Breadth first search
Uniform cost search

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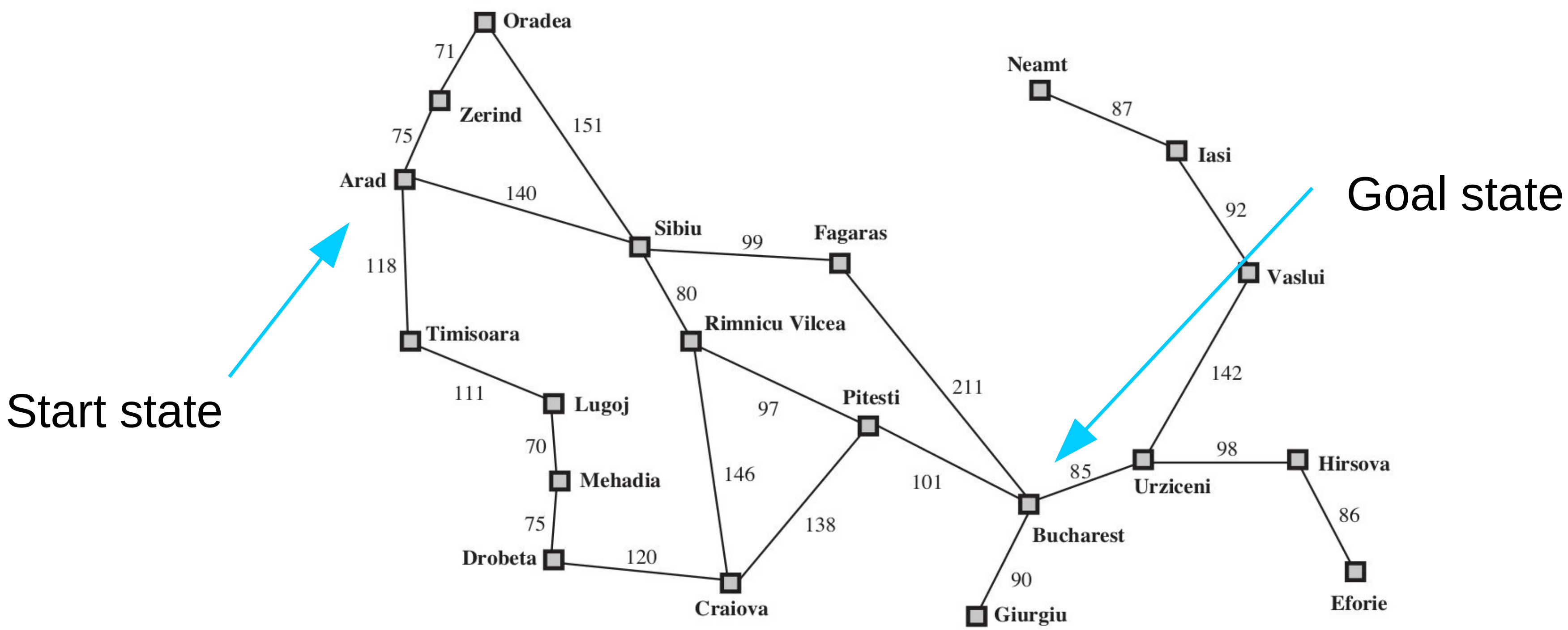
Northeastern University

Some images and slides are used from:
1. CS188 UC Berkeley
2. RN, AIMA

What is graph search?

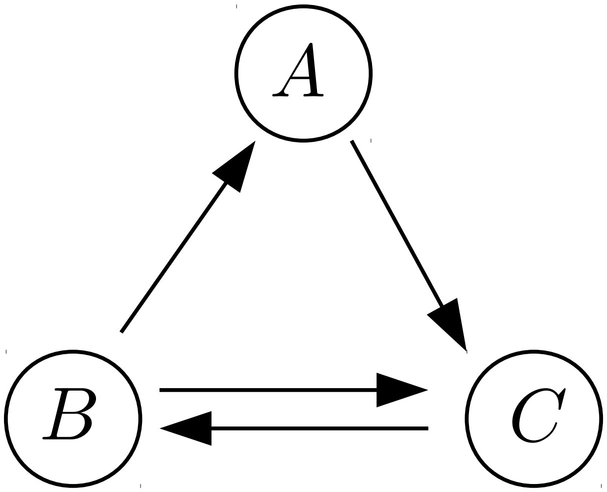


What is a graph?

Graph: $G = (V, E)$

Vertices: V

Edges: E



Directed graph

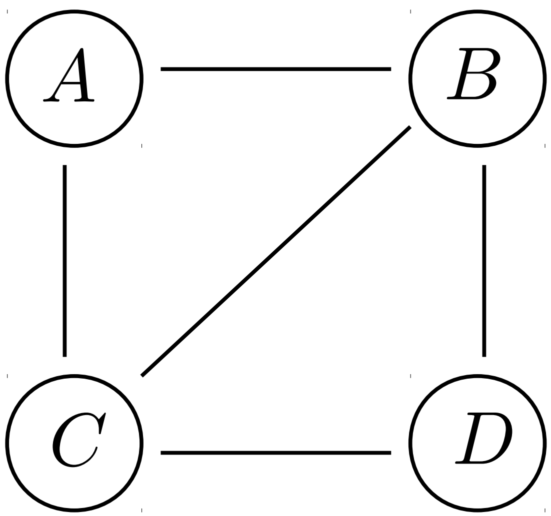
$$V = \{A, B, C\}$$
$$E = \{(B, A), (A, C), (B, C), (C, B)\}$$

What is a graph?

