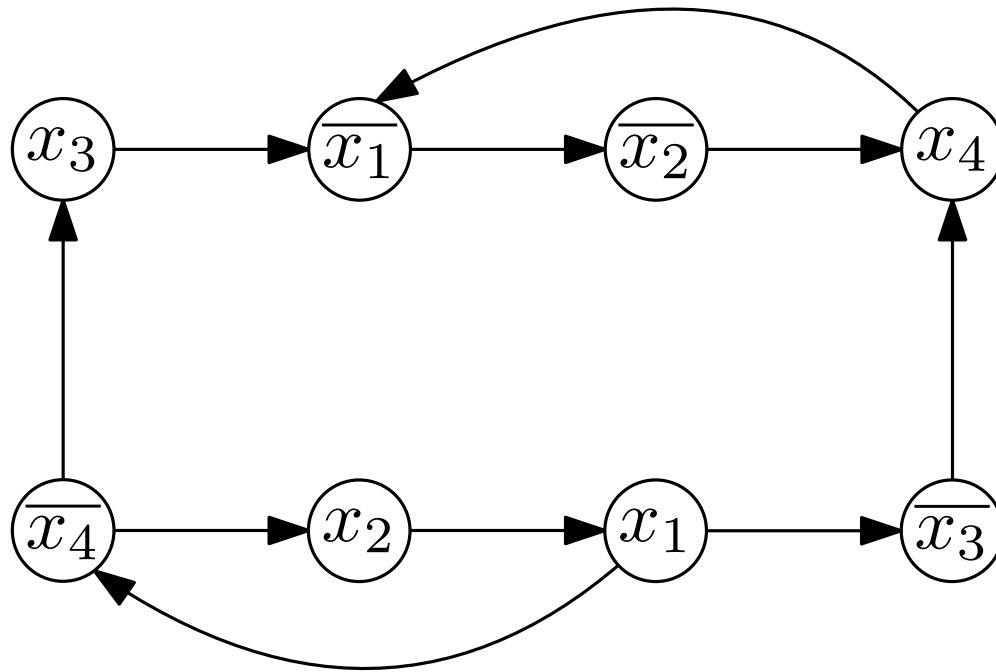
- $n$ : number of variables,  $m$ : number of clauses
- $m$  pairs  $(i, j)$  with  $i, j \neq 0$ .  
A pair  $(i, j)$  represents a clause  $(a \vee b)$ . If  $i > 0$  then  $a = x_i$ .  
If  $i < 0$  then  $a = \overline{x_{-i}}$ .  $b$  is defined similarly from  $j$ .

```
4 5
1 -2
2 4
-1 -3
3 4
-1 -4
```

**Output:** True if  $\phi$  is satisfiable. Otherwise false.

# Example: 2-SAT

**Corollary (from last lecture):**  $\phi$  is satisfiable iff  $\forall x_i, x_i$  and  $\overline{x_i}$  belong to different SCCs of the implication graph  $G_\phi$ .



$$\phi = (x_1 \vee \overline{x_2}) \wedge (x_2 \vee x_4) \wedge (\overline{x_1} \vee \overline{x_3}) \wedge (x_3 \vee x_4) \wedge (\overline{x_1} \vee \overline{x_4})$$

# Example: 2-SAT

```
typedef boost::adjacency_list<boost::vecS, boost::vecS,  
                             boost::directedS> Graph;  
  
//Maps each literal to an id between 0 and 2n-1  
int to_vertex_id(int i){ return (i>0)?(2*i-2):(-2*i-1); }  
  
int solve()  
{  
    int n,m;  
    std::cin >> n >> m;  
  
    Graph G(2*n);  
    for(int i=0; i<m; i++)  
    {  
        int x, y;  
        std::cin >> x >> y;  
  
        boost::add_edge(to_vertex_id(-x), to_vertex_id(y), G);  
        boost::add_edge(to_vertex_id(-y), to_vertex_id(x), G);  
    }  
}
```

# Example: 2-SAT

```
std::vector<int> comp(boost::num_vertices(G));
boost::strong_components(G,
    boost::make_iterator_property_map(comp.begin(),
        get(boost::vertex_index, G)));

for(int i=1; i<=n; i++)
    if(comp[to_vertex_id(i)] == comp[to_vertex_id(-i)])
        return false;

return true;
}

int main()
{
    std::cout << (solve()?"Satisfiable\n":"Not_satisfiable\n");

    return EXIT_SUCCESS;
}
```

# Single Source Distances: Dijkstra

```
void dijkstra_shortest_paths(G, v, named_params...);
```

- Runs Dijkstra's algorithm from vertex  $v$ .

