An Improved Thorup Shortest Paths Algorithm with a Modified Component Tree

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Abstract—This paper provides an improved Thorup algorithm which modified the component tree of the original Thorup algorithm to make it able to maintain the tentative distance of each vertex without the unvisited structure. According to the experimental result, our algorithm showed a better result than the original Thorup algorithm and Fibonacci-based Dijkstra algorithm in practice. By comparison, the time cost of query is reduced by 75.04% and 58.26%, respectively.

Keywords: Dijkstra; Single-Source Shortest Path; Undirected Weights

I. INTRODUCTION

The single source shortest path (SSSP) is the problem of finding the shortest path from a source vertex to every other vertex. It has been applied in many fields such as navigation [1], keyword searching [2], computer network [3], and it is widely used for finding the optimal route in a road network. SSSP problem is described as the following throughout this research. Given a graph \( G = (V, E) \) and a source vertex \( s \in V \), suppose \( s \) can reach each vertex of the graph, then find the shortest path from \( s \) to every vertex \( v \in V \), in which \( V \) and \( E \) represent the vertices and edges of \( G \) [4]. The \( m \) and \( n \) mentioned in the rest of this paper represent \( |E| \) and \( |V| \), respectively. Use \( D(v) \) to represent the tentative distance from the source vertex to \( v \), and use \( d(v) \) to represent the ensured shortest distance from the source vertex to \( v \), and let \( L(v, w) \) represent the positive integer weights of edge \( (v, w) \). At the beginning, \( D(v) = d(v) = 0 \) for every vertex except the source vertex, \( d(s) = 0 \). The length of a shortest path should be the sum of the weights of each edge of the shortest path.

One of the most influential shortest path algorithms is Dijkstra [5][4][6] which is proposed in 1959. Yen’s paper [7] is considered to be the first one which implements Dijkstra with an array. In detail, an array is used to record the tentative distance of each vertex which is adjacent to visited vertices. Every time when a vertex is visited, the distances of the vertices which are adjacent to the vertex will be recorded in an array, and then, the vertex which has the shortest distance will be taken to try to relax the vertices which are adjacent to this vertex. The word relax is described as follows. A vertex, say \( A \), can relax another vertex, say \( B \), means the distance from the source vertex to \( B \) can be shortened through \( A \). It takes \( O(1) \) time to insert a relaxed vertex and \( O(n) \) time to delete a vertex from an array. To relax all vertices, Dijkstra algorithm runs in \( O(m) \) plus the time of maintaining the array, overall, it takes \( O(m + n^2) \).

Thorup [8] is an algorithm which theoretically proved that solving the SSSP problem in linear time with pre-processed index. The paper proposed a hierarchy- and buckets-based algorithm to pre-process indices for performing queries in undirected graphs with non-negative weights. Theoretically, this algorithm constructs the minimum spanning tree in \( O(m) \), constructs the component tree in \( O(n) \), constructs unvisited data structure in \( O(n) \), and calculates distance of all vertices based on constructed structures in \( O(m + n) \). But in practice, due to the difficulty of implementation, Thorup algorithm occasionally does not perform as expected according to the experimental result provided by Asano and Imai [9], and Pruehs [10]. This paper proposes an alternative to accelerate Thorup algorithm by reducing the structures used to maintain the tentative distance of each vertex.

II. RELATED WORKS

Asano and Imai [9], and Pruehs [10] implemented Thorup algorithm with their modifications. Asano and Imai [9] uses an array to realize the function of atomic heaps, which is used in the Thorup algorithm; uses the union with size and find with path compression algorithm instead of the union and find algorithm [11] to construct the component tree, and designs a three-levels tree as an unvisited data structure to maintain the tentative distance of each vertex.


Hagerup [16] proposed an improved hierarchy-based algorithm which theoretically solves SSSP problem in \( O(m \log \log C + n \log \log n) \), and also solves all-path shortest path (APSP) problem in \( O(mn + n^2 \log \log n) \), where \( C \) represents the maximum edge weights. Pettie [17] proposed a...
hierarchy-based algorithm which theoretically solves APSP problems in $O(mn + n^2 \log \log n)$, and proved that no SSSP algorithm can solve the problem in $\Omega(m + n \log n)$.