Graph: $G = (V, E)$

Vertices: V

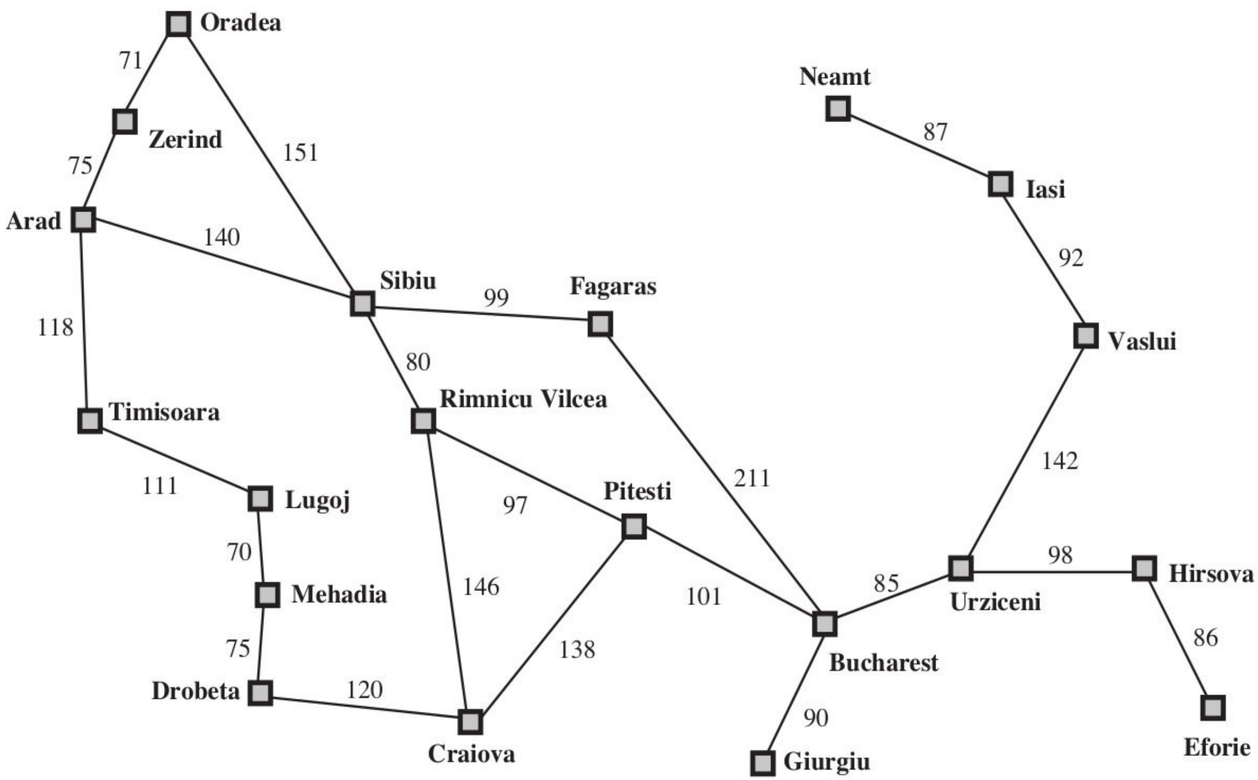
Edges: E



Undirected graph

$$V = \{A, B, C, D\}$$
$$E = \{\{A, C\}, \{A, B\}, \{C, D\}, \{B, D\}, \{C, B\}\}$$

Graph search



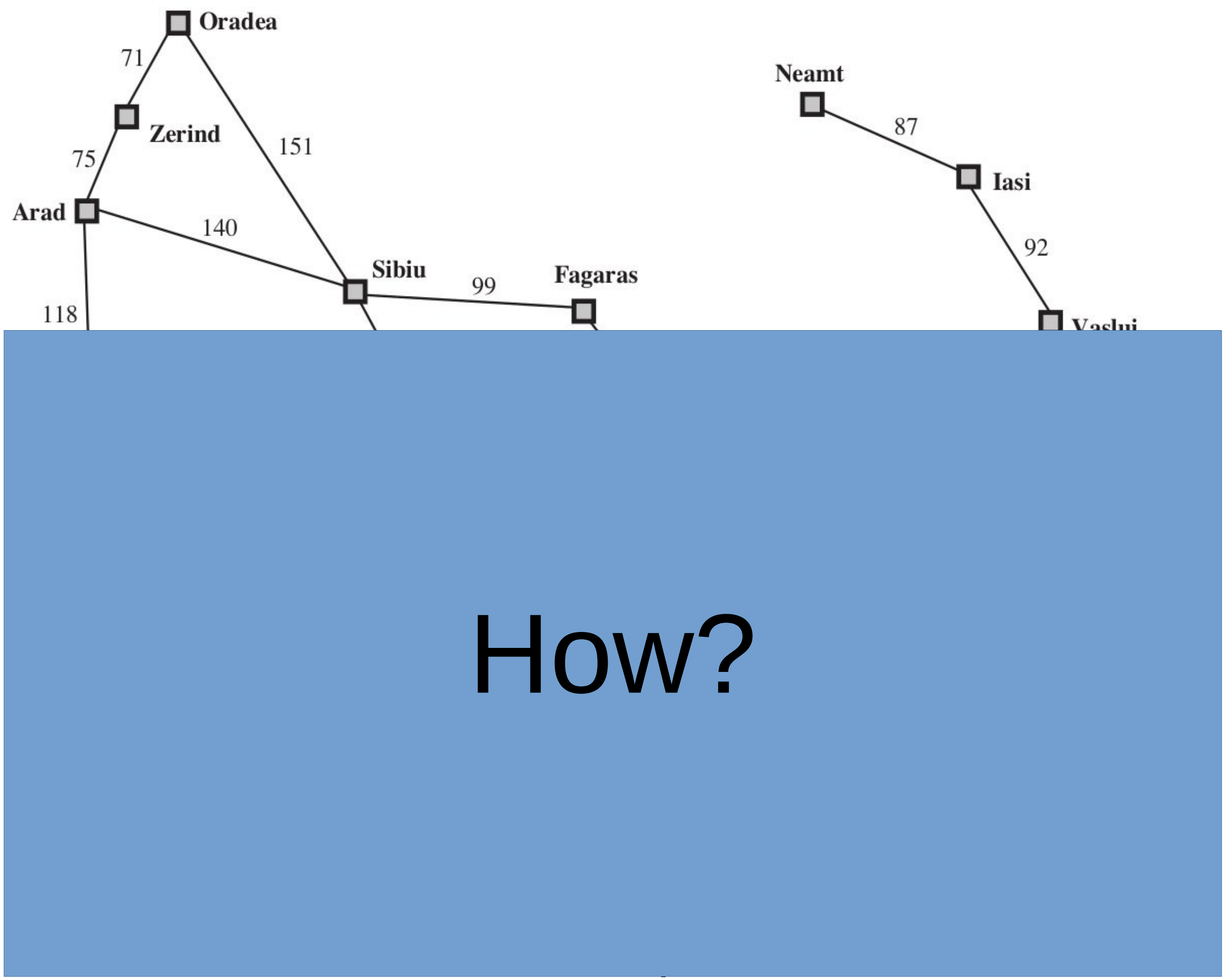
<u>Given</u>: a graph, *G*

<u>Problem</u>: find a path from A to B

– A: start state

– B: goal state

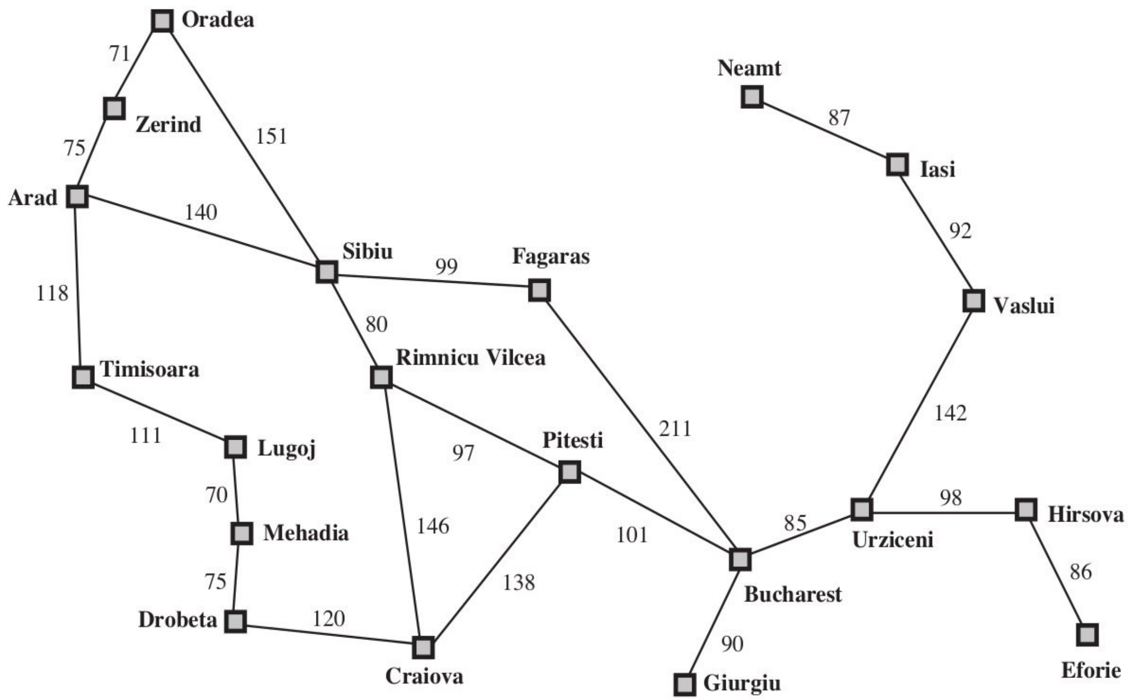
Graph search

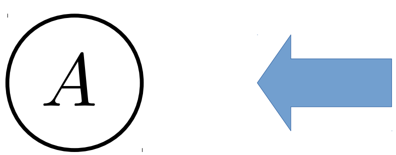


– A: start state

– B: goal state

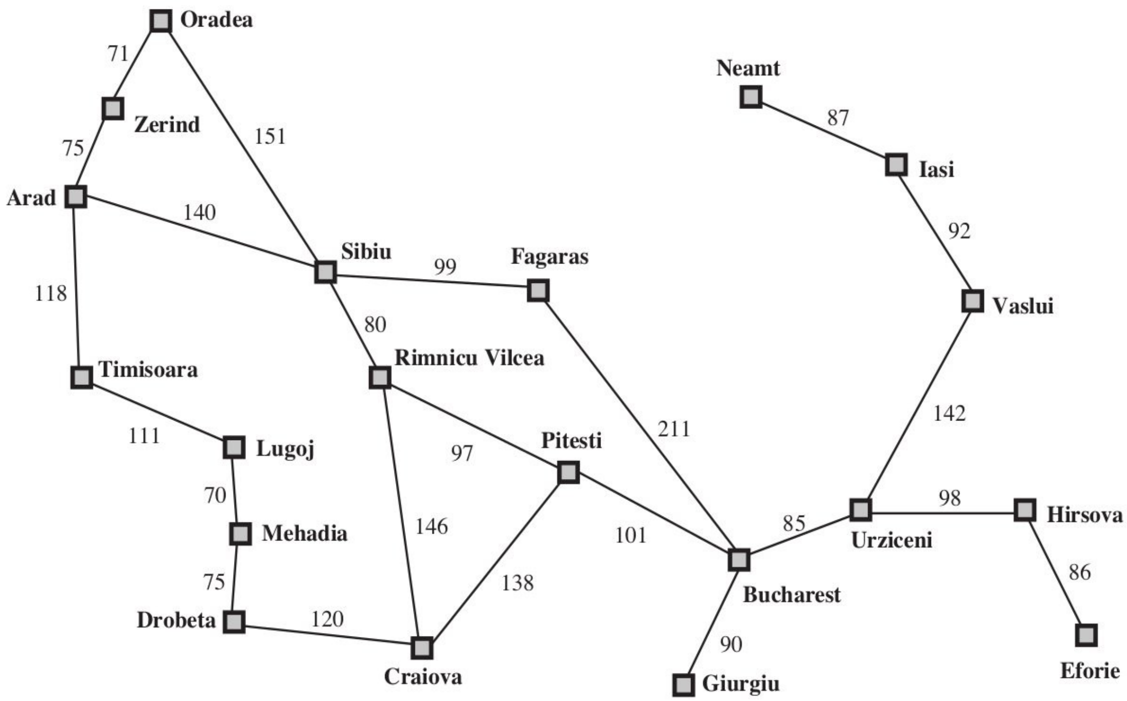
A search tree

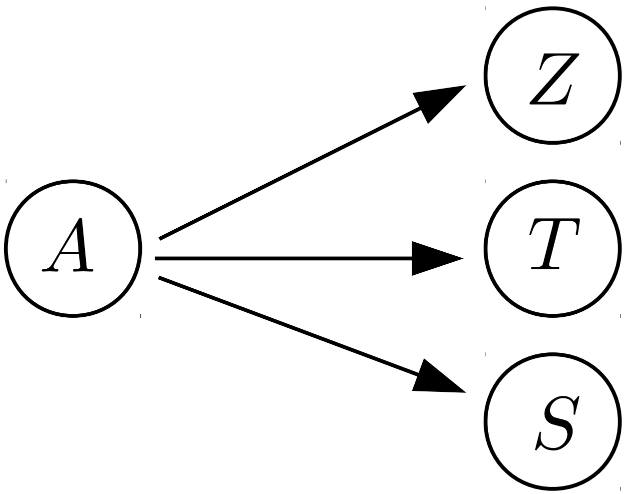




Start at *A*

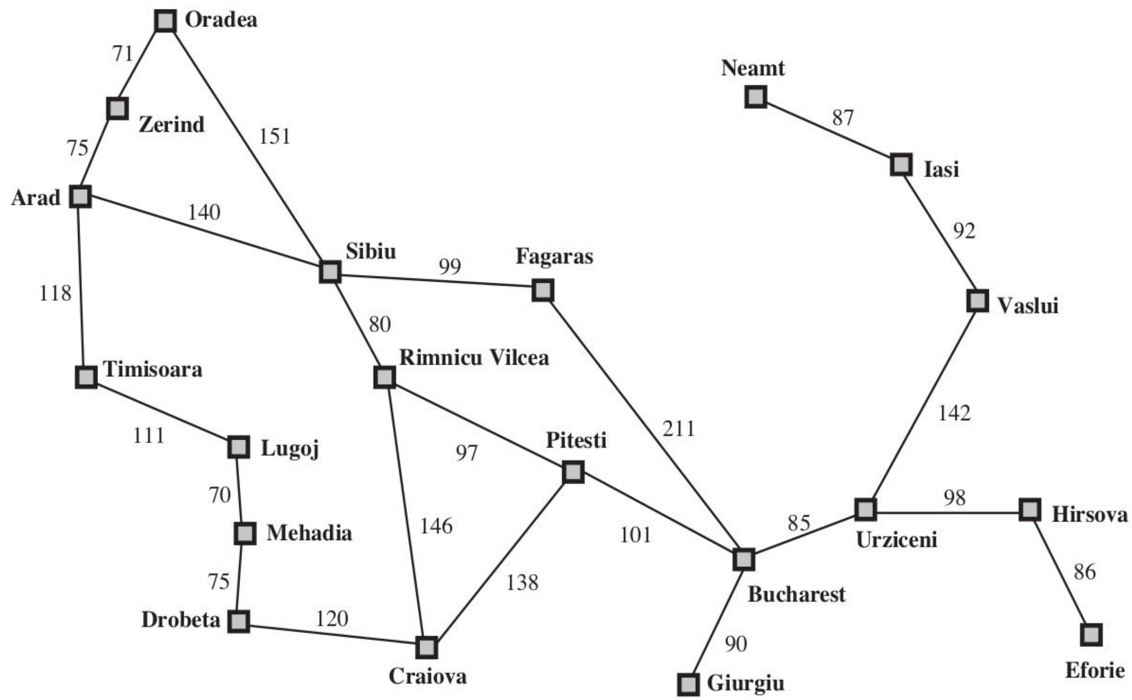
A search tree

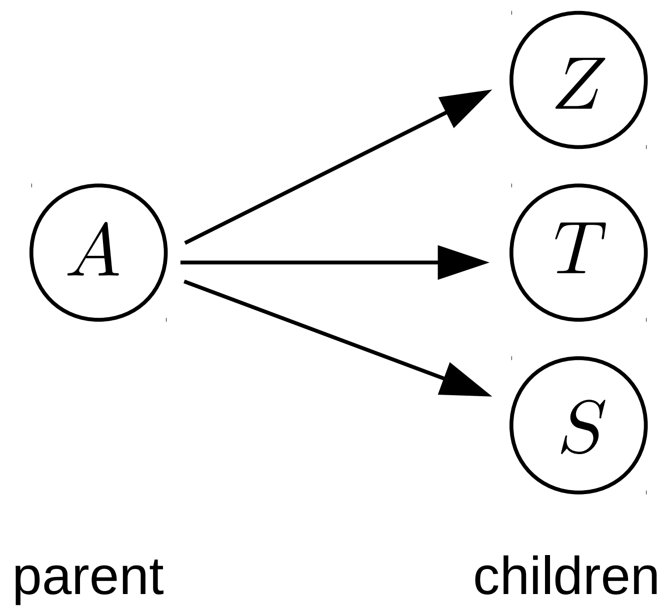




Successors of *A*

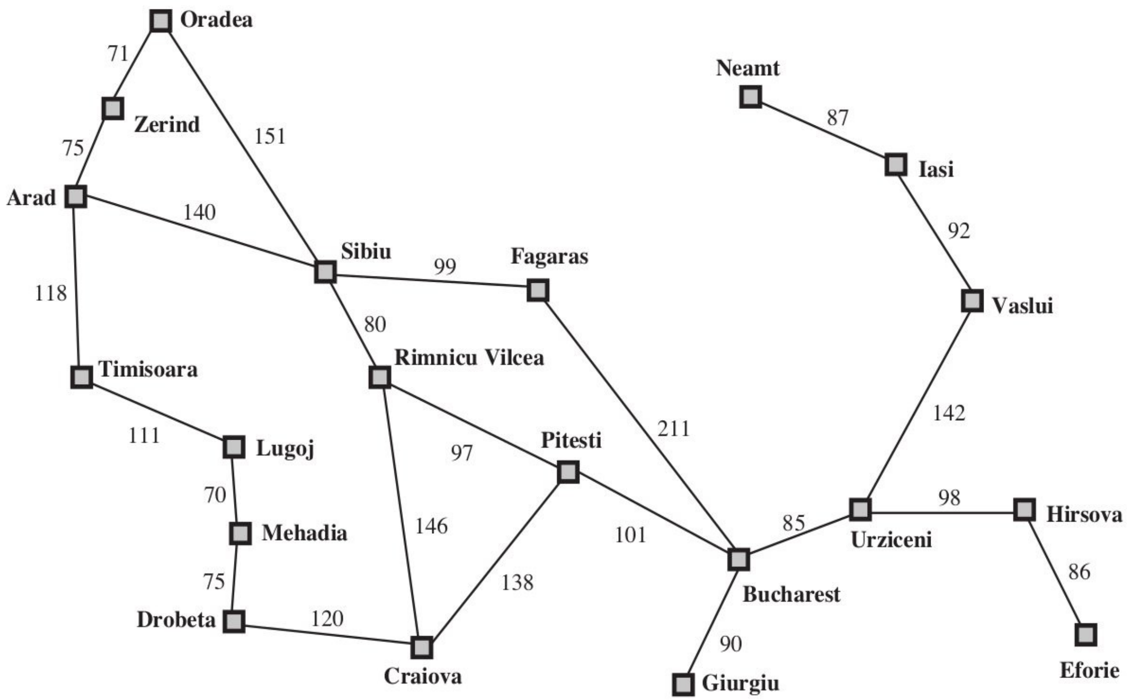
A search tree

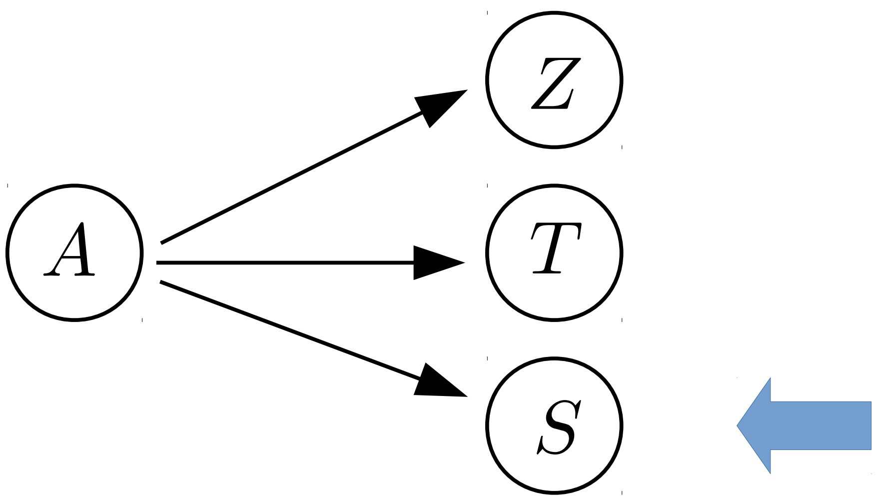




Successors of *A*

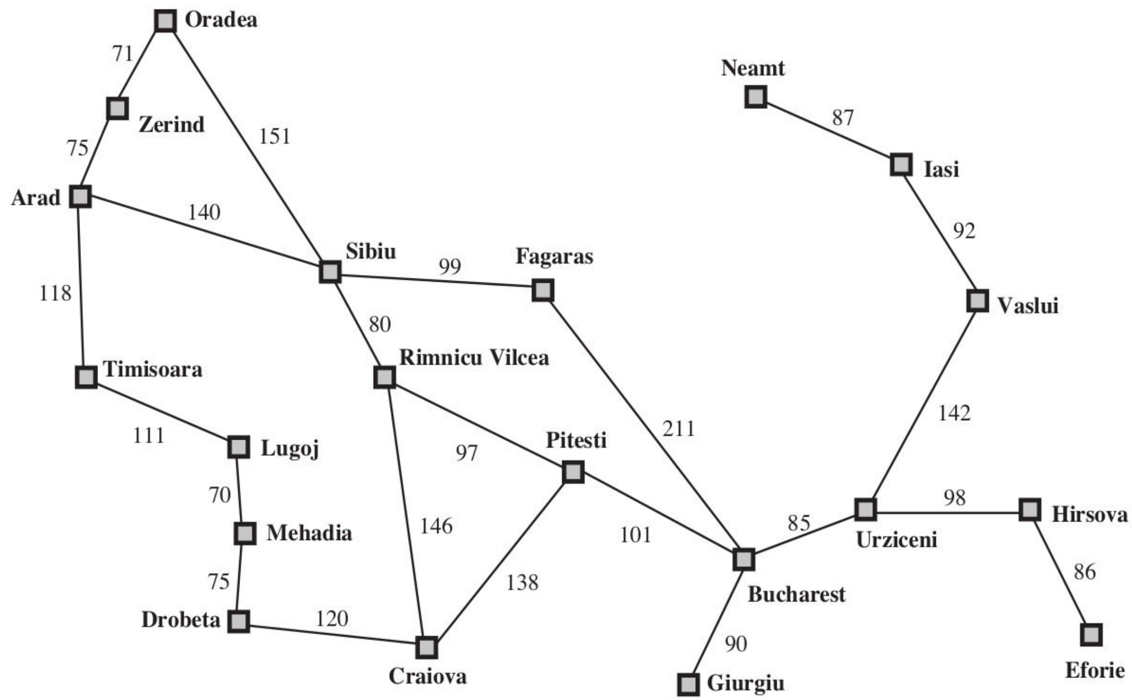
A search tree

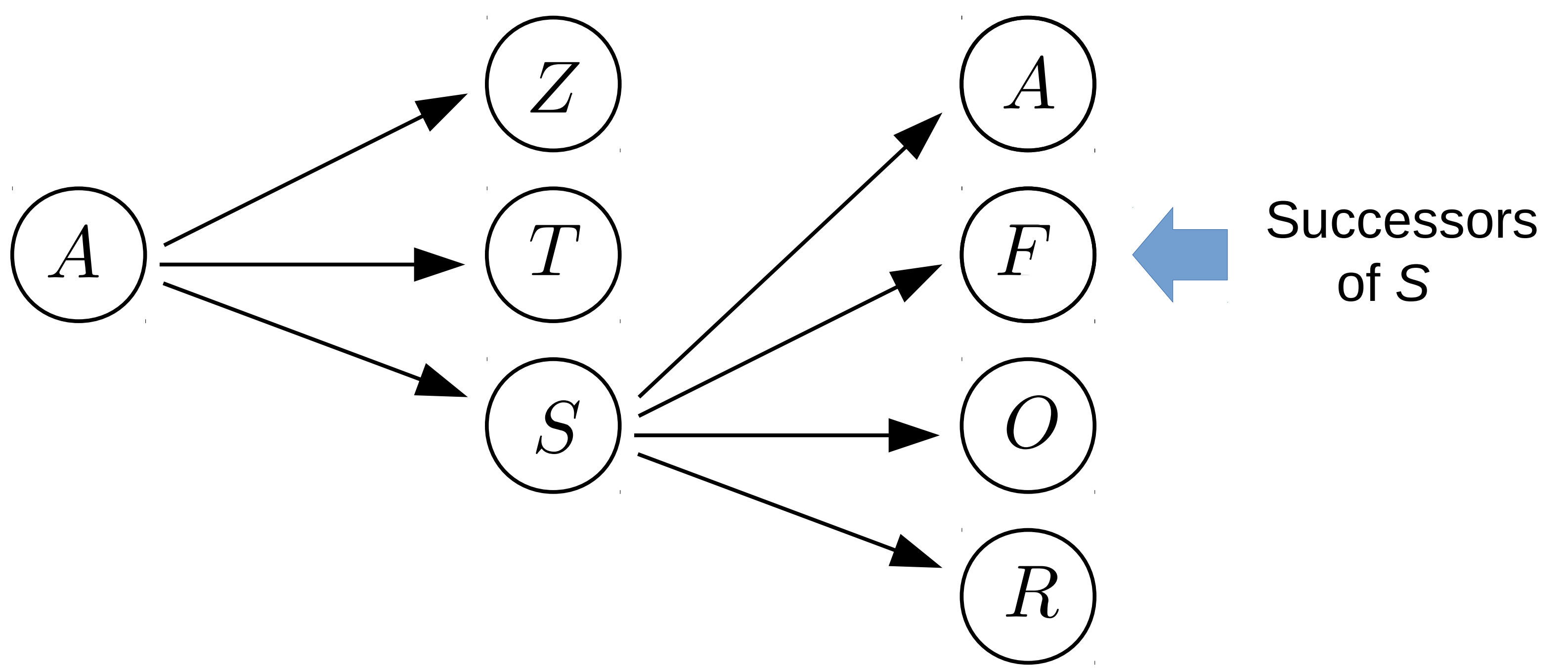




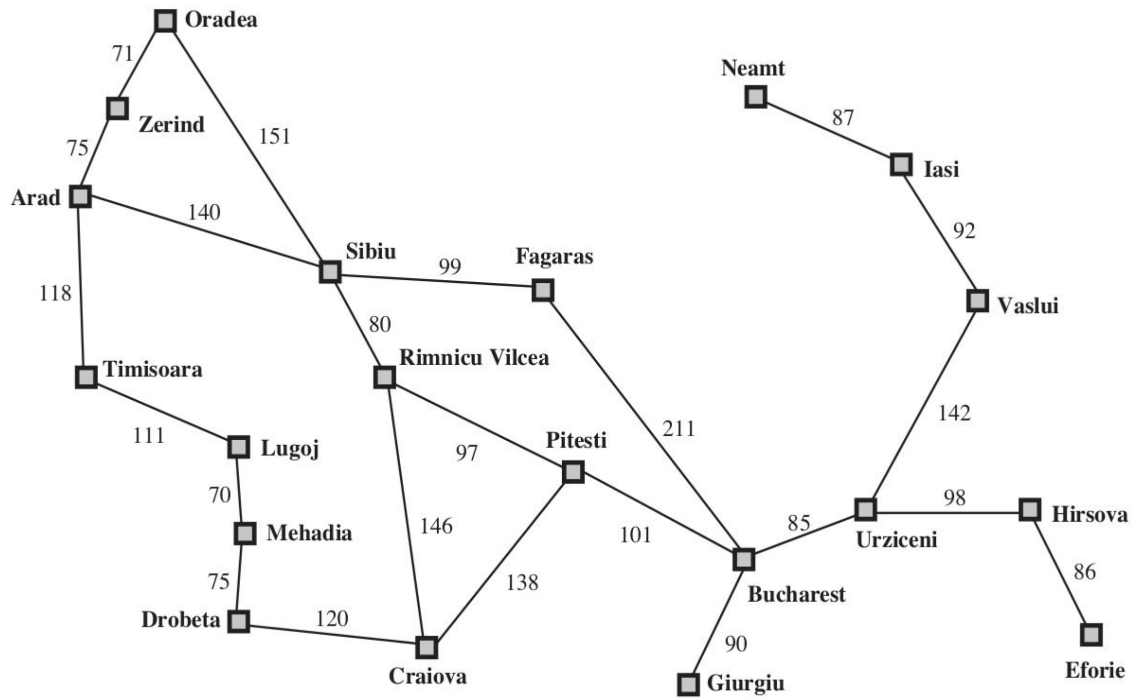
Let's expand S next

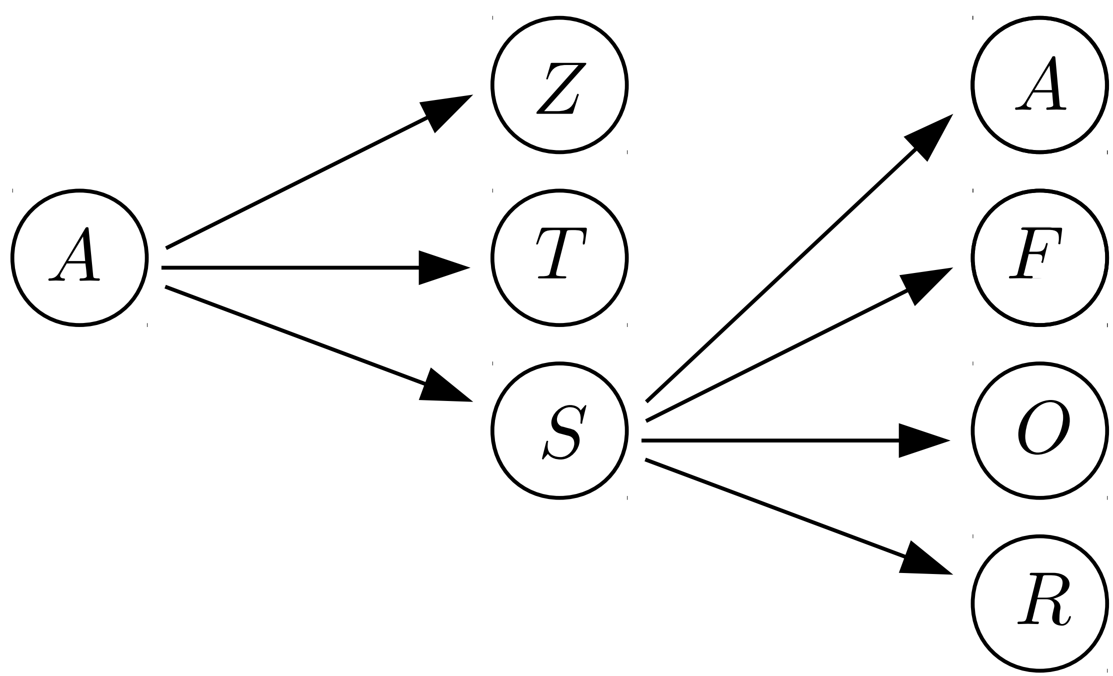
A search tree





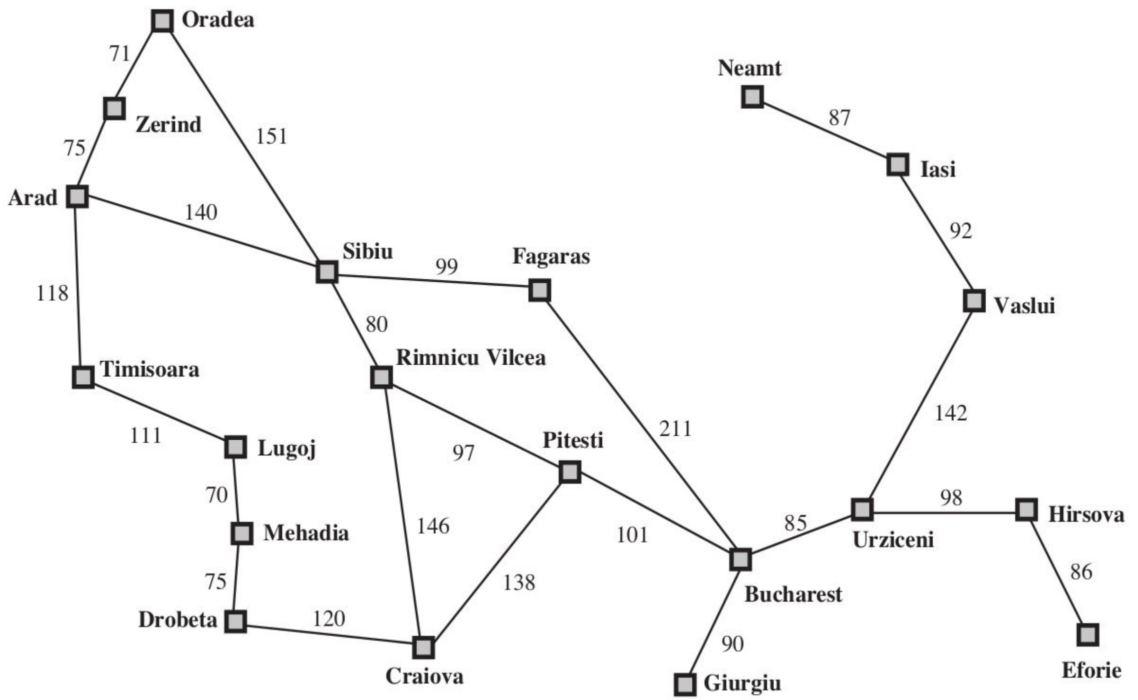
A search tree

