Jukka Suomela Aalto University Locality in online, dynamic, sequential, and distributed graph algorithms

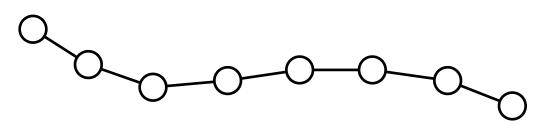
Joint work with:

- Amirreza Akbari
- Navid Eslami
- •Henrik Lievonen
- Darya Melnyk
- Joona Särkijärvi

arxiv.org/abs/2109.06593

Informal introduction to locality

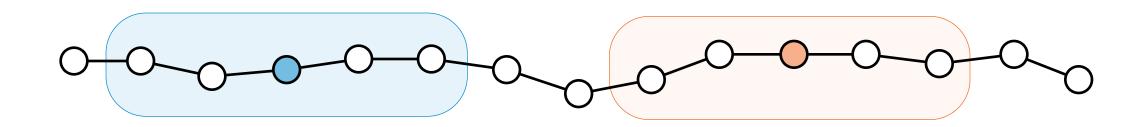
• Given: a path graph



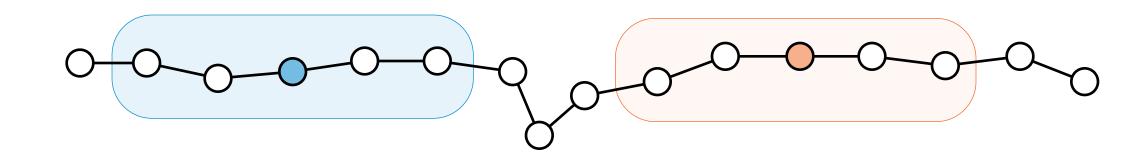
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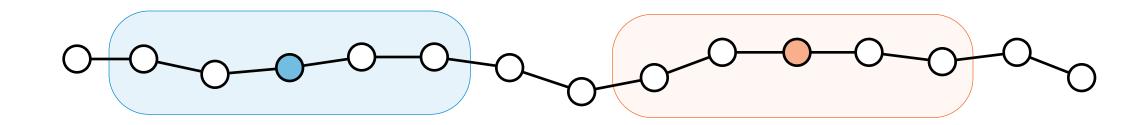


Conclusion: Paths can't be 2-colored with any local strategy

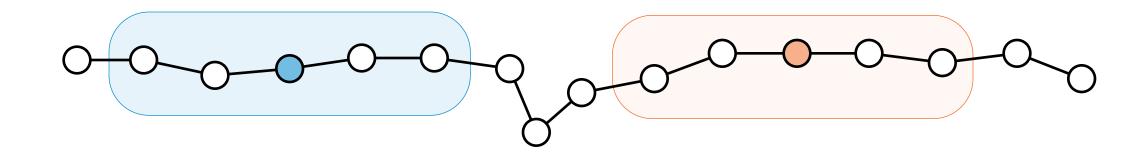
... and it doesn't really depend on exactly how we define "local"

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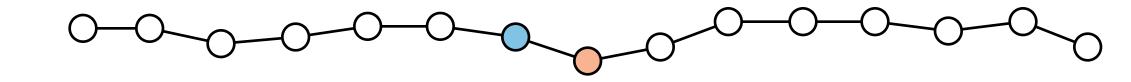


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- randomness
- unique node identifiers
- sequential ordering ...

Nodes labeled with (small) unique identifiers: locality ≈ ½ log* n

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[Cole & Vishkin 1986, Linial 1992, Naor 1991]

Four models of computing

LOCAL distributed, parallel online LOCAL centralized

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LOCAL distributed, parallel

Each node **in parallel**:

- looks at its radius-T neighborhood
- picks its output based on this information

(nodes have unique identifiers)

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Each node in a sequential, adversarial order:

- looks at its radius-T neighborhood
- picks its output & state based on this information

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Graph **constructed** by an adversary that adds nodes and edges one by one

We can see everything

We can **change** our output only within distance *T* from a point of change

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Some unknown input graph is **revealed** piece by piece:

- adversary points at a node v
- we can see the radius-T neighborhood of v
- we have to choose the label for *v*

