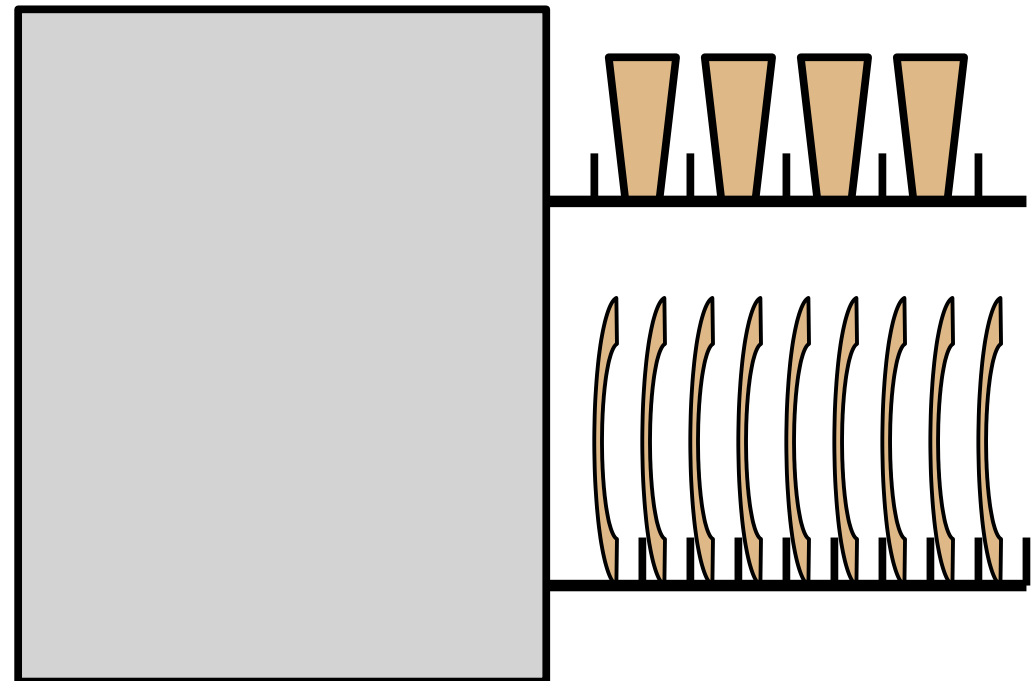
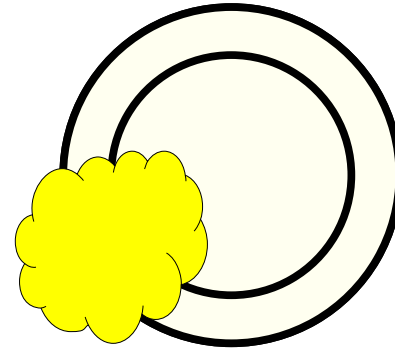


# Amortized Analysis

# A Motivating Analogy

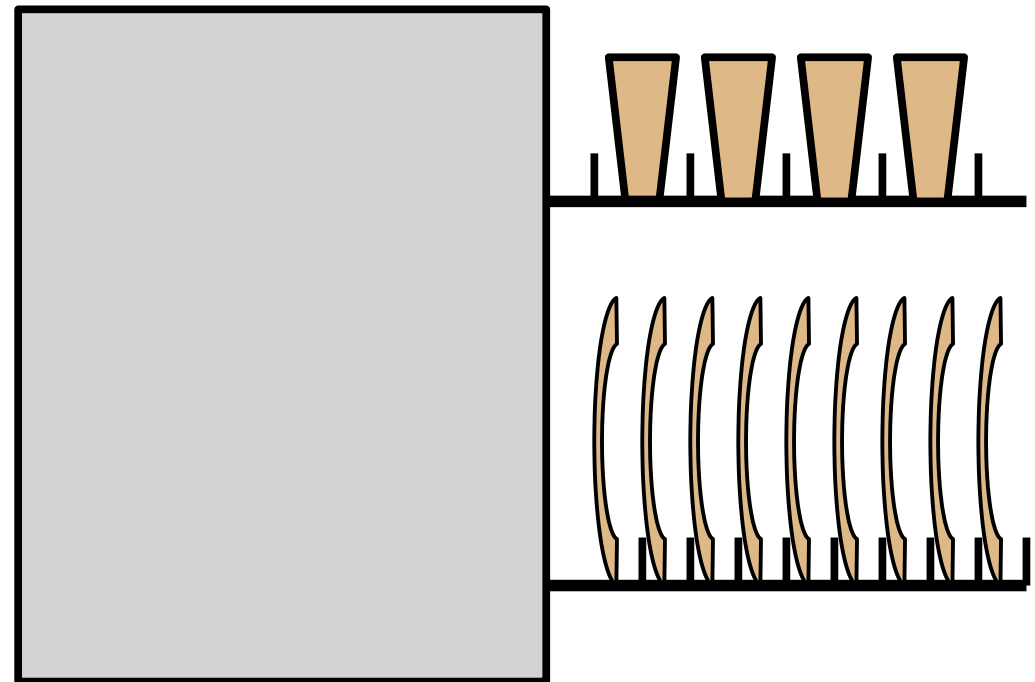
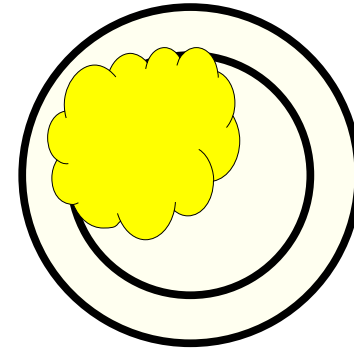
# Doing the Dishes

- What do I do with a dirty dish or kitchen utensil?
- **Option 1:** Wash it by hand.
- **Option 2:** Put it in the dishwasher rack, then run the dishwasher if it's full.



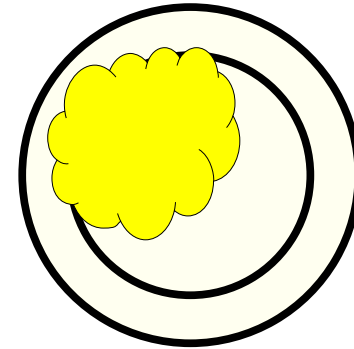
# Doing the Dishes

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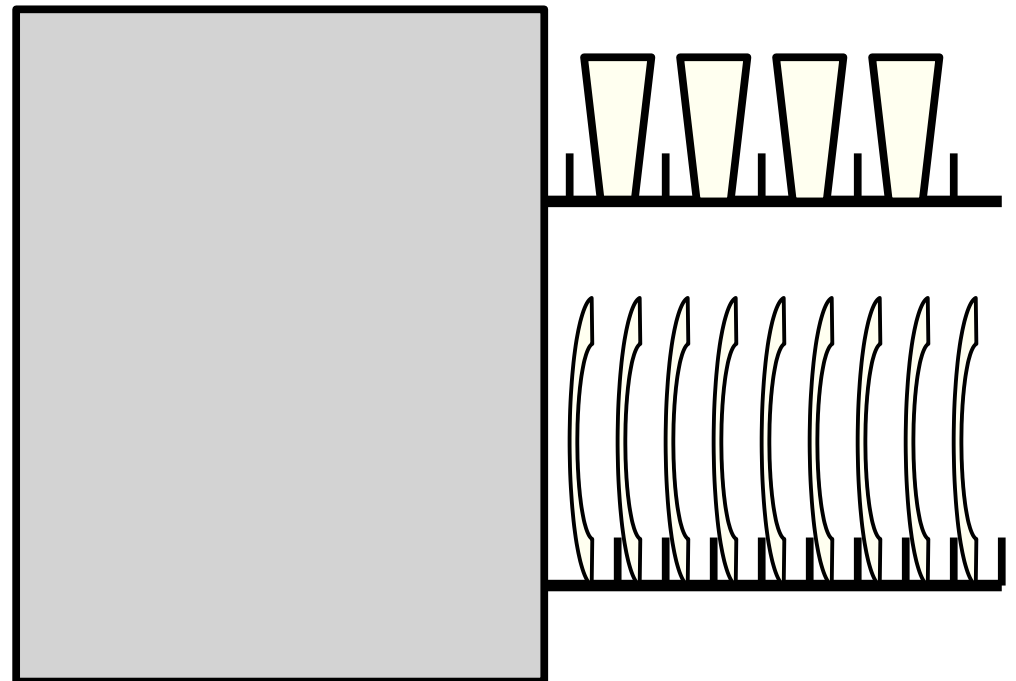
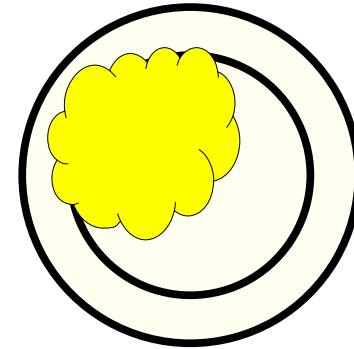
# Doing the Dishes

- What do I do with a dirty dish or kitchen utensil?
- **Option 1:** Wash it by hand.
- **Option 2:** Put it in the dishwasher rack, then run the dishwasher if it's full.



# Doing the Dishes

- Washing every individual dish and utensil by hand is *way* slower than using the dishwasher, but I always have access to my plates and kitchen utensils.
- Running the dishwasher is faster in aggregate, but means I may have to wait a bit for dishes to be ready.
- (This is an example of a tradeoff between ***throughput*** and ***latency***.)



***Key Idea:*** Design data structures that trade *per-operation efficiency* for *overall efficiency*.

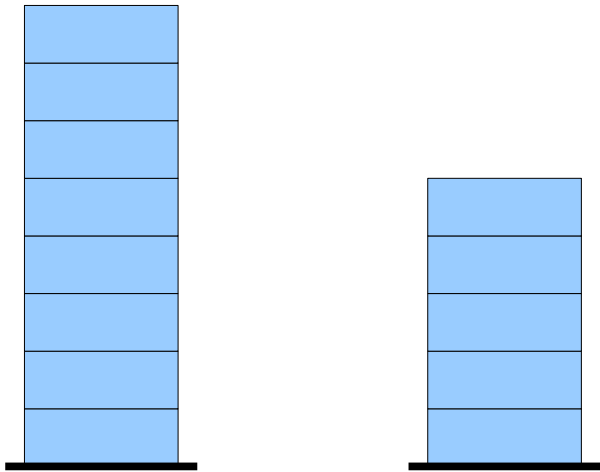
# Where We're Going

- ***Amortized Analysis (Today)***
  - A little accounting trickery never hurt anyone, right?
- ***Binomial Heaps (Next Tuesday)***
  - A fast, flexible priority queue that's a great building block for more complicated structures.
- ***Fibonacci Heaps (Next Thursday)***
  - A priority queue optimized for graph algorithms that, at least in theory, leads to optimal implementations.

# Outline for Today

- ***Amortized Analysis***
  - Trading worst-case efficiency for aggregate efficiency.
- ***Examples of Amortization***
  - Three motivating data structures and algorithms.
- ***Potential Functions***
  - Quantifying messiness and formalizing costs.
- ***Performing Amortized Analyses***
  - How to show our examples are indeed fast.

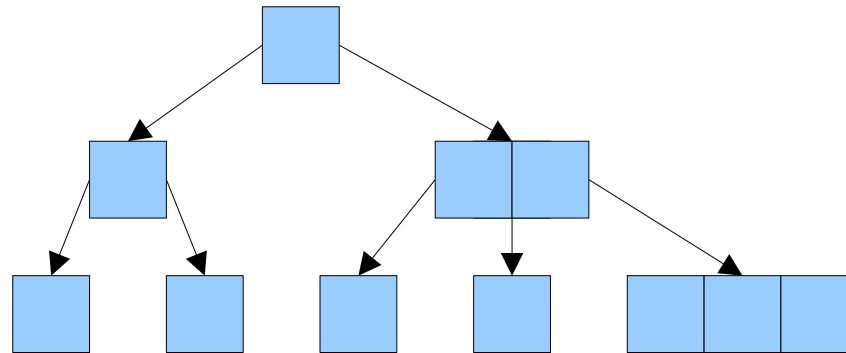
# Three Examples



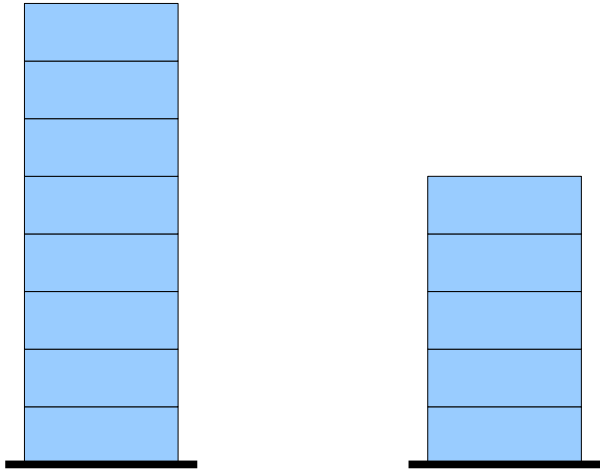
*Two-Stack Queues*



*Dynamic Arrays*



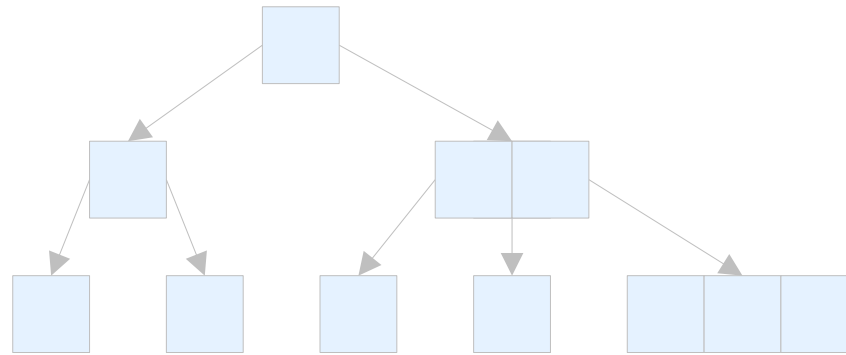
*Building B-Trees*



*Two-Stack Queues*



*Dynamic Arrays*



*Building B-Trees*

# The Two-Stack Queue



**Out**



**In**

# The Two-Stack Queue

**Out**

**1**  
**In**

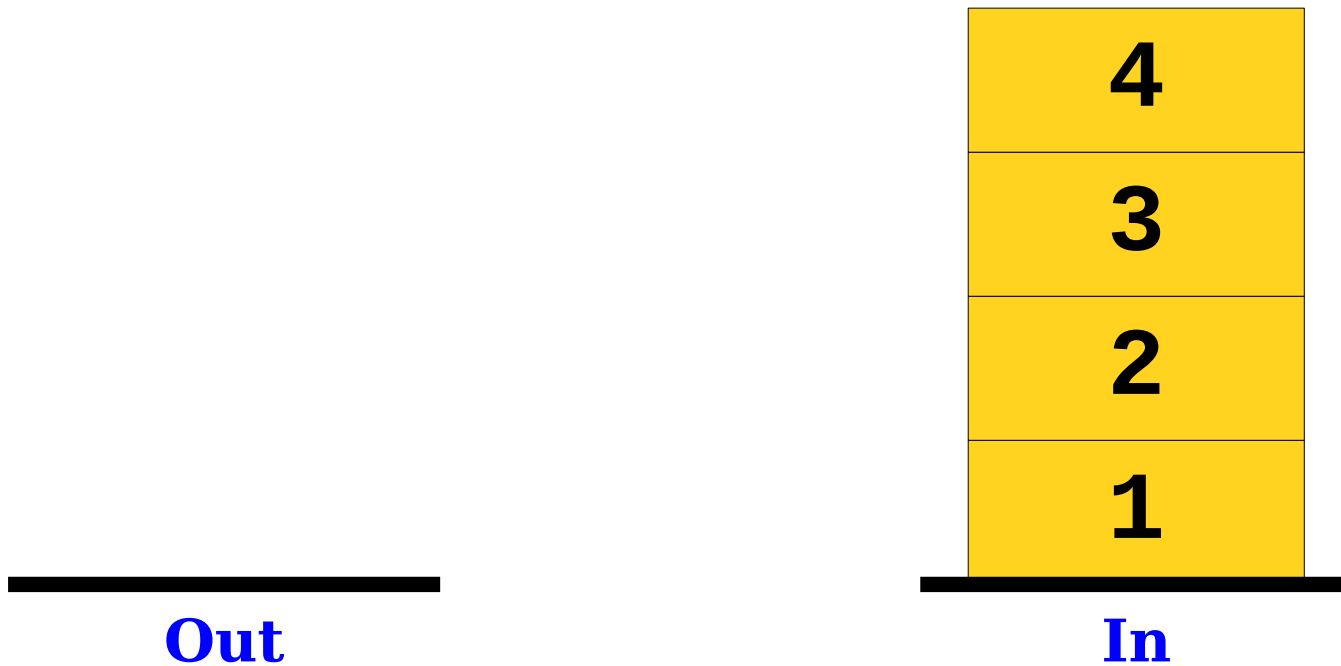
# The Two-Stack Queue



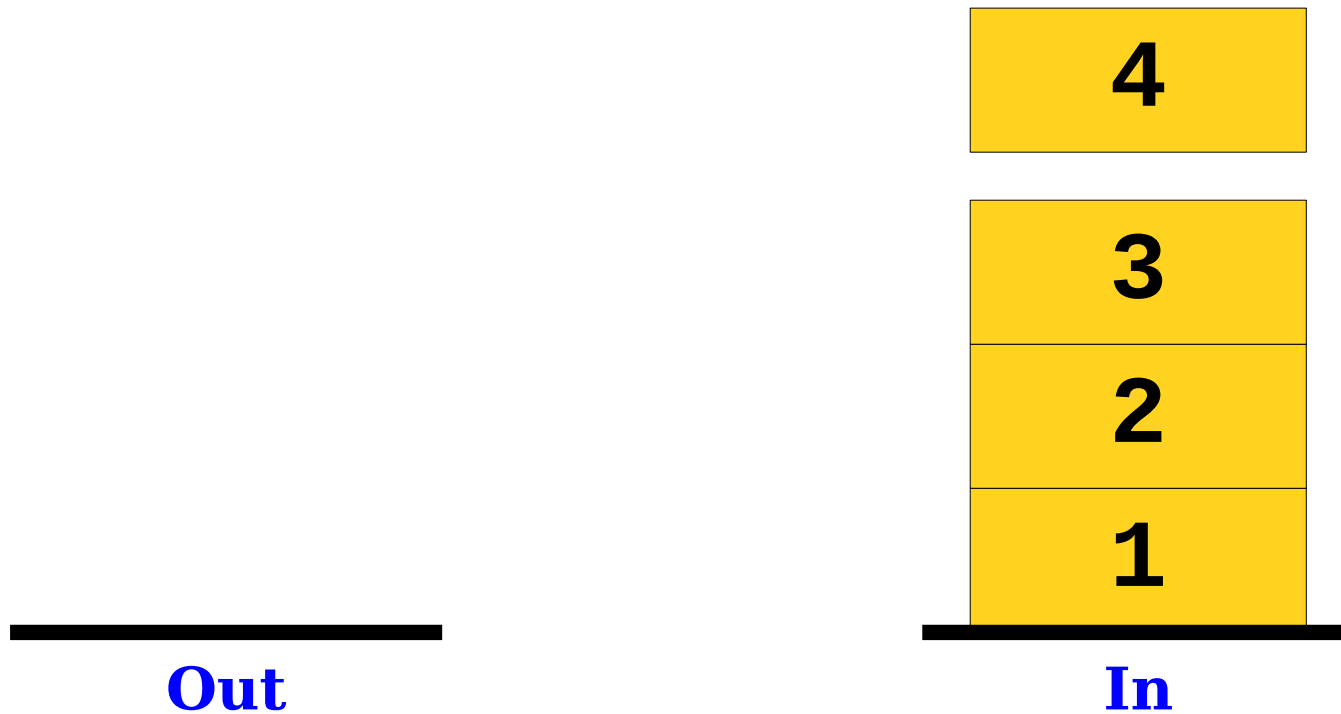
# The Two-Stack Queue



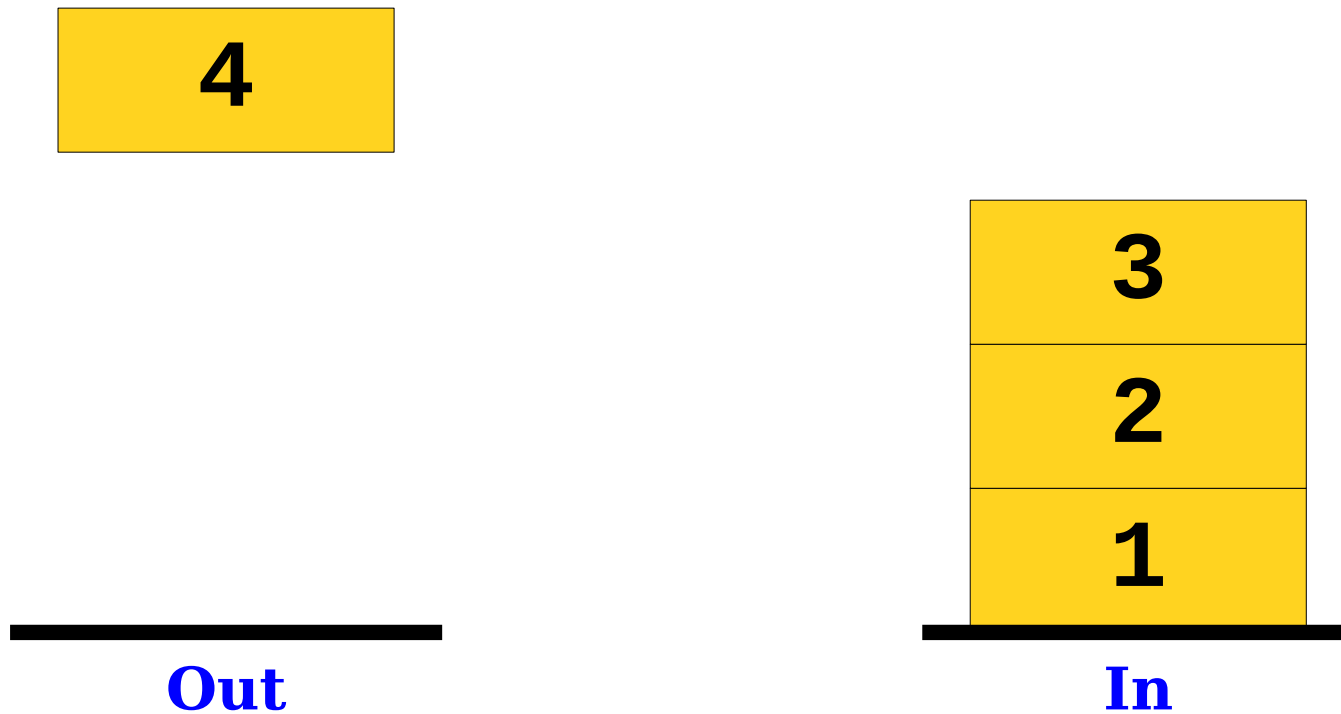
# The Two-Stack Queue



# The Two-Stack Queue



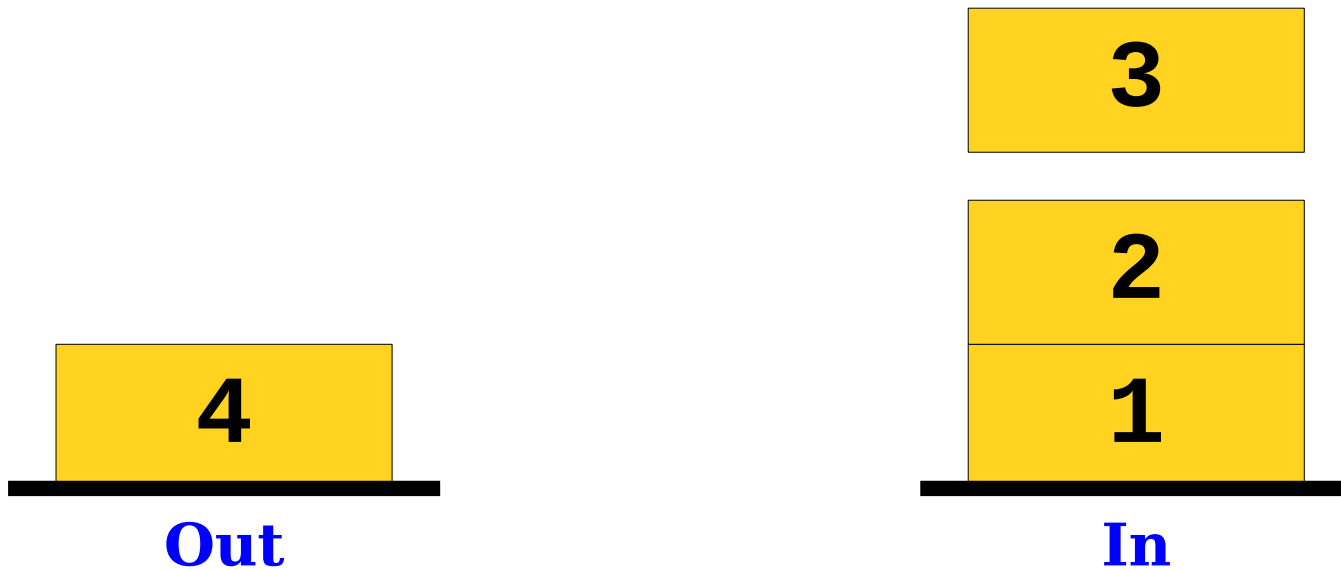
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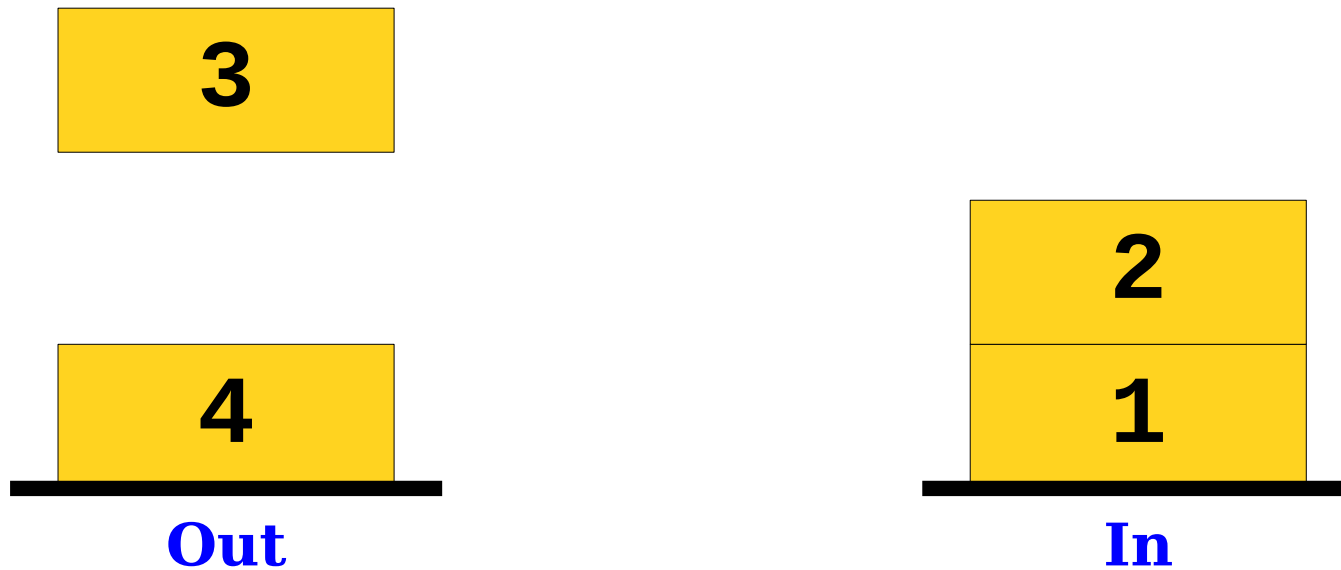
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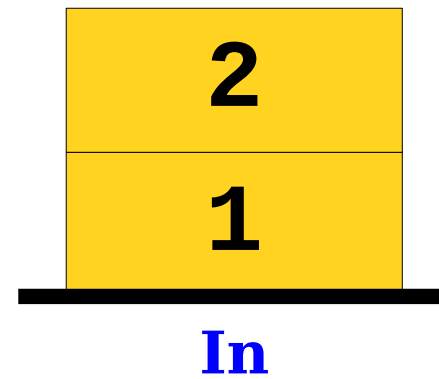
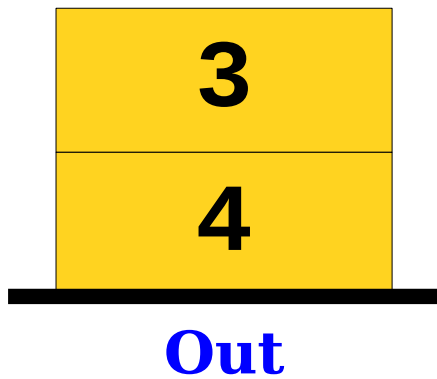
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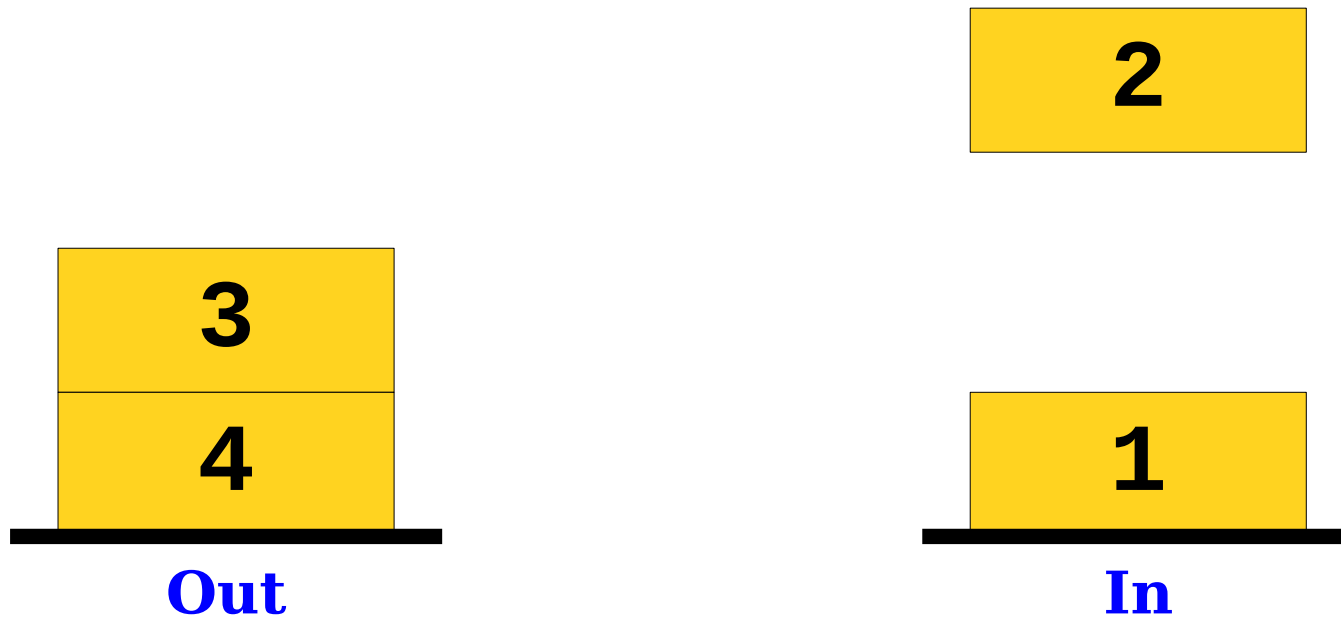
# The Two-Stack Queue