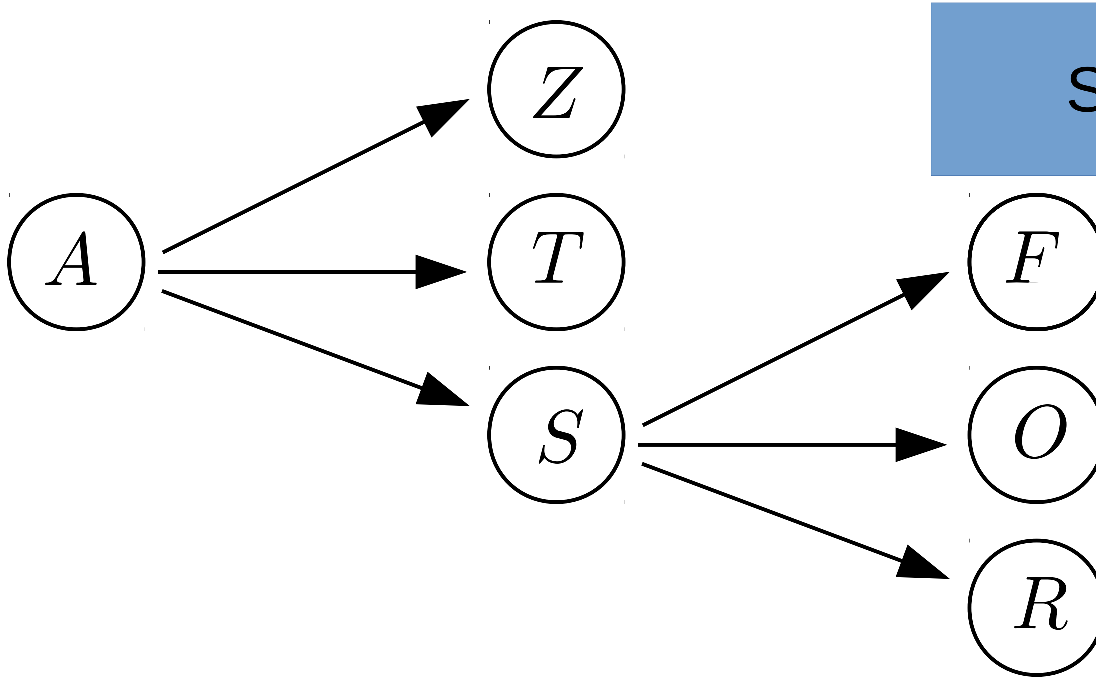




A was already visited!

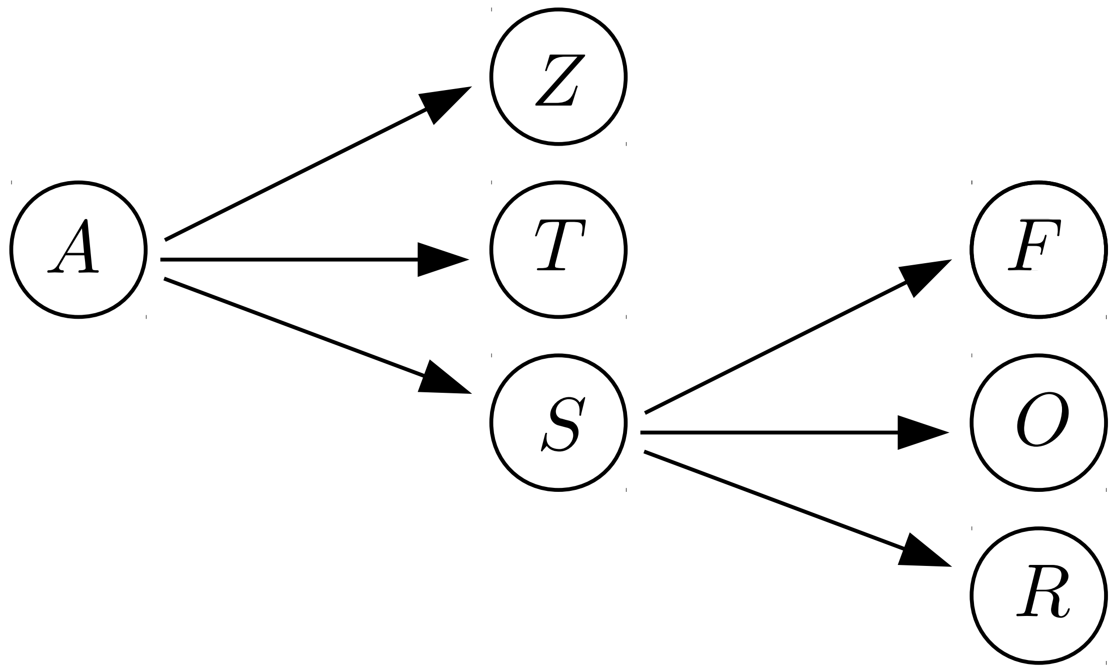
A search tree





So, prune it!

A search tree

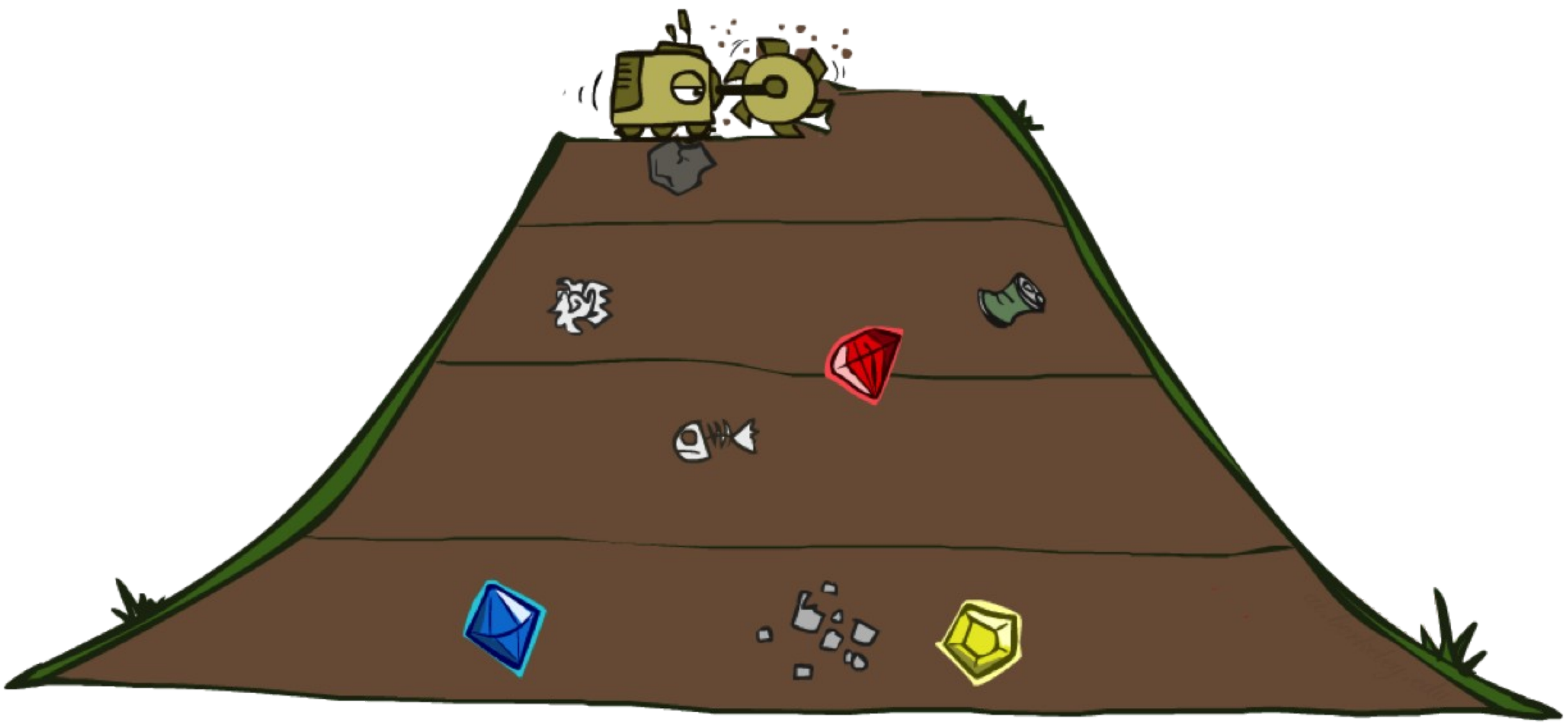


In what order should we expand states?

– here, we expanded *S*, but we could also have expanded *Z* or *T*

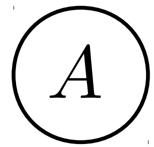
– different search algorithms expand in different orders

Breadth first search (BFS)



Slide: Adapted from Berkeley CS188 course notes (downloaded Summer 2015)

Breadth first search (BFS)



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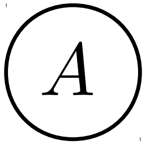
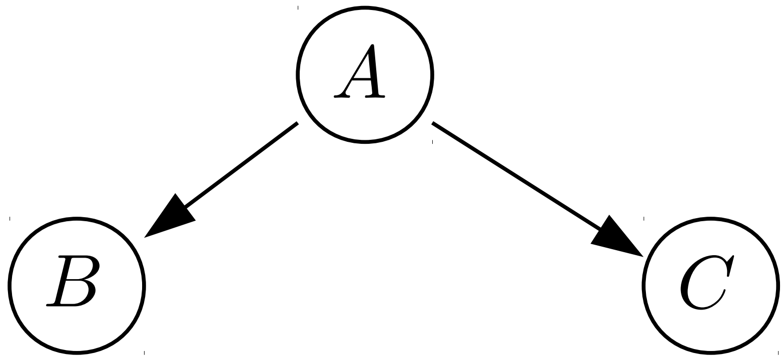


Start node

Breadth first search (BFS)



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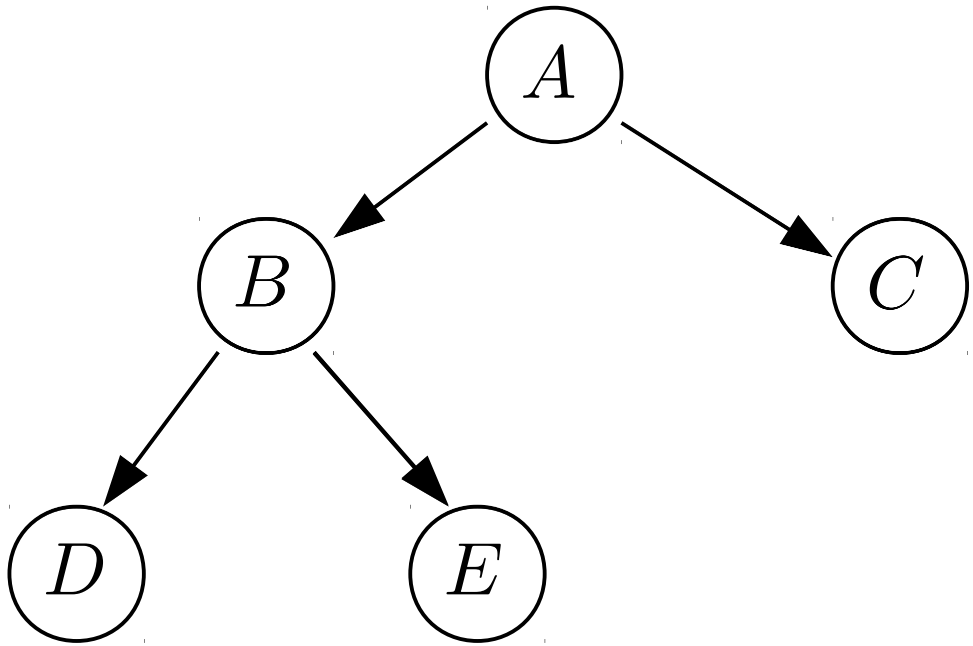

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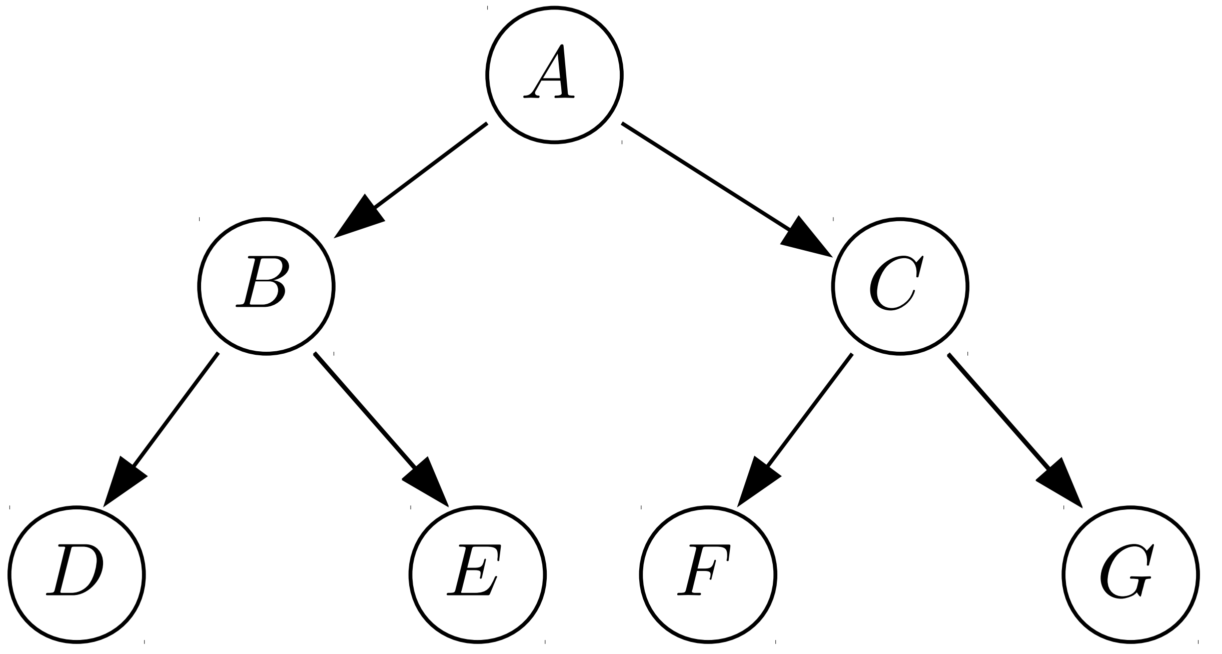


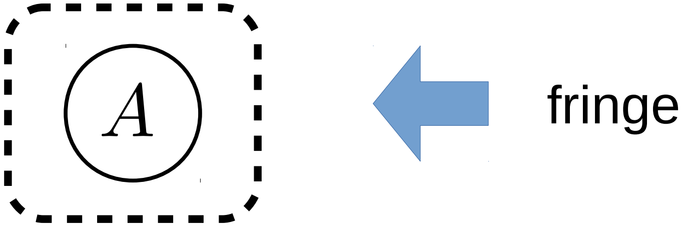
Breadth first search (BFS)

<u>Fringe</u>

We're going to maintain a queue called the <u>fringe</u>

– initialize the fringe as an empty queue

Breadth first search (BFS)