Named parameters:

- `weight_map` (input): maps edges to their weight. Default: internal map with tag `boost::edge_weight_t`
- `distance_map` (output). maps each vertex with its distance from  $v$ . `boost::edge_weight_t`
- `predecessor_map` (output). maps each vertex  $u$  to (the vertex descriptor of) its parent  $p_u$  in the shortest path tree from  $v$ . If  $u$  is unreachable from  $v$ , or  $u = v$ , sets  $p_u = u$ .

Time:  $O(m + n \log n)$



# Single Source Distances: Dijkstra

```
void dijkstra_shortest_paths(G, v, named_params...);
```

```
#include <boost/graph/dijkstra_shortest_paths.hpp>
```

```
Graph G; [...]
```

```
std::vector<int> dist(boost::num_vertices(G));
```

```
std::vector<GT::vertex_descriptor> pred(boost::num_vertices(G));
```

```
boost::dijkstra_shortest_paths(G, 0,  
    distance_map(make_iterator_property_map(dist.begin(),  
        get(boost::vertex_index, G)))  
    .predecessor_map(make_iterator_property_map(pred.begin(),  
        get(boost::vertex_index, G))));
```

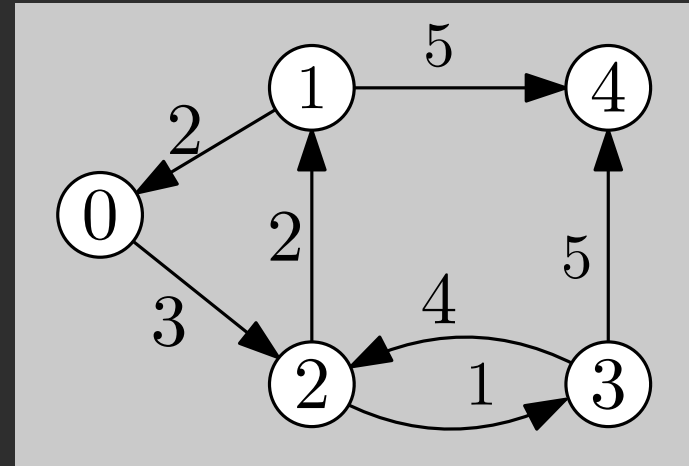
```
for(int i=0; i<boost::num_vertices(G); i++)  
    std::cout << "Distance_␣to_␣" << i << ":_␣" << dist[i]  
        << "_Parent:_␣" << pred[i] << "\n";
```

Time:  $O(m + n \log n)$

# Single Source Distances: Dijkstra

```
void dijkstra_shortest_paths(G, v, named_params...);
```

```
#include <...>
int main() {
    $ g++ -std=c++17 dijkstra.cpp -o dijkstra
    $
    Gra $ ./dijkstra
    Distance to 0: 0 Parent: 0
    sto Distance to 1: 5 Parent: 2
    sto Distance to 2: 3 Parent: 0
    boo Distance to 3: 4 Parent: 2
    for Distance to 4: 9 Parent: 3
}
```



Time:  $O(m + n \log n)$

# Single Source Distances in DAGs

```
void dag_shortest_paths(G, v, named_params...);
```

- Compute the the distances / SPT from  $v$  in a directed acyclic graph.

Named parameters:

- `weight_map` (input): maps edges to their weight. Default: internal map with tag `boost::edge_weight_t`
- `distance_map` (output). maps each vertex with its distance from  $v$ . `boost::edge_weight_t`
- `predecessor_map` (output). maps each vertex  $u$  to (the vertex descriptor of) its parent  $p_u$  in the shortest path tree from  $v$ . If  $u$  is unreachable from  $v$ , or  $u = v$ , sets  $p_u = u$ .