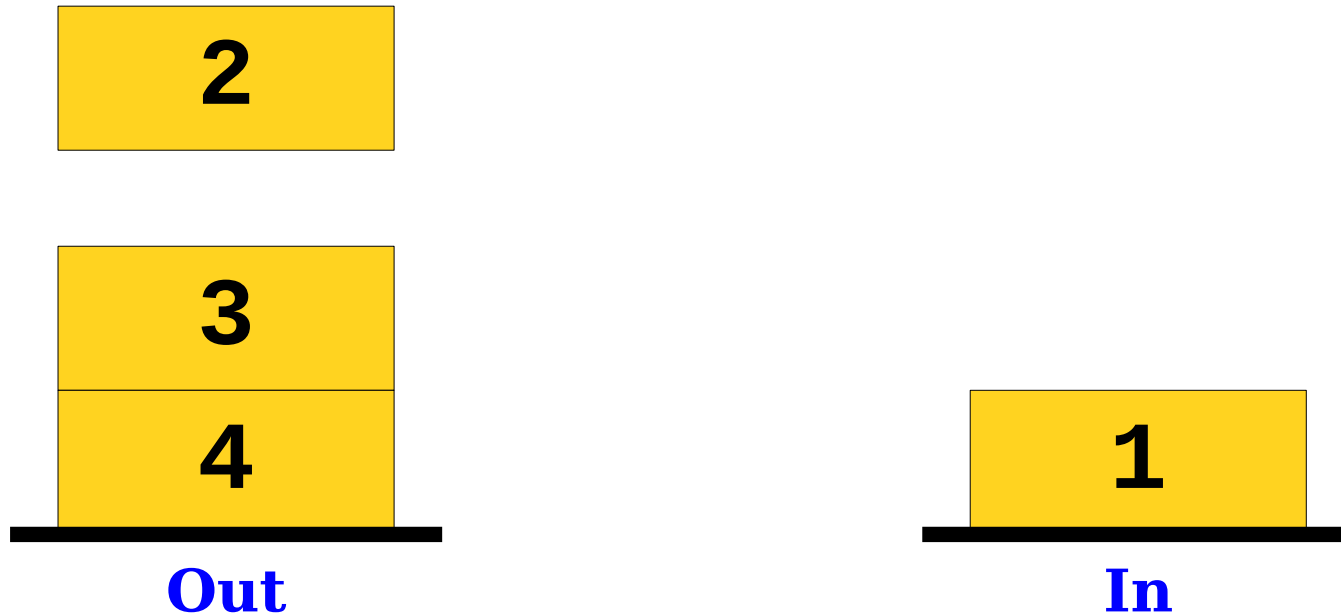
# The Two-Stack Queue



# The Two-Stack Queue



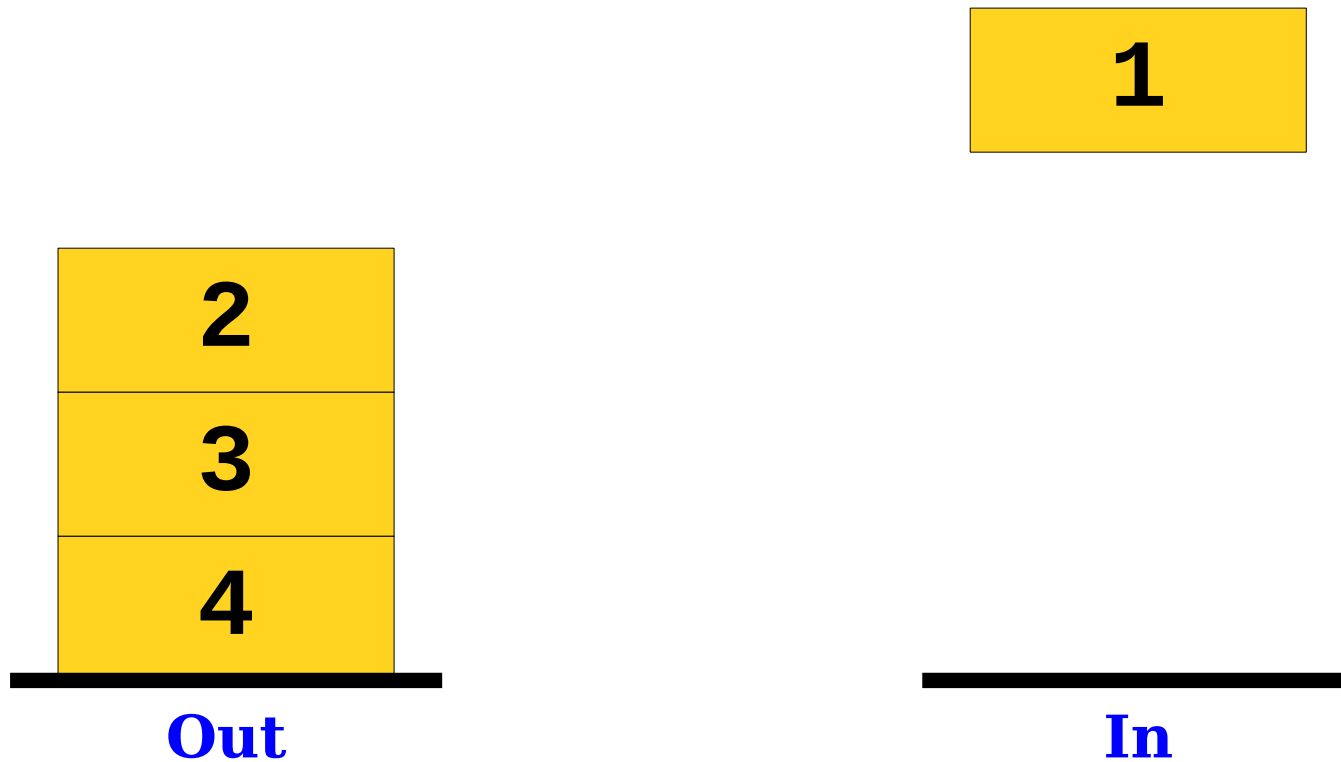
# The Two-Stack Queue



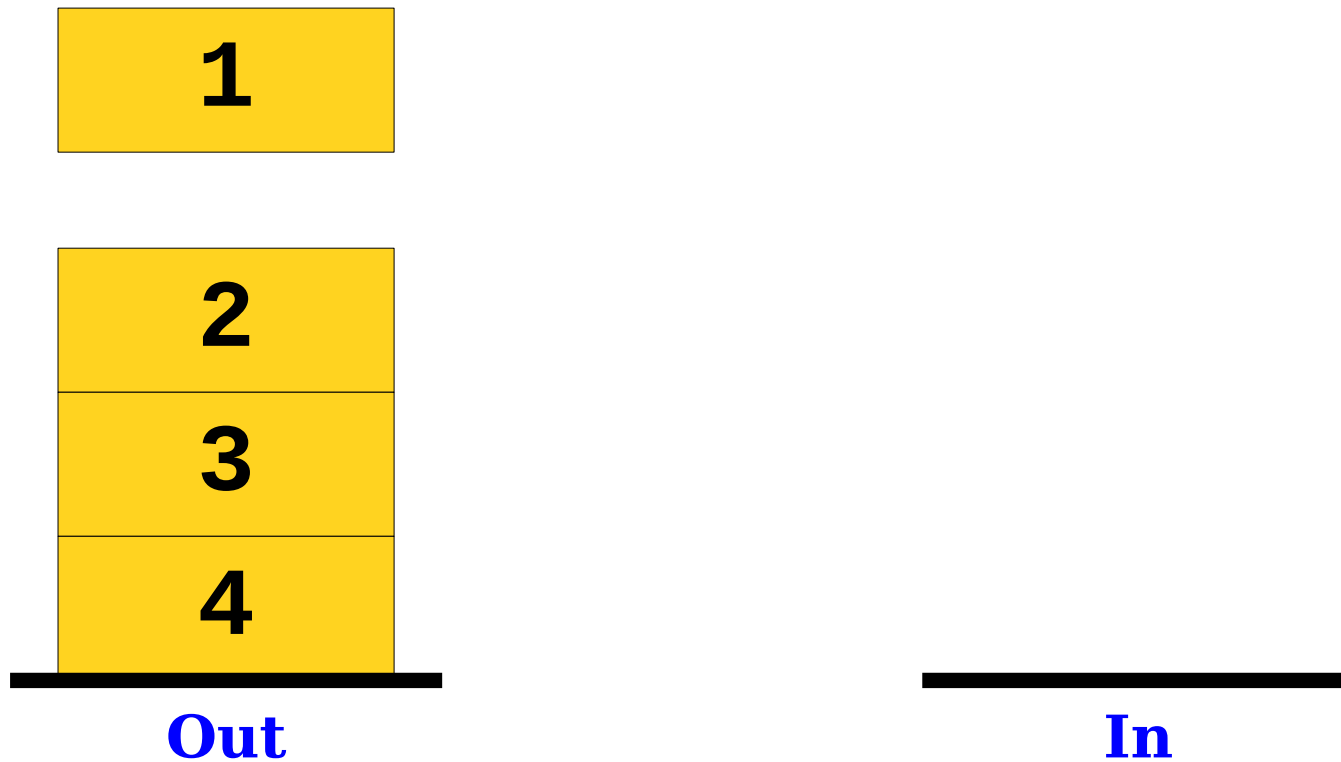
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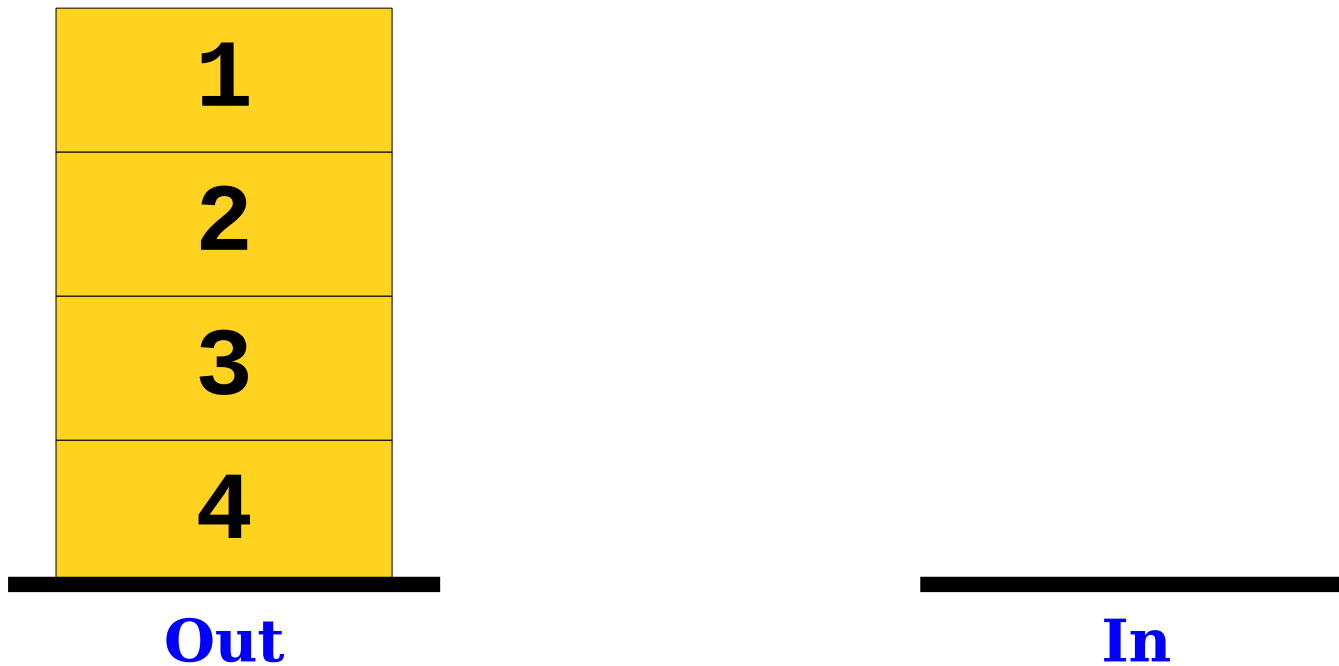
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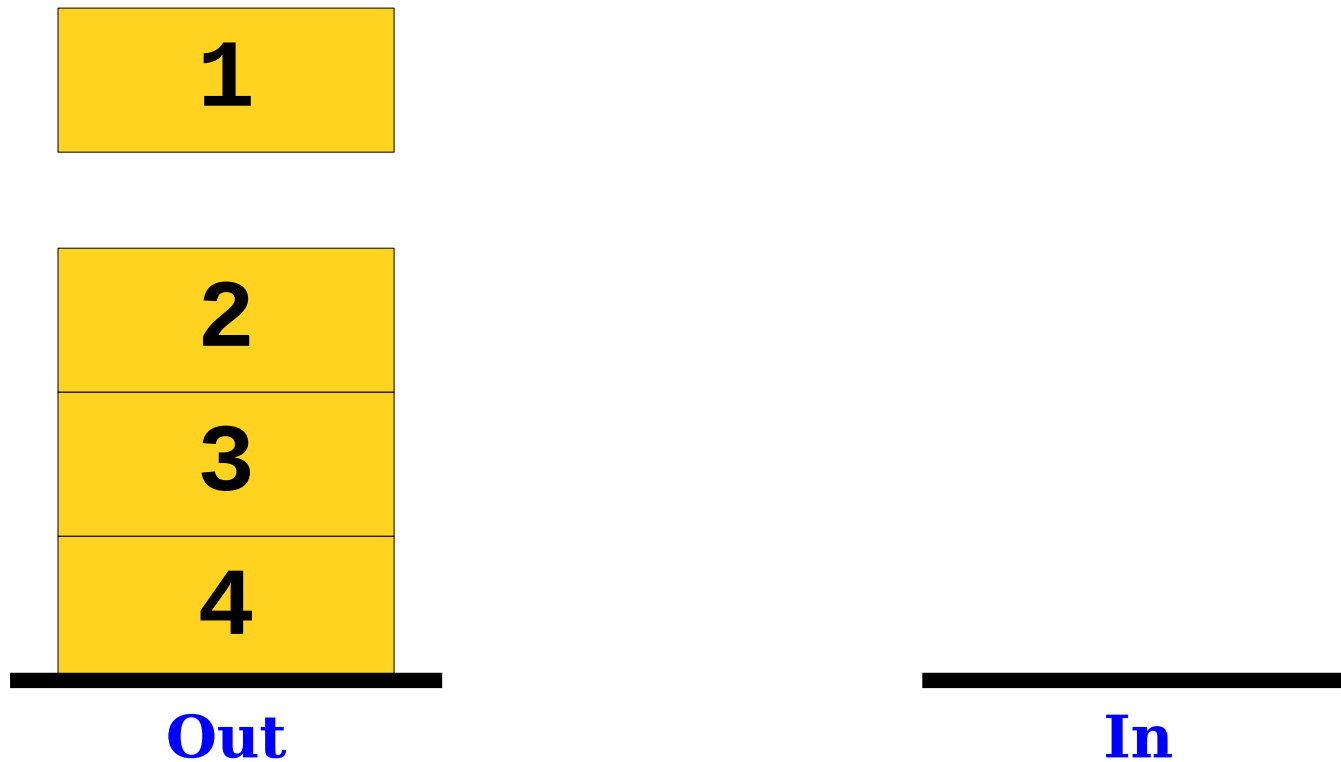
# The Two-Stack Queue



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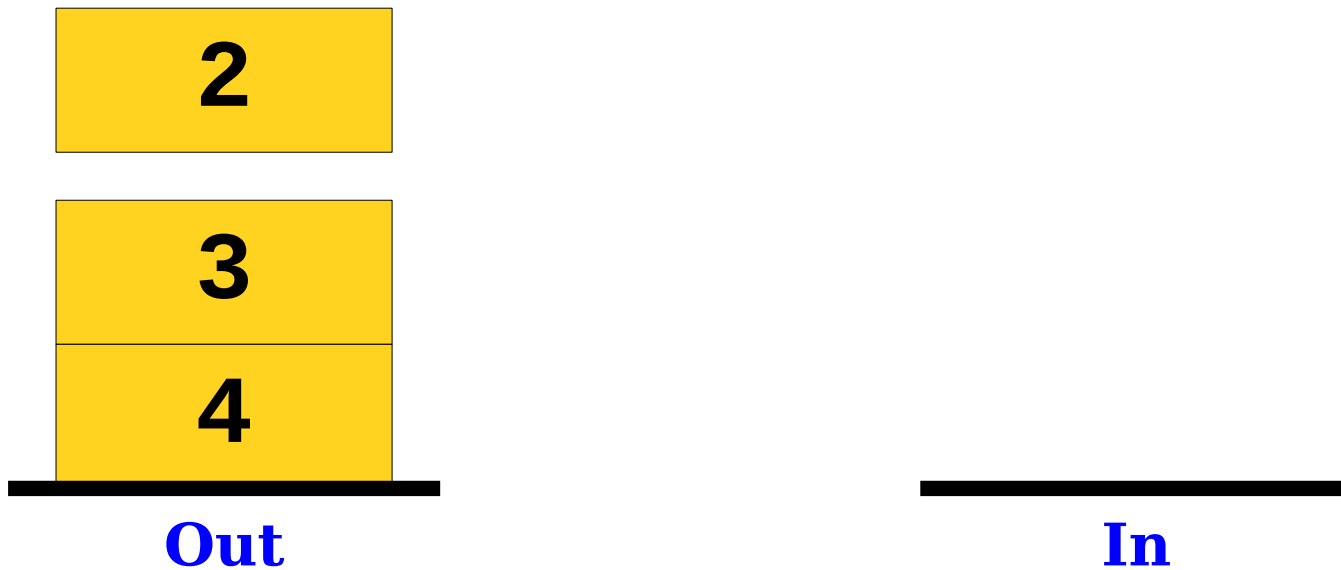
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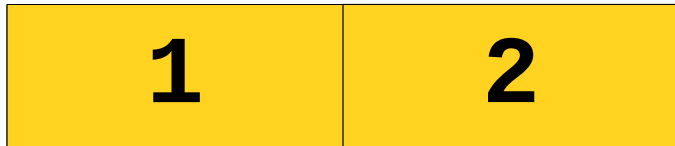
# The Two-Stack Queue



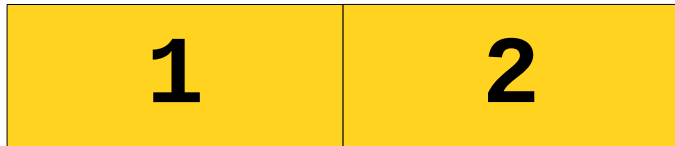
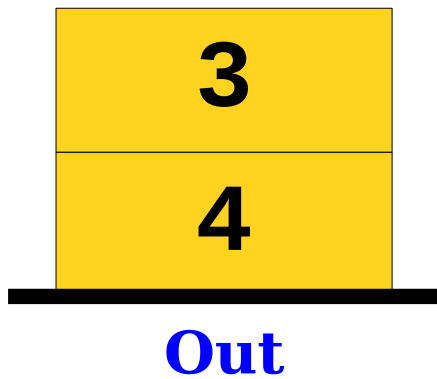
# The Two-Stack Queue



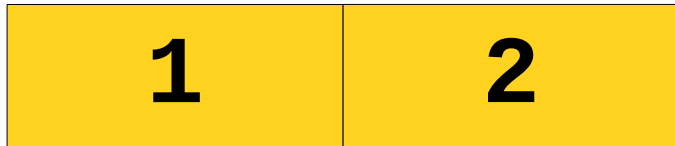
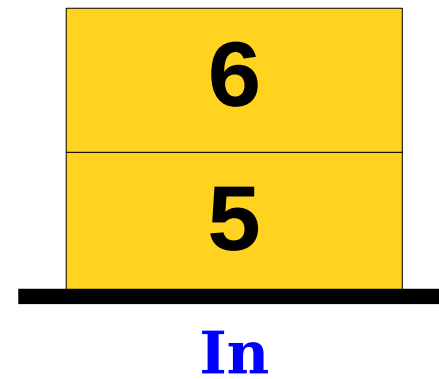
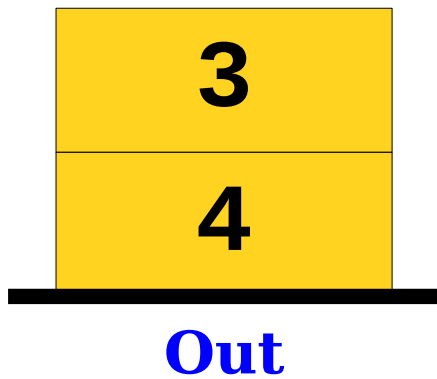
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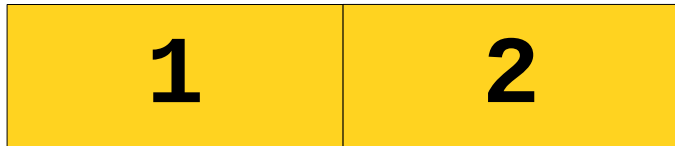
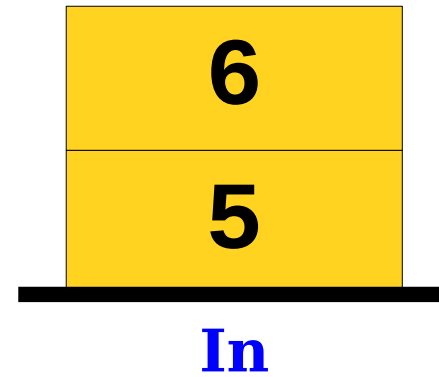
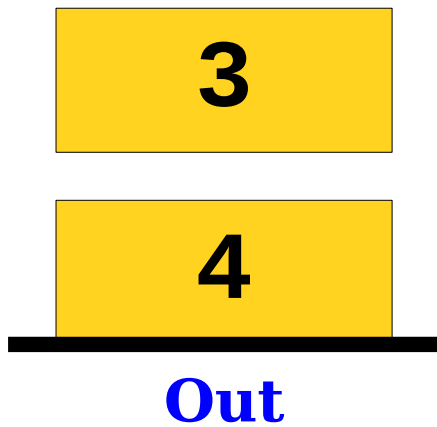
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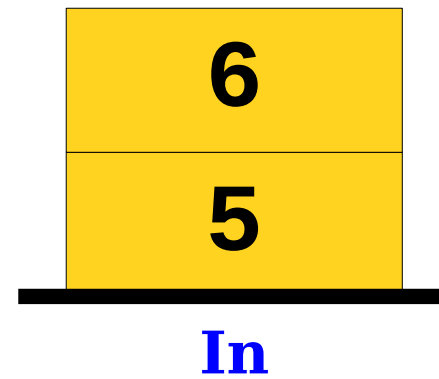
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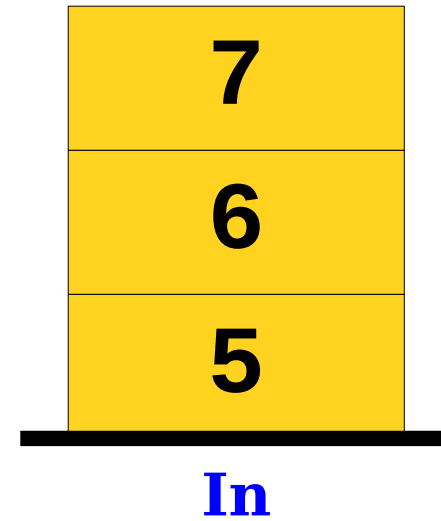
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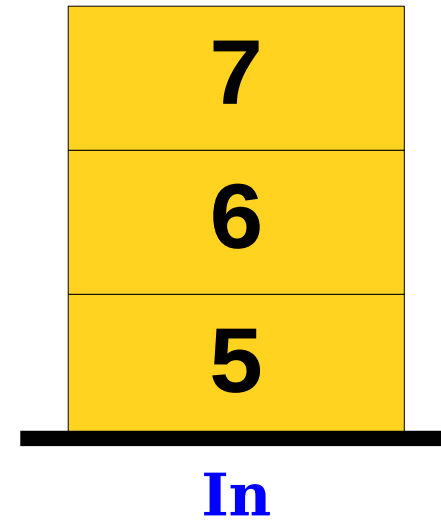
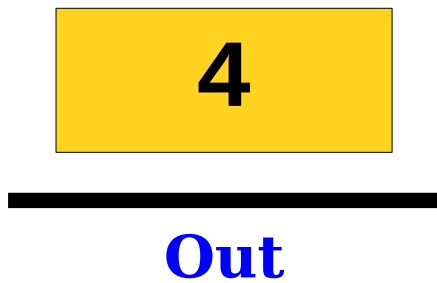
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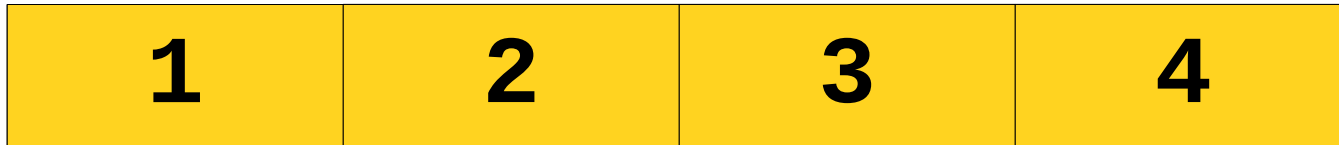
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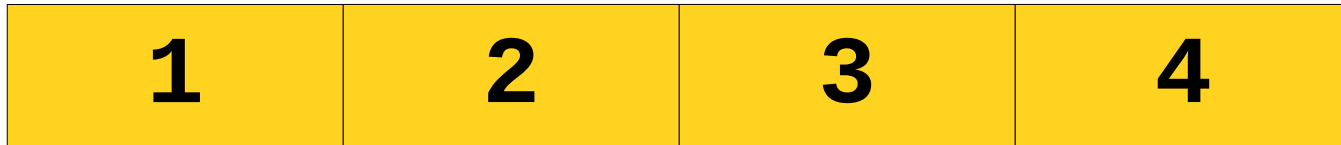
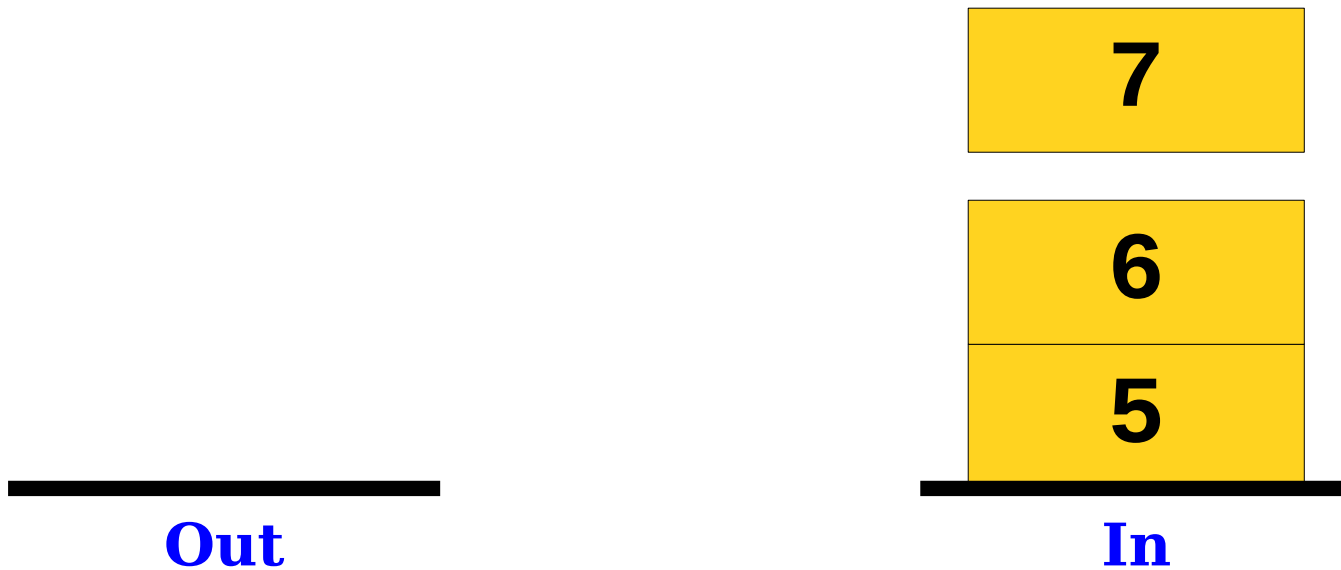
# The Two-Stack Queue