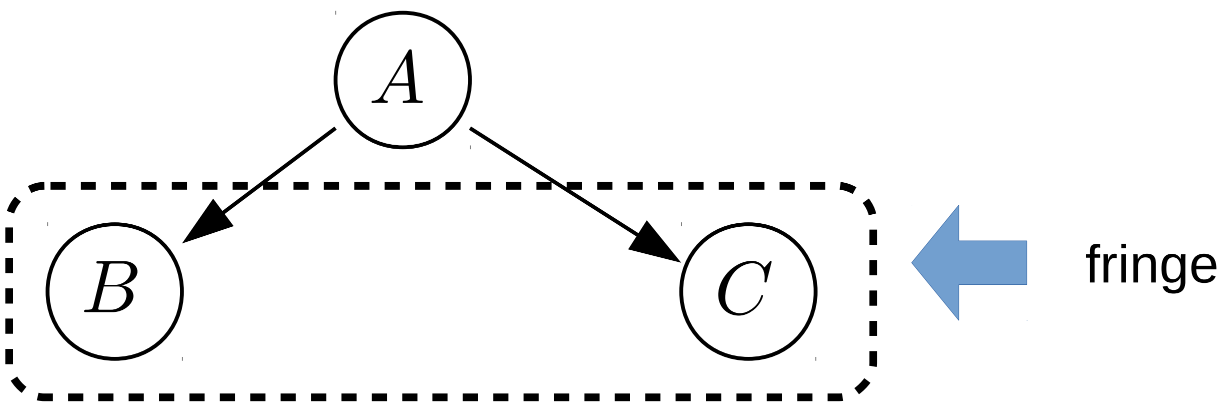


<u>Fringe</u>
A

– add *A* to the fringe

Breadth first search (BFS)

<u>Fringe</u>
B
C

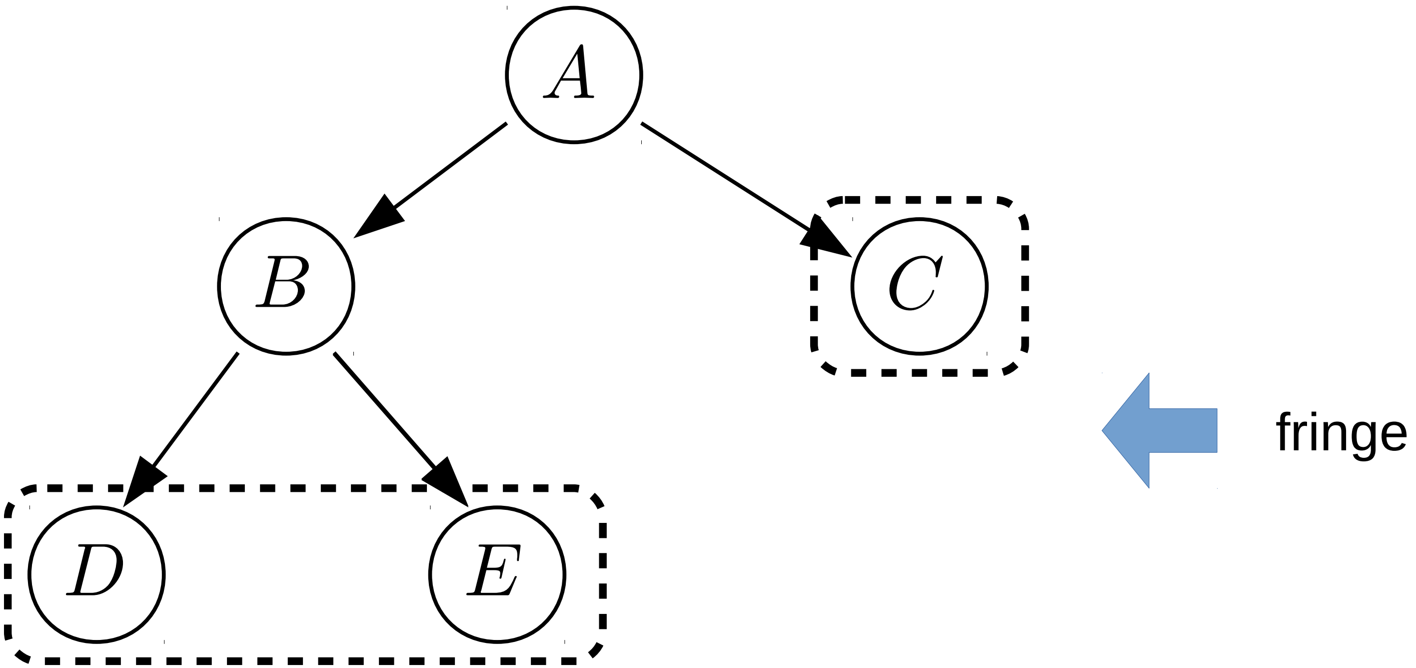


-- remove *A* from the fringe

-- add successors of *A* to the fringe

Breadth first search (BFS)

<u>Fringe</u>
C
D
E

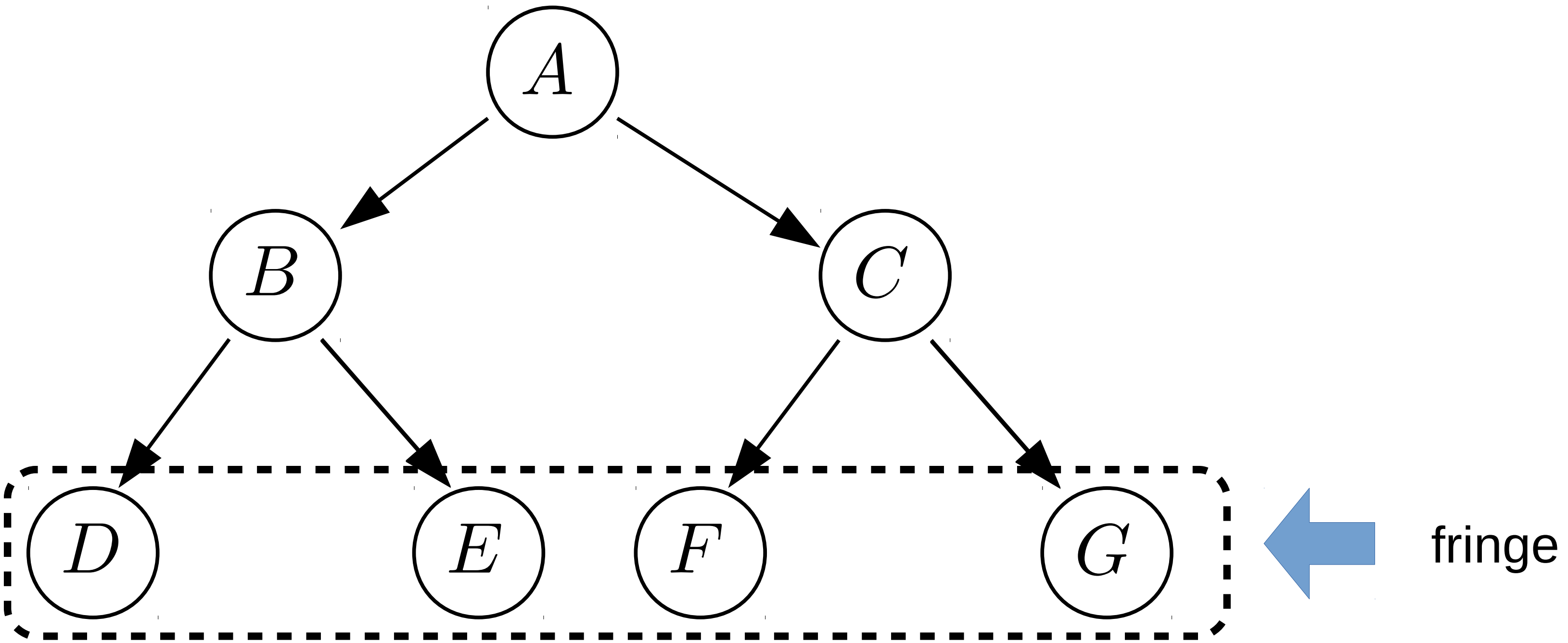


-- remove *B* from the fringe

-- add successors of *B* to the fringe

Breadth first search (BFS)

Fringe
D
E
F
G

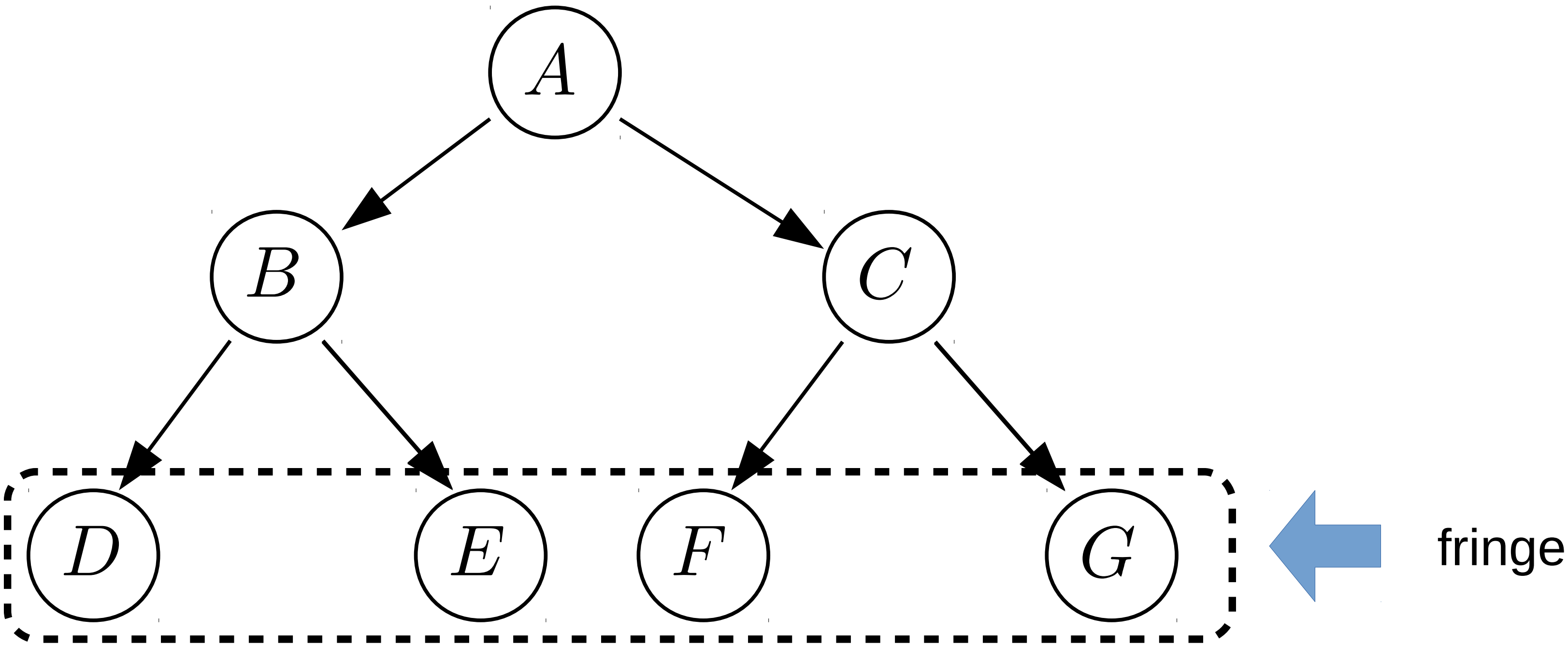


-- remove C from the fringe

-- add successors of C to the fringe

Breadth first search (BFS)

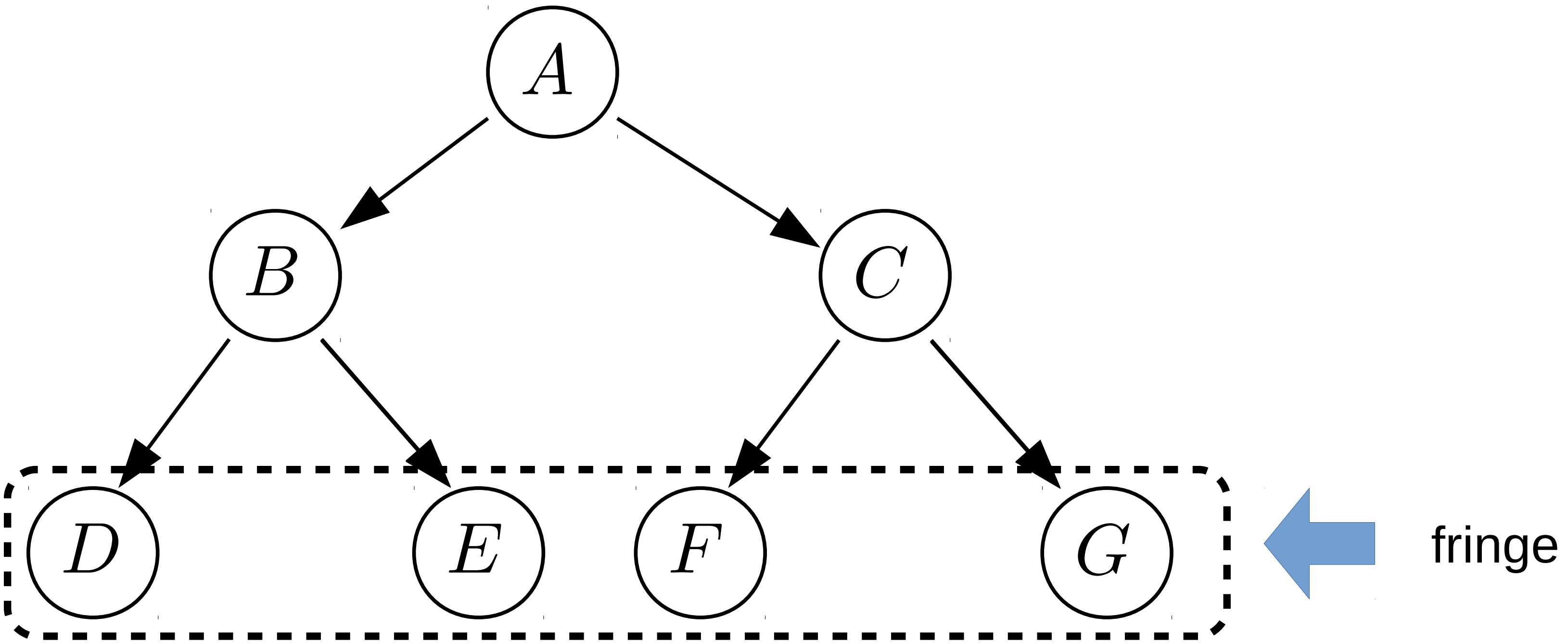
Fringe
D
E
F
G



Which state gets removed next from the fringe?

Breadth first search (BFS)

<u>Fringe</u>
D
E
F
G

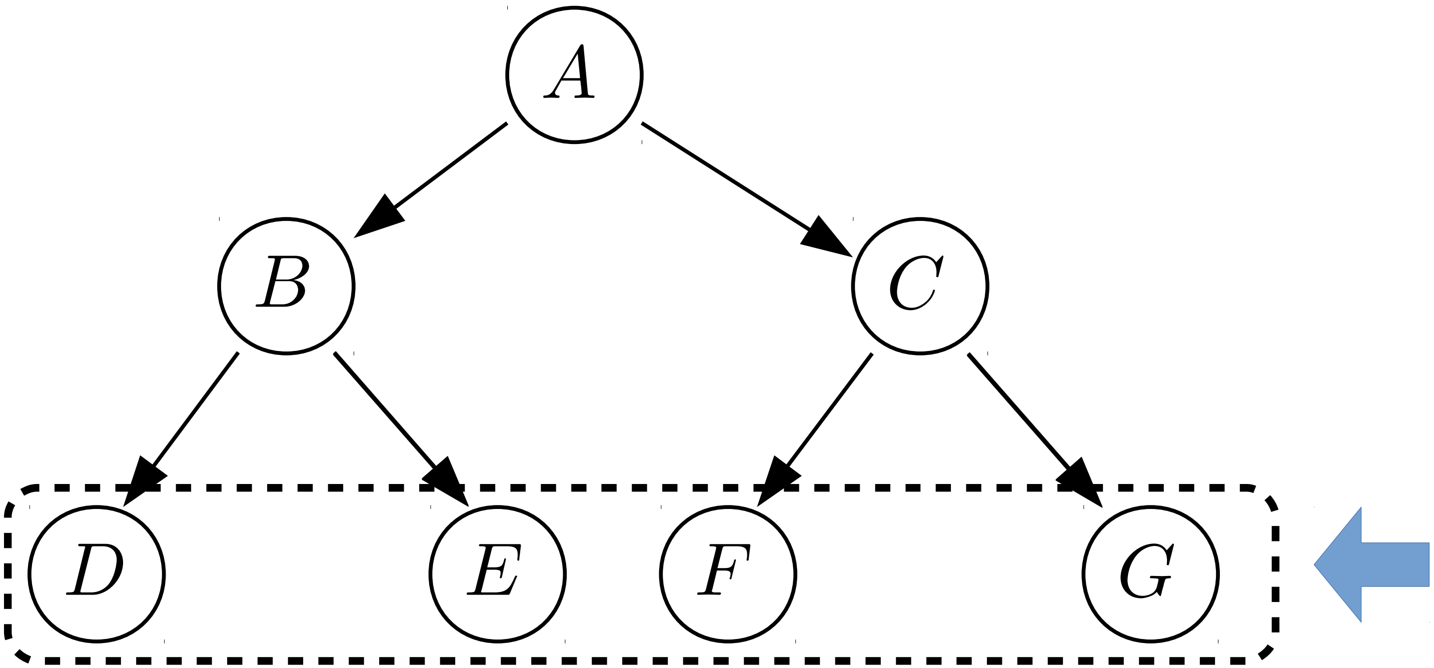


Which state gets removed next from the fringe?

What kind of a queue is this?

Breadth first search (BFS)

<u>Fringe</u>
D
E
F
G



fringe

Which state gets removed next from the fringe?

What kind of a queue is this?

FIFO Queue!
(first in first out)

Breadth first search (BFS)

```
function BREADTH-FIRST-SEARCH(problem) returns a solution, or failure
  node ← a node with STATE = problem.INITIAL-STATE, PATH-COST = 0
  if problem.GOAL-TEST(node.STATE) then return SOLUTION(node)
  frontier ← a FIFO queue with node as the only element
  explored ← an empty set
  loop do
     if EMPTY?(frontier) then return failure
     node ← POP(frontier)   /* chooses the shallowest node in frontier */
     add node.STATE to explored
     for each action in problem.ACTIONS(node.STATE) do
        child ← CHILD-NODE(problem, node, action)
        if child.STATE is not in explored or frontier then
           if problem.GOAL-TEST(child.STATE) then return SOLUTION(child)
           frontier ← INSERT(child, frontier)
```

Figure 3.11 Breadth-first search on a graph.

Breadth first search (BFS)

```
function BREADTH-FIRST-SEARCH(problem) returns a solution, or failure
  node ← a node with STATE = problem.INITIAL-STATE, PATH-COST = 0
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           frontier ← INSERT(child, frontier)
```

Figure 3.11 Breadth-first search on a graph.

What is the purpose of the *explored* set?

BFS Properties

Is BFS <u>complete</u>?
– is it guaranteed to find a solution if one exists?