Time:  $O(m + n)$

# Single Source Distances in DAGs

```
void dag_shortest_paths(G, v, named_params...);

#include <boost/graph/dag_shortest_paths.hpp>

Graph G; [...]

std::vector<int> dist(boost::num_vertices(G));
std::vector<GT::vertex_descriptor> pred(boost::num_vertices(G));

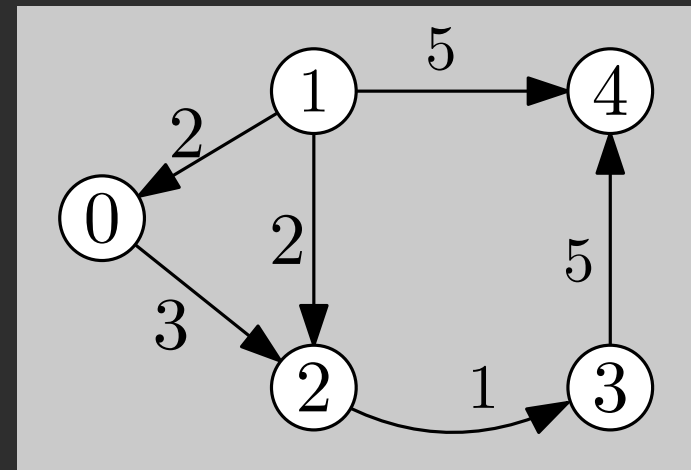
boost::dag_shortest_paths(G, 0,
    distance_map(make_iterator_property_map(dist.begin(),
        get(vertex_index, G))),
    predecessor_map(make_iterator_property_map(pred.begin(),
        get(vertex_index, G))));

for(int i=0; i<boost::num_vertices(G); i++)
    std::cout << "Distance_ to_" << i << ":_ " << dist[i]
        << "_Parent:_ " << pred[i] << "\n";
```

Time:  $O(m + n)$

# Single Source Distances in DAGs

```
voi  
$ g++ -std=c++17 dag_sp.cpp -o dag_sp  
#in  
$ ./dag_sp  
Gra Distance to 0: 0 Parent: 0  
sto Distance to 1: 2147483647 Parent: 1  
sto Distance to 2: 3 Parent: 0  
boo Distance to 3: 4 Parent: 2  
for Distance to 4: 9 Parent: 3
```



```
<< "  Parent:  " << pred[1] << "\n";
```

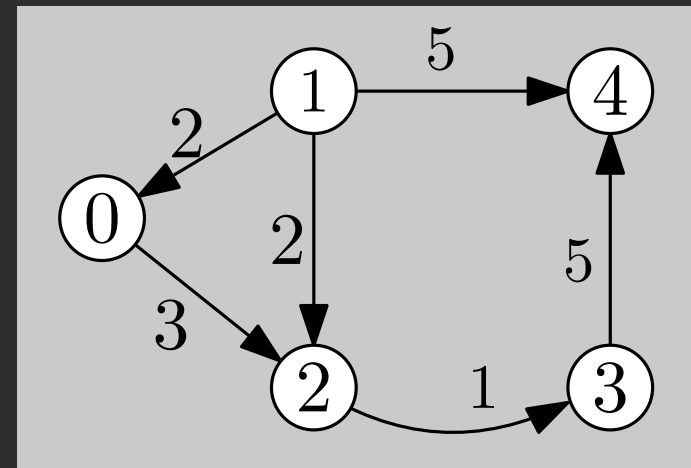
Time:  $O(m + n)$

# Single Source Distances in DAGs

```
voi $ g++ -std=c++17 dag_sp.cpp -o dag_sp
#in $
Gra Distance to 0: 0 Parent: 0
sto Distance to 1: 2147483647 Parent: 1
sto Distance to 2: 3 Parent: 0
boo Distance to 3: 4 Parent: 2
    Distance to 4: 9 Parent: 3
```

unreachable

```
std::numeric_limits<int>::max()
```



```
<< "  Parent:  " << pred[1] << "\n";
```

Time:  $O(m + n)$

# Single Source Distances: Bellman-Ford

```
bool bellman_ford_shortest_paths(G, named_params...);
```

- Runs Bellman-Ford's algorithm.
- Returns true iff all distance from  $s$  are finite (no negative cycle found).