We can **remember** everything

online LOCAL centralized

LOCAL distributed, parallel online LOCAL centralized

Genuinely different models

LOCAL distributed, parallel online LOCAL centralized



LOCAL distributed, parallel online LOCAL centralized



LOCAL distributed, parallel online LOCAL centralized





dynamic

LOCAL

centralized

LOCAL distributed, parallel

> cycle detection

online LOCAL centralized

leader election Closely related models **SLOCAL** distributed, sequential

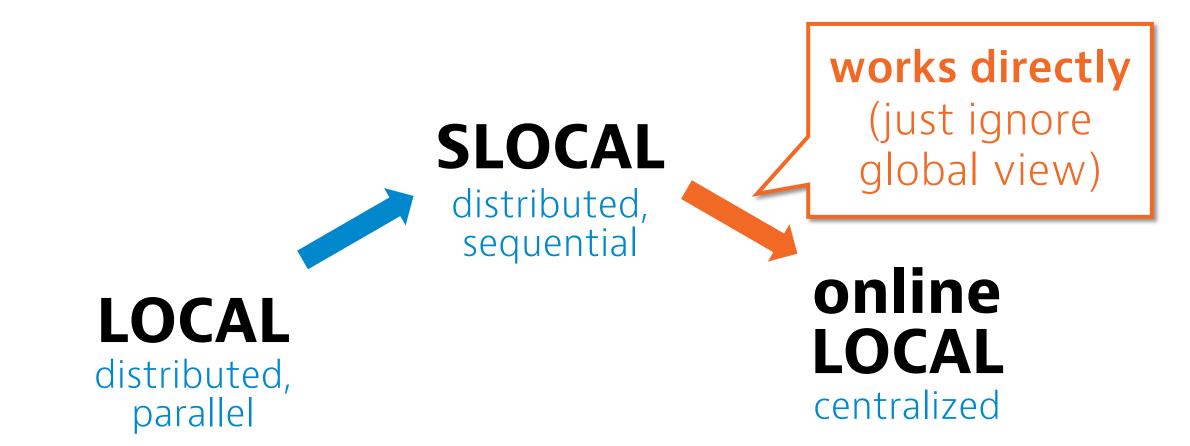
LOCAL distributed, parallel online LOCAL centralized

dynamic LOCAL centralized works directly (just ignore local states)