# The Two-Stack Queue



# The Two-Stack Queue



# The Two-Stack Queue

7



**Out**

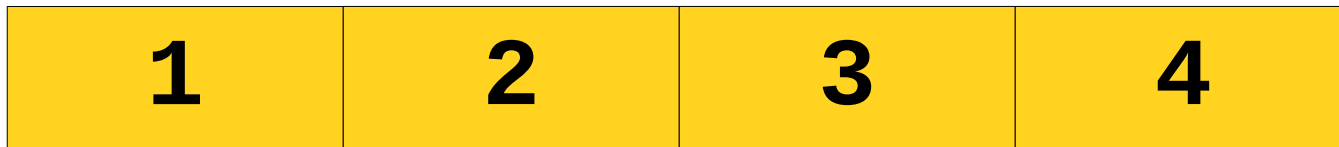
6  
5



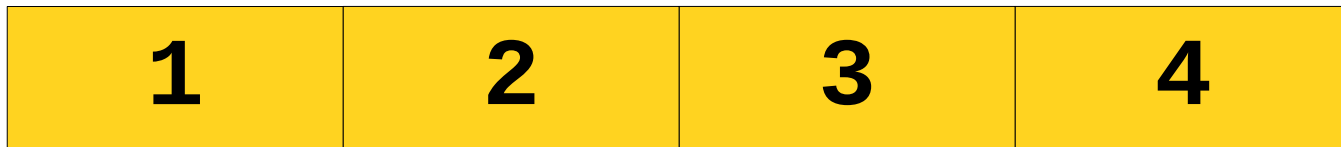
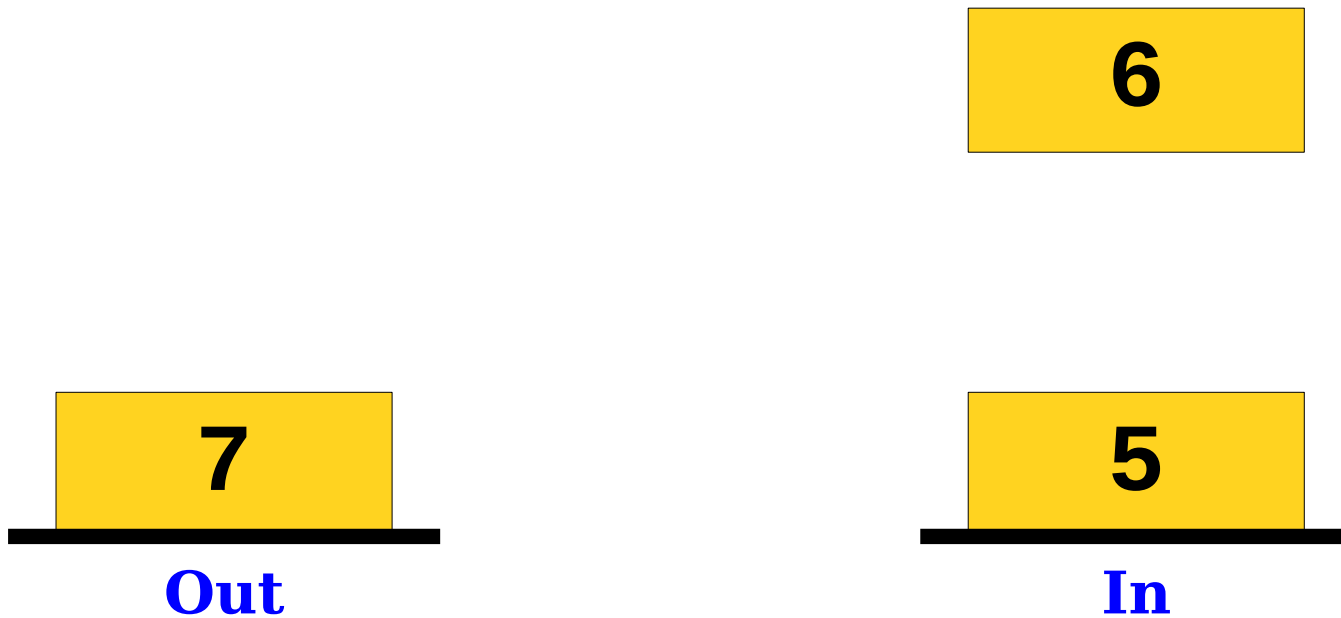
**In**

1 2 3 4

# The Two-Stack Queue



# The Two-Stack Queue



# The Two-Stack Queue

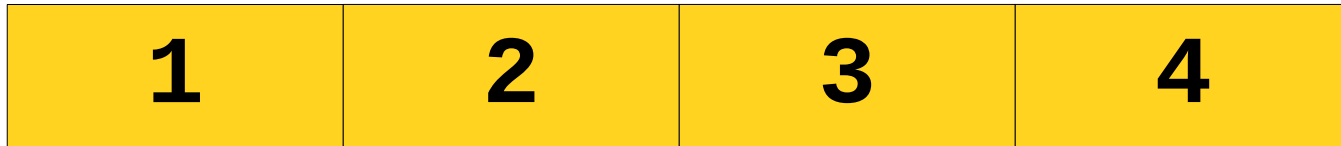
6

7  
**Out**

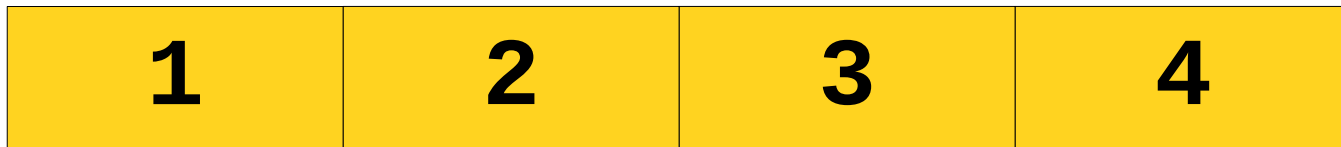
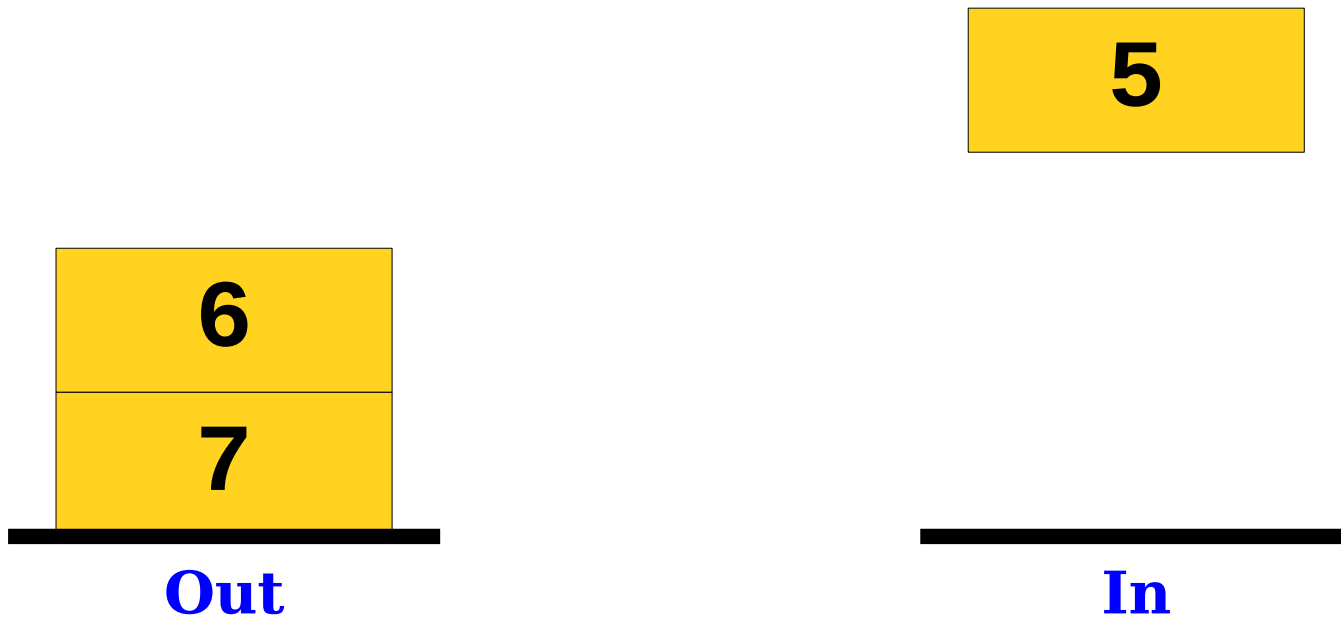
5  
**In**

1 2 3 4

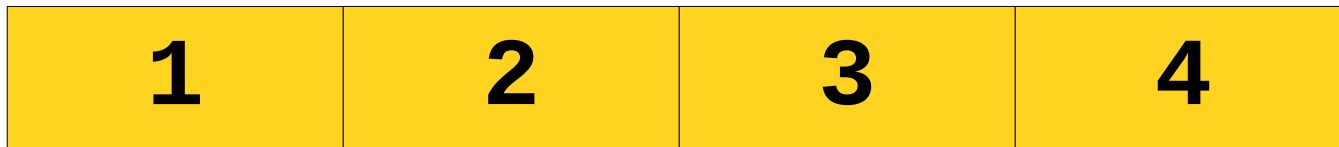
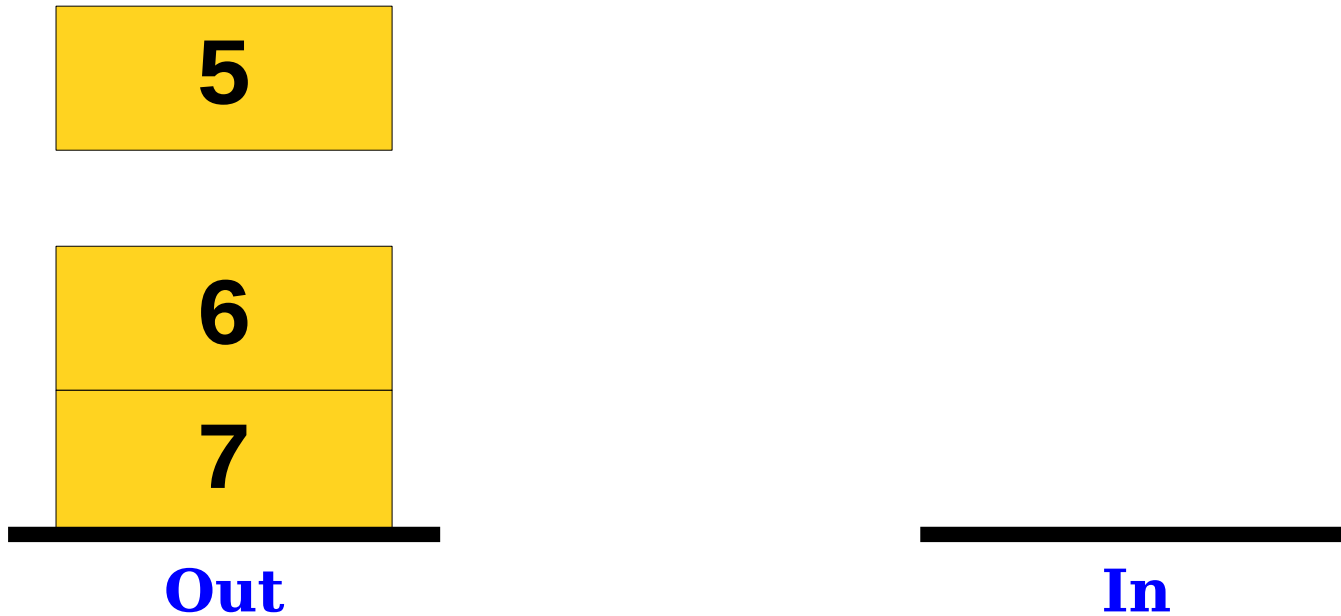
# The Two-Stack Queue



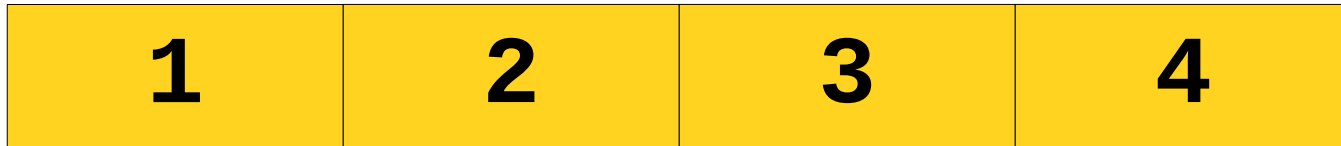
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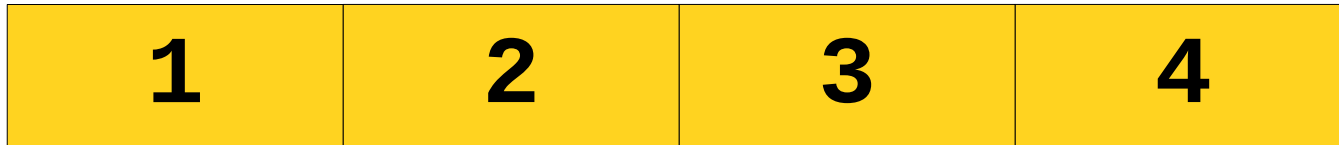
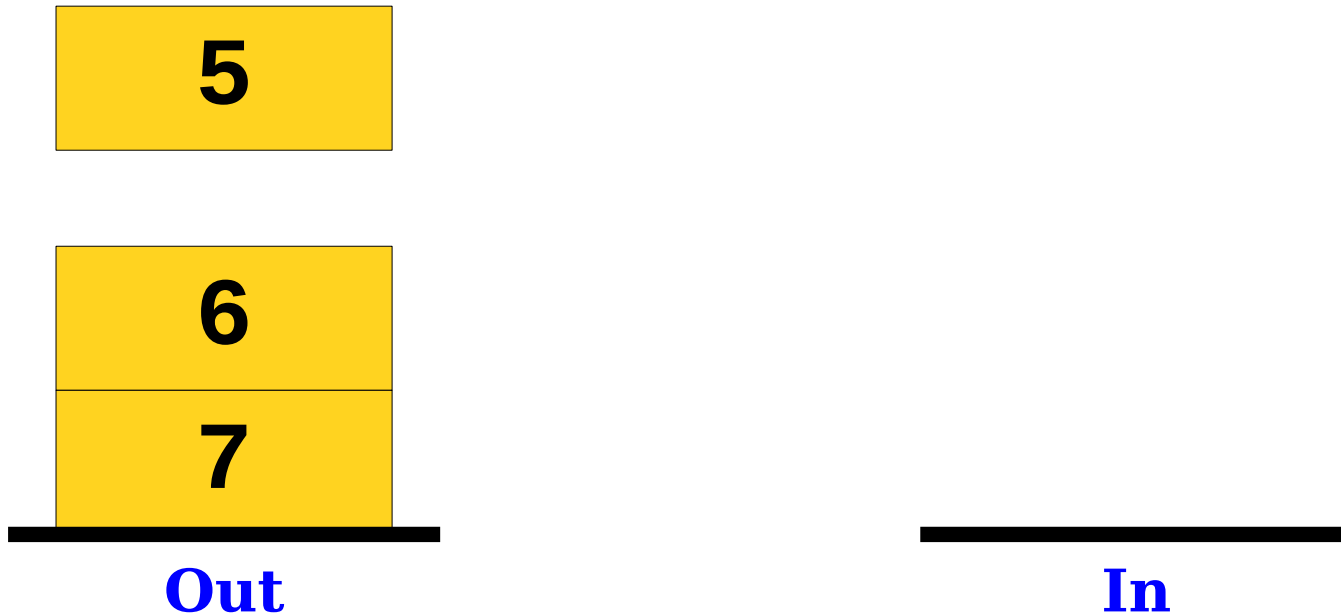
# The Two-Stack Queue



# The Two-Stack Queue



# The Two-Stack Queue



# The Two-Stack Queue



# The Two-Stack Queue

- Maintain an ***In*** stack and an ***Out*** stack.
- To enqueue an element, push it onto the ***In*** stack.
- To dequeue an element:
  - If the ***Out*** stack is nonempty, pop it.
  - If the ***Out*** stack is empty, pop elements from the ***In*** stack, pushing them into the ***Out*** stack. Then dequeue as usual.