Named parameters:

- `root_vertex` (input). The source vertex.
- `weight_map` (input): maps edges to their weight. Default: internal map with tag `boost::edge_weight_t`
- `distance_map` (output). maps each vertex with its distance from  $v$ . `boost::edge_weight_t`
- `predecessor_map` (output). maps each vertex  $u$  to (the vertex descriptor of) its parent  $p_u$  in the shortest path tree from  $v$ . If  $u$  is unreachable from  $v$ , or  $u = v$ , sets  $p_u = u$ .

Time:  $O(nm)$

# Single Source Distances: Bellman-Ford

```
bool bellman_ford_shortest_paths(G, named_params...);
```

```
#include <boost/graph/bellman_ford_shortest_paths.hpp>
```

```
Graph G; [...]
```

```
std::vector<int> dist(boost::num_vertices(G));
```

```
std::vector<GT::vertex_descriptor> pred(boost::num_vertices(G));
```

```
boost::bellman_ford_shortest_paths(G, root_vertex(0)  
    .distance_map(make_iterator_property_map(dist.begin(),  
        get(vertex_index, G)))  
    .predecessor_map(make_iterator_property_map(pred.begin(),  
        get(vertex_index, G))));
```

```
for(int i=0; i<boost::num_vertices(G); i++)  
    std::cout << "Distance_ to_" << i << ":_ " << dist[i]  
        << "_Parent:_ " << pred[i] << "\n";
```

Time:  $O(nm)$



# All to All Distances: Floyd-Warshall

```
bool floyd_warshall_all_pairs_shortest_paths(G, matrix, named_params...);
```

- Runs Floyd-Warshall's algorithm.
- Returns true iff there is no negative-weight cycle in  $G$ .
- `matrix` stores the computed distance matrix of  $G$ .  
`matrix[i][j]` must return a mutable reference, where `i` and `j` are vertex descriptors.

Named parameters:

- `weight_map` (input): maps edges to their weight. Default: internal map with tag `boost::edge_weight_t`

Time:  $O(n^3)$

# All to All Distances: Floyd-Warshall

```
bool floyd_warshall_all_pairs_shortest_paths(G, matrix, named_params...);
```

```
#include <boost/graph/floyd_warshall_shortest.hpp>
```

```
Graph G; [...]
```

```
// n x n matrix of int
```

```
std::vector<std::vector<int>> M(boost::num_vertices(G),  
                               std::vector<int>(boost::num_vertices(G)));
```

```
boost::floyd_warshall_all_pairs_shortest_paths(G, M);
```

```
for(auto row : M)
```

```
{
```

```
    for(int d : row)
```

```
        std::cout << d << "□";
```

```
    std::cout << "\n";
```

```
}
```