III. THORUP ALGORITHM

Thorup [8] is a hierarchy- and buckets-based algorithm which preprocesses indices for performing queries in undirected graphs with non-negative weights. It consists of two phases: construction and visiting. In the first phase, it constructs a minimum spanning tree [13], and then constructs a component tree in linear time based on the constructed minimum spanning tree. Each node of the component tree is a component that includes vertices. Leaf-nodes always contain only one vertex. A component is created by the connected vertices, in which their weights are smaller than $2^i$, where $i$ represents an integer that increases from 0 to $2^i \geq$ the largest weights of $G$. In the second phase, the tentative distance of each reached component will be mapped to its parent’s buckets, for deciding the order to visit vertices in different components in a hierarchy structure. This method will overcome the sorting bottleneck of priority queue-based algorithms. That is, when trying to get the vertex which has the smallest tentative distance, no method can sort the distances in linear time currently. This problem reduces the performance of Dijkstra algorithm every time when getting the vertex from a priority queue. An unvisited data structure is used to maintain the tentative distance of each vertex. It is not limited to a specific structure, and any structure that can retrieve the smallest value from numerous values efficiently can be used. Atomic heaps and Split-findmin structure are two candidates given in Thorup algorithm for the calculation.

Fig. 1 to Fig. 5 gives an example of the component hierarchy and component tree which are invented by Thorup. Fig. 1 shows a graph with five vertices. The component hierarchy of the graph is given in Fig. 2. In the figure, the identification of a component is set to the smallest ID among all vertices in the same component plus the level of the component. Please note the level is counted from the bottom. For instance, “[1]2” represents the component on level 2 of the component hierarchy in Fig. 2. It includes vertices with ID 1 and ID 2, because 1 is the smallest ID, so use “[1]” to represent this component. As the example shown in Fig. 3, for enhancing the performance, the component hierarchy is compressed to the component tree by pruning component $[v]i = [v]i-1$, where $i$ represents the level of component $v$. Fig. 4 and Fig. 5 show the components of the graph on level 1 and level 2 in the Fig. 2, respectively.

Since Thorup algorithm does not construct indices based on any source vertex, the constructed indices can be used to calculate with different source vertex without reconstruction. The atomic heaps used by Thorup’s algorithm is defined for the number of vertices more than $2^{125}$. Thorup [8] gives an alternative to avoid using atomic heaps by using split-findmin algorithm [11]. This changing reduces the algorithm’s cost to $O(C + \alpha(m, n)m)$, where $C$ represents the maximum edge weights, and $\alpha$ is an inverse function of Ackermann which grows very slowly. If the number of vertices is less than $10^{96}$, $\alpha(m, n)$ should be equal to, or less than 4 [18].

![Figure 1](image1.png)

![Figure 2](image2.png)

![Figure 3](image3.png)

![Figure 4](image4.png)

![Figure 5](image5.png)
IV. IMPROVED THORUP ALGORITHM

In this Section, an improved Thorup algorithm is proposed which can maintain the tentative distance of each vertex with the component tree itself, so as to avoid using the unvisited data structure. This change has two benefits as follows.

1. Save the time cost to construct unvisited structures.
2. Accelerate the process of calculating shortest paths.

Two variables should be added to each node of a component tree.

1. distance, which is used to record the tentative distance of each component.
2. deleted, which is used to record that if the tentative of a component is not needed to be updated. It happens when we start bucketing the component’s children.

The followings are the improved algorithms starting from the one named Visit, which were in the original Thorup paper.

1. Visit(v)
2. if v is a leaf node of component tree then
3.   VisitLeaf(v)
4.   Remove v from the bucket of v’s parent
5.   return
6. end if
7. if v has not been visited previously then
8.   Expand(v)
9.   v.ix0 = v.distance >> i-1
10. end if
11. repeat until v has no child or v.ix >> j-i is increased
12. while the bucket B[v.ix] is not empty
13.   let wh equal to the node in bucket B[v.ix]
14.   Visit(wh)
15. end while
16. v.ix = v.ix+1
17. end repeat
18. if v has any child then
19.   move v to bucket B[v.ix>>j-i] of v’s parent
20. end if
21. if v do not has child and v is not the root of the component tree then
22.   remove v from bucket of v’s parent
23. end if

Figure 6. Algorithm of visit.