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  - – d: depth of shallowest solution
  - – complexity = ???

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  – complexity = $O(b^d)$

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What is the space complexity of BFS?
– how much memory is required?
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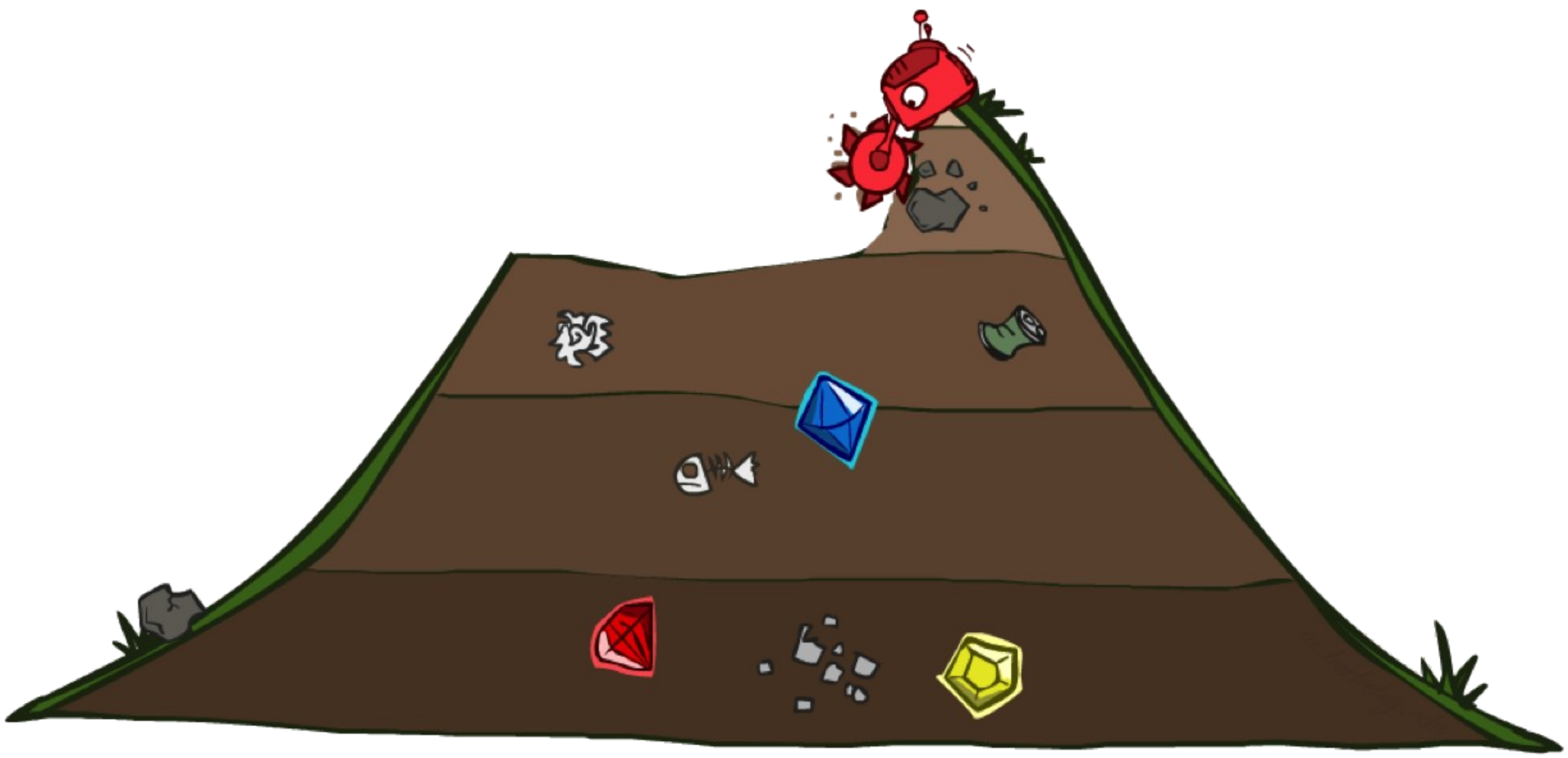
What is the space complexity of BFS?
– how much memory is required?
– complexity = $O(b^d)$

Is BFS optimal?
– is it guaranteed to find the best solution (shortest path)?

Another BFS example...

Uniform Cost Search (UCS)



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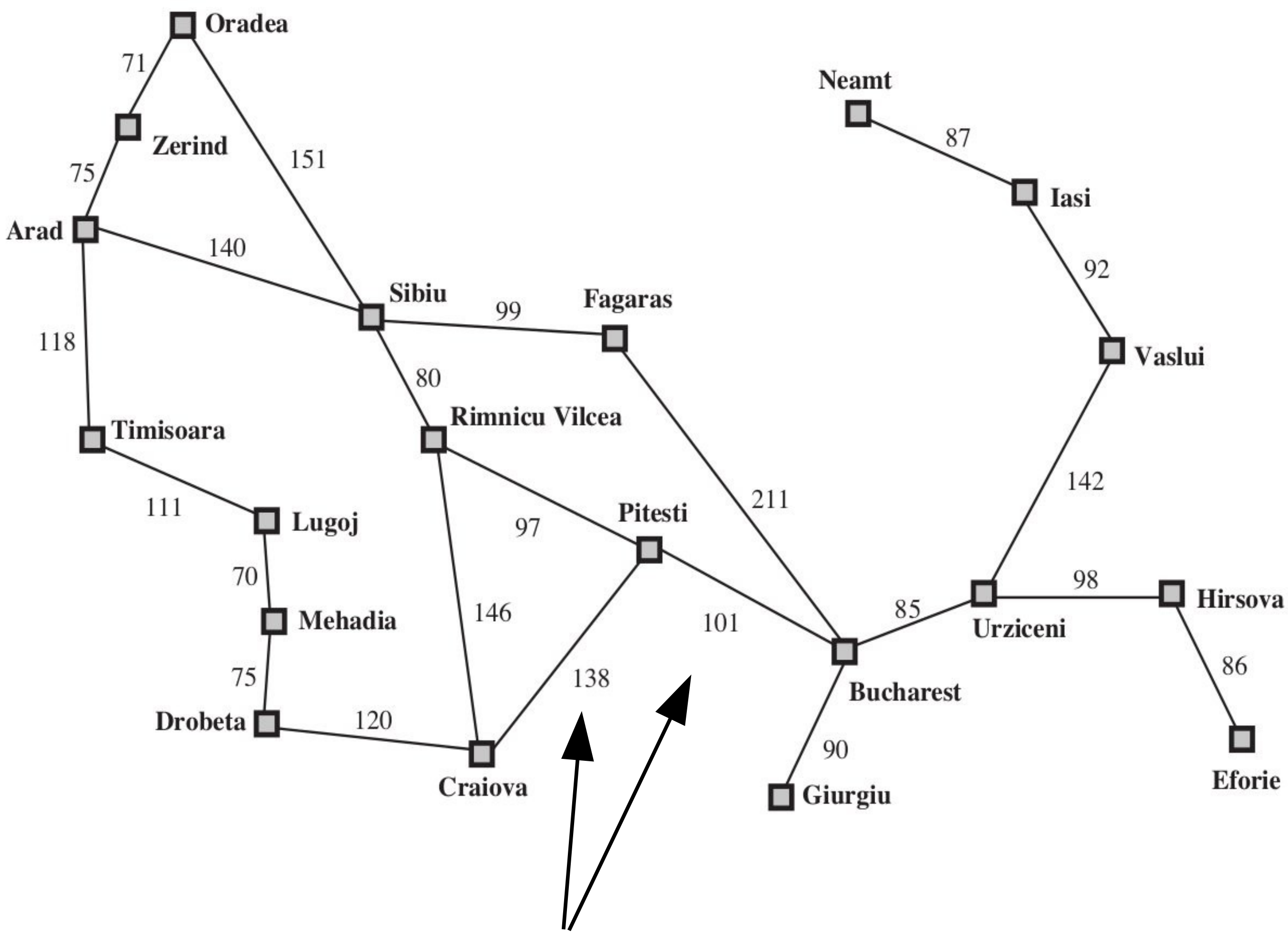
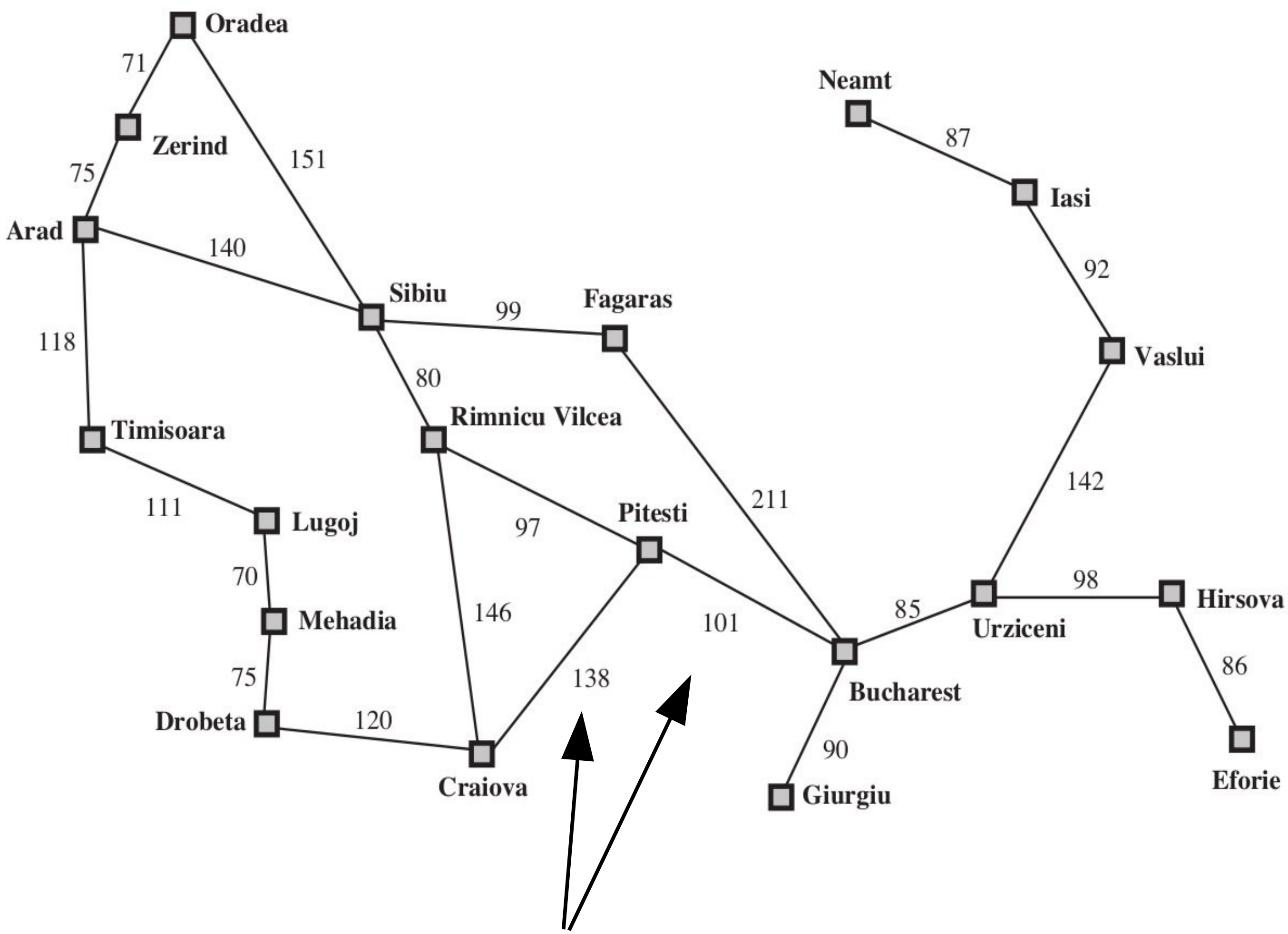
Uniform Cost Search (UCS)



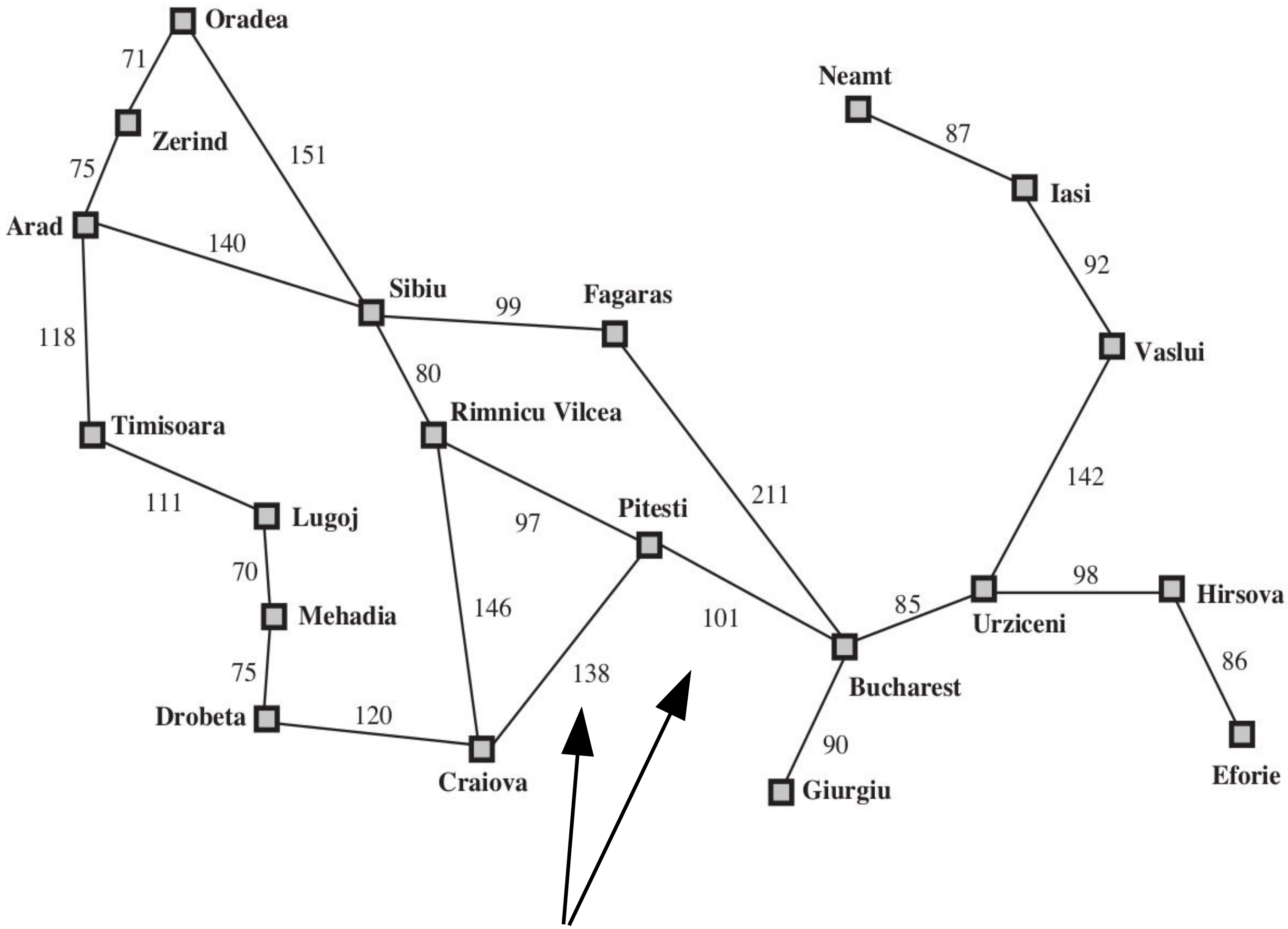
Notice the distances between cities

Uniform Cost Search (UCS)



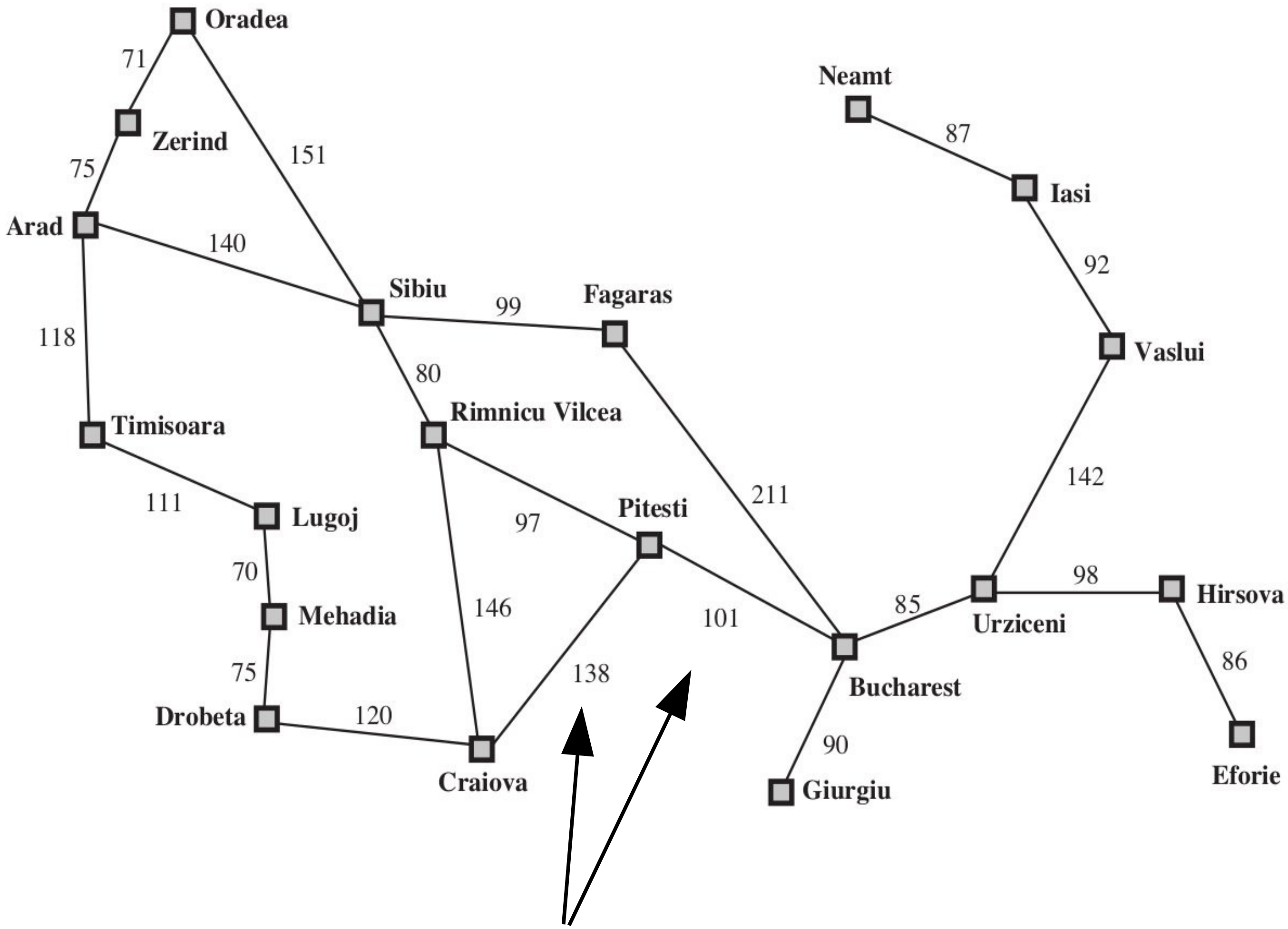
Notice the distances between cities
– does BFS take these distances into account?