# The Two-Stack Queue

---

*Clean  
Dishes*

---

*Dirty  
Dishes*

# The Two-Stack Queue



*Clean  
Dishes*

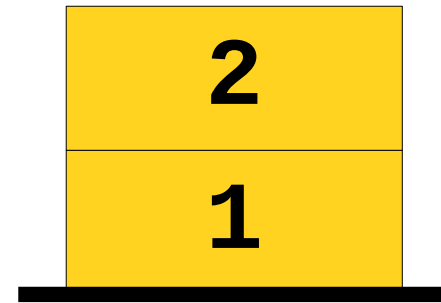


*Dirty  
Dishes*

# The Two-Stack Queue



*Clean  
Dishes*

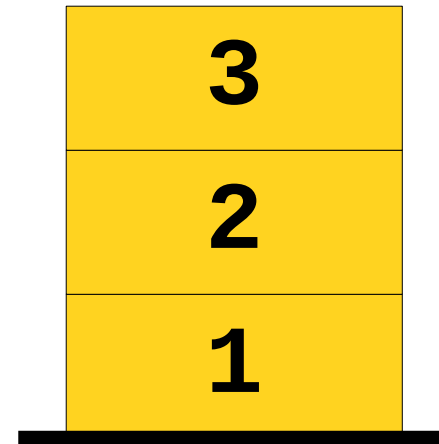


*Dirty  
Dishes*

# The Two-Stack Queue

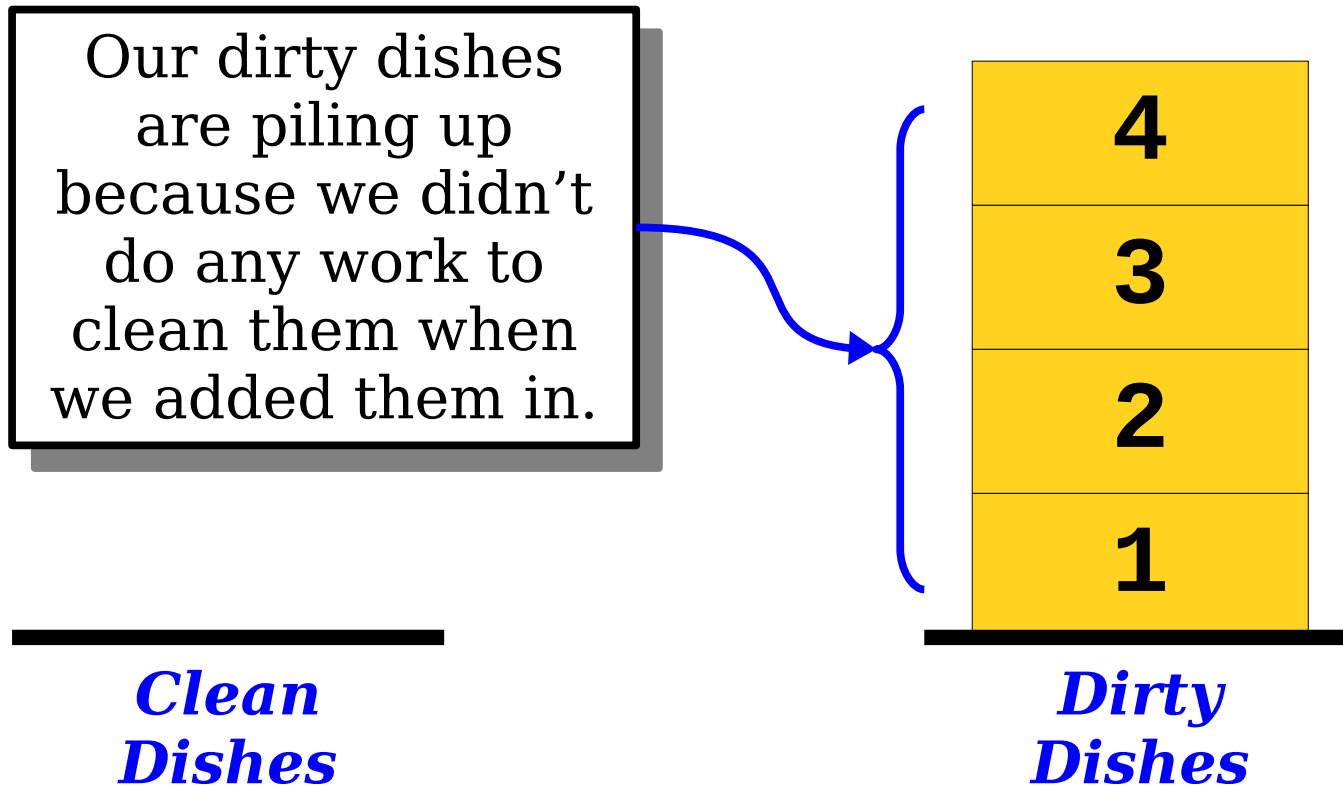


*Clean  
Dishes*

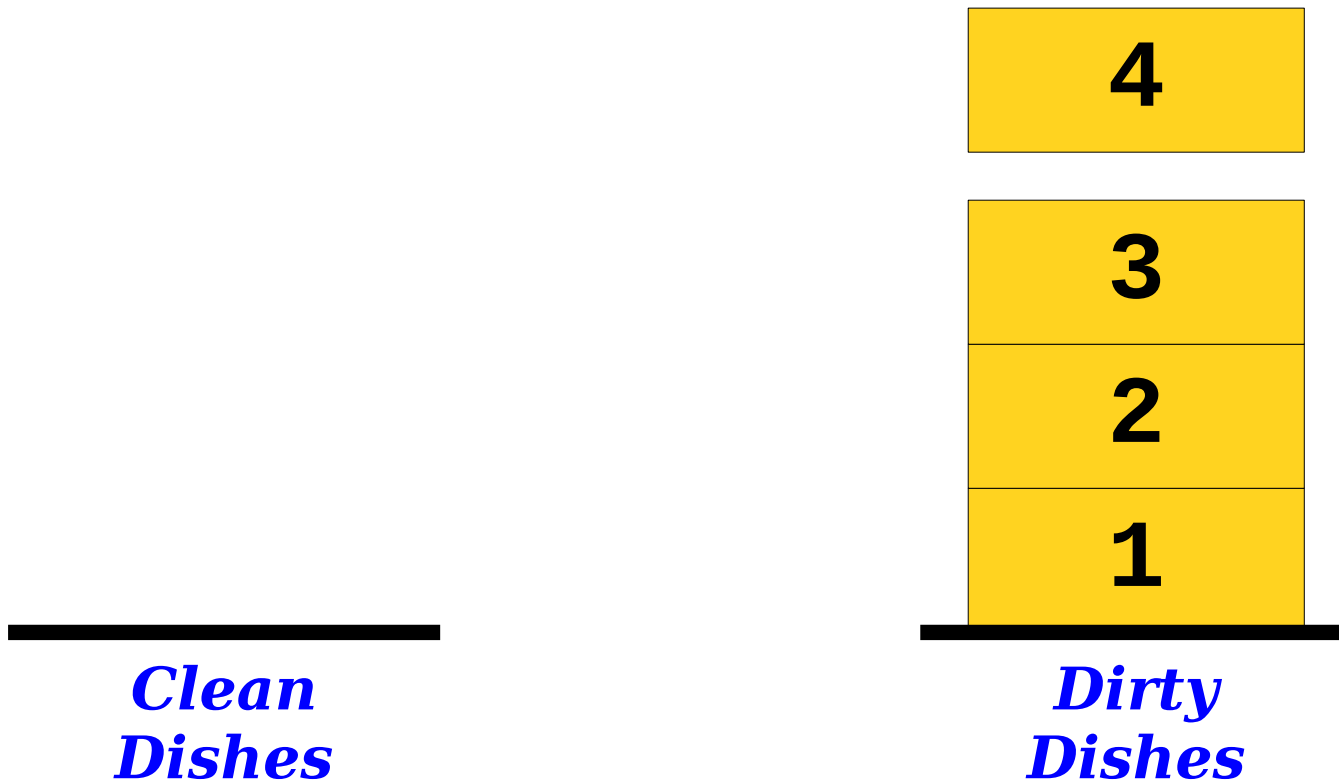


*Dirty  
Dishes*

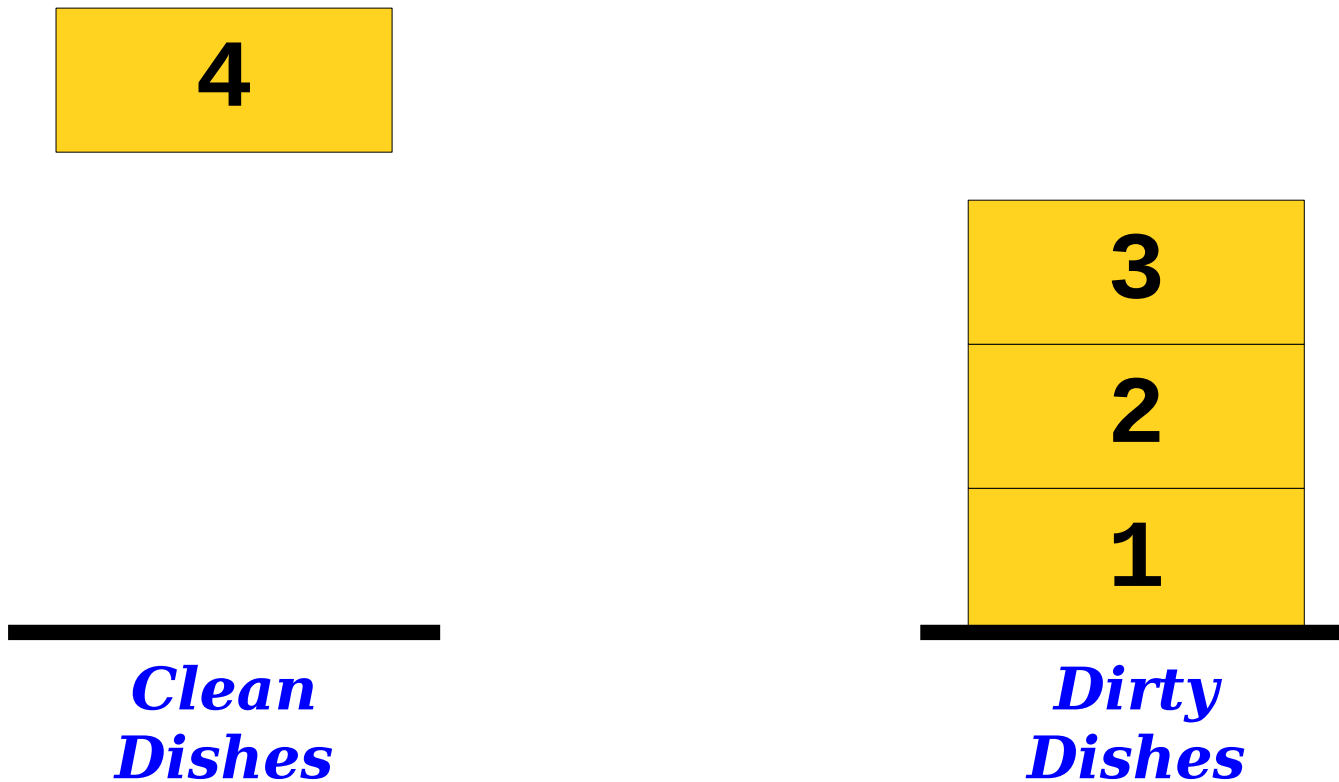
# The Two-Stack Queue



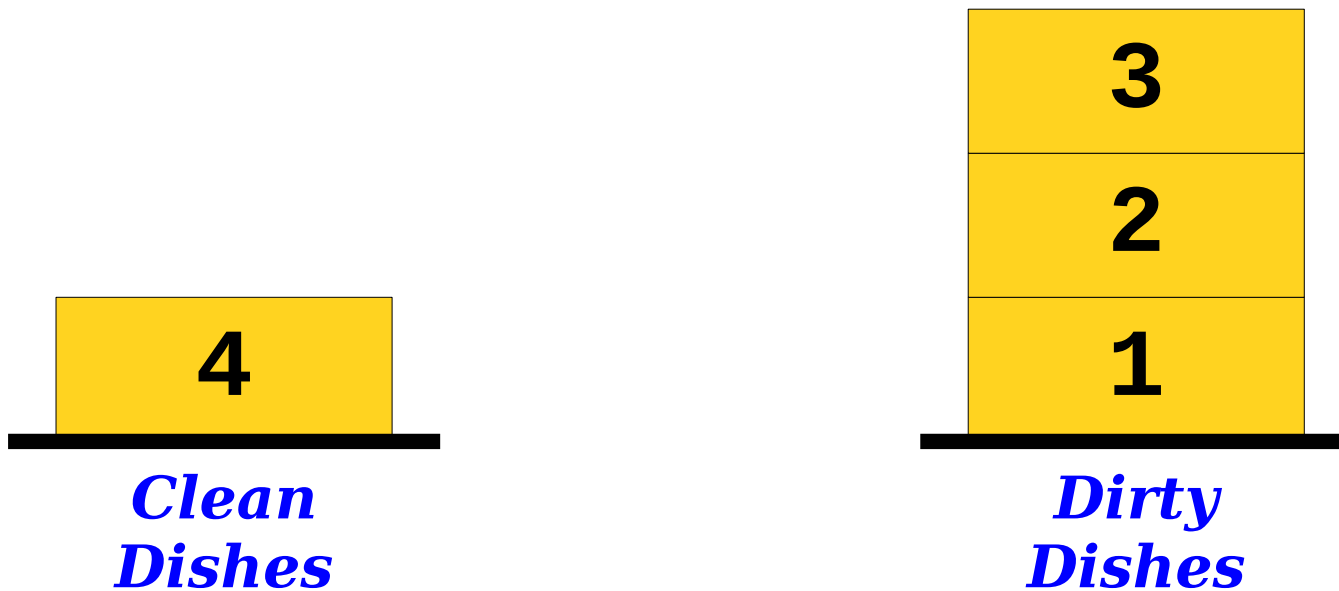
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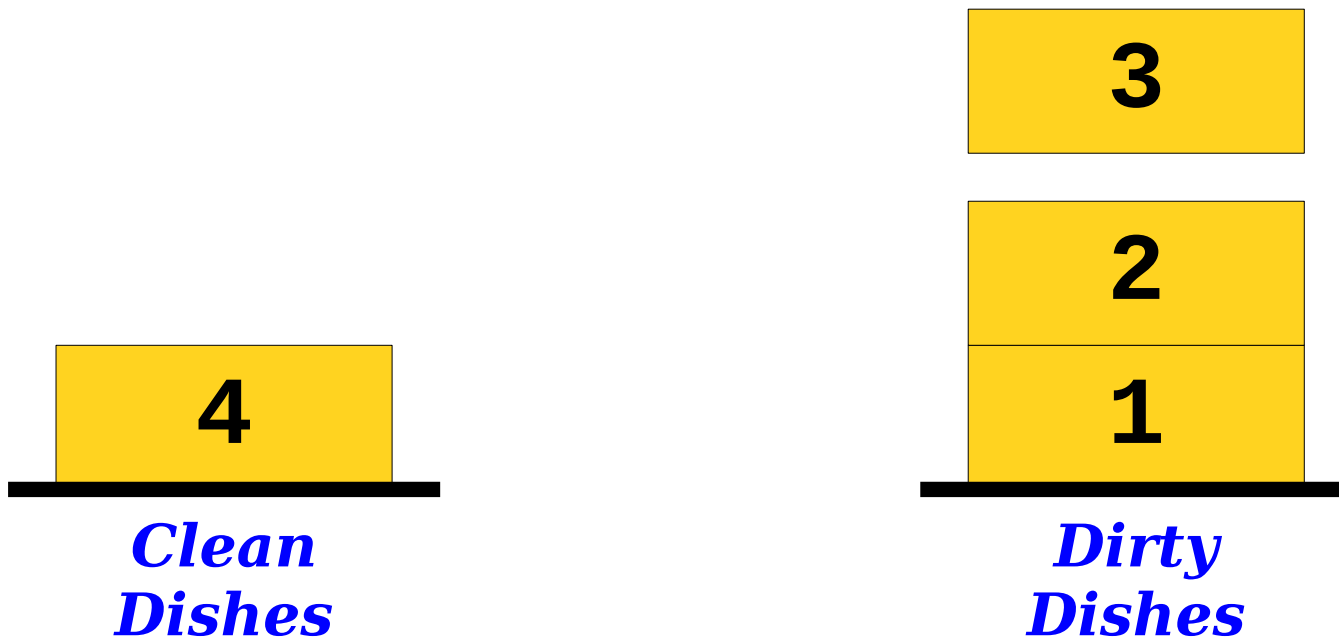
# The Two-Stack Queue



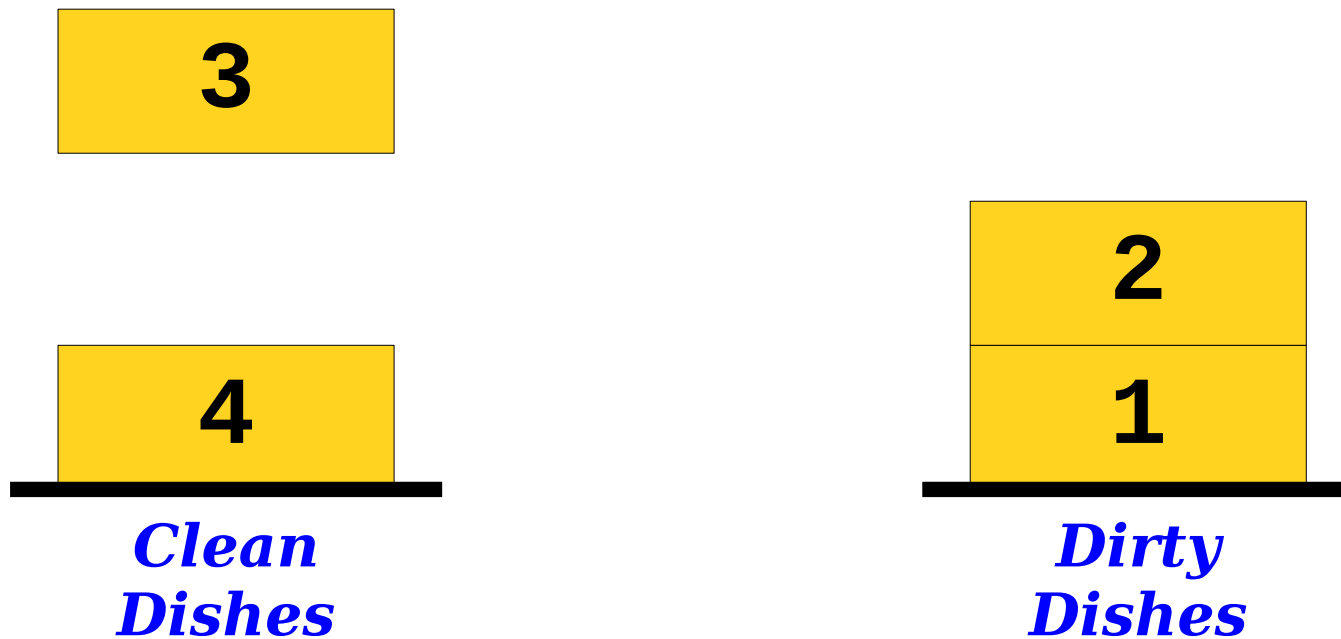
# The Two-Stack Queue



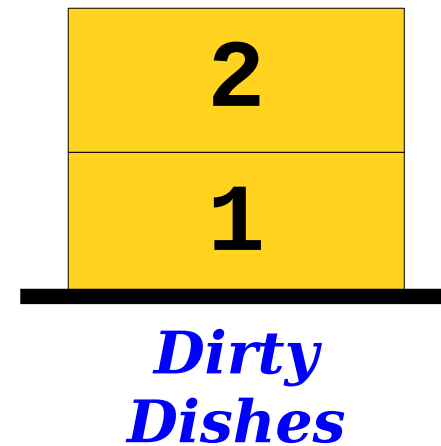
# The Two-Stack Queue



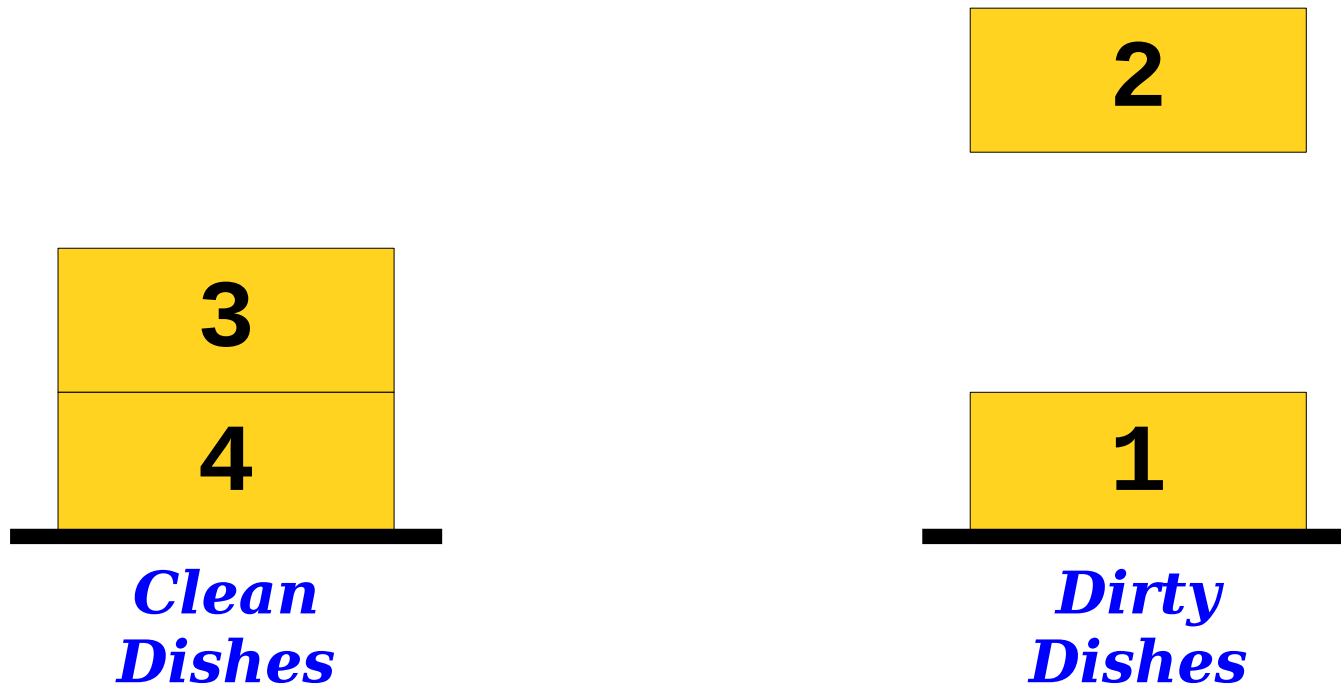
# The Two-Stack Queue



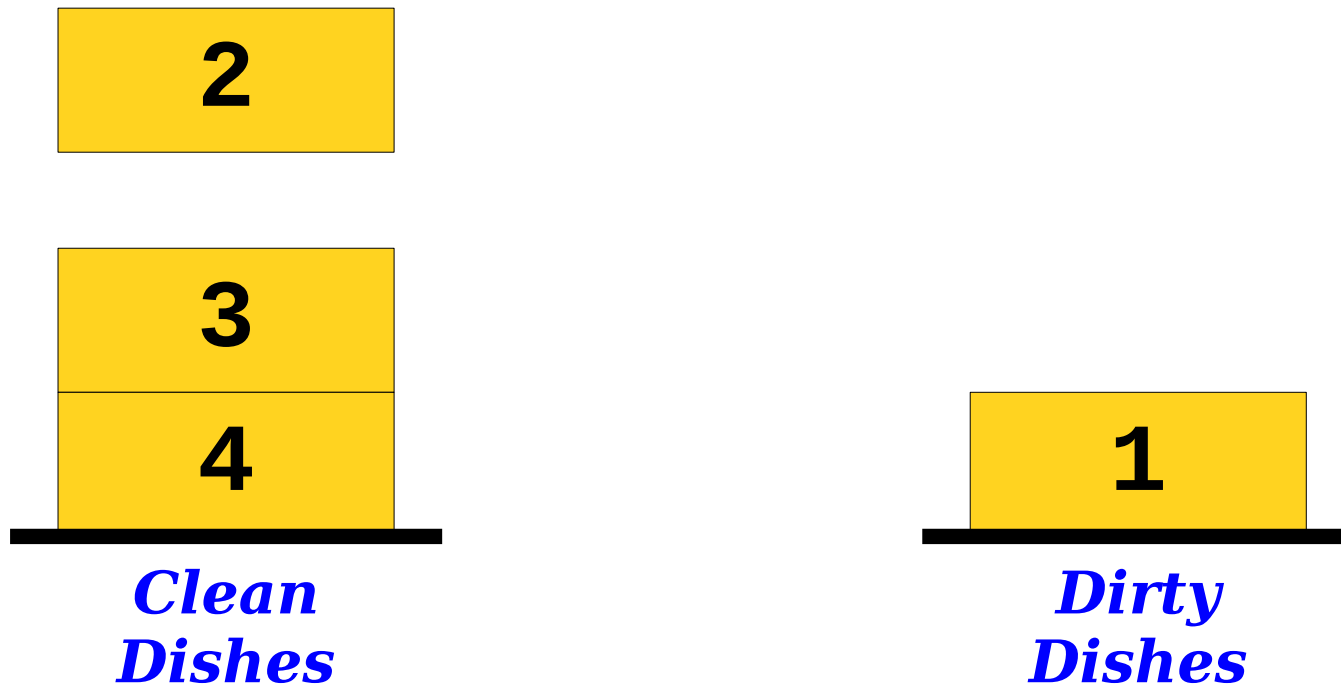
# The Two-Stack Queue



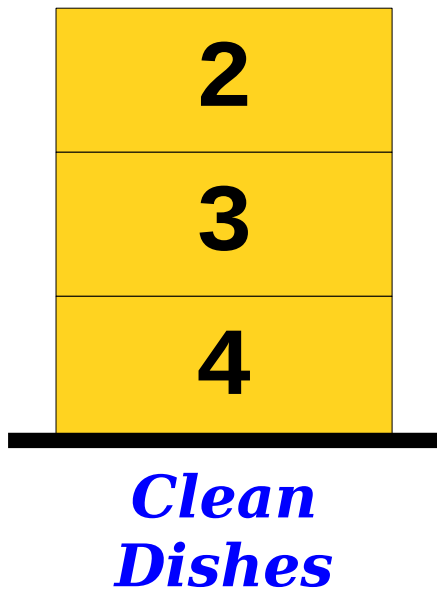
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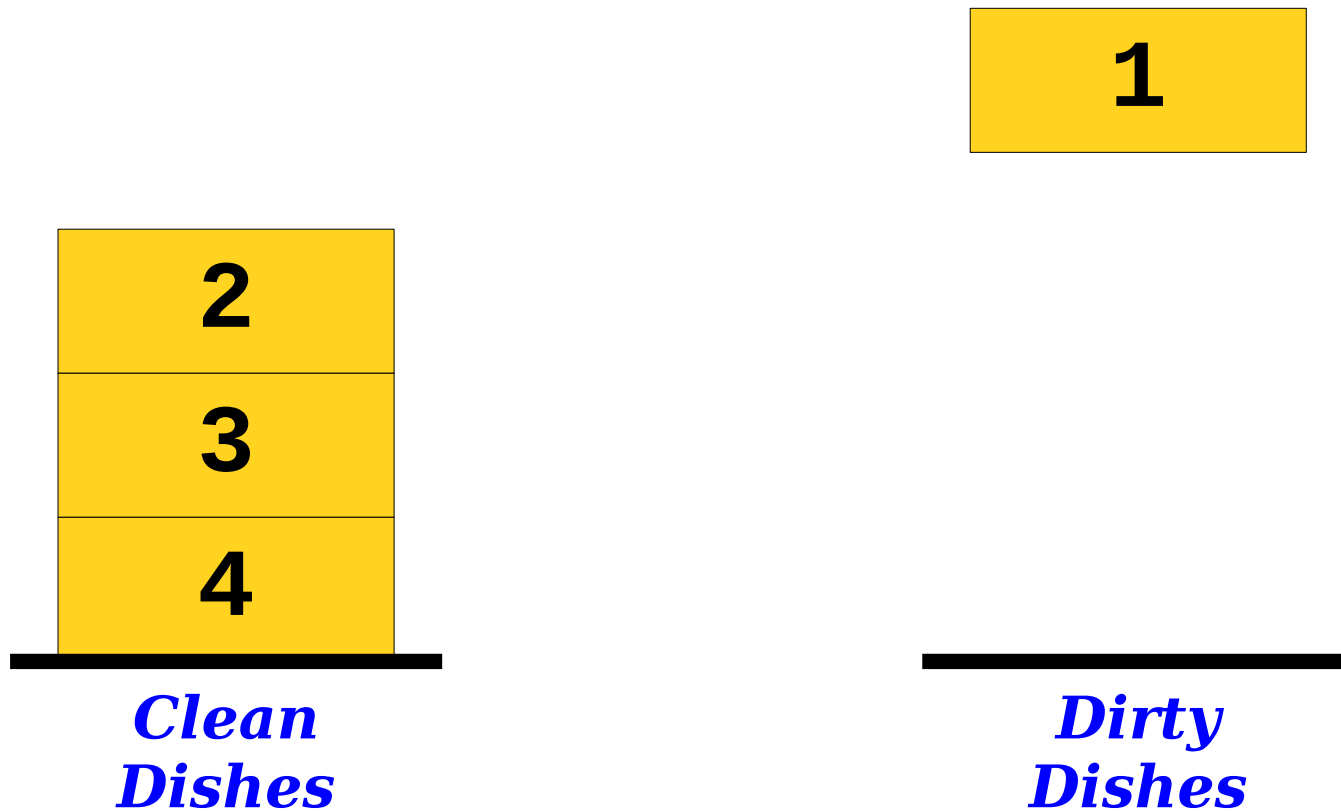
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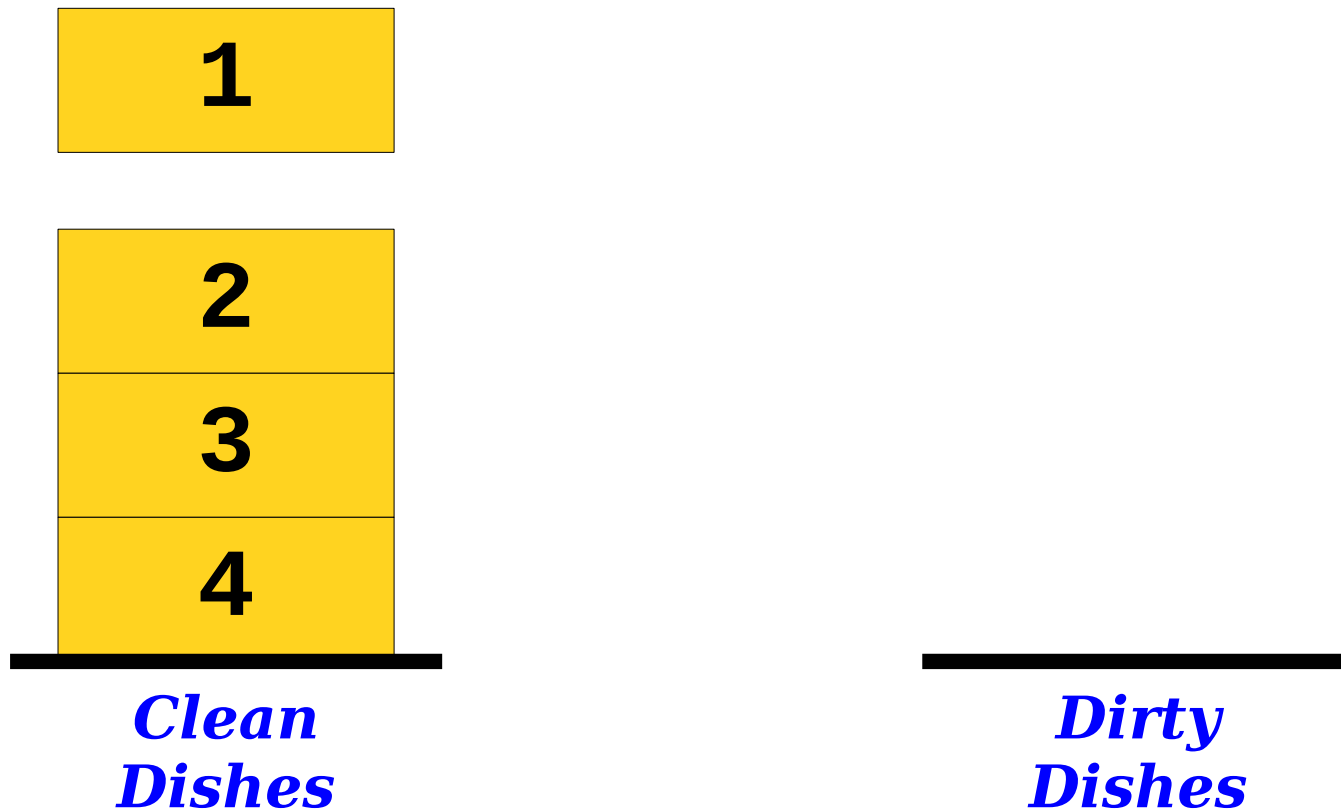
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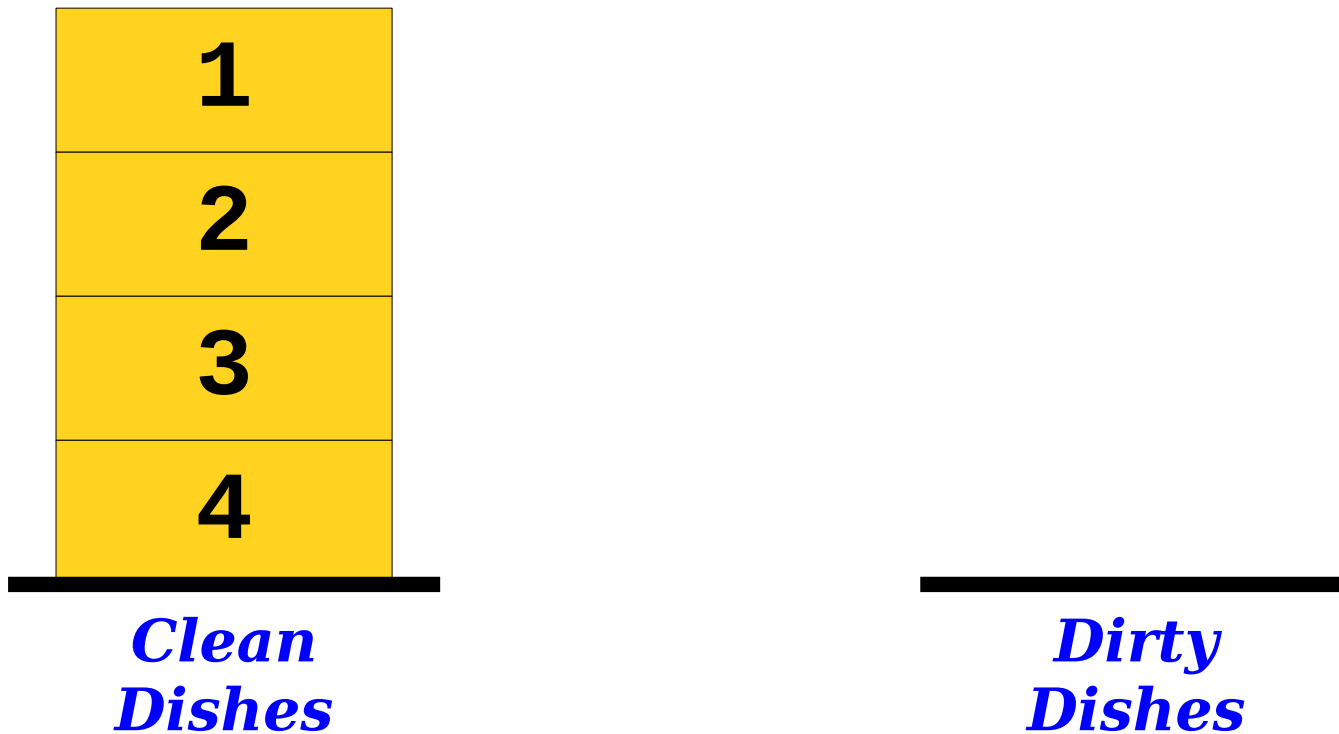
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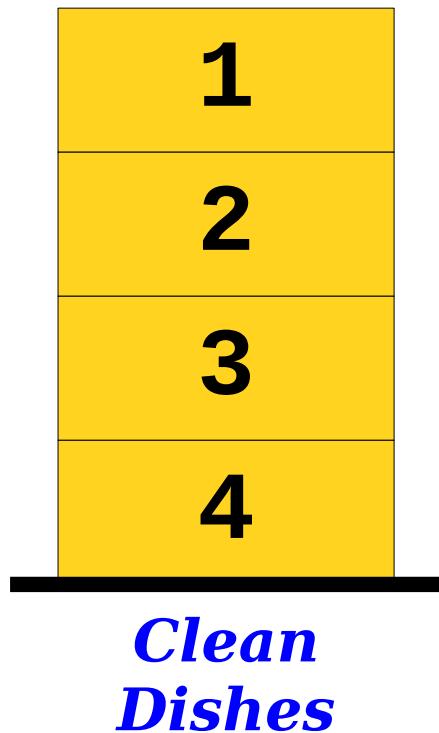
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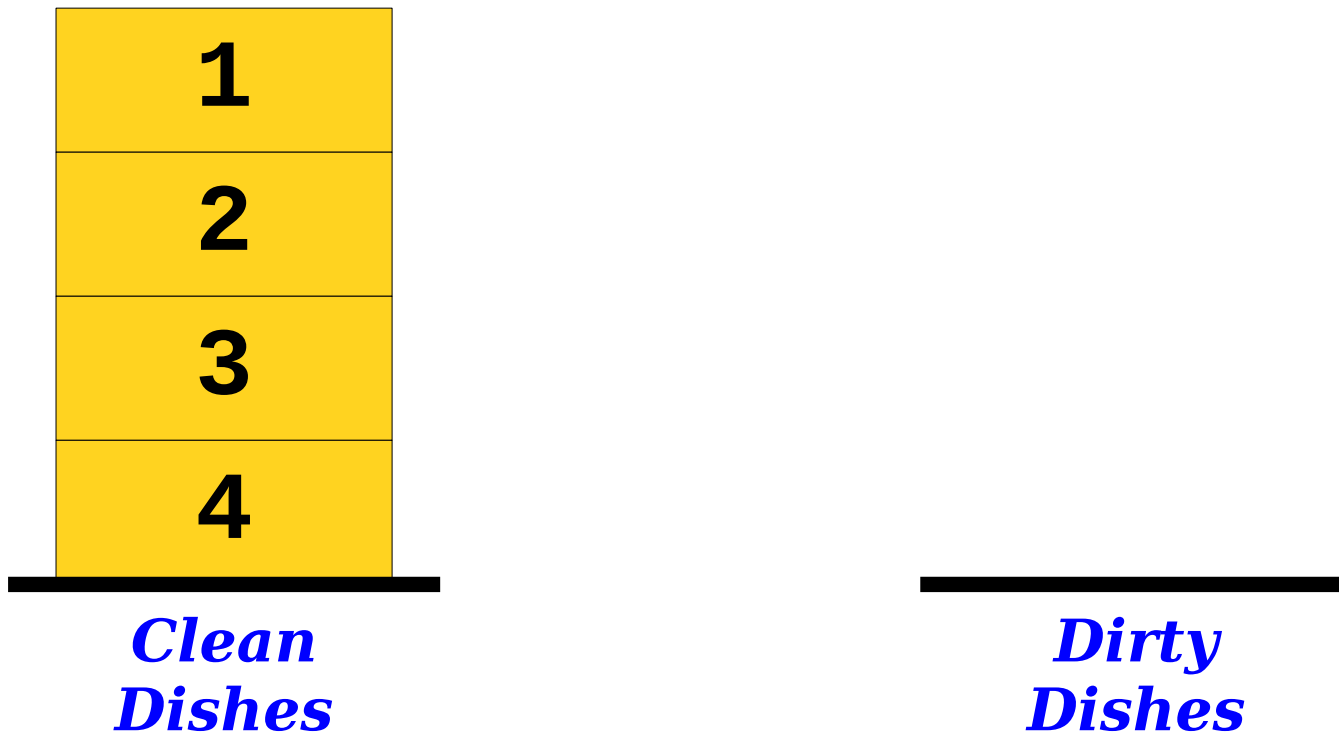
# The Two-Stack Queue