1. Expand (v)
2. v.ix0 = v.distance >>i-1
3. v.deleted = TRUE
4. for each child wh of v
5.   store wh in bucket B[wh.distance >>i-1])
6. end for

Figure 7. Algorithm of Expand.

1. VisitLeaf(v)
2. for each vertex w connected with v, if v.distance + L(v, w) < w.distance
3.   Let wh be the unvisited root of leaf w
4.   Let wi be the unvisited parent of wh
5.   Decrease(w, v.distance +L(v, w))
6. if this decreases wh.distance >> i-1 then
7.   Move wh to bucket B[wh.distance >> i-1] of wi
8. end if
9. end for

Figure 8. Algorithm of VisitLeaf.

1. Decrease (v, newValue)
2. if v.distance > newValue and v.deleted ! = TRUE then
3.   v.distance = newValue
4.   let n to be the parent of v
5.   while n.deleted != TRUE and n.distance >newValue
6.     n.distance = newValue
7.   let n to be the parent of n
8. end while
9. end if

Figure 9. Algorithm of Decrease.

V. EXPERIMENT

The performance of the improved Thorup algorithm is evaluated through our modified experiment which originally provided by Pruehs [10]. The experiment compared the performance of Dijkstra and Thorup algorithm with synthetic datasets. The time cost of finding the distance of every vertex to a given source vertex is compared among the following three: Dijkstra with array-based primary queue, Dijkstra with Fibonacci-based primary queue, and Thorup. Since some algorithms mentioned in the Thorup algorithm [8] are difficult
to implement [9][10], Pruehs [10] replaced some algorithms with other algorithms. The detail information is as follows.

1. Use Kruskal’s algorithm [12] to generate a minimum spanning tree so as to avoid using Fredman and Willard’s union-find algorithm [13], since their algorithm uses atomic heaps as a priority queue, which requires $n > 2^{1220}$. It is the same as the solution given by Thorup [8]. Moreover, in Kruskal’s algorithm, Tarjan’s union-find algorithm [14] is used to make set. The time cost of constructing a minimum spanning tree is bounded in $O(\alpha(m, n) m)$. Here $\alpha$ is an inverse function of Ackermann, which grows very slowly. If the number of vertices is less than $10^{60}$, $\alpha(m, n)$ should be equal to, or less than $4[18]$. 


3. Use Gabow’s Split-findmin data structure [11] instead of atomic heaps to maintain the tentative distance of each vertex. It is called unvisited data structure in [8]. It is the same as the solution given by Thorup [8].

We modified the experiment in two phases,

1. Added the code of the improved Thorup algorithm.

2. Made the experiment possible to run with real datasets.

Because we avoid using unvisited structure in our algorithm, so the third change made by Pruehs[10] is not suitable for our algorithm. The dataset we used originally comes from the Geospatial Information Authority of Japan, which can be found from the link below:


For making it suitable for the experiment, the dataset is cut into five parts. All the datasets are pruned to delete single lines which both sides of this kind of line do not connect to other lines. Otherwise the minimum spanning tree cannot be constructed. An instance of a single line is shown in Fig. 10. The algorithm of the prune single line is given in Fig. 11.

```python
Delete_single_line (dataset)
1  for each line x in dataset
2    start = x.StartPoint
3    end = x.EndPoint
4  for each line y in dataset
5    if (start.intersection(y) && x!, y) then
6      start_intersect = TURE
7      end if
8    if (end.intersection(y) && x!, y) then
9      end_intersect = TURE
10   end if
11   if (start_intersect == TURE &&
12     end_intersect == TURE)
13     newdataset.add(x)
14   break
15 end for
16 return newdataset
```