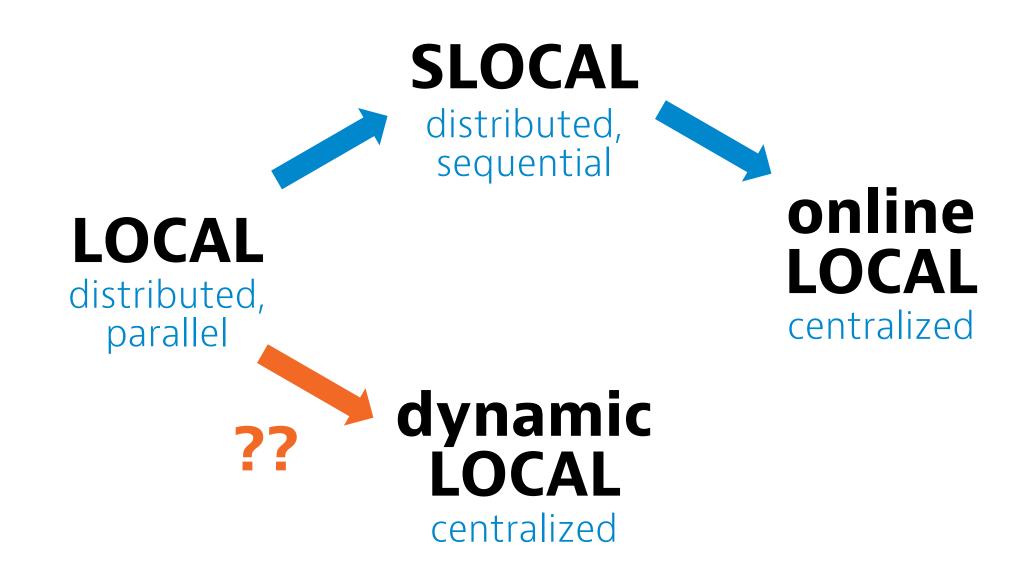
SLOCAL distributed, sequential

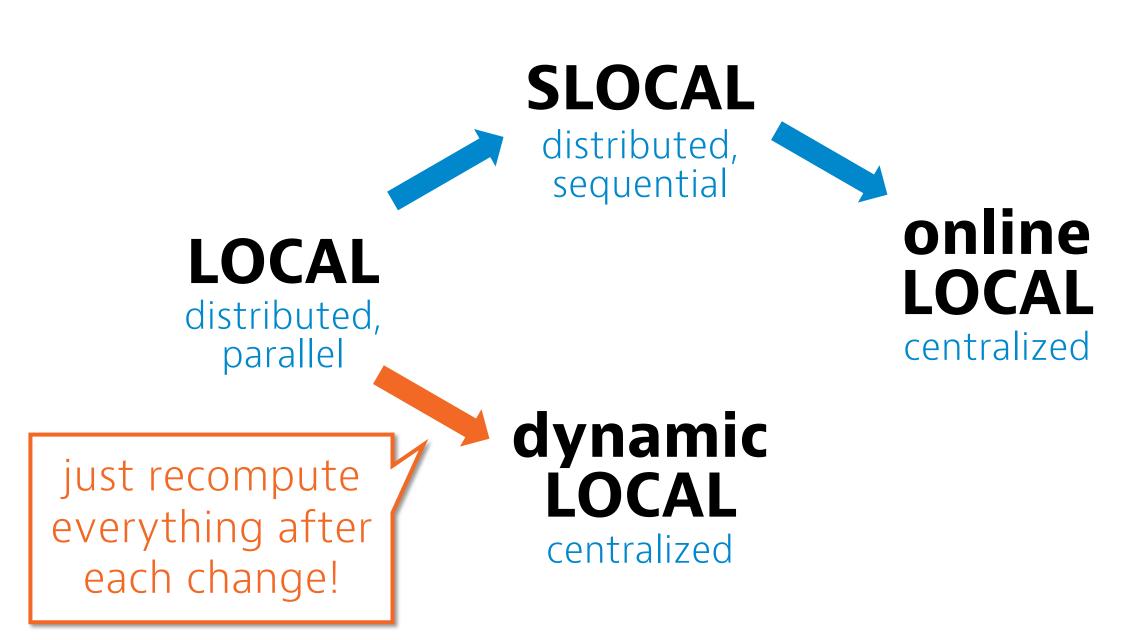