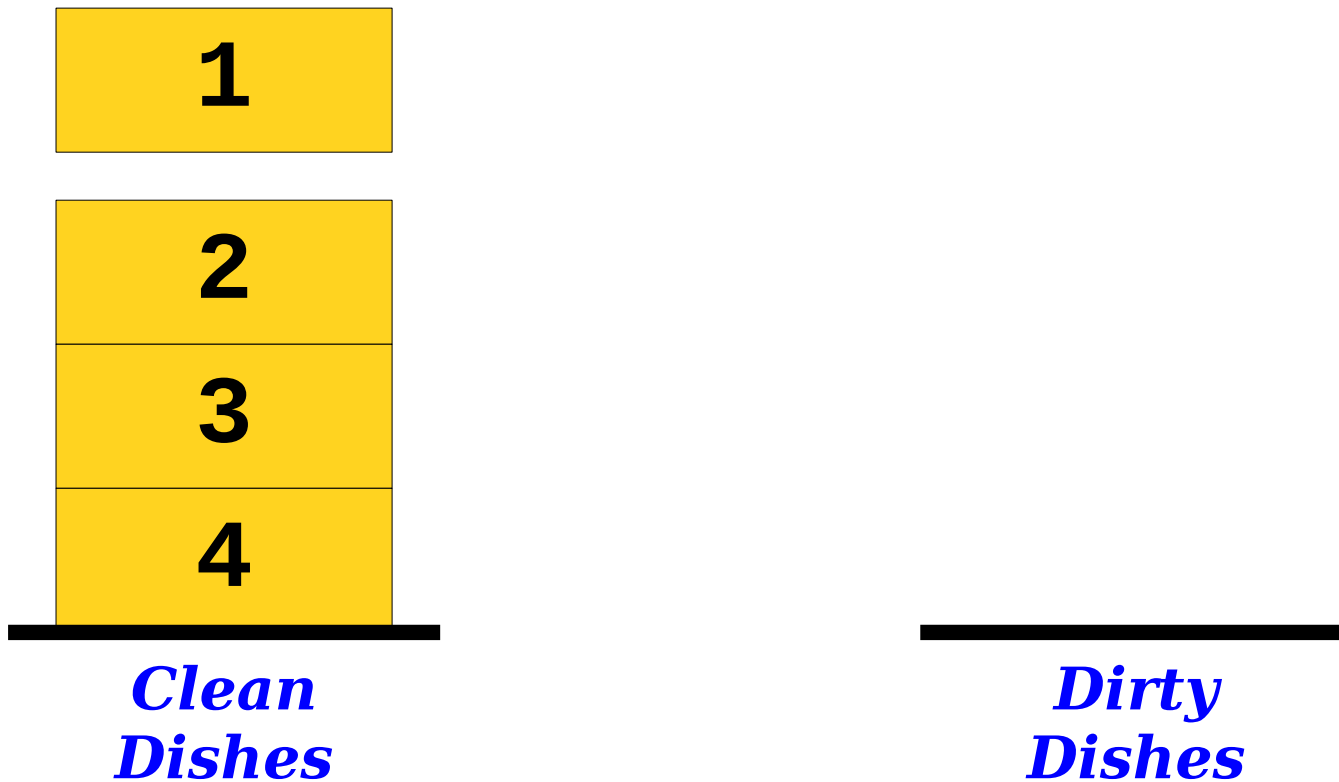
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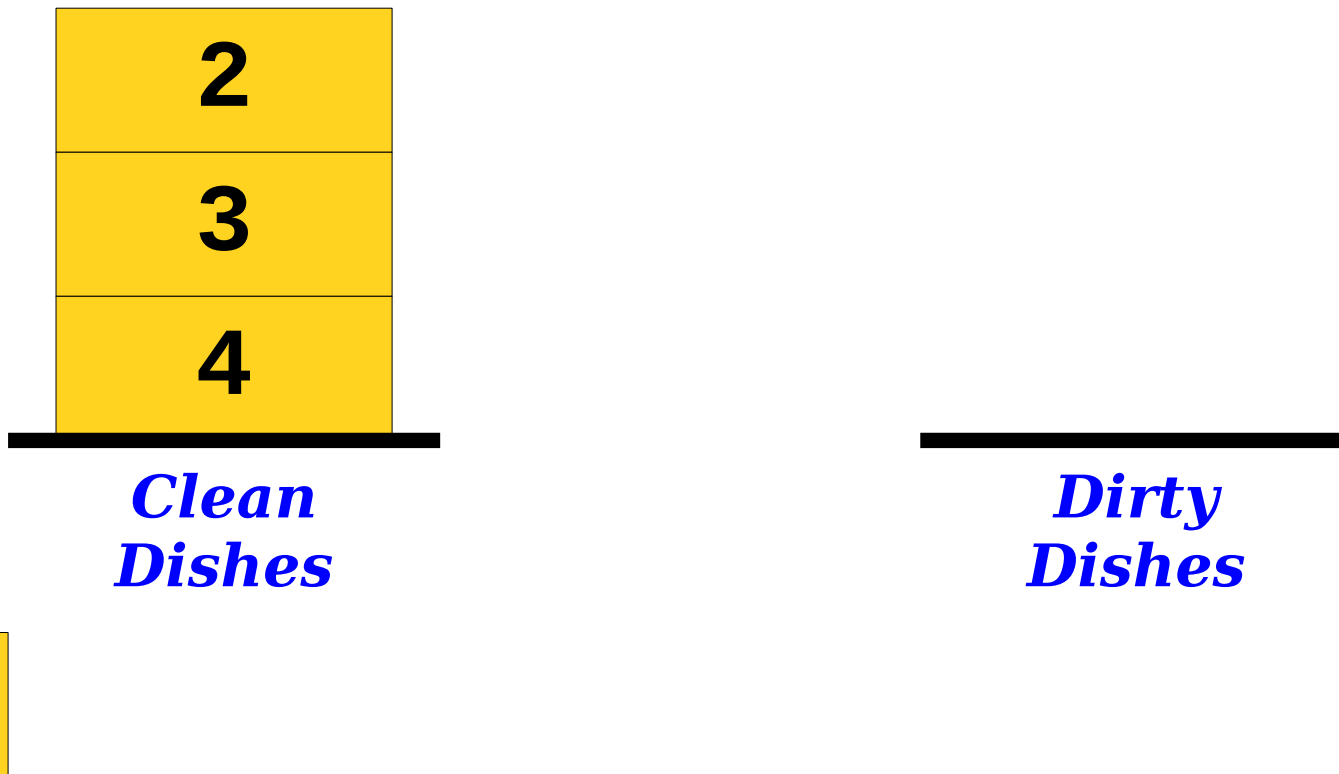
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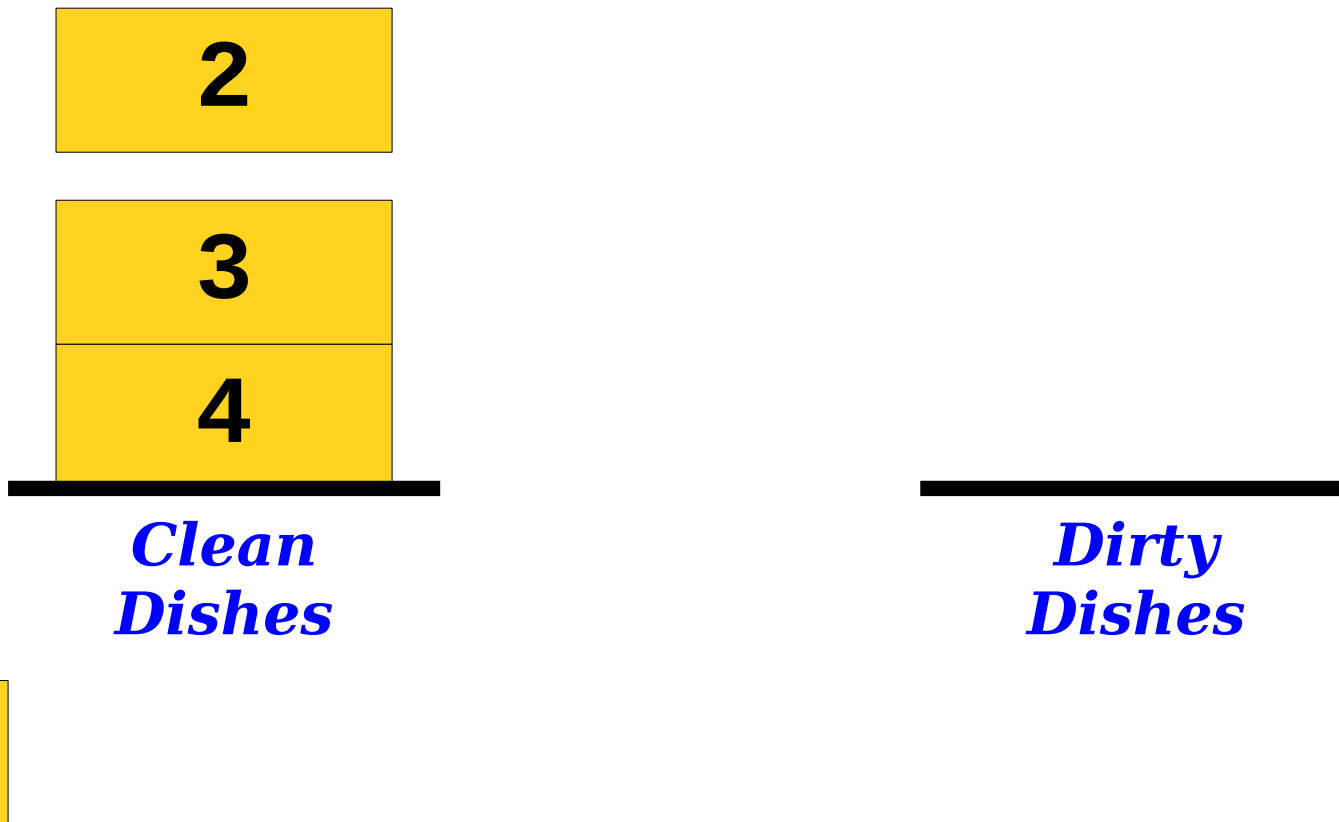
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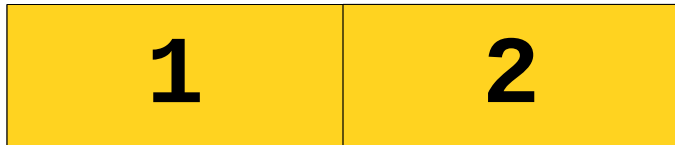
# The Two-Stack Queue



# The Two-Stack Queue

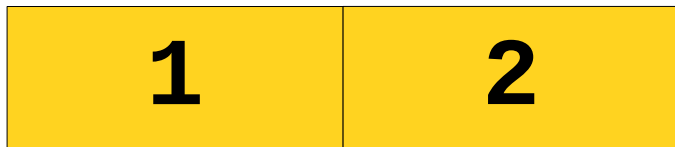
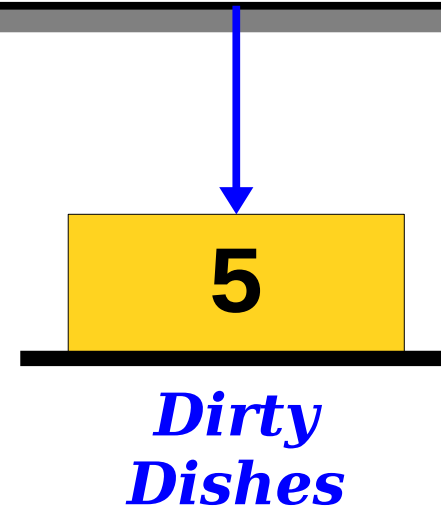
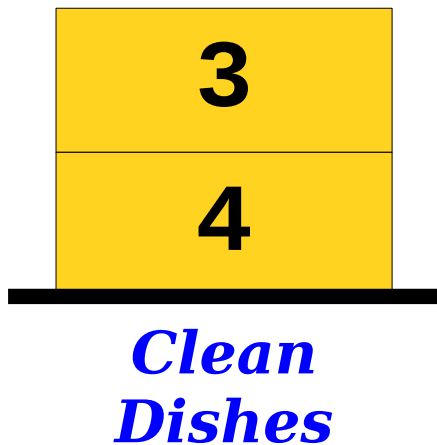


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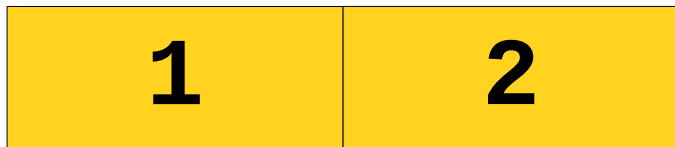
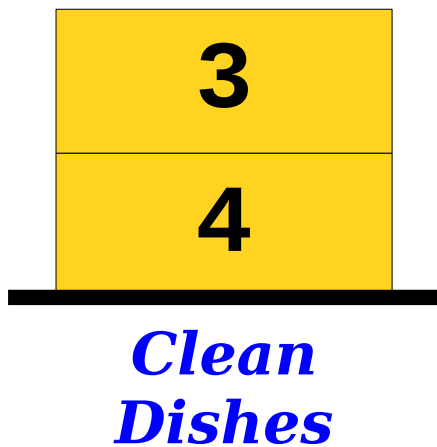


# The Two-Stack Queue

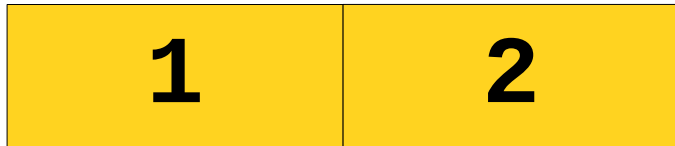
We need to do some “cleanup” on this before it’ll be useful. It’s fast to add it here because we’re deferring that work.



# The Two-Stack Queue



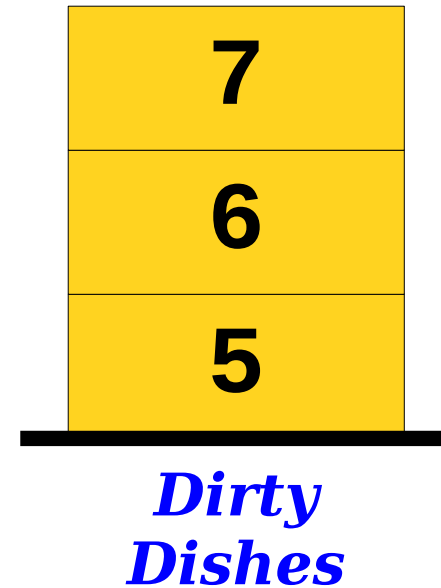
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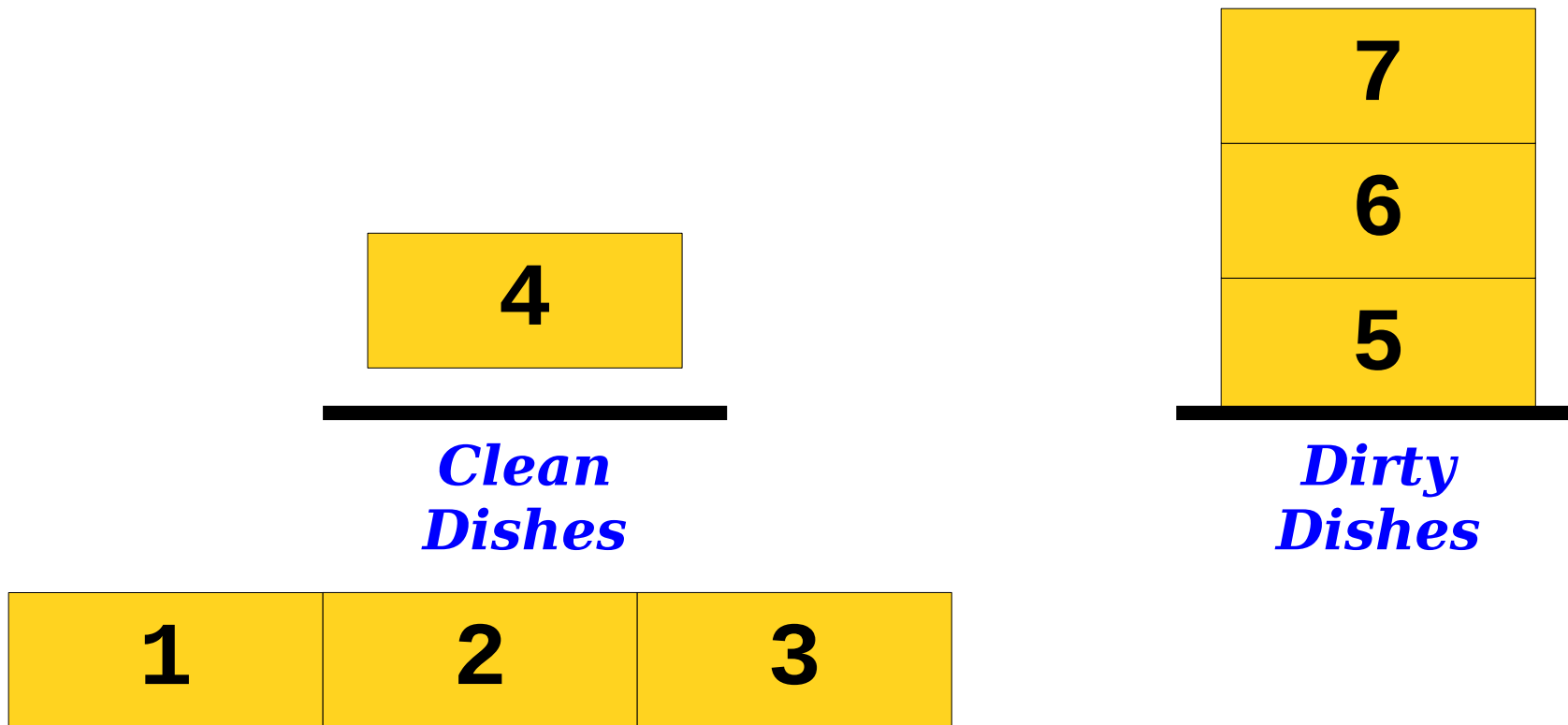
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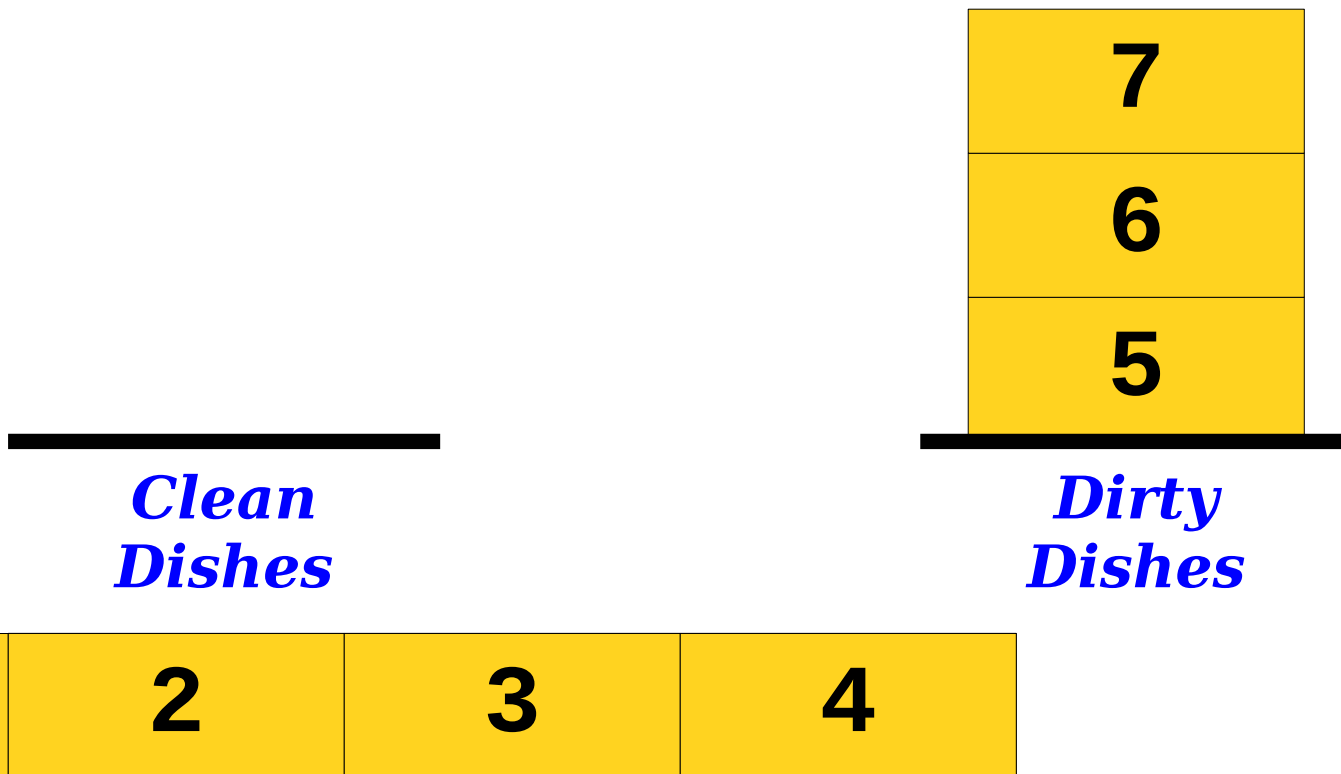
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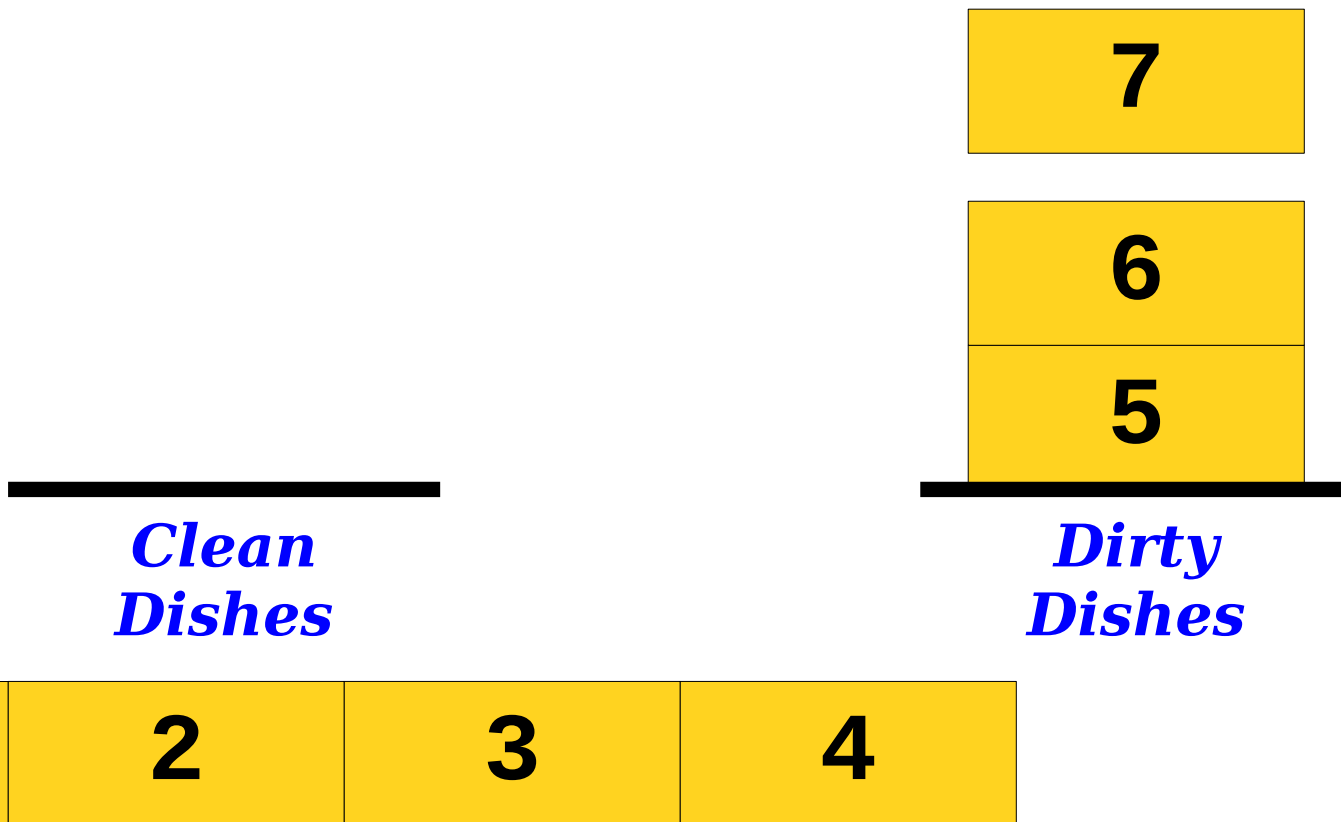
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# The Two-Stack Queue