---

Detailed information of datasets is given by Table I. The pruned datasets can be found:

http://weiyusi.com/resource/gm-jpn-trans_u_2.7z

The source code of this project can be found:

http://weiyusi.com/resource/ShortestPaths.7z

**TABLE I. INFORMATION OF DATASETS.**

<table>
<thead>
<tr>
<th>Info/Data</th>
<th>1</th>
<th>2</th>
<th>3</th>
<th>4</th>
<th>5</th>
</tr>
</thead>
<tbody>
<tr>
<td>Vertices</td>
<td>1889</td>
<td>6913</td>
<td>11478</td>
<td>14295</td>
<td>16670</td>
</tr>
<tr>
<td>Edges</td>
<td>5920</td>
<td>21798</td>
<td>36262</td>
<td>44904</td>
<td>53318</td>
</tr>
</tbody>
</table>

The experiment proposed by Pruehs [10] originally can generate datasets, but does not support import of external dataset. We modified the project to make it able to transform Line Shapfiles to experimental datasets. Since the amount of the code is big, the algorithm is given in Appendix. It uses hash tables to allocate a unique vertex ID to each endpoint of each line in a Shapfile, and gets the length of a line as the weights of an edge. So that it turns endpoints to vertices, and turns lines to edges, which will be used in the experiment. In the situation that many lines have the same endpoints, the one has the shortest length will be reserved, and the others will be ignored.
In the algorithm introduced in the Appendix, from the line 5 to 7, we got the information of each line including weights and the coordinates of both of its endpoints. From the line 8 to line 21, we attempt to allocate a unique ID to each endpoint which was not allocated before. Each allocated endpoint will be stored in a hash table. Before allocating an ID, firstly, the program checks whether the endpoint is already in the hash table, which means it was allocated an ID before. This is used to make sure the spatial intersection point of two or more lines will not be allocated as two different IDs. When there are more than one line having the same endpoints, line 22 to 30 make sure that only the edge which has the shortest length can be kept in the dataset. As the example shown in Fig.12, there are two lines A and B, they are composed of many points, and they share the same endpoints, vertex v1 and v2. Assume the path’s length of A is shorter than B, and then A will be reserved in the dataset. Line 32 to the end of this algorithm creates an adjacent list with all transformed data which are used as an experimental dataset.

The result of comparison between Dijkstra, Thorup and our algorithm is given in Table II and Fig. 13. Because of Thorup algorithm can respond in arbitrary time of shortest path query from any vertex by constructing an index only one time, here we focus on the comparison of visiting part. Comparing to the Fibonacci-based Dijkstra and the original Thorup algorithm, our algorithm reduced 58.26% and 75.04% of time cost with all the five datasets, respectively. Comparing to the array-based Dijkstra algorithm, however, our algorithm takes 29.87% more time to finish query.

**VI. CONCLUSION**

We have proposed a practically-improved Thorup-based algorithm. It maintains the tentative distance of each vertex by a modified component tree of the Thorup algorithm so as to avoid using unvisited data structure. It costs 58.26% and 75.04% less time than Fibonacci-based Dijkstra and the original Thorup algorithm, respectively, but still slower than the array-based Dijkstra algorithm. In the future work, we shall try to find the structure that performs better than a component tree in maintaining the tentative distance of each vertex, and try to use the component tree to visit vertices in a more efficient way.
APPENDIX

The algorithm of transforming a Shapfile to experimental dataset is listed as follows.

```java
1. Hashtable hb, hbw
2. List edges, graph
3. Int id = 0
4. for each line l of the Shapfile do
5.    sp = l.StartPoint
6.    ep = l.EndPoint
7.    weight = l.Length
8.    s = hb.get(sp)
9.    e = hb.get(ep)
10. if s ==null then
11.    hb.put(s, id)
12.    id++
13. else sEdge = s
14. end if
15. if e ==null then
16.    hb.put(e, id)
17.    id++
18. else eEdge = e
19. end if
20. w = hbw.get(eEdge)
21. if w == null then
22.    hbw.put(w, weight)
23.    edges.add(WeightedEdge(sEdge, eEdge))
24. else if w > weight then
25.    hbw.remove(w)
26.    hbw.put(w, weight)
27. end if
28. end for
29. for each edge e in edges do
30.    sEdge = e.Source
31. end for
32. eEdge = e.Target
33. weight = hbw.get(sEdge + "-" + eEdge)
34. graph.add(WeightedEdge(sEdge, eEdge, weight))
35. graph.add(WeightedEdge(eEdge, sEdge, weight))
```

REFERENCES