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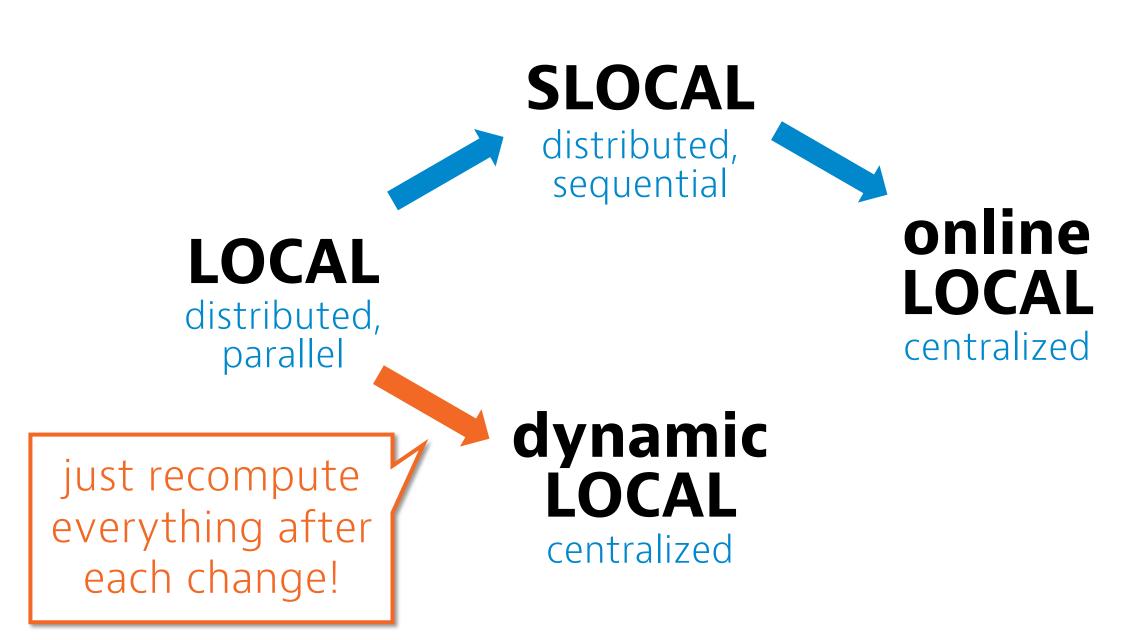