7

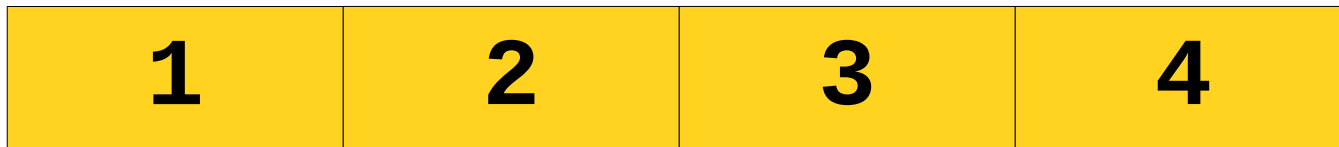
6  
5

*Clean  
Dishes*

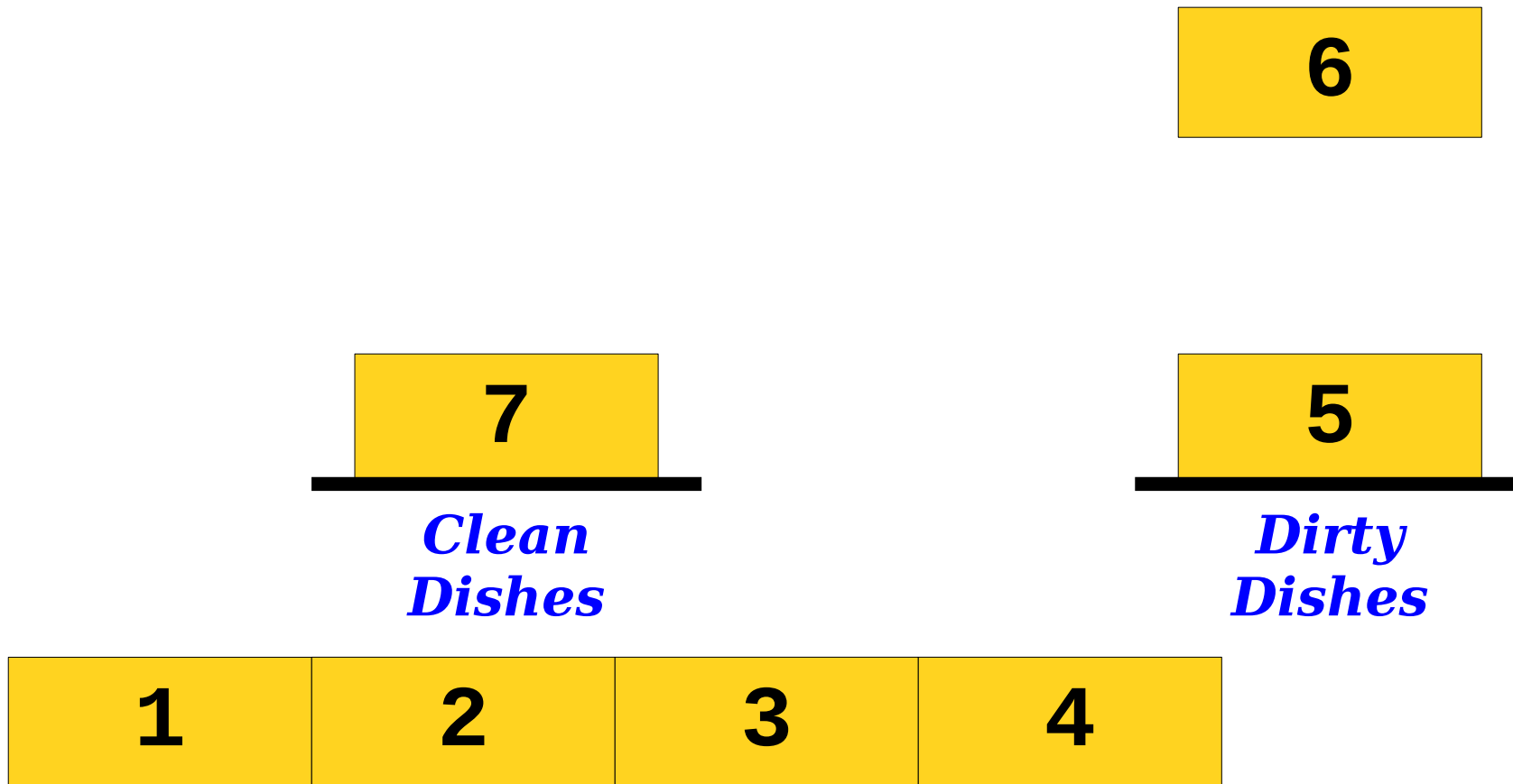
*Dirty  
Dishes*

1 2 3 4

# The Two-Stack Queue



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# The Two-Stack Queue

6

7

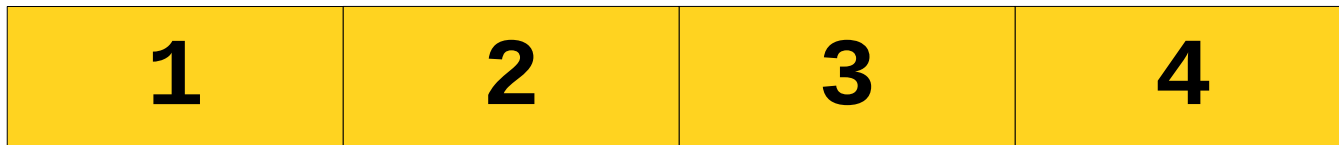
*Clean  
Dishes*

5

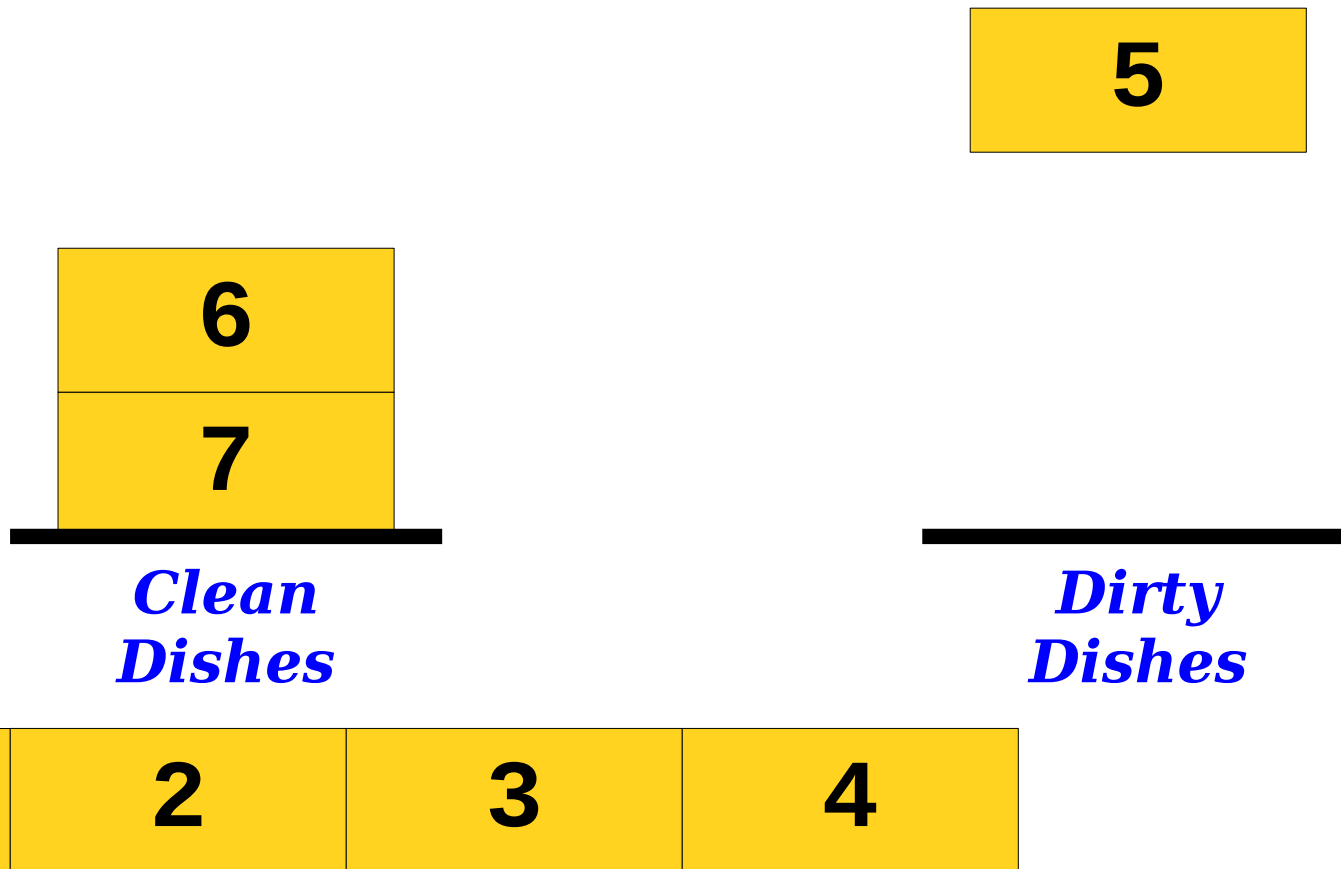
*Dirty  
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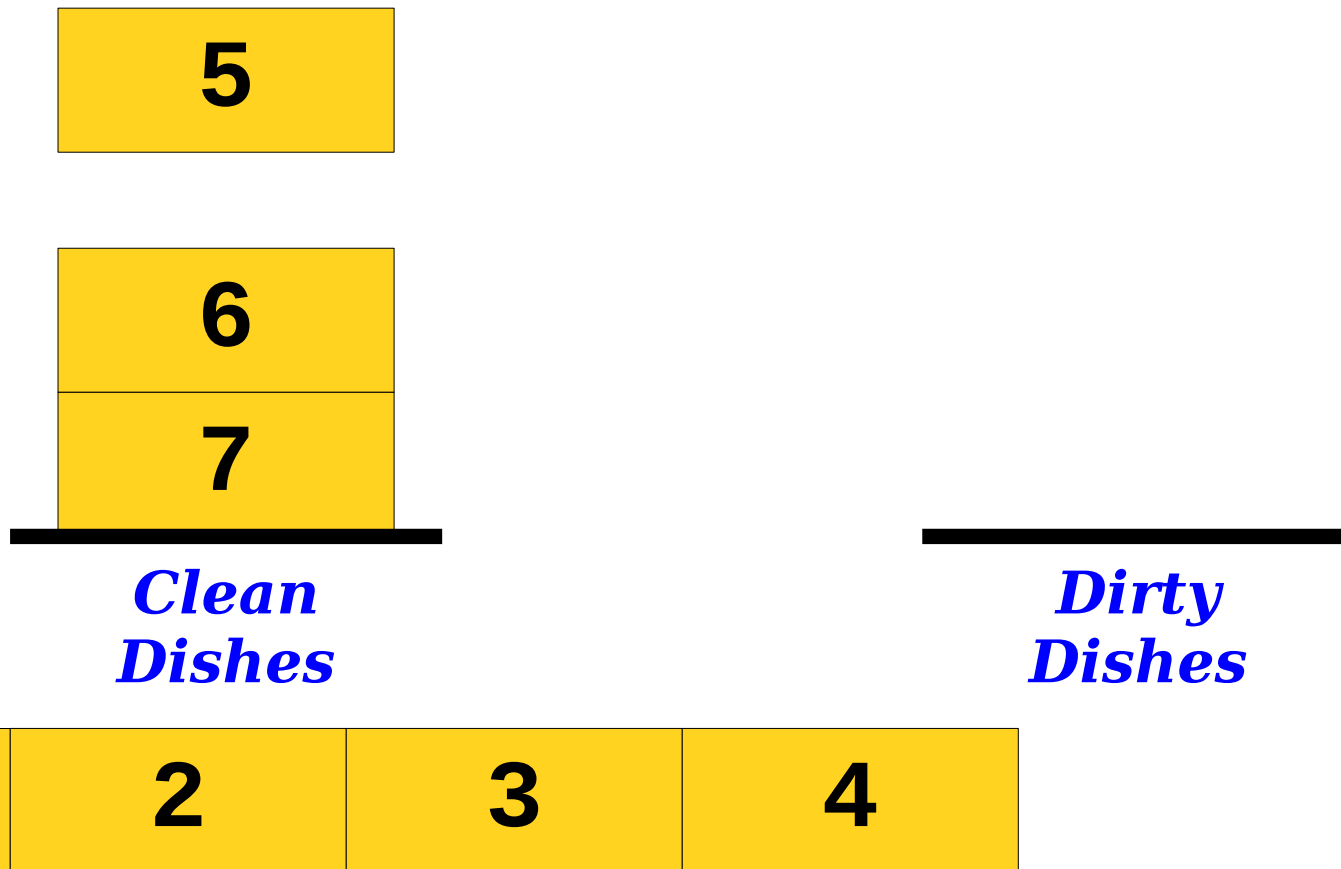
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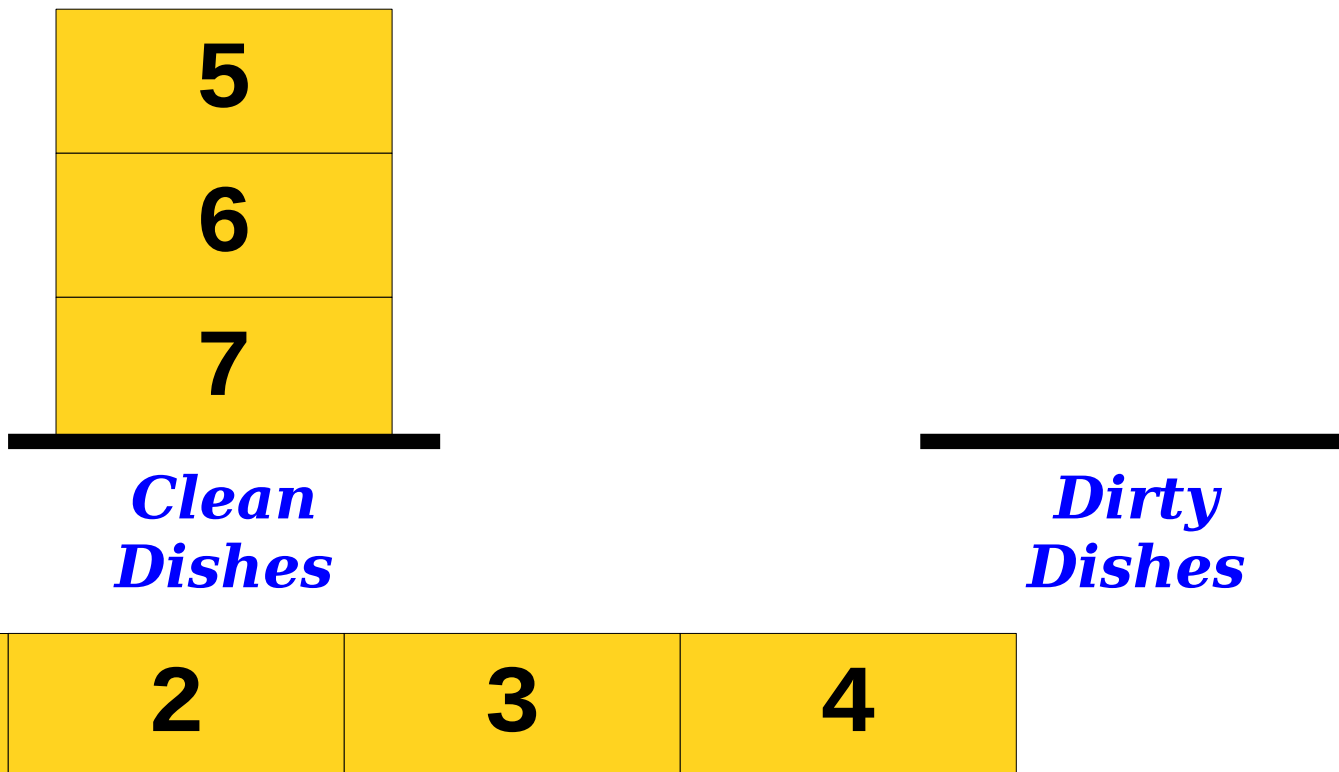
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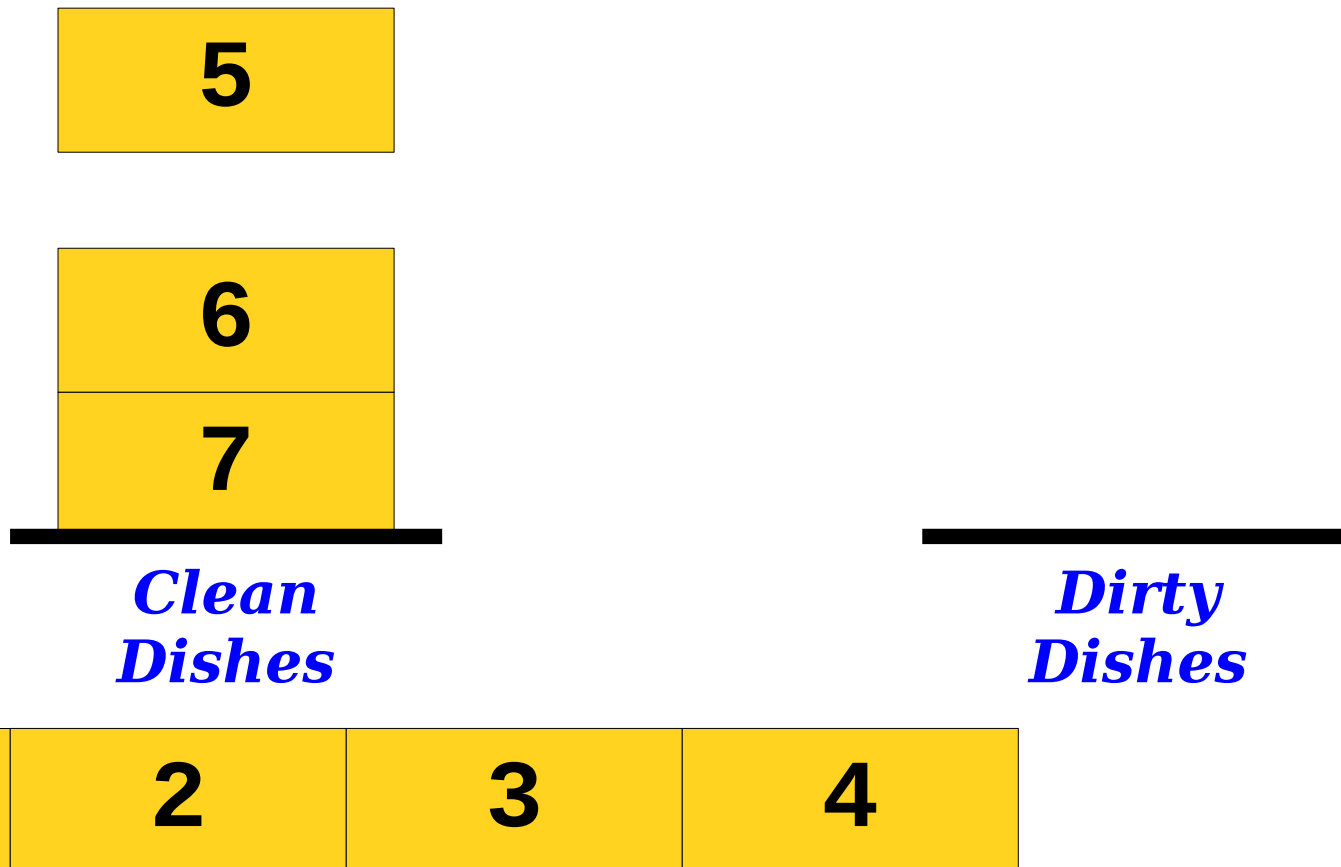
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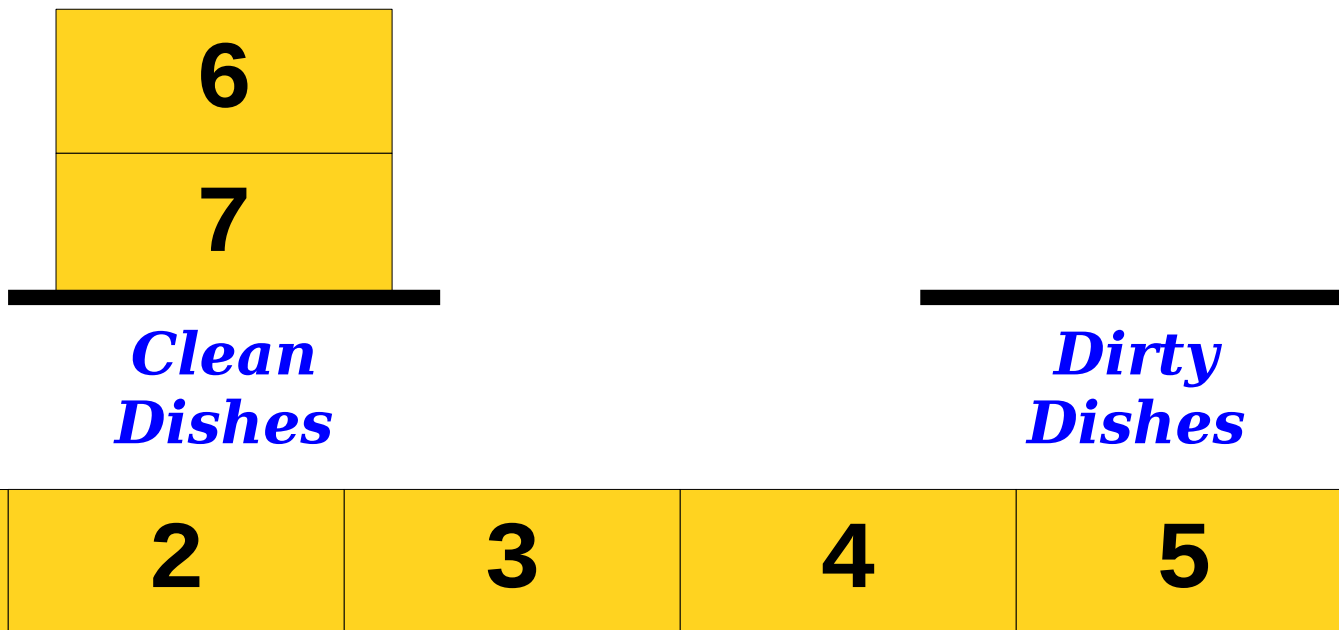
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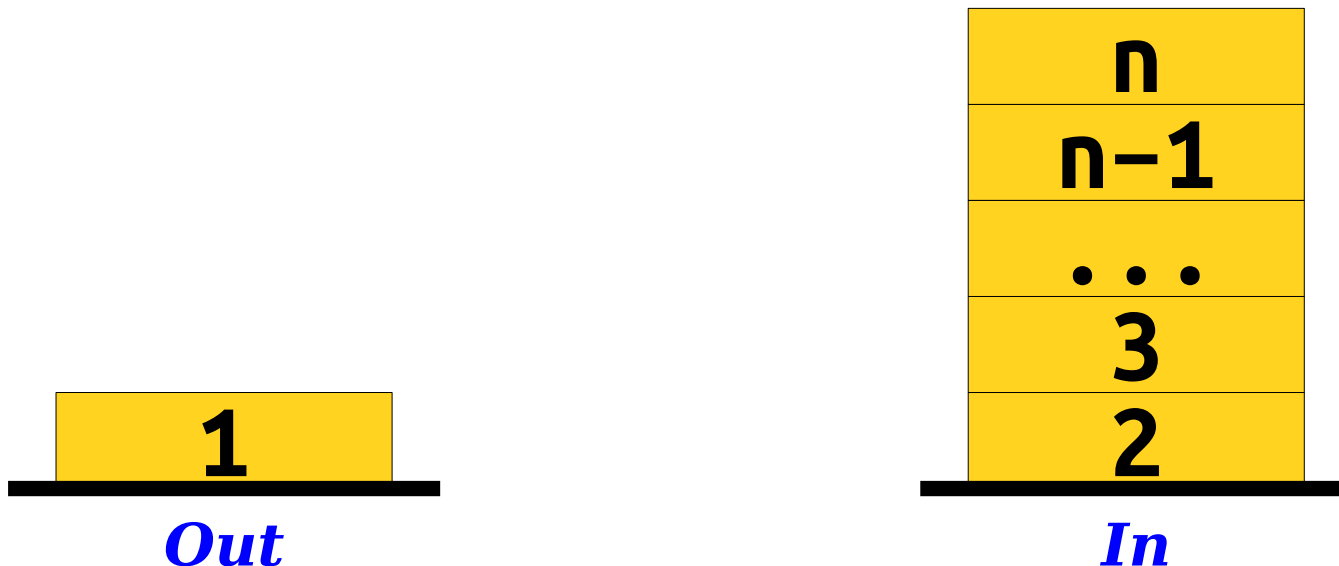


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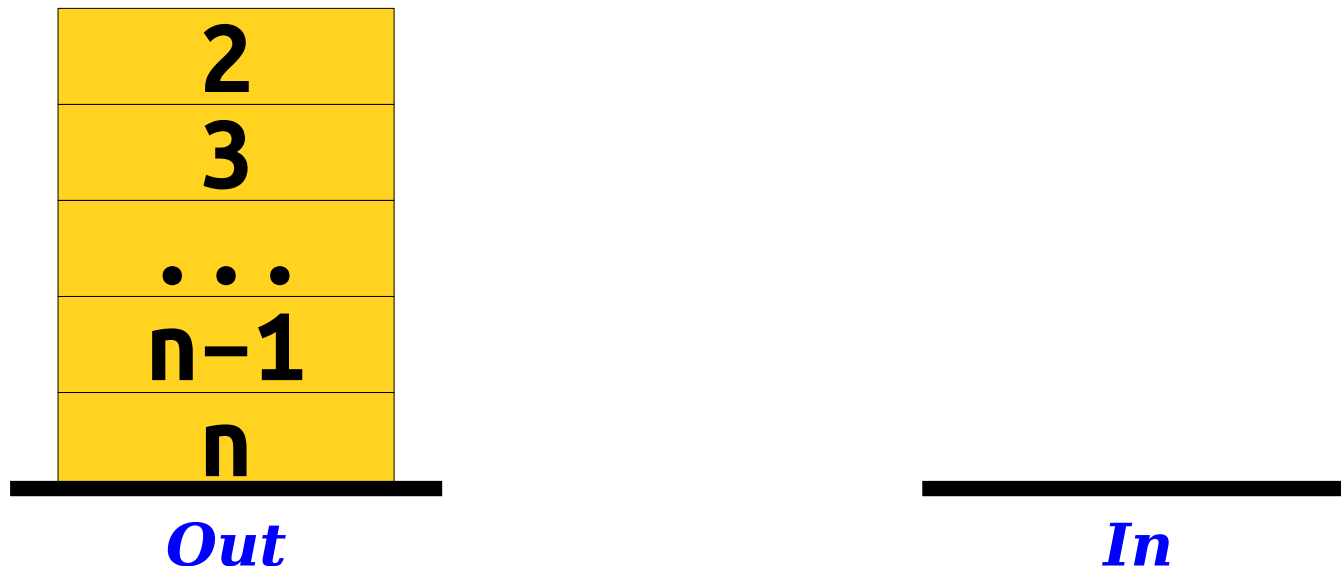
# The Two-Stack Queue

- Each enqueue takes time  $O(1)$ .
  - Just push an item onto the **In** stack.
- Dequeues can vary in their runtime.
  - Could be  $O(1)$  if the **Out** stack isn't empty.
  - Could be  $\Theta(n)$  if the **Out** stack is empty.



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# The Two-Stack Queue

- **Intuition:** We only do expensive dequeues after a long run of cheap enqueues.
- Think “dishwasher:” we very slowly introduce a lot of dirty dishes that get cleaned up all at once.
- Provided we clean up all the dirty dishes at once, and provided that dirty dishes accumulate slowly, this is a fast strategy!



# The Two-Stack Queue

- **Key Fact:** Any series of  $n$  operations on an (initially empty) two-stack queue will take time  $O(n)$ .
- **Why?**

Answer at  
<https://cs166.stanford.edu/pollev>



# The Two-Stack Queue

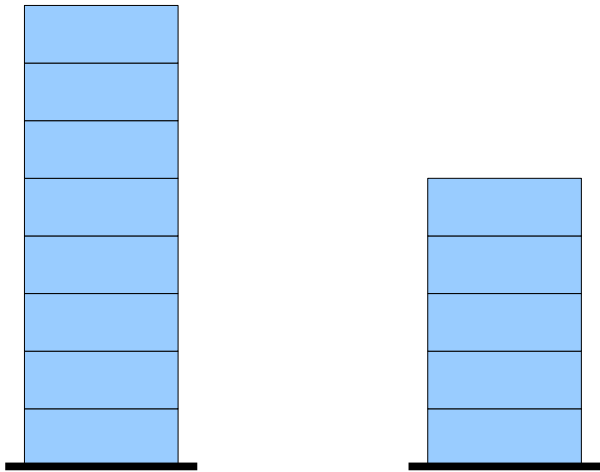
- **Key Fact:** Any series of  $n$  operations on an (initially empty) two-stack queue will take time  $O(n)$ .
- **Why?**
- Each item is pushed into at most two stacks and popped from at most two stacks.
- Adding up the work done per element across all  $n$  operations, we can do at most  $O(n)$  work.



# The Two-Stack Queue

- It's correct but misleading to say the cost of a dequeue is  $O(n)$ .
  - This is comparatively rare.
- It's wrong, but useful, to pretend the cost of a dequeue is  $O(1)$ .
  - Some operations take more time than this.
  - However, if we pretend each operation takes time  $O(1)$ , then the sum of all the costs never underestimates the total.
- **Question:** What's an honest, accurate way to describe the runtime of the two-stack queue?

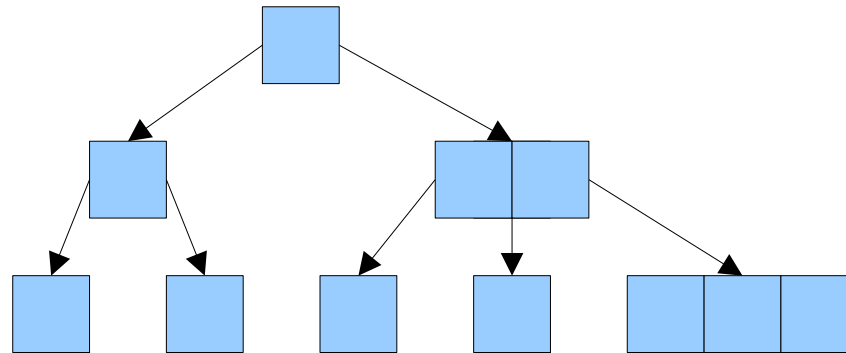




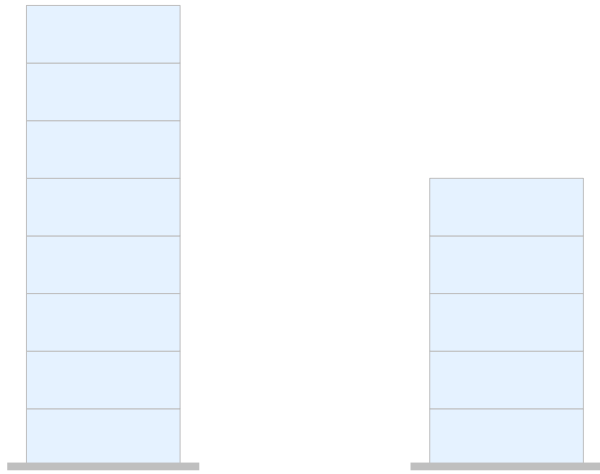
*Two-Stack Queues*



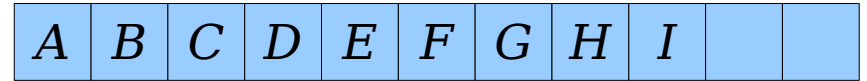
*Dynamic Arrays*



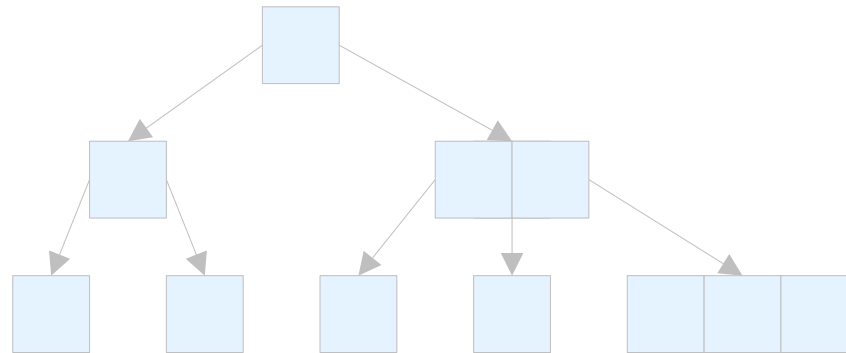
*Building B-Trees*



*Two-Stack Queues*



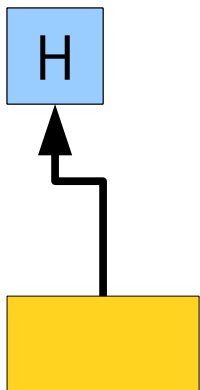
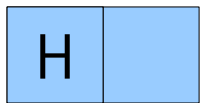
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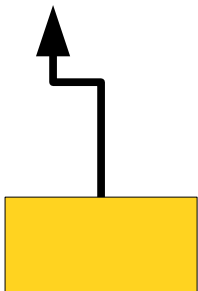
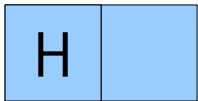
# Dynamic Arrays

- A ***dynamic array*** is the most common way to implement a list of values.
- Maintain an array slightly bigger than the one you need. When you run out of space, double the array size and copy the elements over.