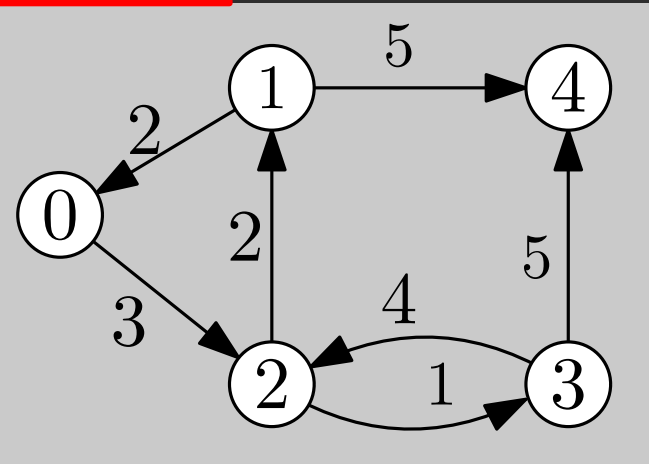
Time:  $O(n^3)$

# All to All Distances: Floyd-Warshall

```
bool floyd_warshall_all_pairs_shortest_paths(G, matrix, named_params...);
```

```
#include <string>
using namespace std;
int main() {
    Graph G(5);
    // Add edges
    G.addEdge(0, 1, 5);
    G.addEdge(0, 2, 3);
    G.addEdge(0, 4, 9);
    G.addEdge(1, 2, 2);
    G.addEdge(1, 4, 5);
    G.addEdge(2, 0, 4);
    G.addEdge(2, 3, 1);
    G.addEdge(2, 4, 6);
    G.addEdge(3, 2, 4);
    G.addEdge(3, 4, 5);
    G.addEdge(4, 0, 8);
    G.addEdge(4, 1, 6);
    G.addEdge(4, 2, 0);
    G.addEdge(4, 3, 5);
    // Print shortest paths
    for (int i = 0; i < G.V(); i++)
        for (int j = 0; j < G.V(); j++)
            cout << G.shortestPath(i, j) << " ";
    cout << endl;
}
```

```
for (int i = 0; i < G.V(); i++)
{
    std::numeric_limits<int>::max()
}
```



Time:  $O(n^3)$

# Minimum Spanning Trees: Kruskal

```
kruskal_minimum_spanning_tree(G, result, named_params...);
```

- Runs Kruskal's MST algorithm.
- `result` is an output iterator.
- Edges of the MST are written to `result`.

Named parameters:

- `weight_map` (input): maps edges to their weight. Default: internal map with tag `boost::edge_weight_t`

Time:  $O(m \log n)$

# Minimum Spanning Trees: Kruskal

```
kruskal_minimum_spanning_tree(G, result, named_params...);
```

```
#include <boost/graph/kruskal_min_spanning_tree.hpp>
```

```
Graph G; [...]
```

```
std::vector<GT::edge_descriptor> edges;
```

```
boost::kruskal_minimum_spanning_tree(G, std::back_inserter(edges));
```

```
for(GT::edge_descriptor e : edges)
```

```
    std::cout << "Edge_from_" << boost::source(e, G)
```

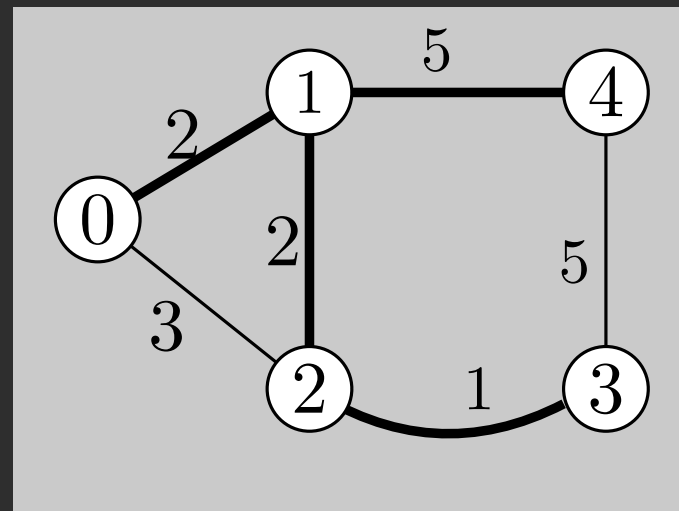
```
        << "_to_" << boost::target(e, G) << "\n";
```

Time:  $O(m \log n)$

# Minimum Spanning Trees: Kruskal

```
kruskal_minimum_spanning_tree(G, result, named_params...);
```

```
#include <...>
using namespace std;
int main() {
    Graph G(5);
    G.add_edge(2, 3, 3);
    G.add_edge(1, 2, 2);
    G.add_edge(1, 0, 2);
    G.add_edge(1, 4, 5);
    G.add_edge(2, 3, 1);
    G.add_edge(1, 4, 5);
    G.add_edge(2, 3, 5);
    kruskal_minimum_spanning_tree(G, result, named_params...);
    for (int i = 0; i < result.size(); i++) {
        cout << "Edge from " << result[i].u << " to " << result[i].v << endl;
    }
}
```



Time:  $O(m \log n)$

# Minimum Spanning Trees: Prim

```
prim_minimum_spanning_tree(G, pred, named_params...);
```

- Runs Prim's MST algorithm.
- `pred` (output). maps each vertex  $u$  to (the vertex descriptor of) its parent  $p_u$  in the (rooted) MST. If  $u$  is the root or is unreachable then  $p_u = u$ .