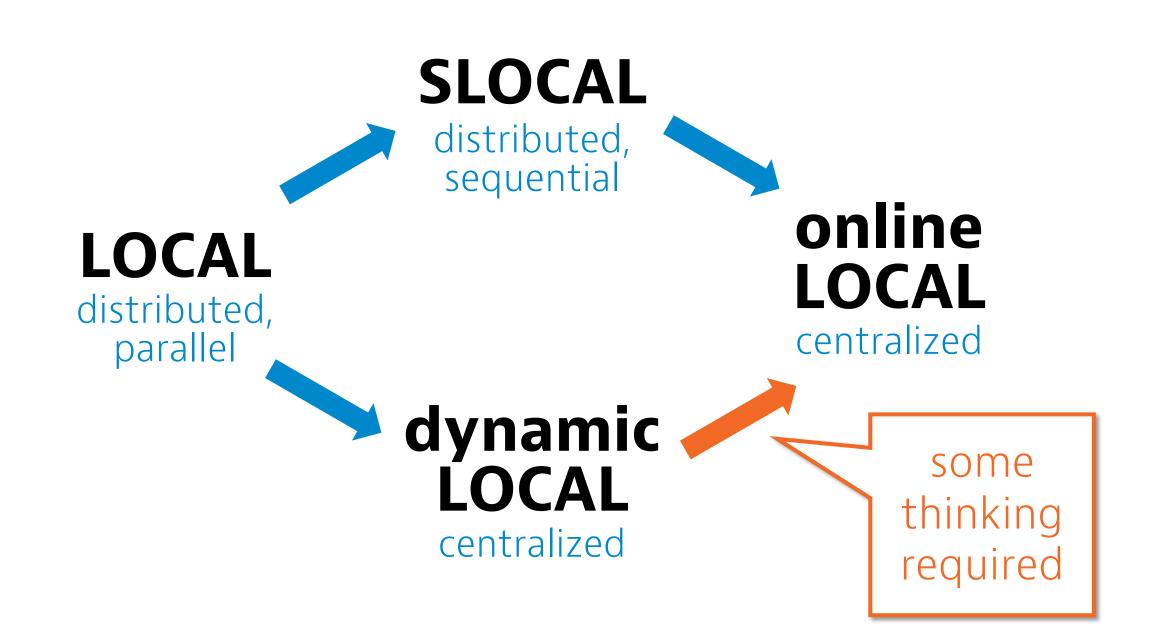
Equivalent perspectives

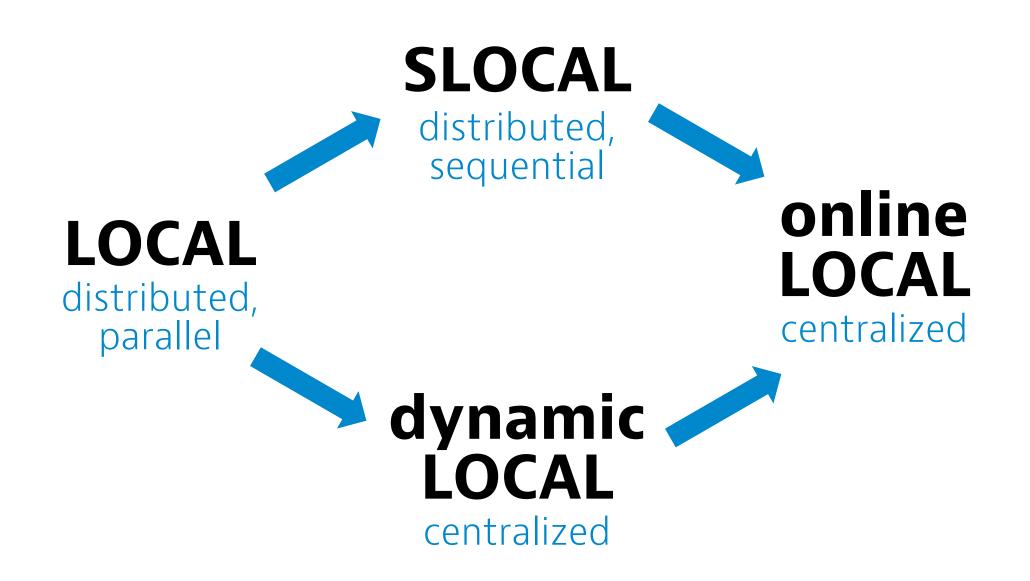
- Output of node v only depends on inputs of nodes u with dist(u, v) ≤ T
 - this is what we have by definition in LOCAL algorithms

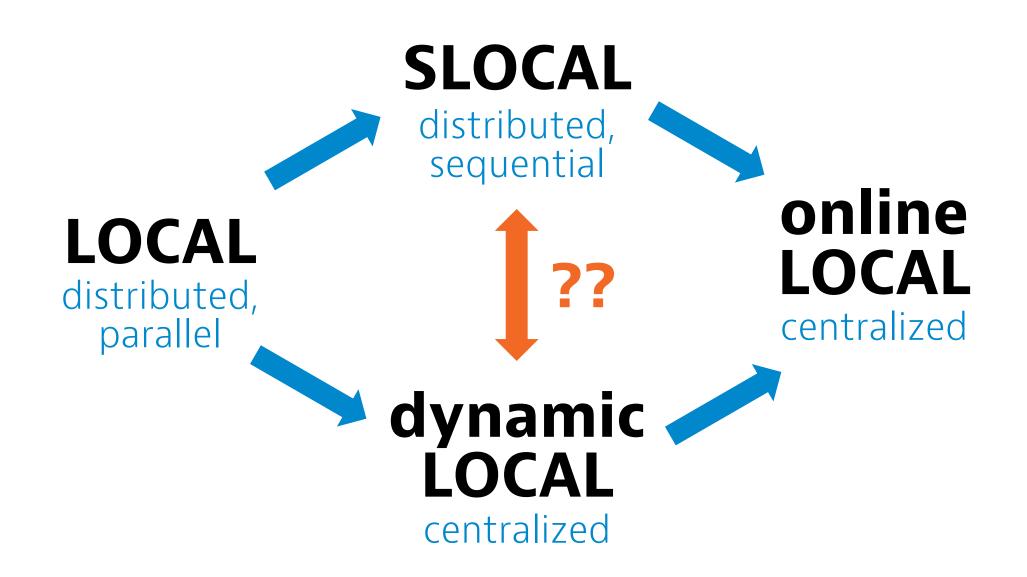