Uniform Cost Search (UCS)



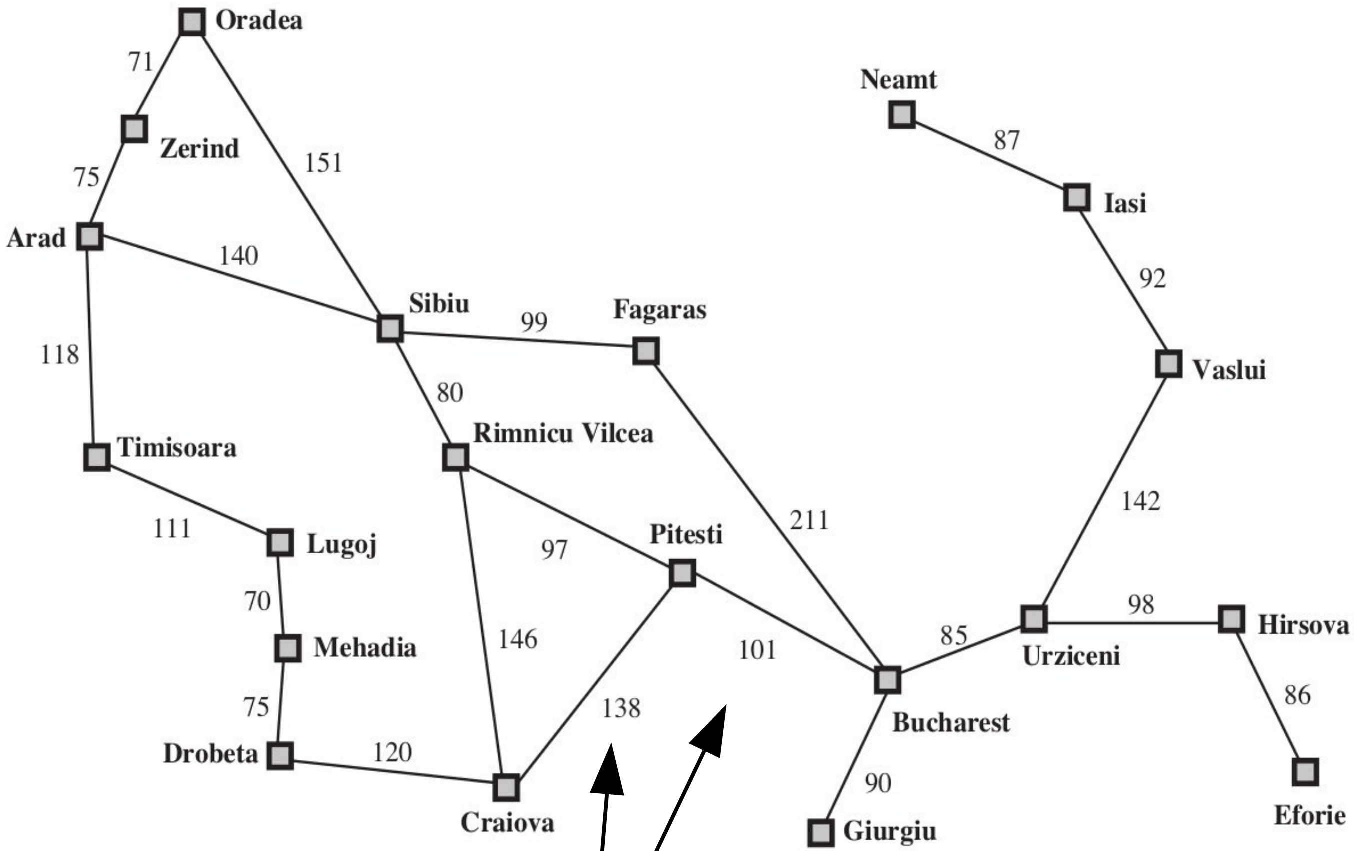
Notice the distances between cities
– does BFS take these distances into account?
– does BFS find the path w/ shortest milage?

Uniform Cost Search (UCS)



Notice the distances between cities
– does BFS take these distances into account?
– does BFS find the path w/ shortest milage?
– compare S-F-B with S-R-P-B. Which costs less?

Uniform Cost Search (UCS)



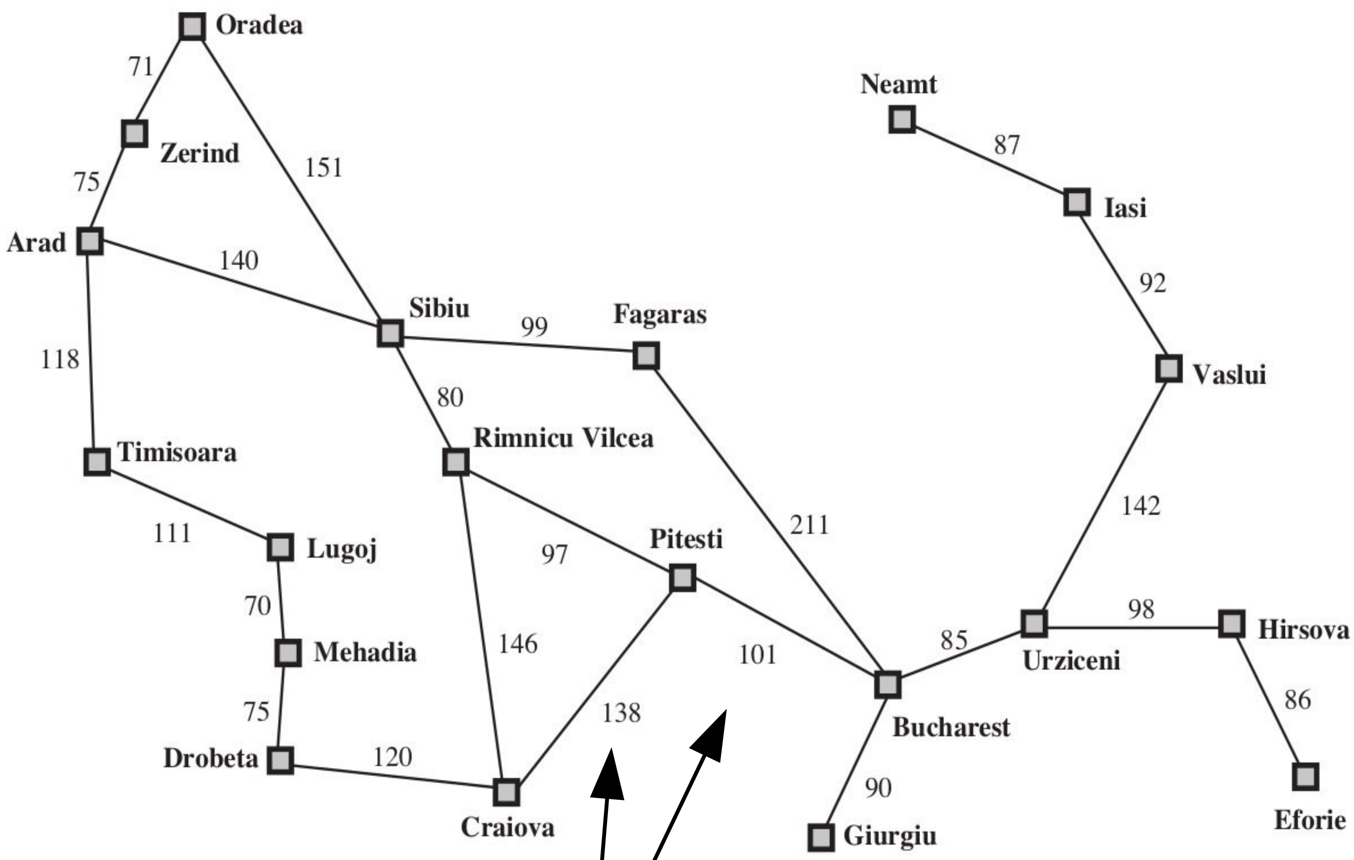
Notice
– doe
– doe
– com

How do we fix this?

nt?

less?

Uniform Cost Search (UCS)



Notice
– doe nt?
– doe
– com less?

How do we fix this?
UCS!

Uniform Cost Search (UCS)

Same as BFS except: expand node w/ smallest <u>path cost</u>

Length of path

Uniform Cost Search (UCS)

Same as BFS except: expand node w/ smallest path cost

Length of path

Cost of going from state *A* to *B*: $c(A, B)$

Minimum cost of path going from start state to *B*: $g(B)$

Uniform Cost Search (UCS)

Same as BFS except: expand node w/ smallest <u>path cost</u>

Length of path

Cost of going from state *A* to *B:* $c(A, B)$

Minimum cost of path going from start state to *B:* $g(B)$

BFS: expands states in order of hops from start

UCS: expands states in order of $g(s)$

Uniform Cost Search (UCS)

Same as BFS except: expand node w/ smallest path cost

Length of path

Cost of going from state *A* to *B:* $c(A, B)$

Minimum cost of path going from start state to *B:* $g(B)$

BFS: exp

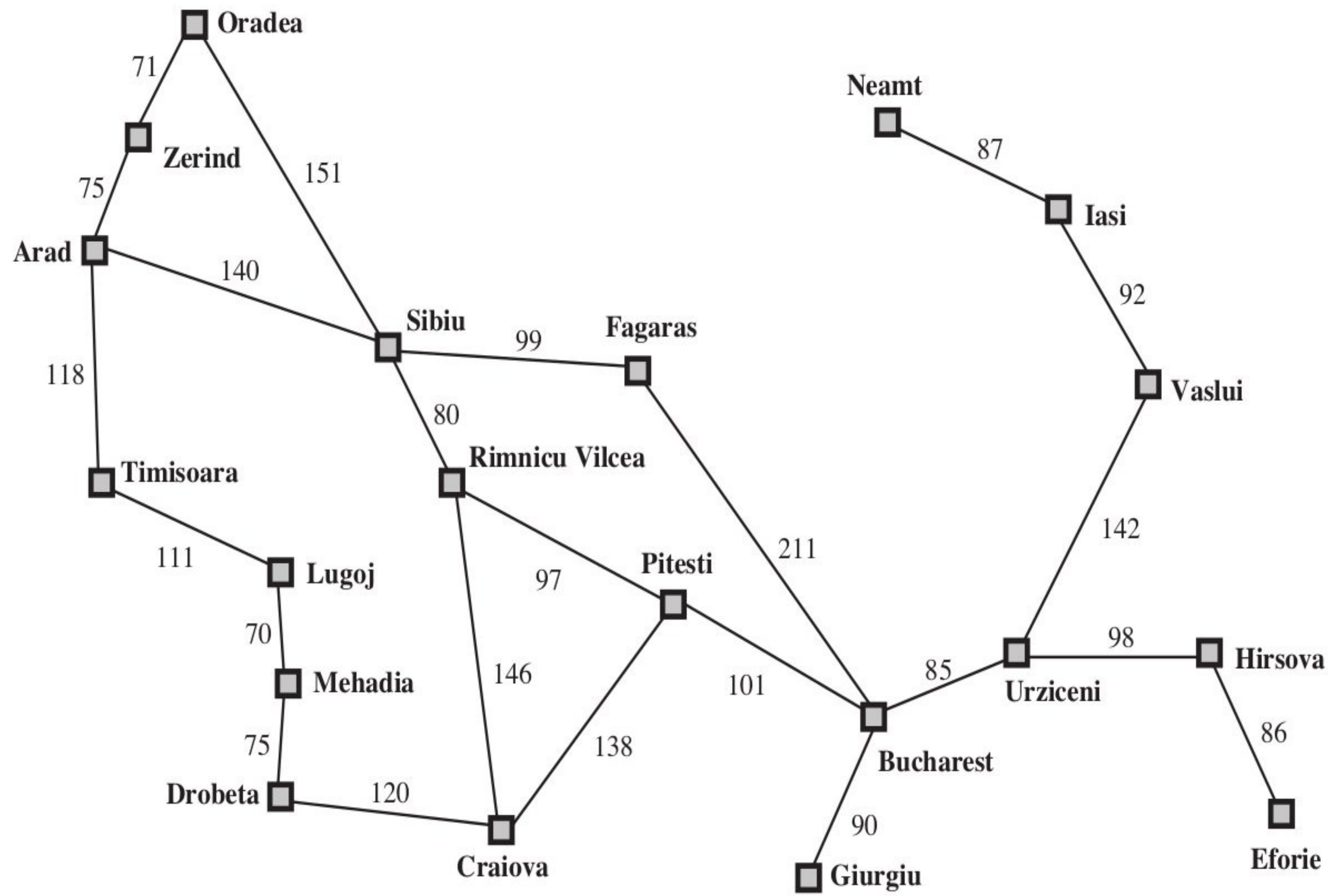
UCS: ex

How?

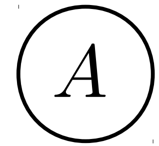
Uniform Cost Search (UCS)

Simple answer: change the FIFO to a priority queue
– the priority of each element in the queue is its path cost.

Uniform Cost Search (UCS)



UCS

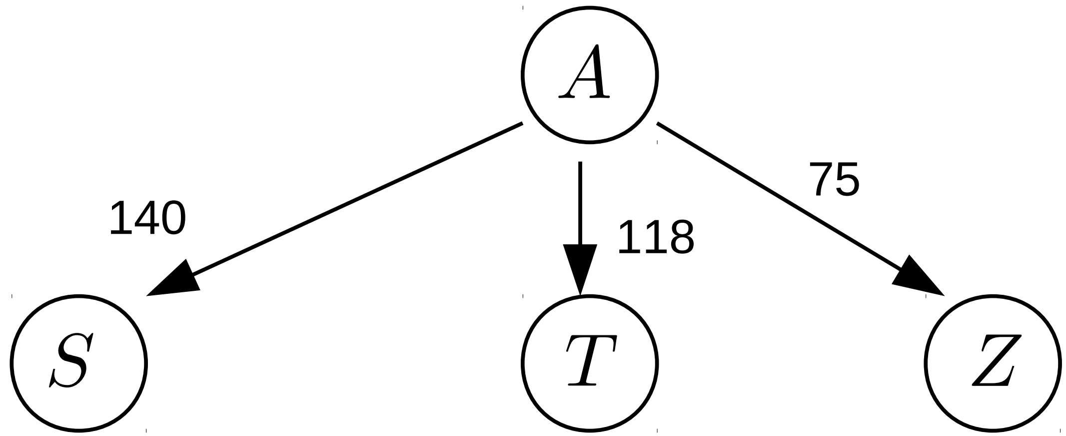


Fringe	Path Cost
A	0

Explored set:

UCS

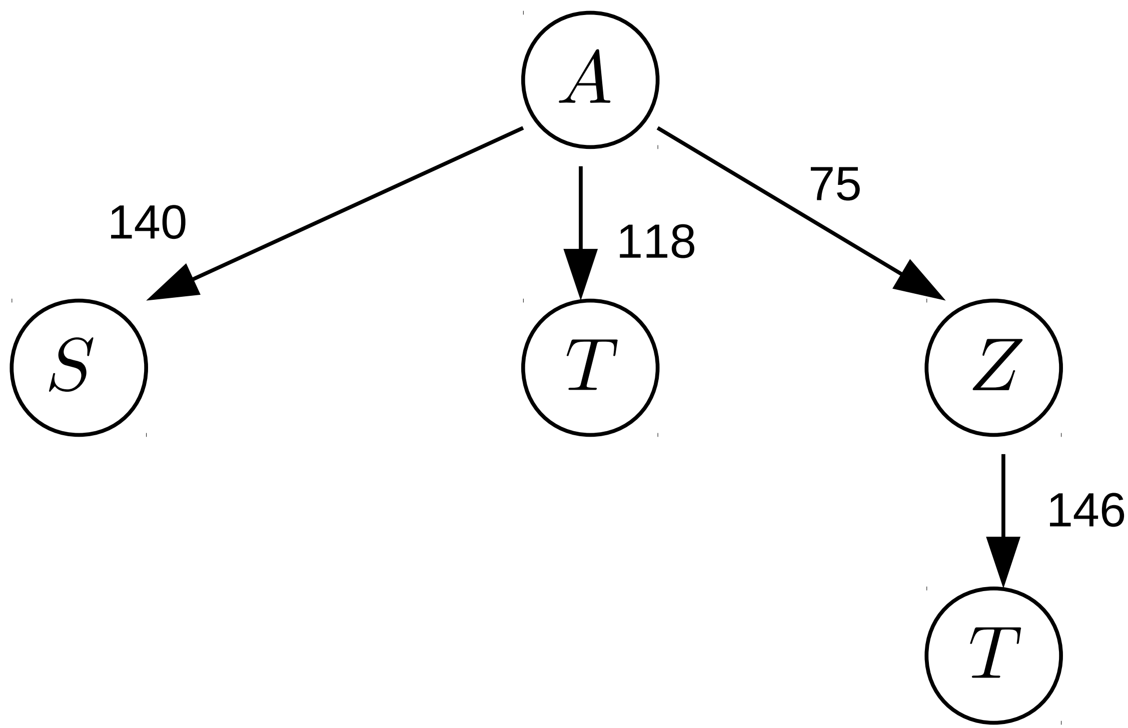
<u>Fringe</u>	<u>Path Cost</u>
~~A~~	~~0~~
S	140
T	118
Z	75