Named parameters:

- `weight_map` (input): maps edges to their weight. Default: internal map with tag `boost::edge_weight_t`
- `root_vertex` (input). The root vertex of the MST. Default: the first vertex.

Time:  $O(m \log n)$

# Minimum Spanning Trees: Prim

```
prim_minimum_spanning_tree(G, pred, named_params...);
```

```
#include <boost/graph/prim_min_spanning_tree.hpp>
```

```
Graph G; [...]
```

```
std::vector<GT::vertex_descriptor> pred(boost::num_vertices(G));
```

```
boost::prim_minimum_spanning_tree(G,  
    make_iterator_property_map(pred.begin(),  
        get(boost::vertex_index, G)),  
    boost::root_vertex(0));
```

```
for(int i=0; i<boost::num_vertices(G); i++)  
    std::cout << "Parent_of_" << i << ":_"  
        << pred[i] << "\n";
```

Time:  $O(m \log n)$



# Minimum Spanning Trees: Prim

```
prim_minimum_spanning_tree(G, pred, named_params...);
```

```
#include
```

```
$ g++ -std=c++17 prim.cpp -o prim
```

```
Graph
```

```
$
```

```
$ ./prim
```

```
std::
```

```
Parent of 0: 0
```

```
Parent of 1: 0
```

```
book
```

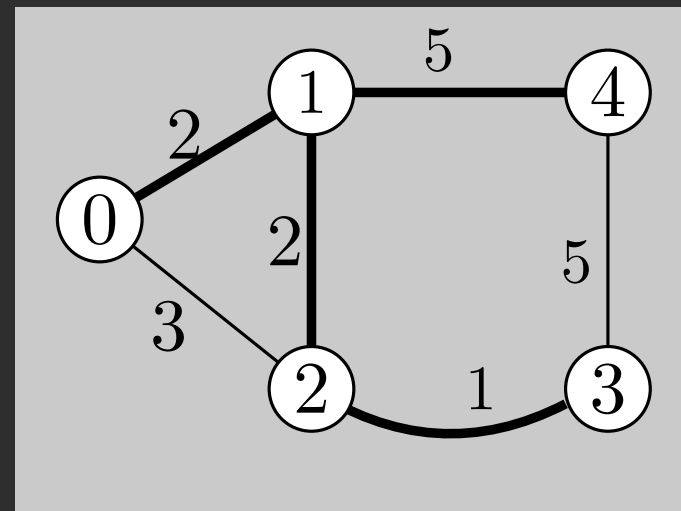
```
Parent of 2: 1
```

```
Parent of 3: 2
```

```
Parent of 4: 1
```

```
$
```

```
for
```



Time:  $O(m \log n)$

# Breadth First Search

```
breadth_first_search(G, r, bfs_visitor);
```

- Performs a BFS visit of the graph from vertex  $r$ .
- Generates “events” during the visit.
- Events are dispatched by invoking methods of a custom `bfs_visitor` object.

Some events:

- `discover_vertex(v, G)`: A new vertex  $v$  is discovered.
- `examine_vertex(v, G)`: Vertex  $v$  is visited.
- `examine_edge(e, G)`: An edge  $e$  is examined.
- `finish_vertex(v, G)`: All the outgoing edges from  $v$  have been examined.
- `tree_edge(e, G)`: An edge  $e$  of the BFS tree is discovered.
- `non_tree_edge(e, G)`: An edge  $e$  that is *not* in the BFS tree is discovered.