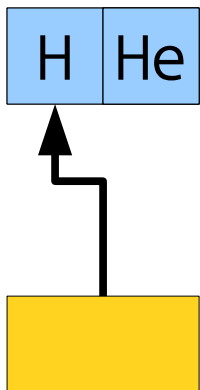
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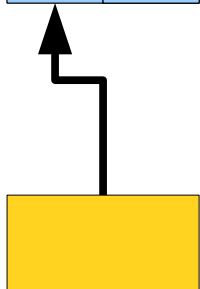
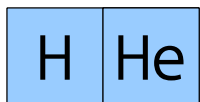
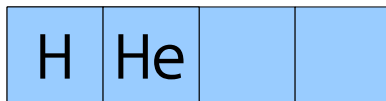
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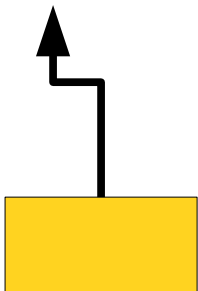
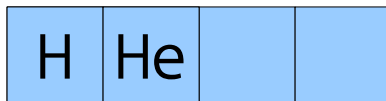
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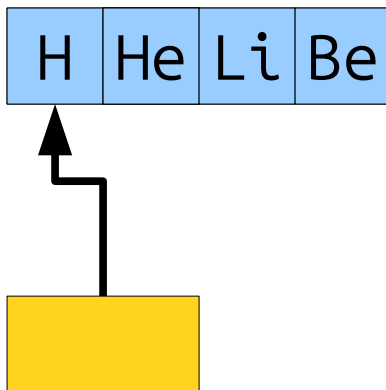
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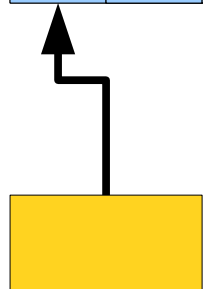
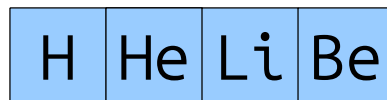
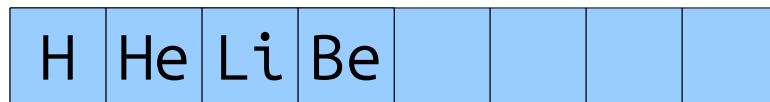
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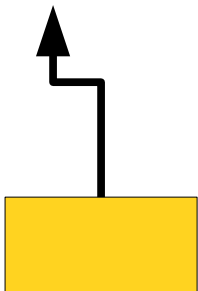
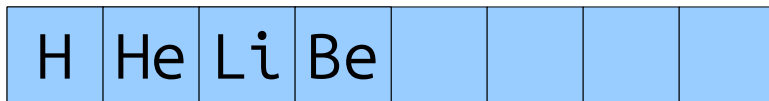
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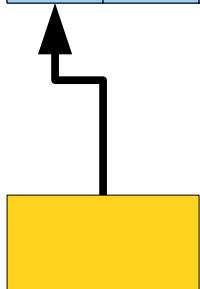
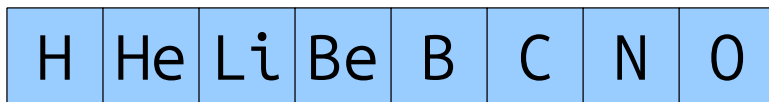
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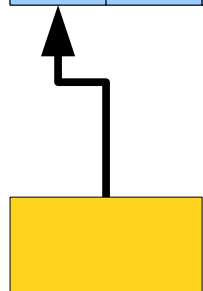
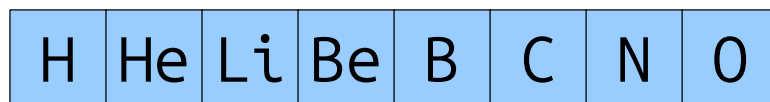
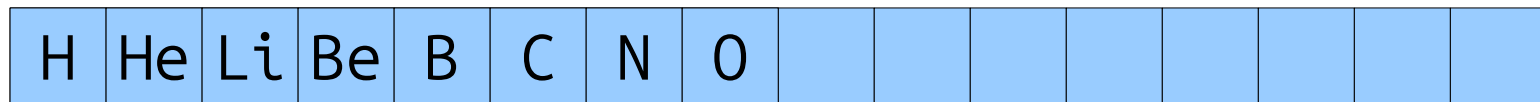
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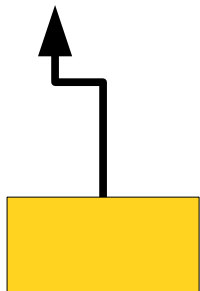
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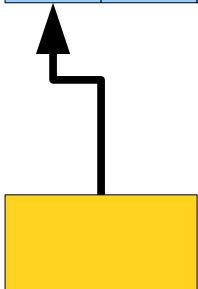
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H	He	Li	Be	B	C	N	O	F	Ne	Na	Mg	Al	Si	P	S
---	----	----	----	---	---	---	---	---	----	----	----	----	----	---	---



# Dynamic Arrays

- Most appends to a dynamic array take time  $O(1)$ .
- Infrequently, we do  $\Theta(n)$  work to copy all  $n$  elements from the old array to a new one.
- Think “dishwasher:”
  - We slowly accumulate “messes” (filled slots).
  - We periodically do a large “cleanup” (copying the array).
- **Claim:** The cost of doing  $n$  appends to an initially empty dynamic array is always  $O(n)$ .



# Dynamic Arrays

- **Claim:** Appending  $n$  elements always takes time  $O(n)$ .
- The array doubles at sizes  $2^0, 2^1, 2^2, \dots$ , etc.
- The very last doubling is at the largest power of two less than  $n$ . This is at most  $2^{\lceil \lg n \rceil}$ . (Do you see why?)
- Total work done across all doubling is at most

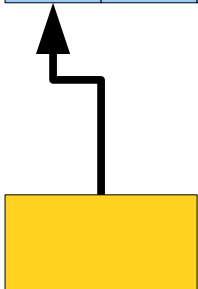
$$\begin{aligned} 2^0 + 2^1 + \dots + 2^{\lceil \lg n \rceil} &= 2^{\lceil \lg n \rceil + 1} - 1 \\ &\leq 2^{\lg n + 1} \\ &= 2n. \end{aligned}$$

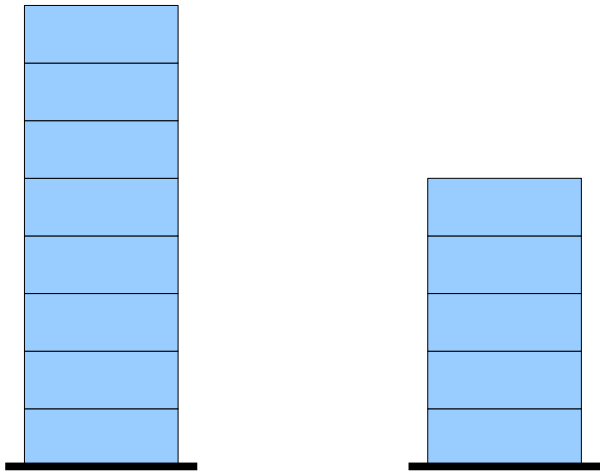


# Dynamic Arrays

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  - However, pretending each operation takes  $O(1)$  time never underestimates the true total runtime.
- **Question:** What's an honest, accurate way to describe the runtime of the dynamic array?

H	He	Li	Be	B	C	N	O	F	Ne	Na	Mg	Al	Si	P	S
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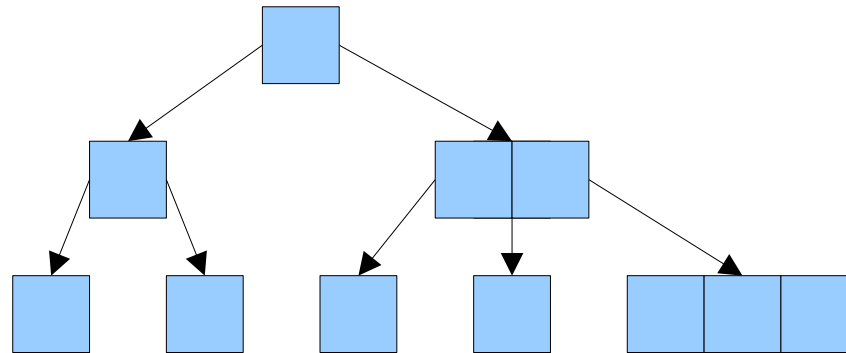




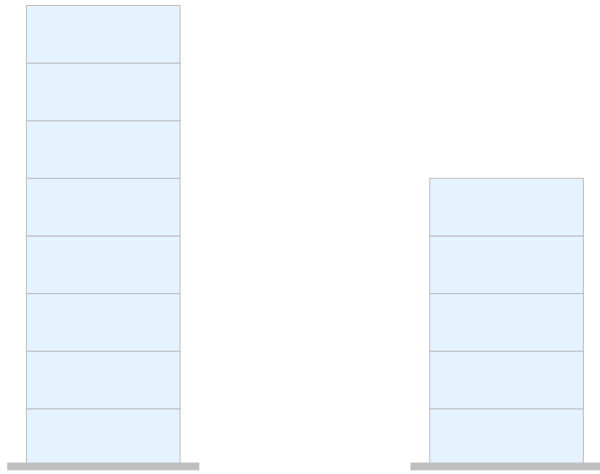
*Two-Stack Queues*



*Dynamic Arrays*



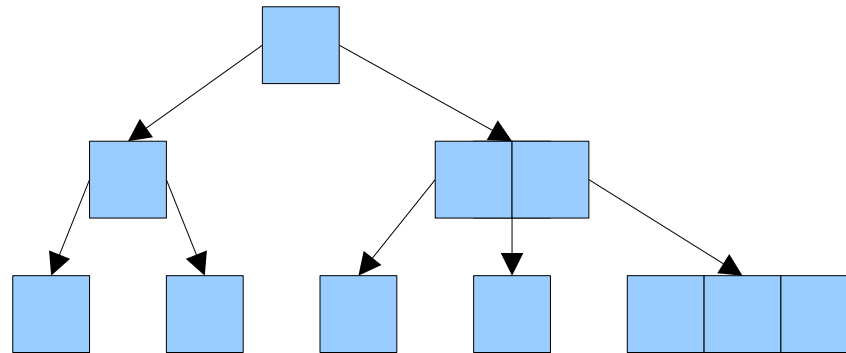
*Building B-Trees*



*Two-Stack Queues*



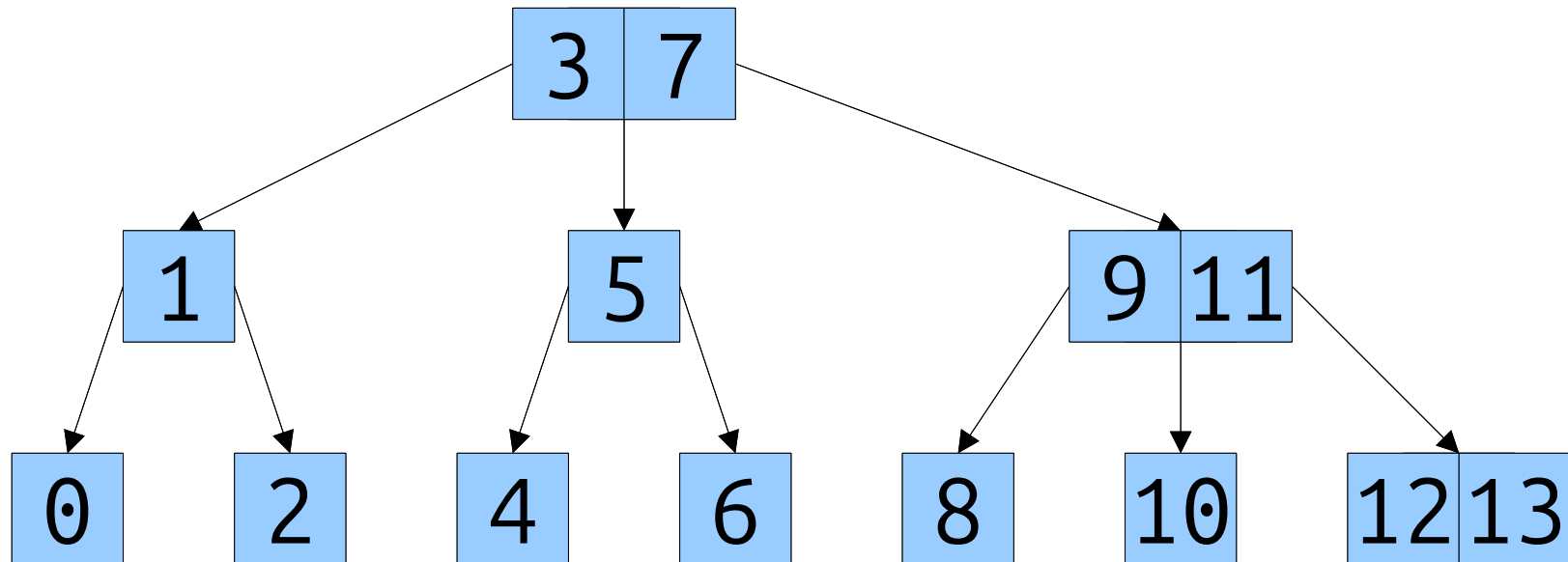
*Dynamic Arrays*



*Building B-Trees*

# Building B-Trees

- You're given a sorted list of  $n$  values and a value of  $b$ .
- What's the most efficient way to construct a B-tree of order  $b$  holding these  $n$  values?
- **One Option:** Think really hard, calculate the shape of a B-tree of order  $b$  with  $n$  elements in it, then place the items into that B-tree in sorted order.
- Is there an easier option?



# Building B-Trees

- ***Idea 1:*** Insert the items into an empty B-tree in sorted order.

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0	1
---	---

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0	1	2
---	---	---

# Building B-Trees

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0	1	2	3
---	---	---	---

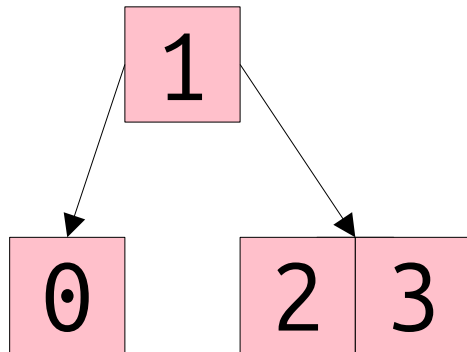
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0	1	2	3
---	---	---	---

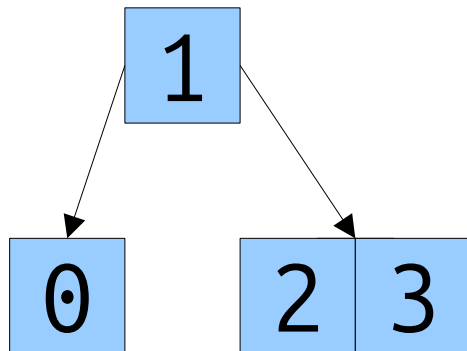
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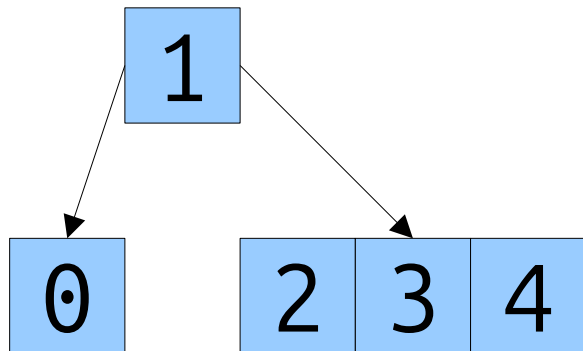
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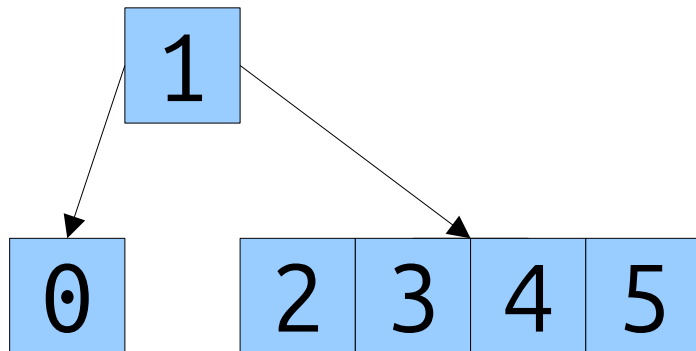
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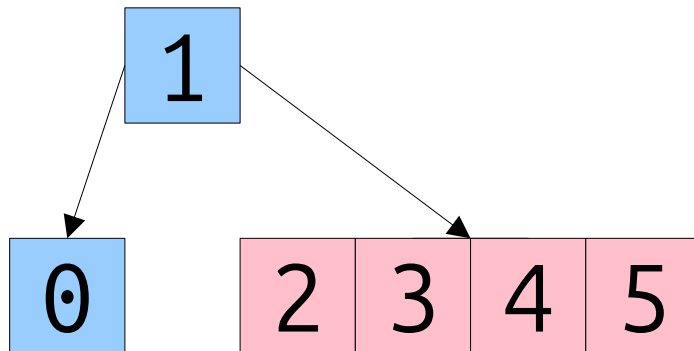
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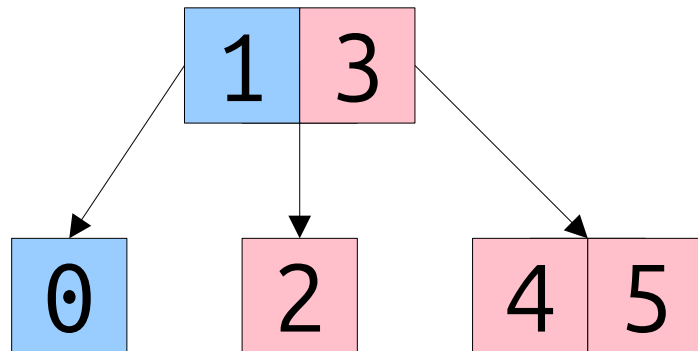
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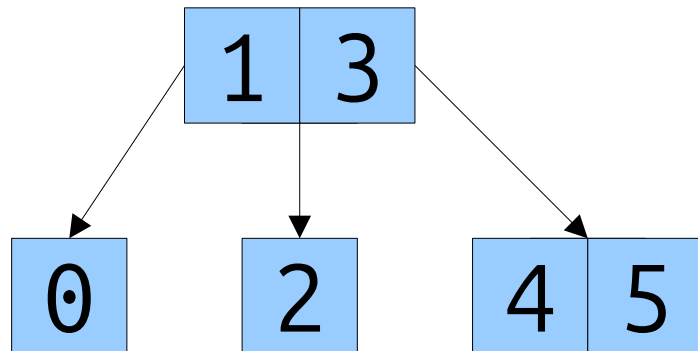
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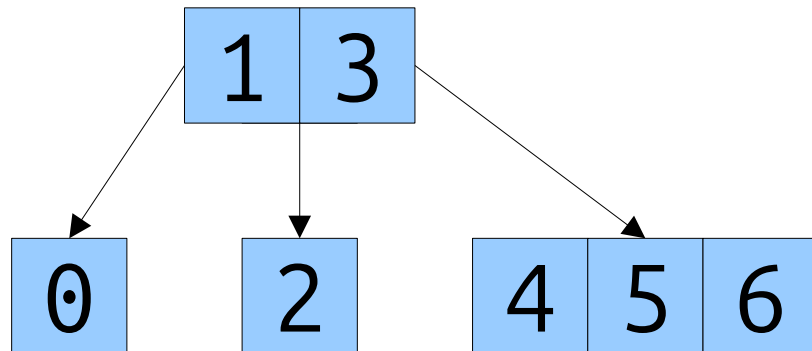
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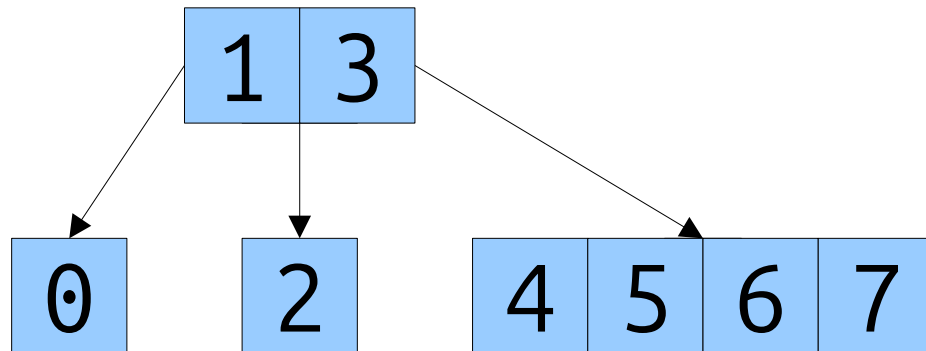
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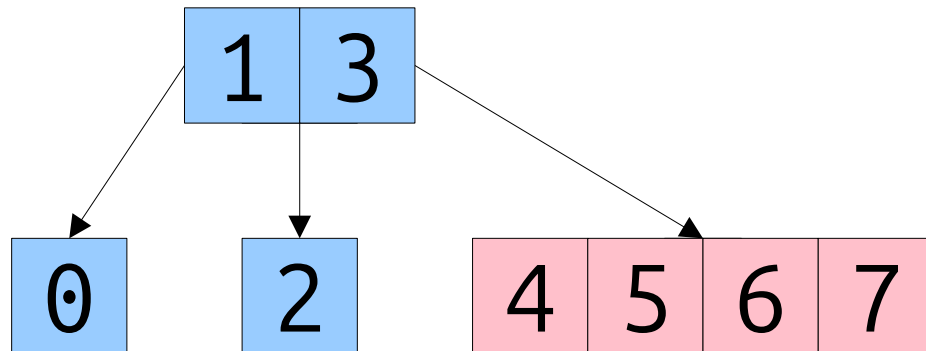
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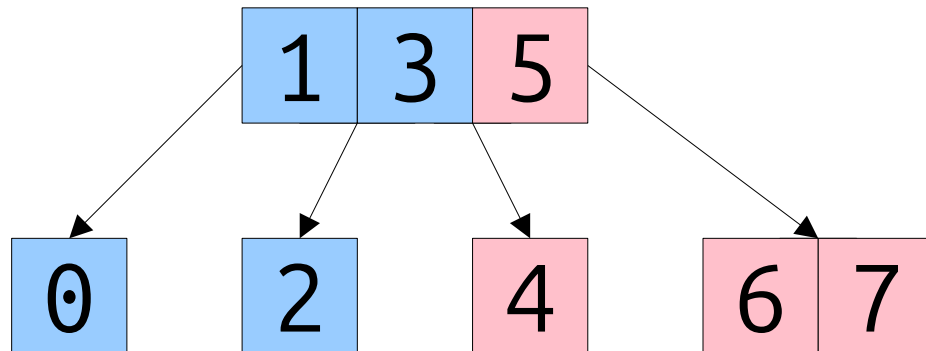
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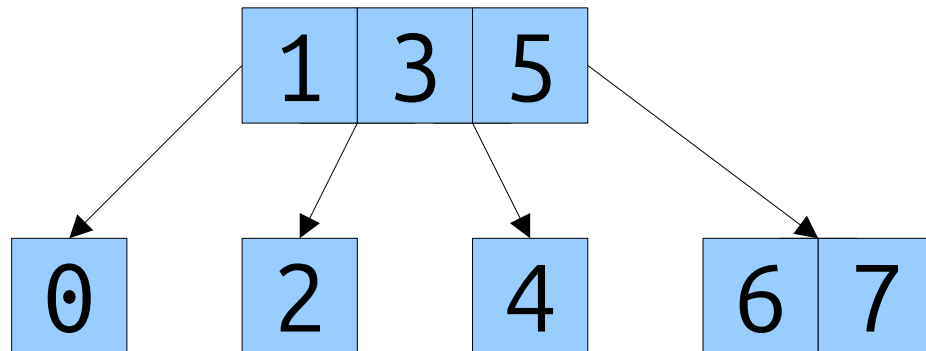
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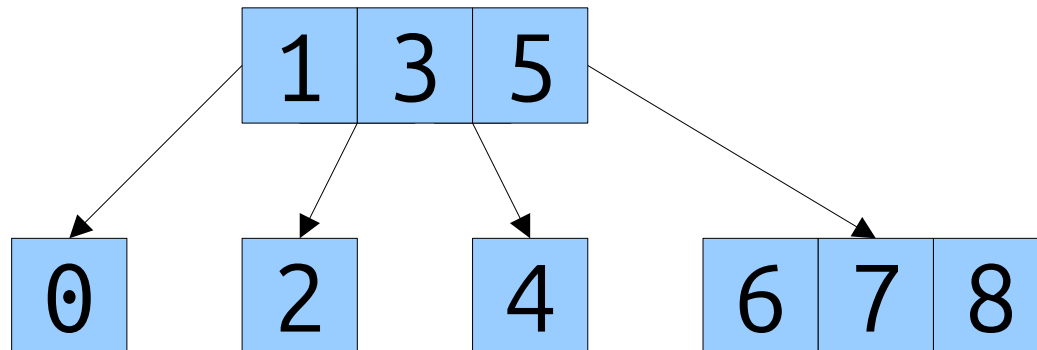
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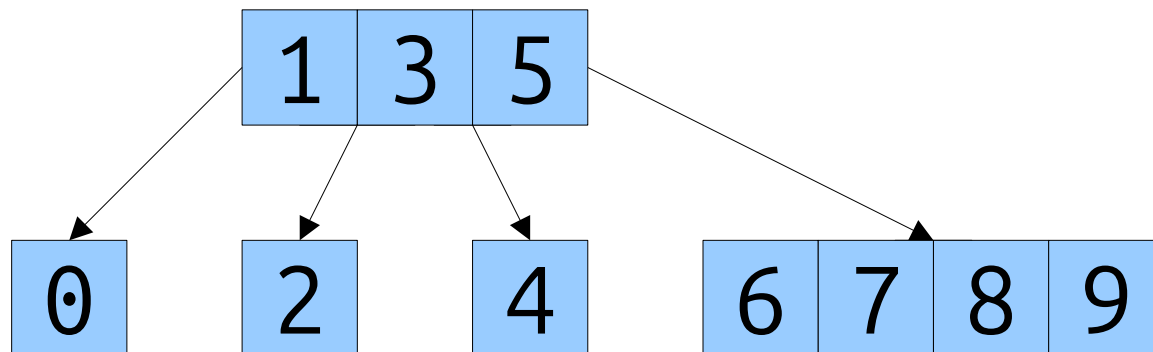
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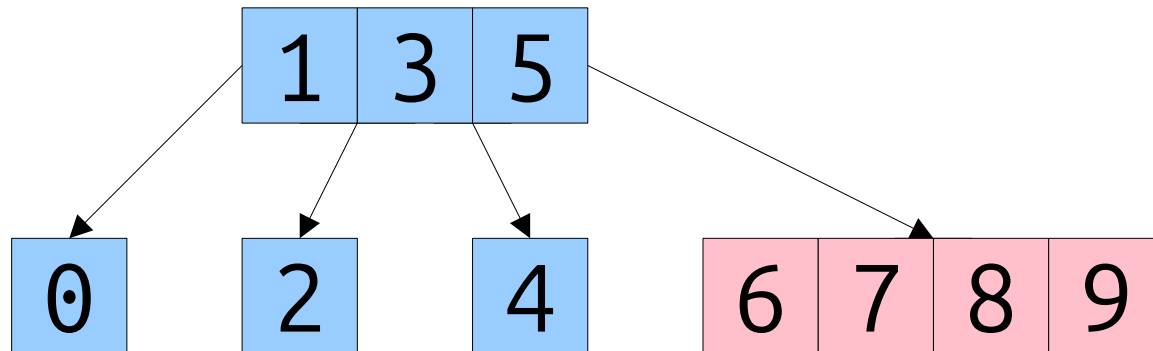
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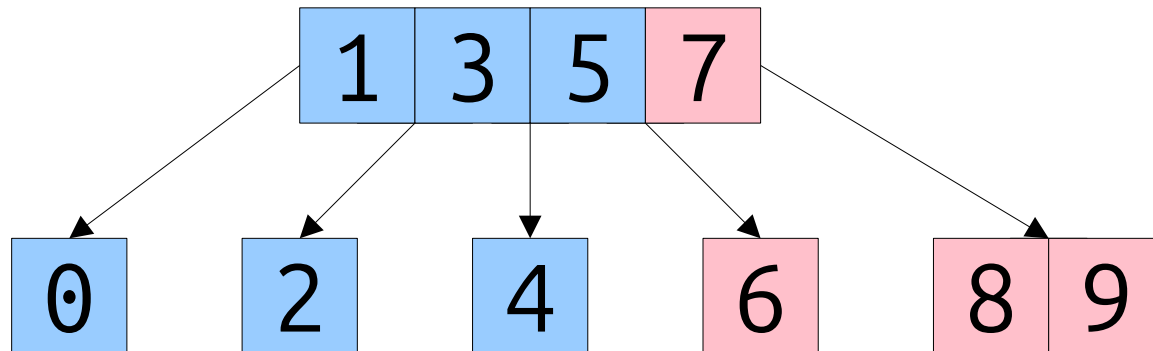
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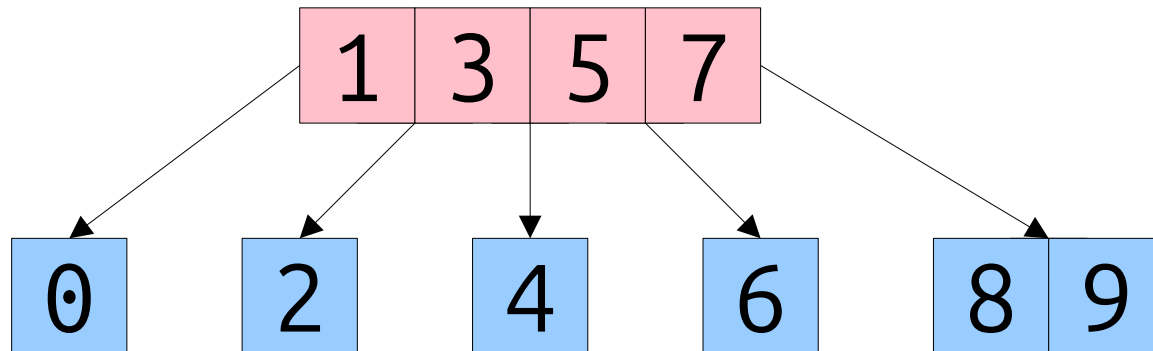
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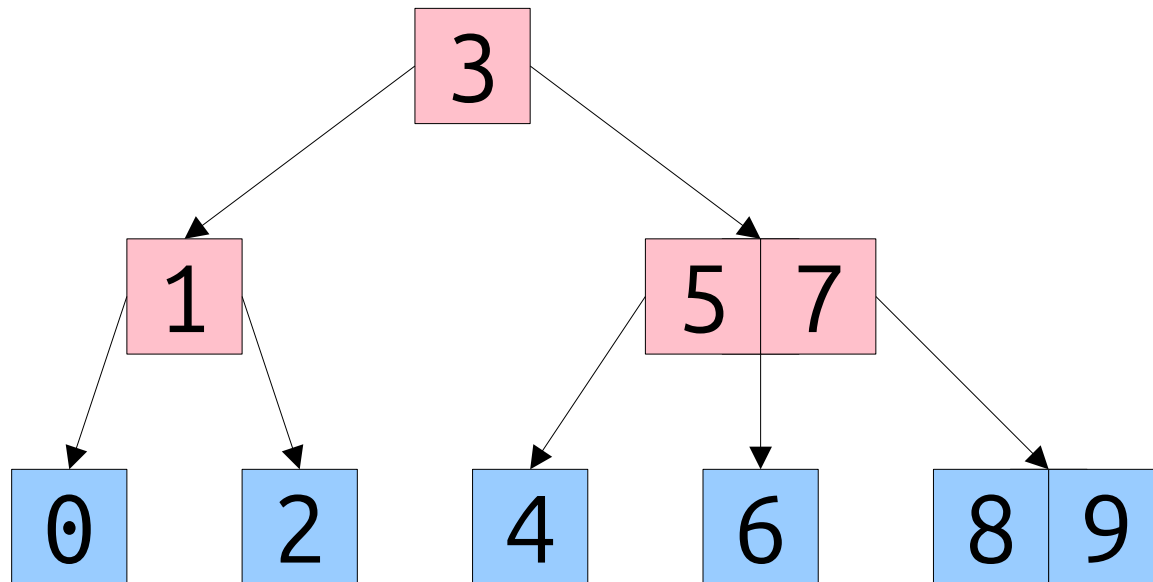
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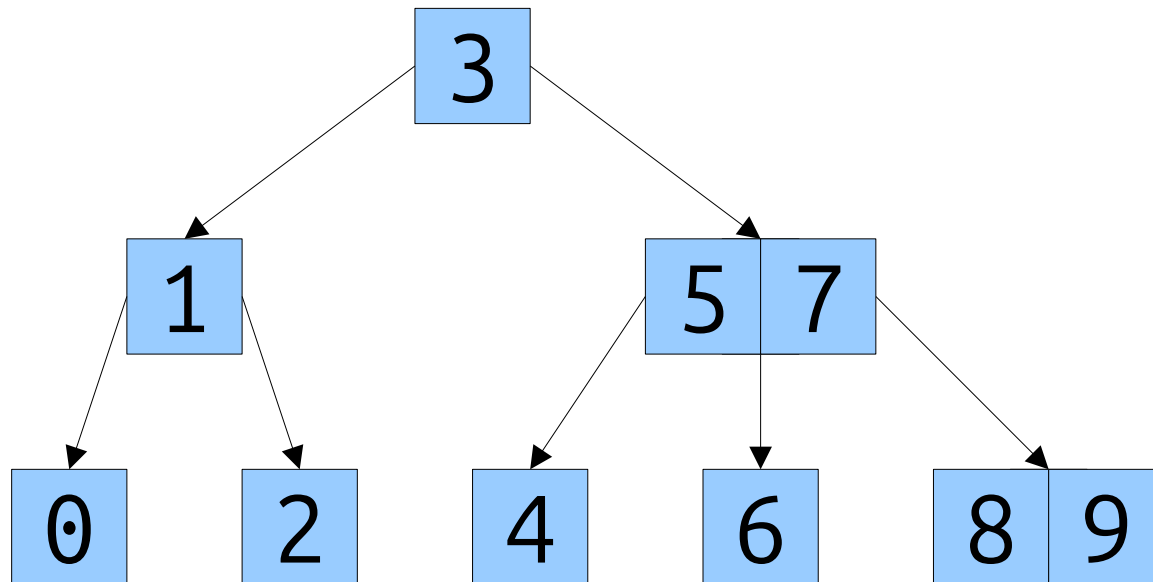
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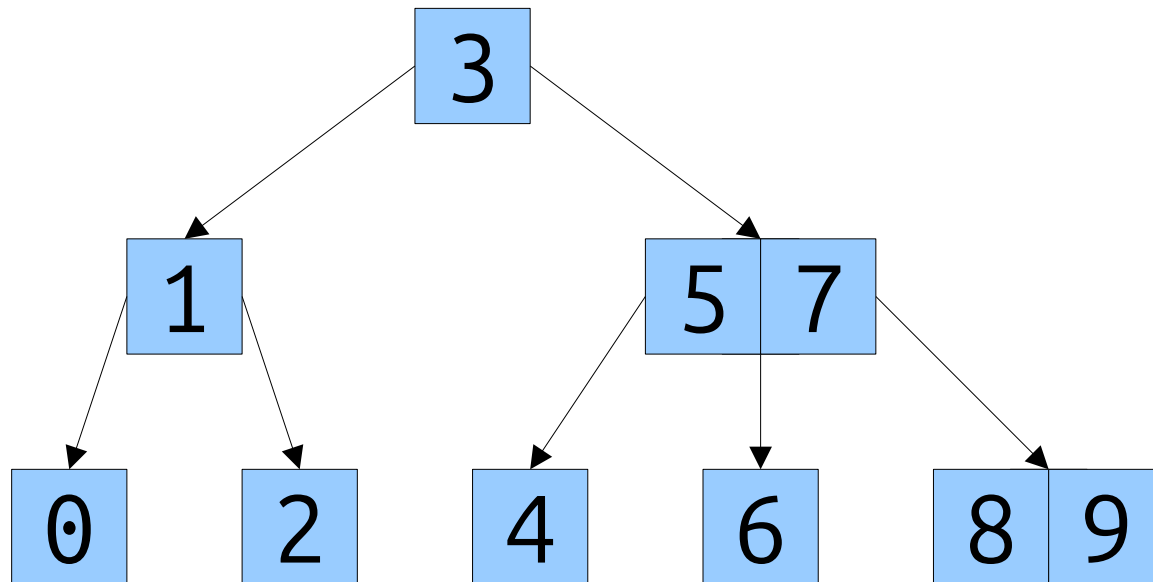
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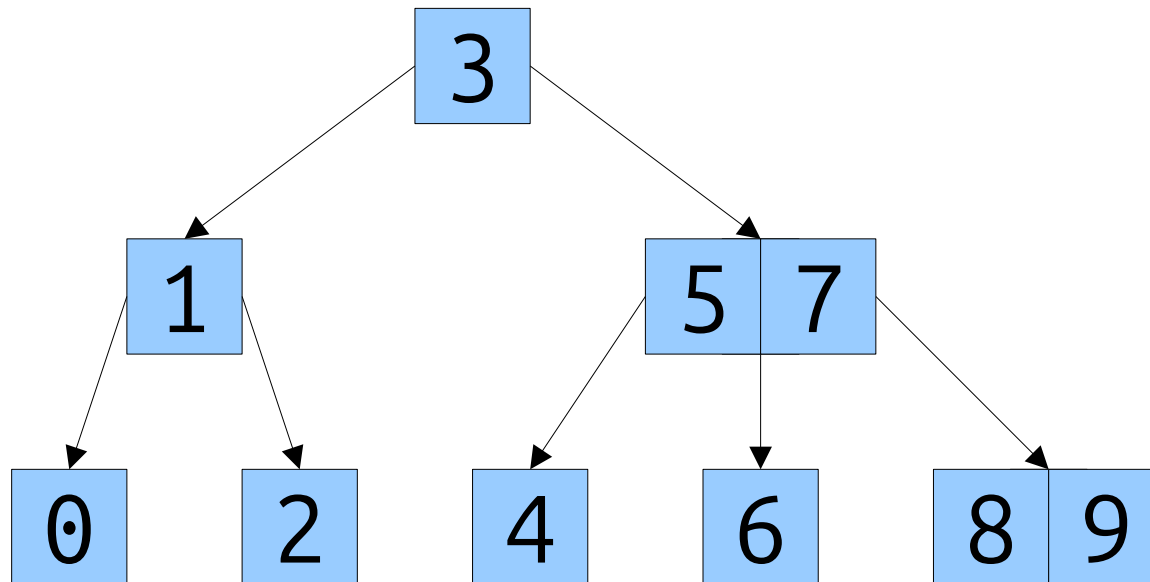
# Building B-Trees