Explored set: A

UCS

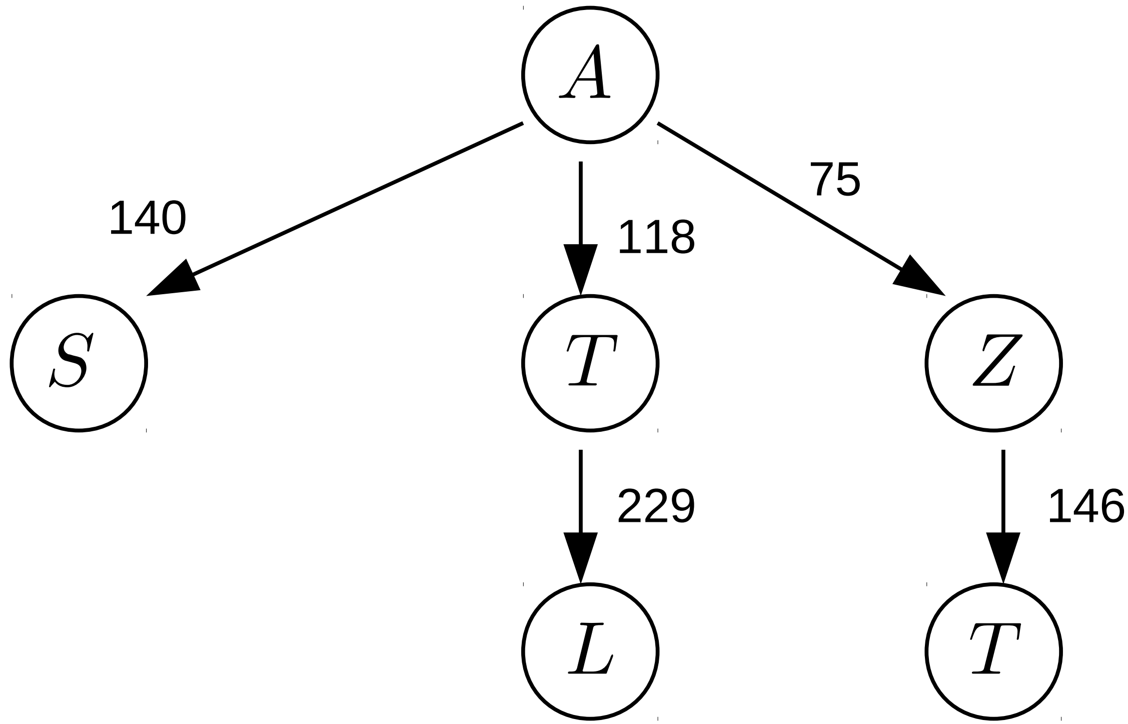
Fringe	Path Cost
~~A~~	~~0~~
S	140
T	118
~~Z~~	~~75~~
T	146



Explored set: A, Z

UCS

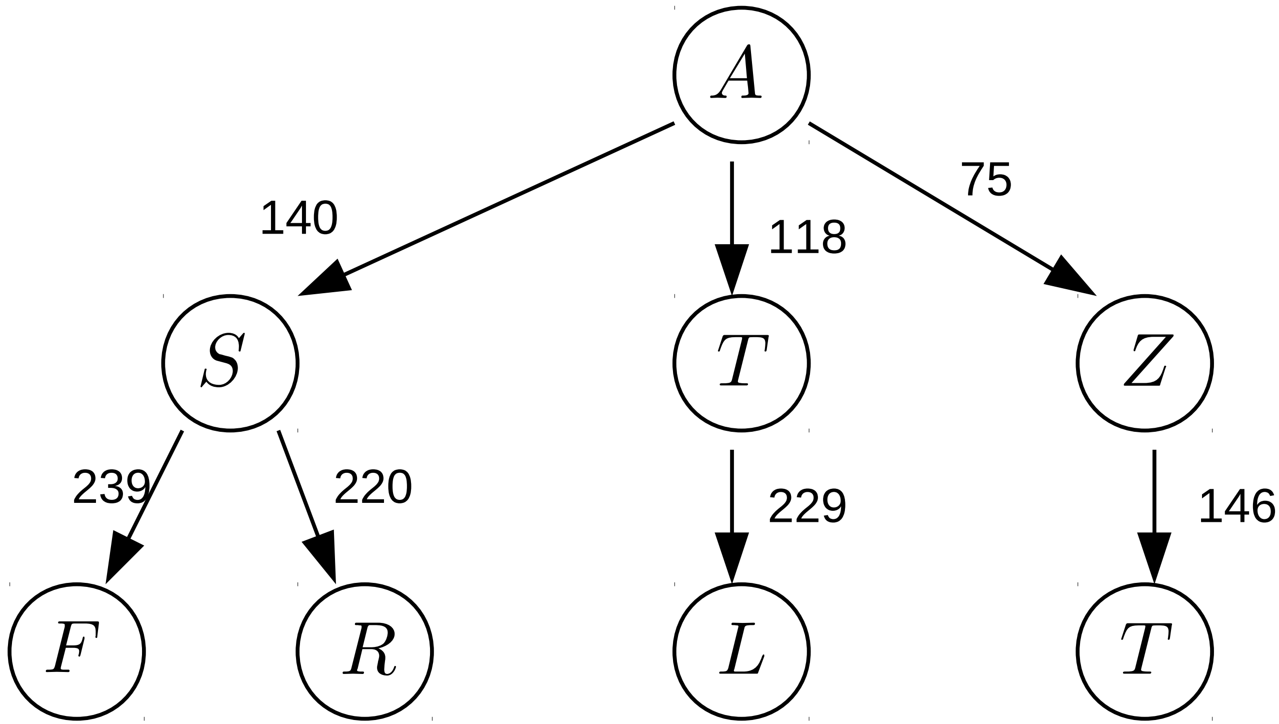
Fringe	Path Cost
~~A~~	~~0~~
S	140
~~T~~	~~118~~
~~Z~~	~~75~~
T	146
L	229



Explored set: A, Z, T

UCS

Fringe	Path Cost
~~A~~	~~0~~
~~S~~	~~140~~
~~T~~	~~118~~
~~Z~~	~~75~~
T	146
L	229
F	239
R	220



Explored set: A, Z, T, S

UCS

Fringe	Path Cost
~~A~~	~~0~~
~~S~~	~~140~~
~~T~~	~~118~~
~~Z~~	~~75~~
~~T~~	~~146~~
L	229
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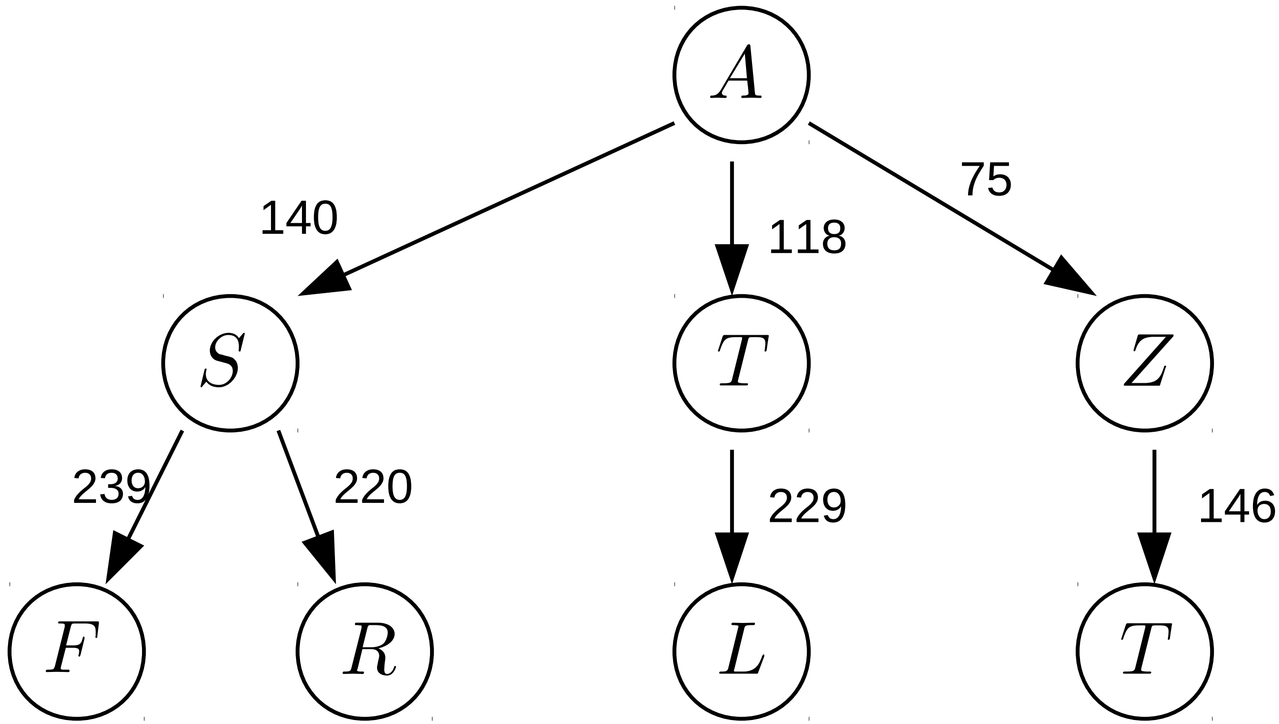
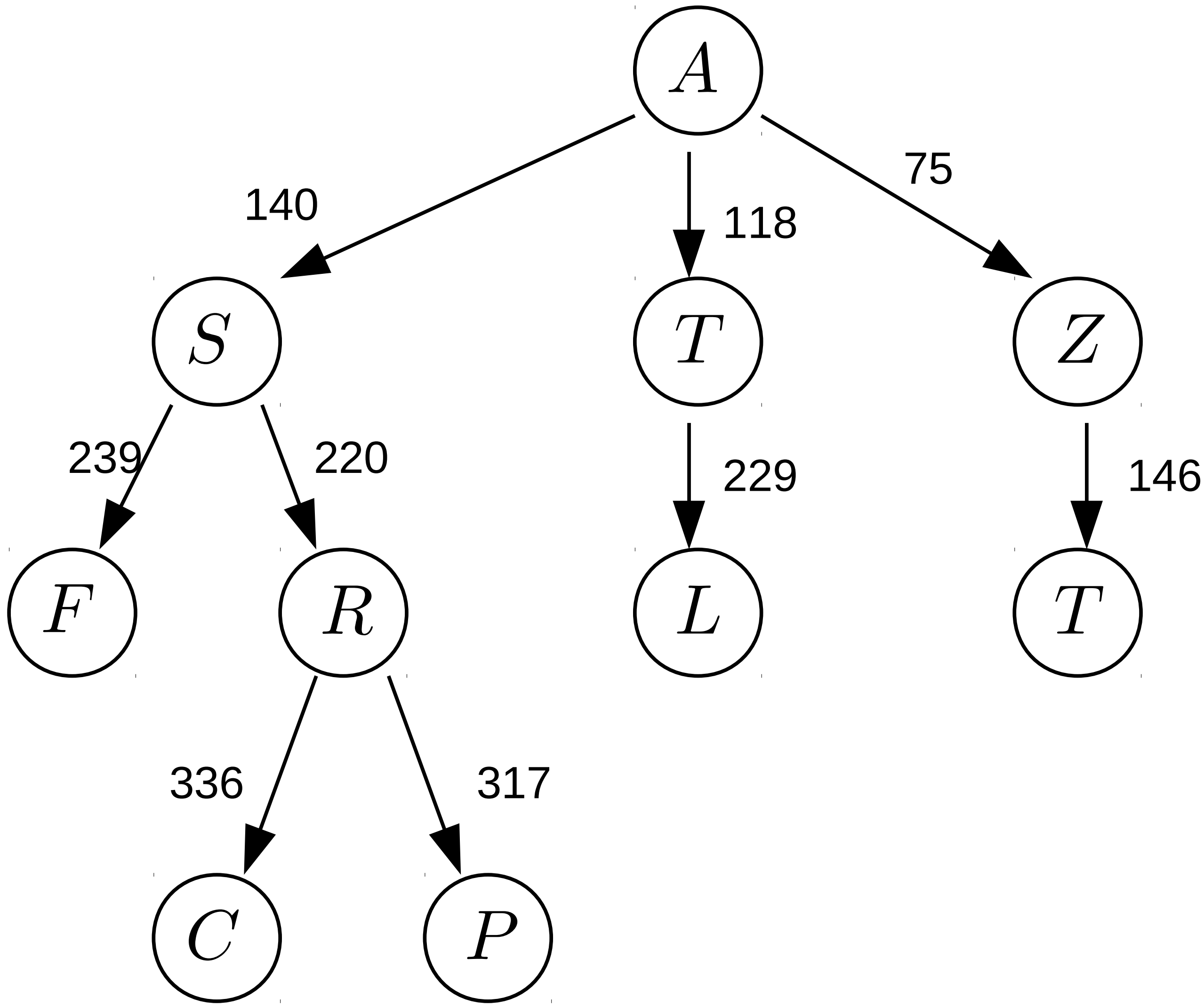


Explored set: A, Z, T, S

UCS

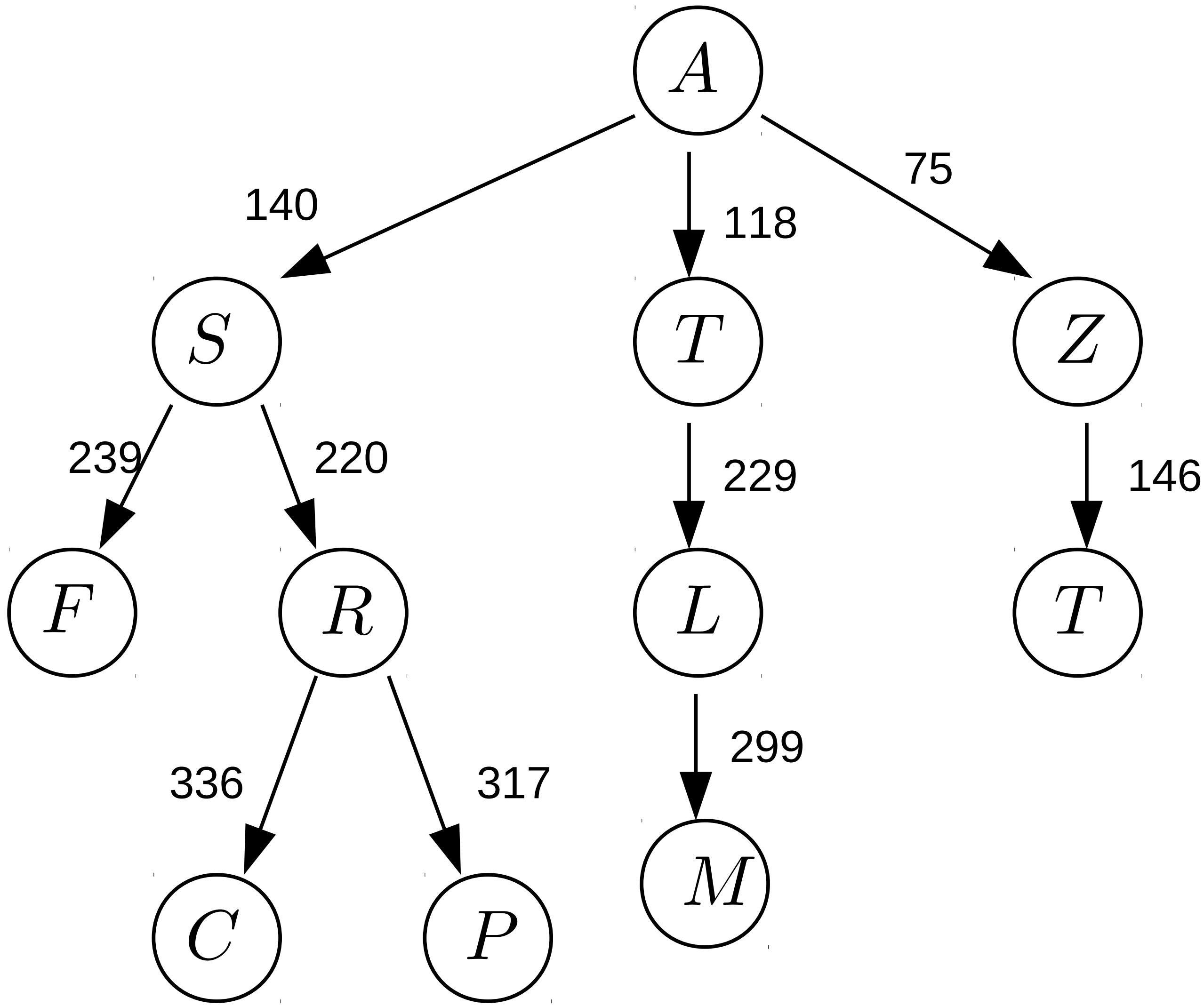
Fringe	Path Cost
~~A~~	~~0~~
~~S~~	~~140~~
~~T~~	~~118~~
~~Z~~	~~75~~
~~T~~	~~146~~
L	229
F	239
~~R~~	~~220~~
C	336
P	317



Explored set: A, Z, T, S, R

UCS

Fringe	Path Cost
~~A~~	~~0~~
~~S~~	~~140~~
~~T~~	~~118~~
~~Z~~	~~75~~
~~T~~	~~146~~
~~L~~	~~229~~
F	239
~~R~~	~~220~~
C	336
P	317
M	299

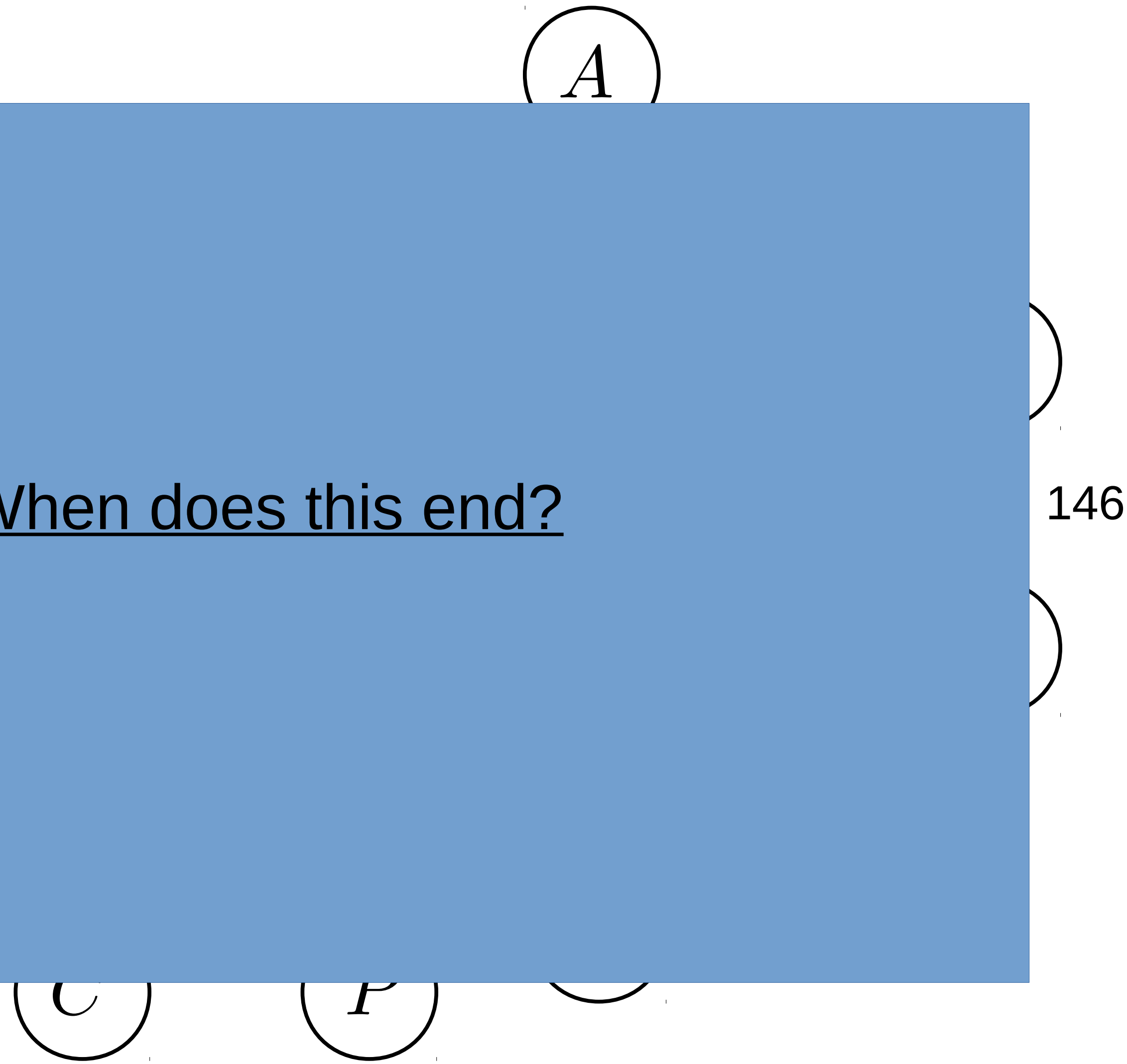


Explored set: A, Z, T, S, R, L

UCS

Fringe

~~A~~
~~S~~
~~T~~
~~Z~~
~~T~~
~~L~~
F
~~R~~
C
P
M



When does this end?