Time:  $O(m + n)$

# A Custom BFS Visitor

```
#include <boost/graph/breadth_first_search.hpp>

class custom_visitor : public boost::default_bfs_visitor
{
public:
    void examine_vertex(GT::vertex_descriptor u, const Graph& G)
    {
        std::cout << "Visiting_\u005Cvertex_\u005C" << u << "\n";
    }

    void tree_edge(GT::edge_descriptor e, const Graph& G)
    {
        std::cout << "Discovered_\u005Ctree_\u005Cedge_\u005Cfrom_\u005C"
            << boost::source(e, G) << "_\u005Cto_\u005C"
            << boost::target(e, G) << "\n";
    }
};
```

# Starting the BFS Visit

```
Graph G; [...]
```

```
//Create an instance of our custom visitor
```

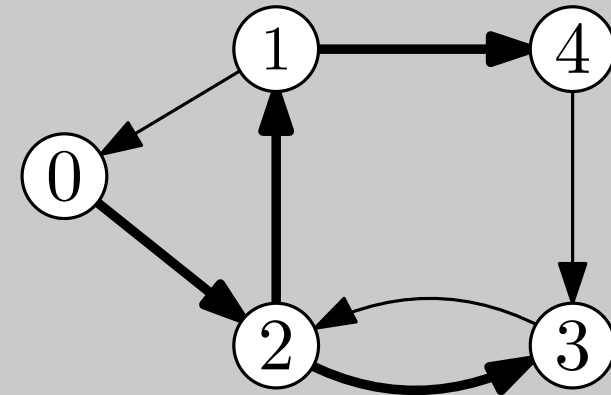
```
custom_visitor vis;
```

```
//Start the BFS visit
```

```
boost::breadth_first_search(G, 0, boost::visitor(vis));
```

# Starting the BFS Visit

```
$ g++ -std=c++17 bfs.cpp -o bfs
$
$ ./bfs
Visiting vertex 0
Discovered tree edge from 0 to 2
Visiting vertex 2
Discovered tree edge from 2 to 1
Discovered tree edge from 2 to 3
Visiting vertex 1
Discovered tree edge from 1 to 4
Visiting vertex 3
Visiting vertex 4
$
```



# Depth First Search

```
depth_first_search(G, named_params...);
```

- Performs a DFS visit of the graph.
- Generates “events” during the visit.

Named parameters:

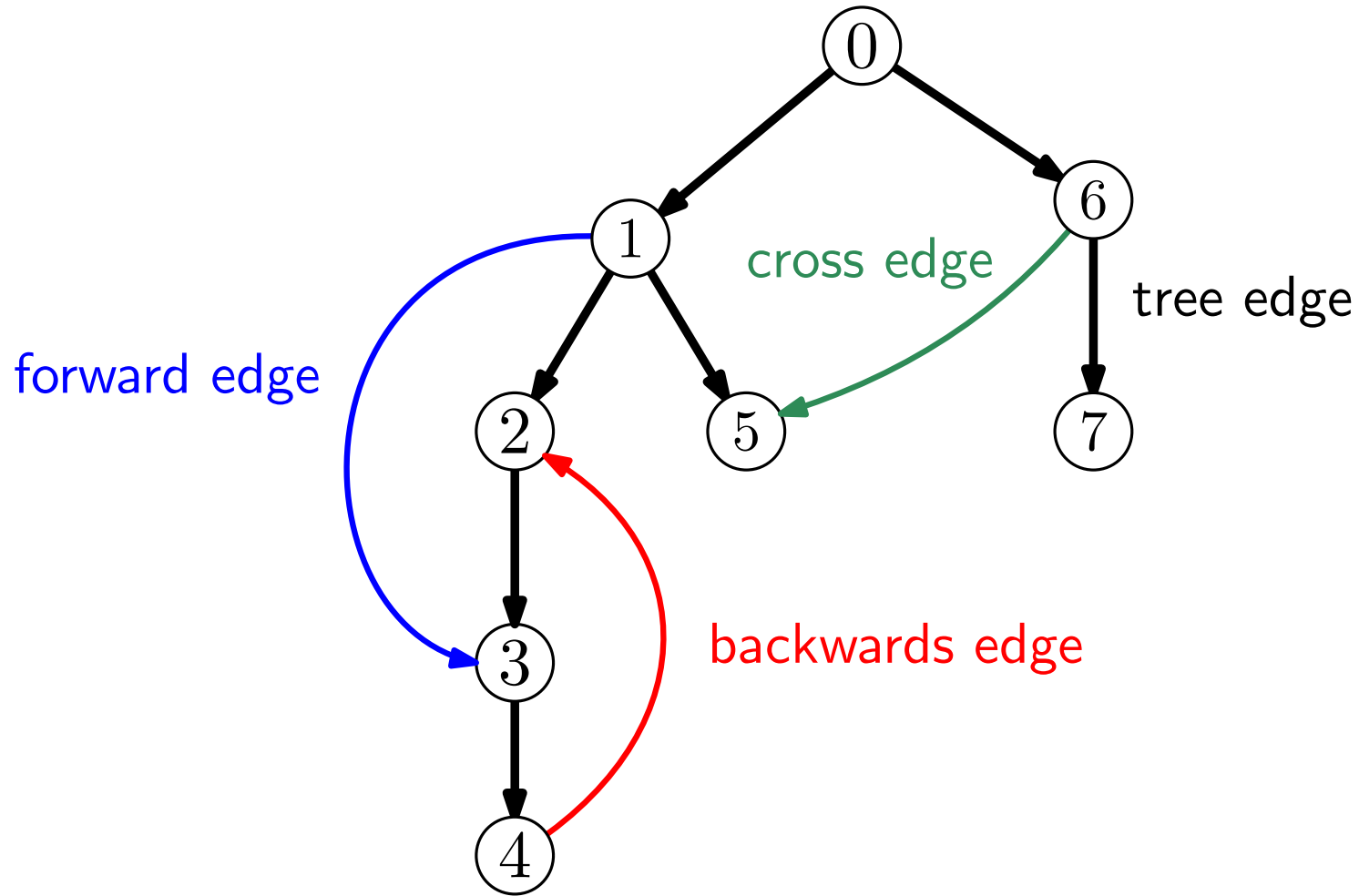
- `root_vertex` (input). The root vertex of the DFS. Default: the first vertex.
- `visitor` (input). Events are dispatched by invoking methods of a custom visitor object.

Some events:

- `discover_vertex(v, G)`: A new vertex  $v$  is discovered (visited).
- `examine_edge(e, G)`: An edge  $e$  is examined.
- `finish_vertex(v, G)`: All the neighbors of  $v$  have been examined.
- `tree_edge(e, G)`: An edge  $e$  of the DFS tree is discovered.
- `back_edge(e, G)`: A backwards edge  $e$  is discovered.
- `forward_or_cross_edge(e, G)`: A forward or cross edge  $e$  is discovered.

Time:  $O(m + n)$

# Depth First Search



# A Custom DFS Visitor

```
#include <boost/graph/depth_first_search.hpp>

class custom_visitor : public boost::default_dfs_visitor
{
public:
    void tree_edge(GT::edge_descriptor e, const Graph& G)
    {
        std::cout << "Discovered_tree_edge_from_"
                  << boost::source(e, G) << "_to_"
                  << boost::target(e, G) << "\n";
    }

    void back_edge(GT::edge_descriptor e, const Graph& G)
    {
        std::cout << "Discovered_back_edge_from_"
                  << boost::source(e, G) << "_to_"
                  << boost::target(e, G) << "\n";
    }
};
```



# Starting the DFS Visit

```
Graph G; [...]  
  
//Create an instance of our custom visitor  
custom_visitor vis;  
  
//Start the DFS visit  
boost::depth_first_search(G, boost::root_vertex(0).visitor(vis));
```

# Starting the DFS Visit

```
$ g++ -std=c++17 dfs.cpp -o dfs
$
$ ./dfs
Discovered tree edge from 0 to 2
Discovered tree edge from 2 to 1
Discovered back edge from 1 to 0
Discovered tree edge from 1 to 4
Discovered tree edge from 4 to 3
Discovered back edge from 3 to 2
$
```