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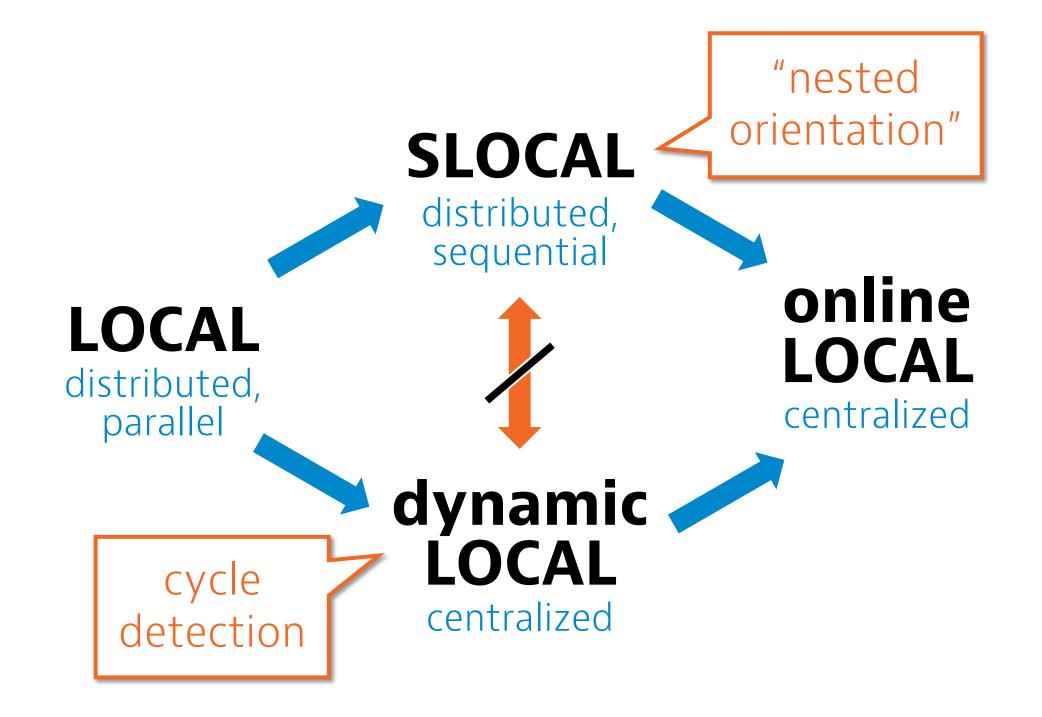
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 - this is what we have by definition in LOCAL algorithms
- Changes at node *u* can only influence outputs of nodes *v* with dist(*u*, *v*) ≤ *T*
 - this is enough to have a dynamic LOCAL algorithm