Explored set: A, Z, T, S, R, L

UCS

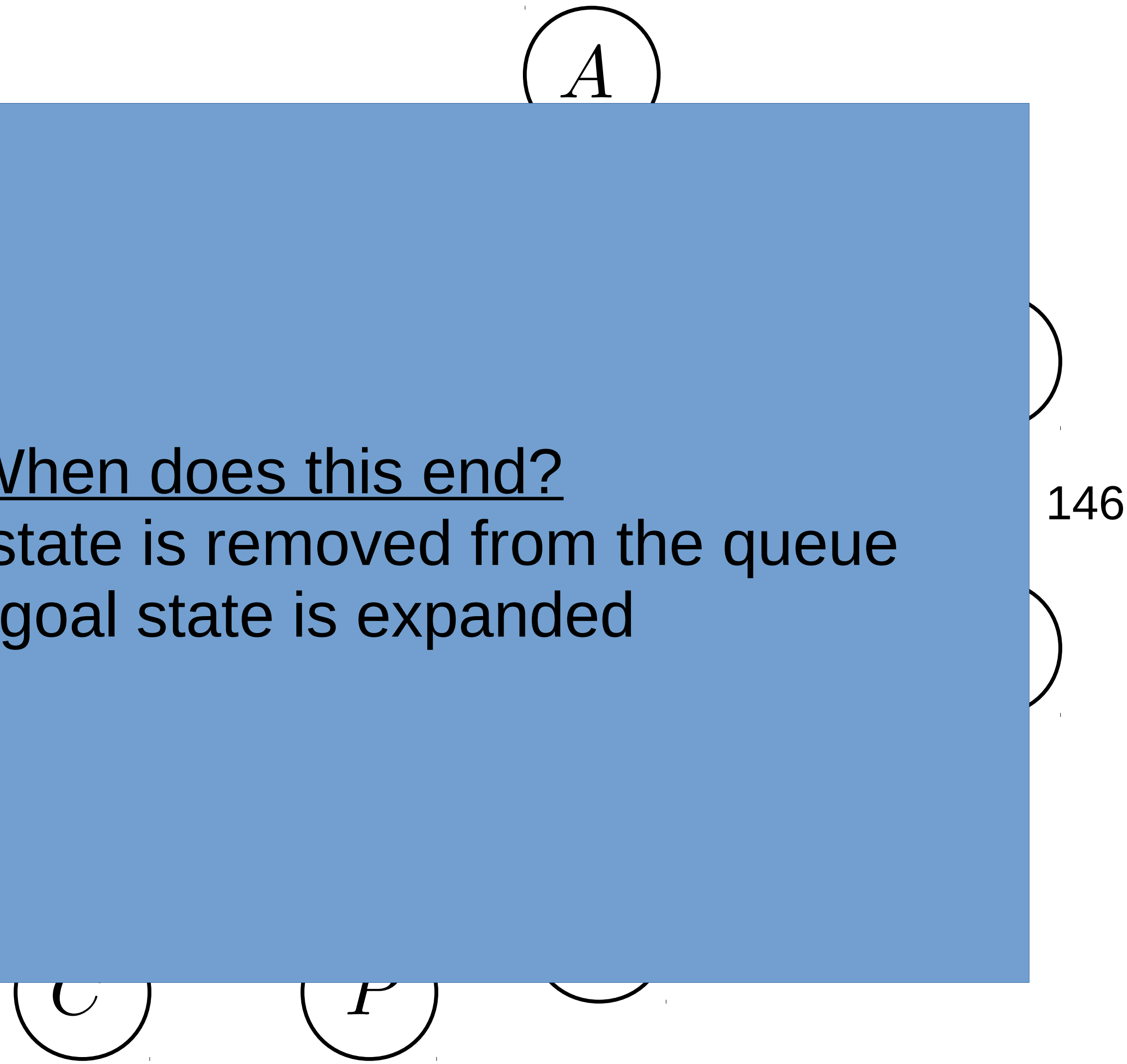
<u>Fringe</u>
~~A~~
~~S~~
~~T~~
~~Z~~
~~T~~
~~L~~
F
~~R~~
C
P
M

<u>When does this end?</u>
– when the goal state is removed from the queue

146

Explored set: A, Z, T, S, R, L

UCS



Fringe
~~A~~
~~S~~
~~T~~
~~Z~~
~~T~~
~~L~~
F
~~R~~
C
P
M

When does this end?
– when the goal state is removed from the queue
– NOT when the goal state is expanded

Explored set: A, Z, T, S, R, L

UCS

function UNIFORM-COST-SEARCH(*problem*) **returns** a solution, or failure

```
node ← a node with STATE = problem.INITIAL-STATE, PATH-COST = 0
frontier ← a priority queue ordered by PATH-COST, with node as the only element
explored ← an empty set
loop do
    if EMPTY?(frontier) then return failure
    node ← POP(frontier)   /* chooses the lowest-cost node in frontier */
    if problem.GOAL-TEST(node.STATE) then return SOLUTION(node)
    add node.STATE to explored
    for each action in problem.ACTIONS(node.STATE) do
        child ← CHILD-NODE(problem, node, action)
        if child.STATE is not in explored or frontier then
            frontier ← INSERT(child, frontier)
        else if child.STATE is in frontier with higher PATH-COST then
            replace that frontier node with child
```

Figure 3.14 Uniform-cost search on a graph. The algorithm is identical to the general graph search algorithm in Figure 3.7, except for the use of a priority queue and the addition of an extra check in case a shorter path to a frontier state is discovered. The data structure for *frontier* needs to support efficient membership testing, so it should combine the capabilities of a priority queue and a hash table.

UCS Properties

Is UCS <u>complete</u>?
– is it guaranteed to find a solution if one exists?

What is the <u>time complexity</u> of UCS?
– how many states are expanded before finding a sol'n?
  – b: branching factor
  – C*: cost of optimal sol'n
  – e: min one-step cost
  – complexity = $O(b^{C^*/e})$

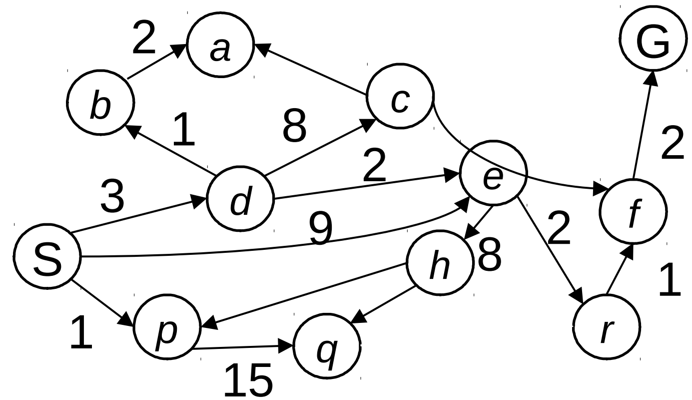
What is the <u>space complexity</u> of BFS?
– how much memory is required?
  – complexity = $O(b^{C^*/e})$

Is BFS optimal?
– is it guaranteed to find the best solution (shortest path)?

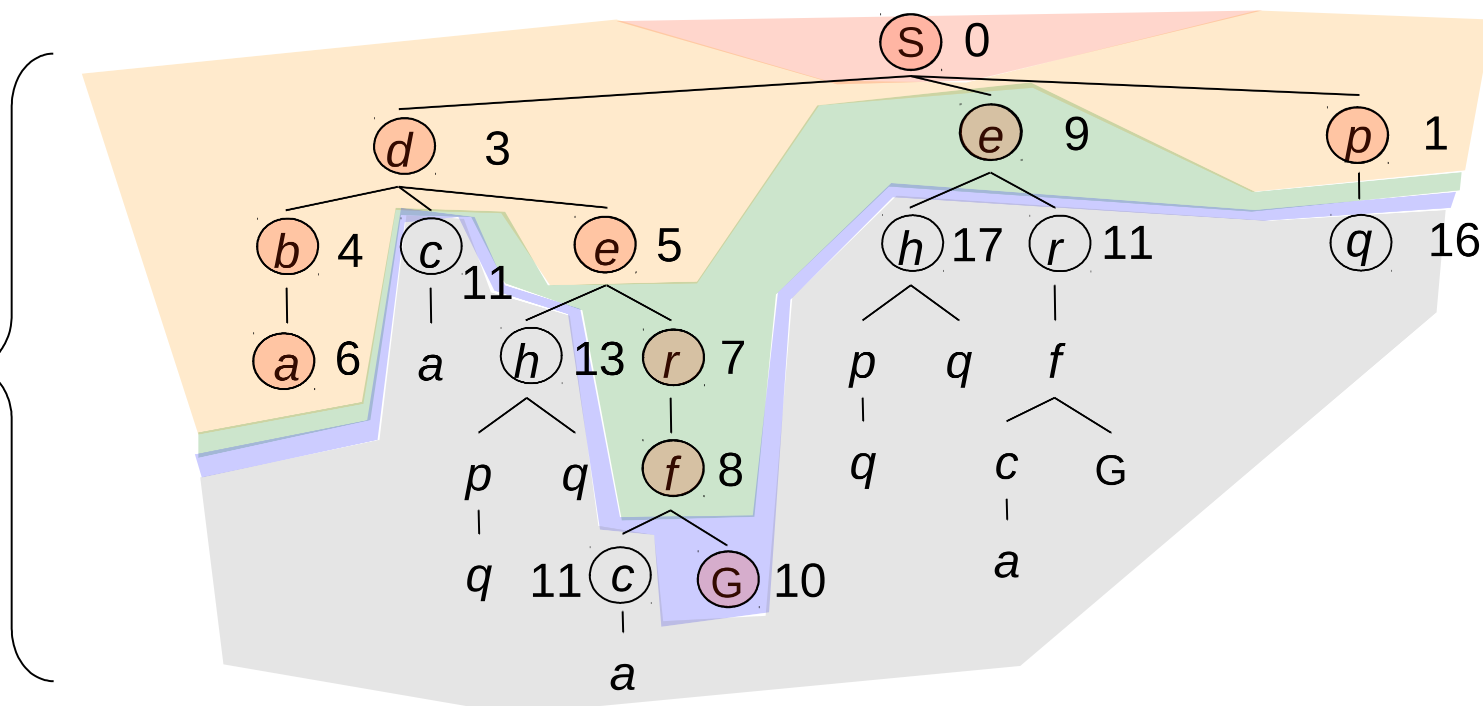
UCS vs BFS

Strategy: expand a cheapest node first:

Fringe is a priority queue (priority: cumulative cost)



Cost contours



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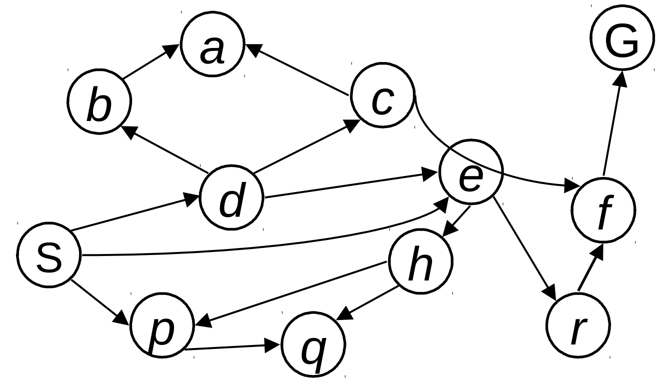
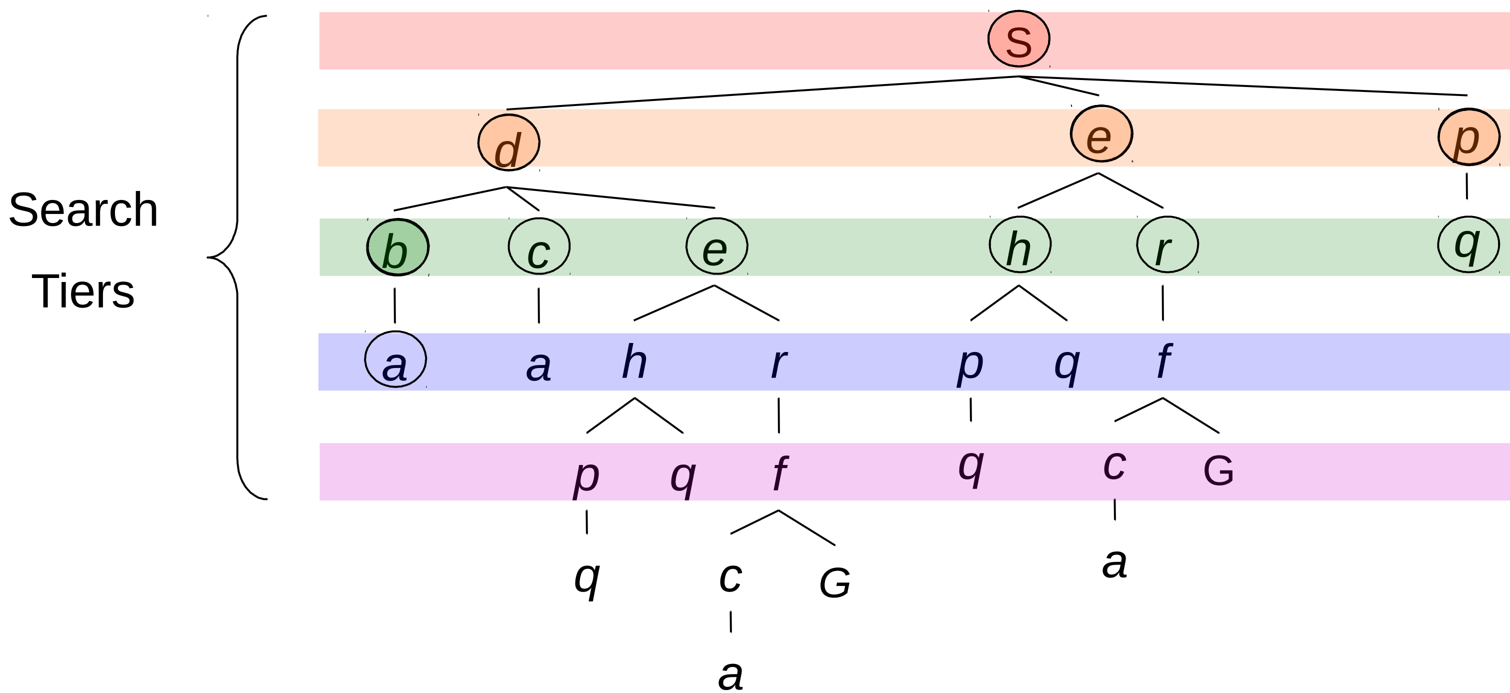
UCS vs BFS

Strategy: expand a shallowest node first

Implementation: Fringe is a FIFO queue





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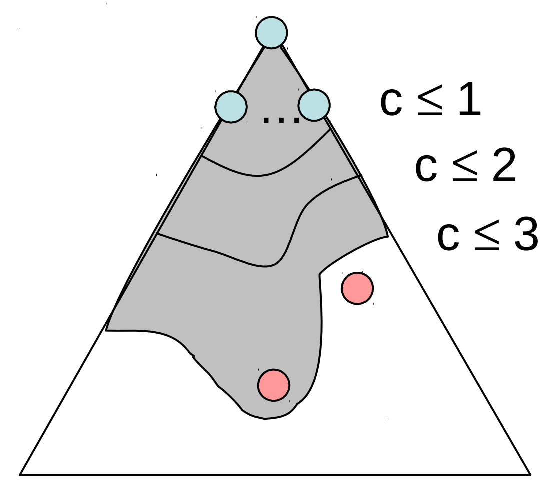
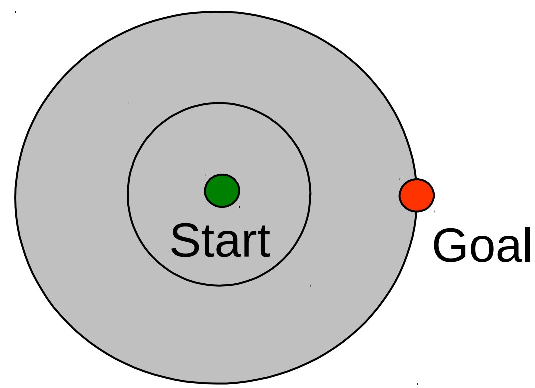
UCS vs BFS

- Remember: UCS explores increasing cost contours
- The good: UCS is complete and optimal!
- The bad:
  - Explores options in every “direction”
  - No information about goal location
- We’ll fix that soon!





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