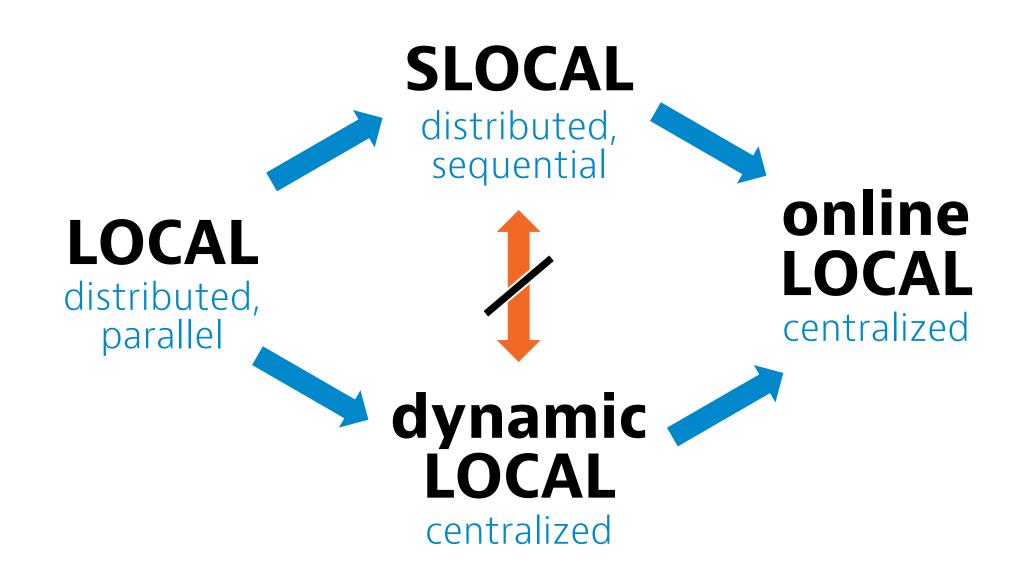












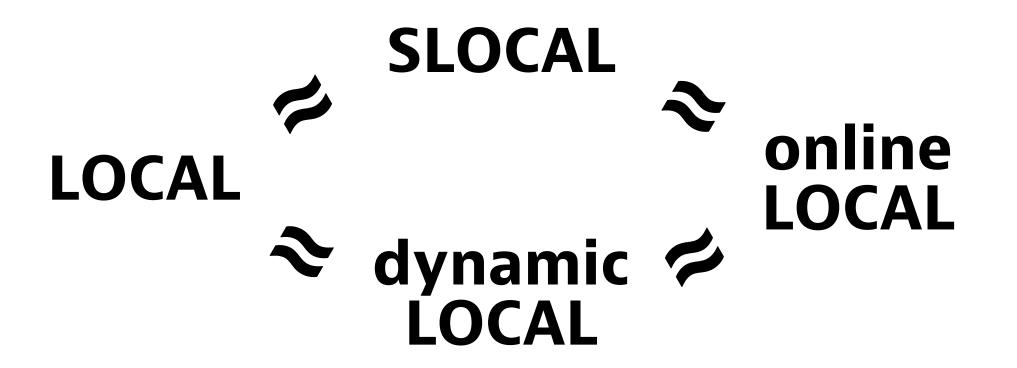
Collapse in rooted trees

LCLs in rooted trees

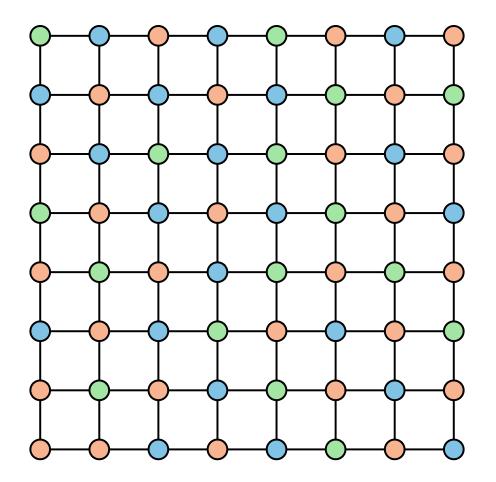
- Rooted regular trees
- Locally checkable labelings (LCLs)
 - solution valid if it "looks good everywhere"
 - example: 3-coloring

In this setting all models equally strong!

LCLs in rooted trees



Case study: grids



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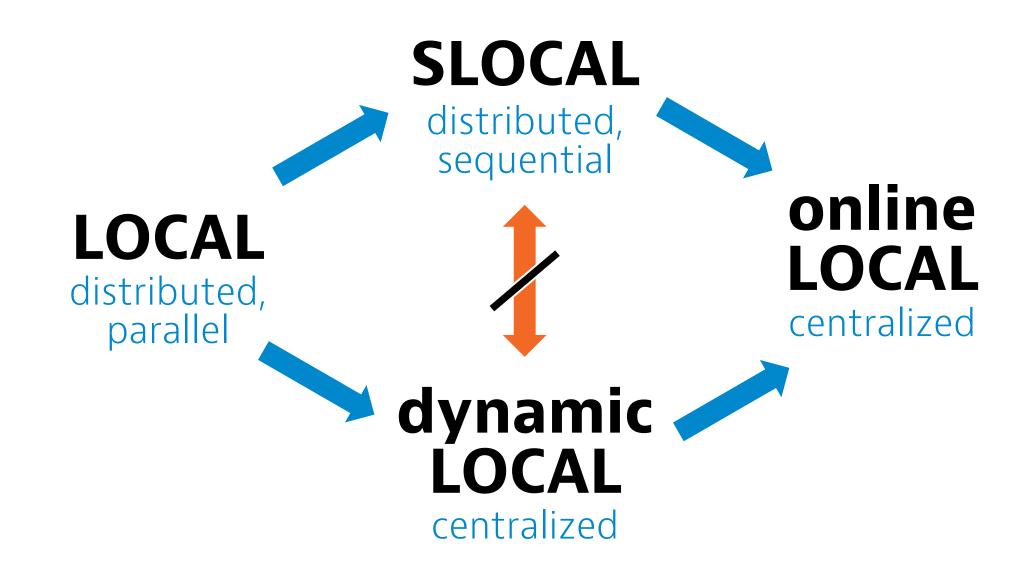
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- LOCAL, SLOCAL: global
- online-LOCAL: O(log n) is this tight?
- dynamic-LOCAL: **open**

Distinct in general, equivalent for LCLs in trees



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