- **Idea 1:** Insert the items into an empty B-tree in sorted order.
- Cost:  $\Omega(n \log_b n)$ , due to the top-down search.
- **Can we do better?**



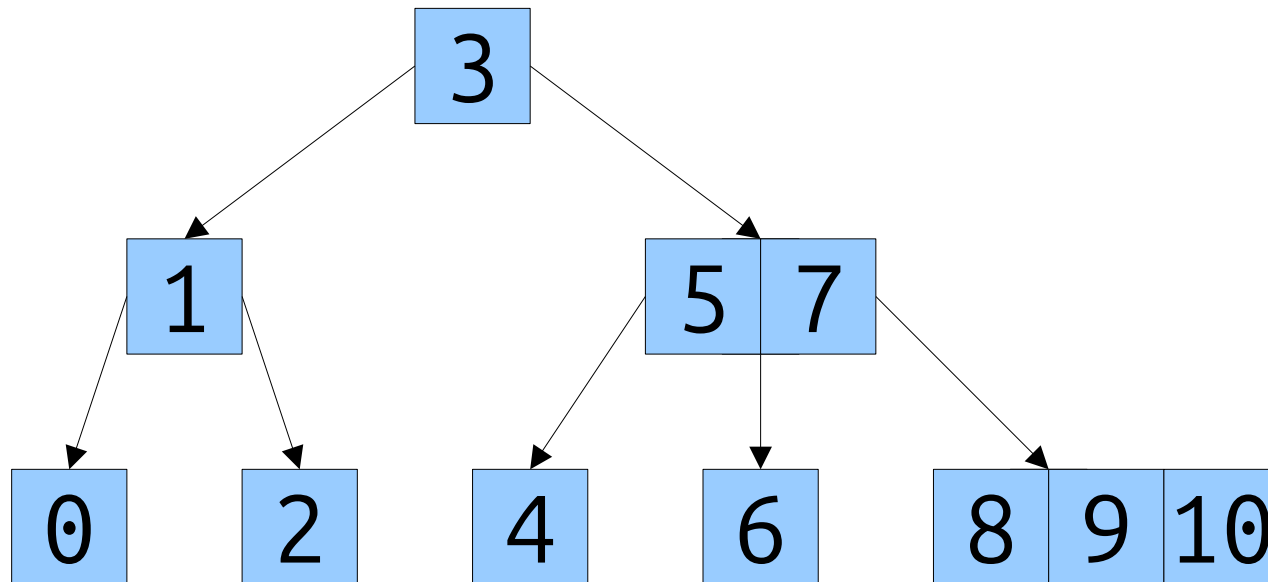
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- **Idea 2:** Since all insertions will happen at the rightmost leaf, store a pointer to that leaf. Add new values by appending to this leaf, then doing any necessary splits.



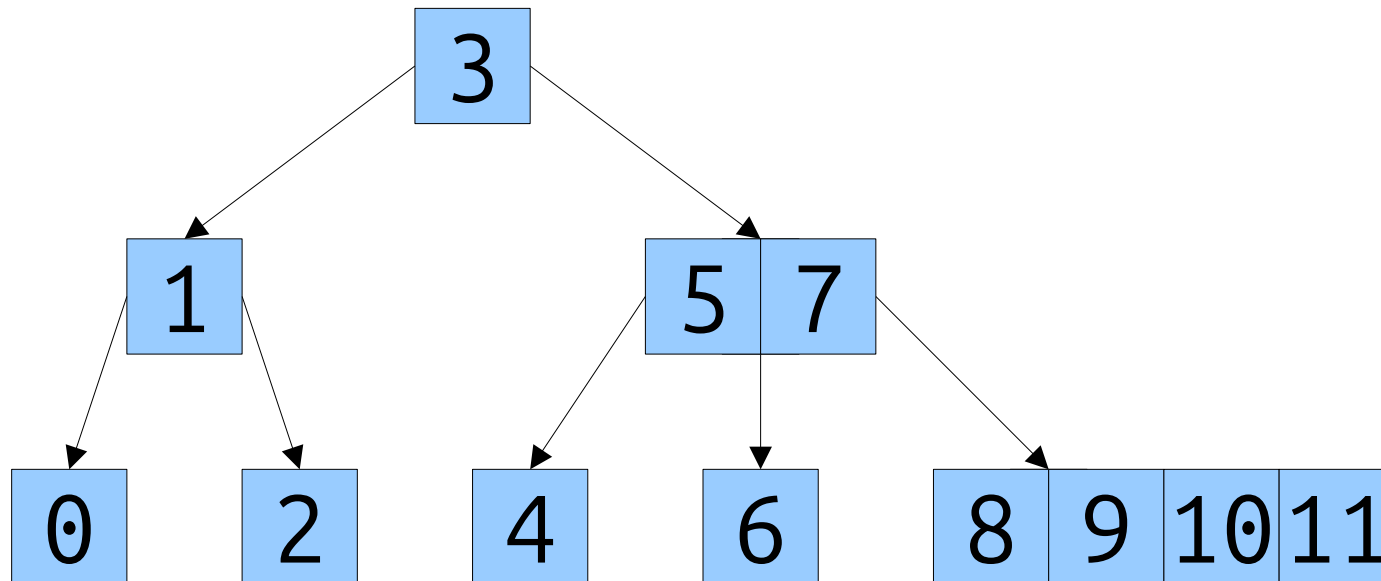
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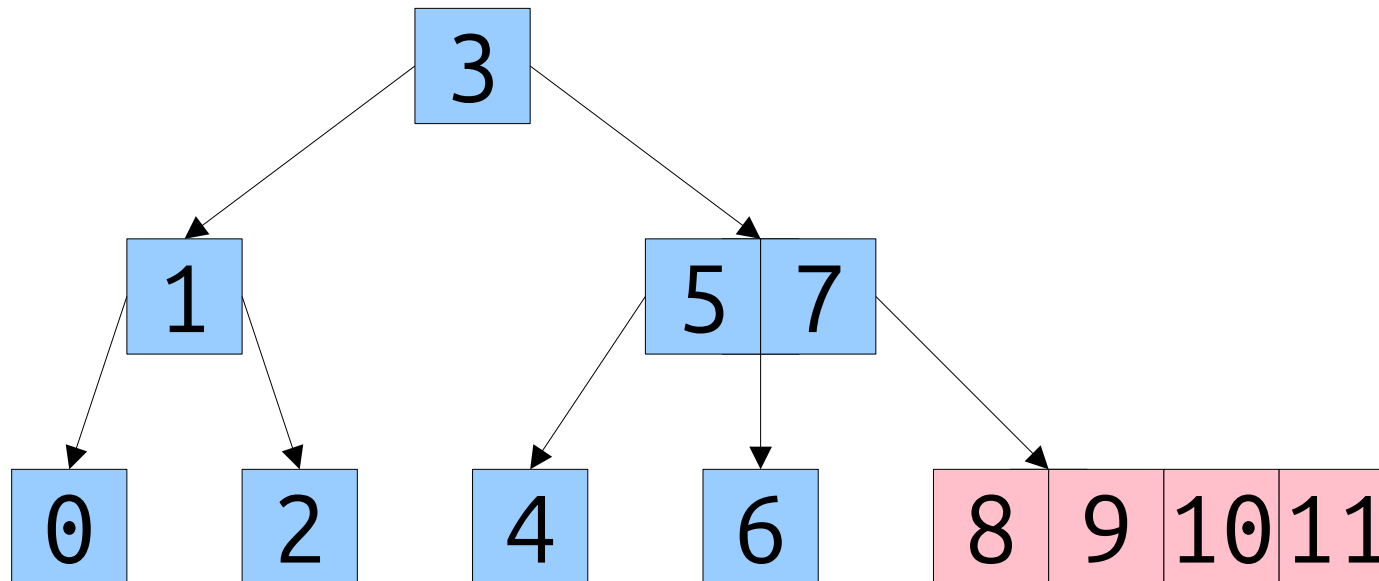
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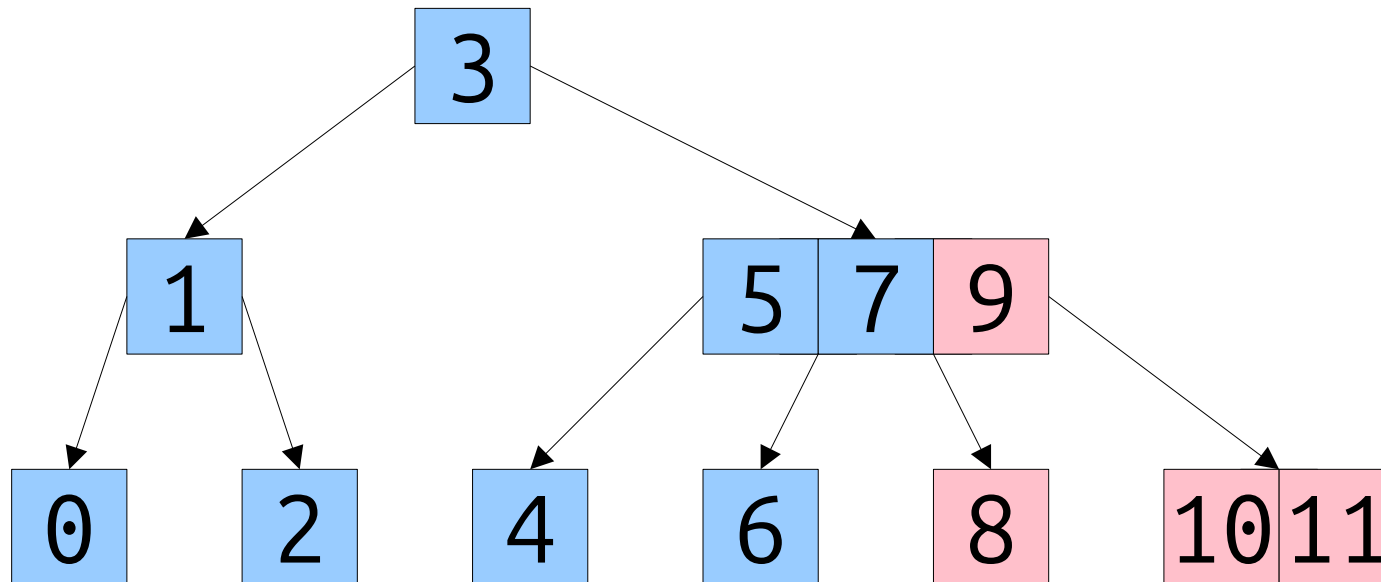
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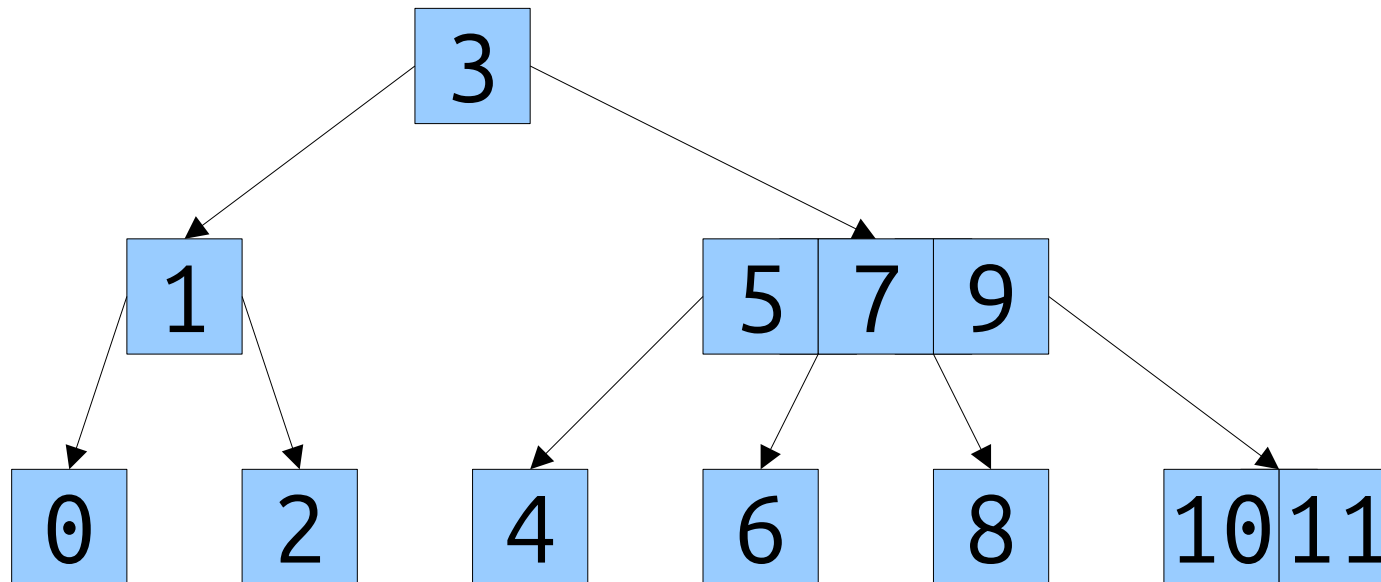
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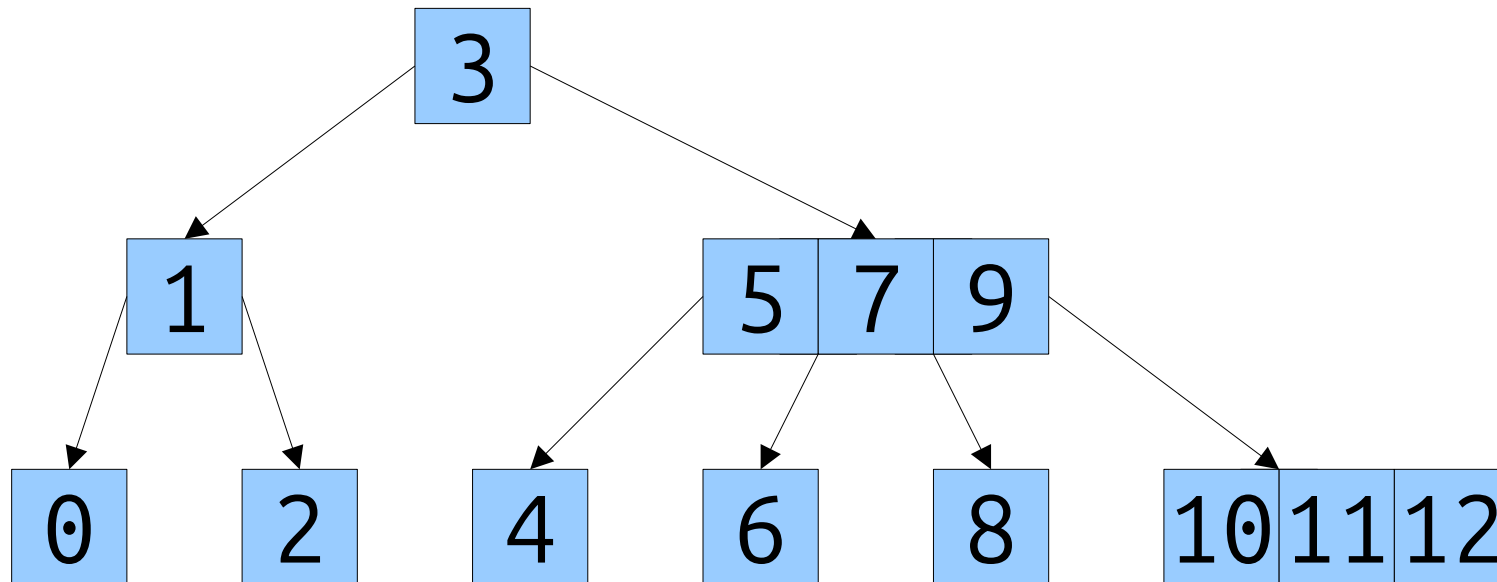
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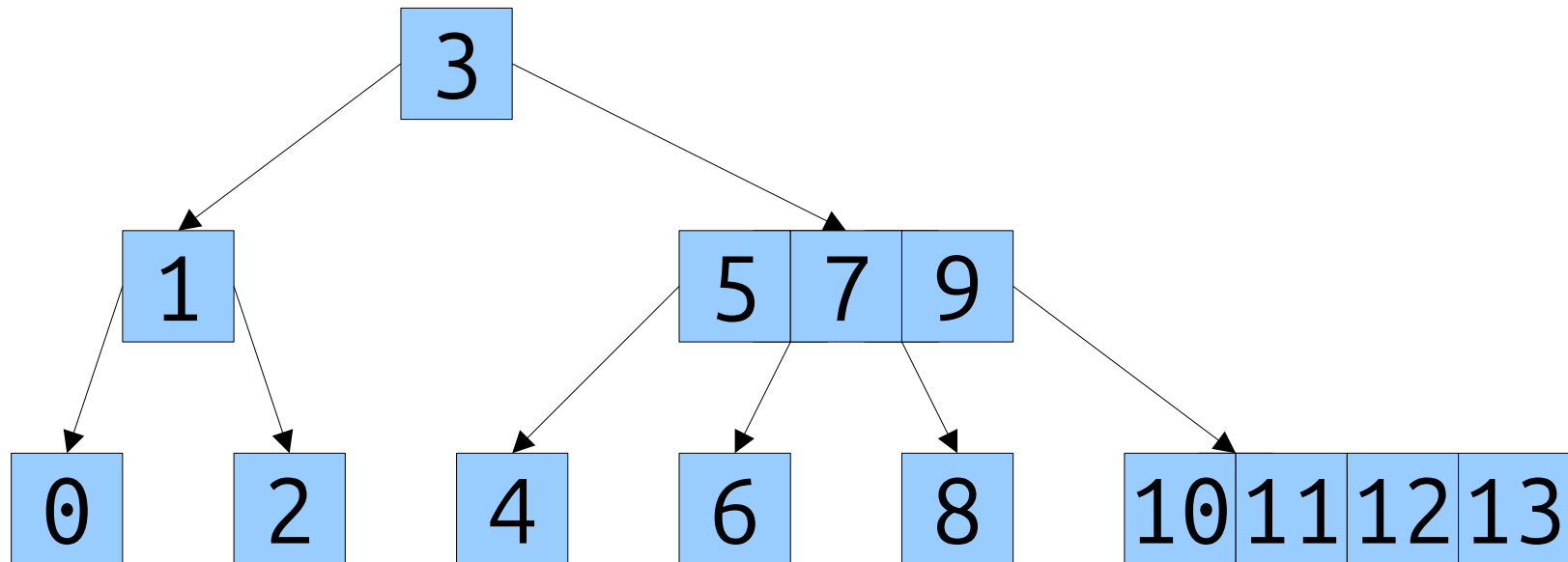
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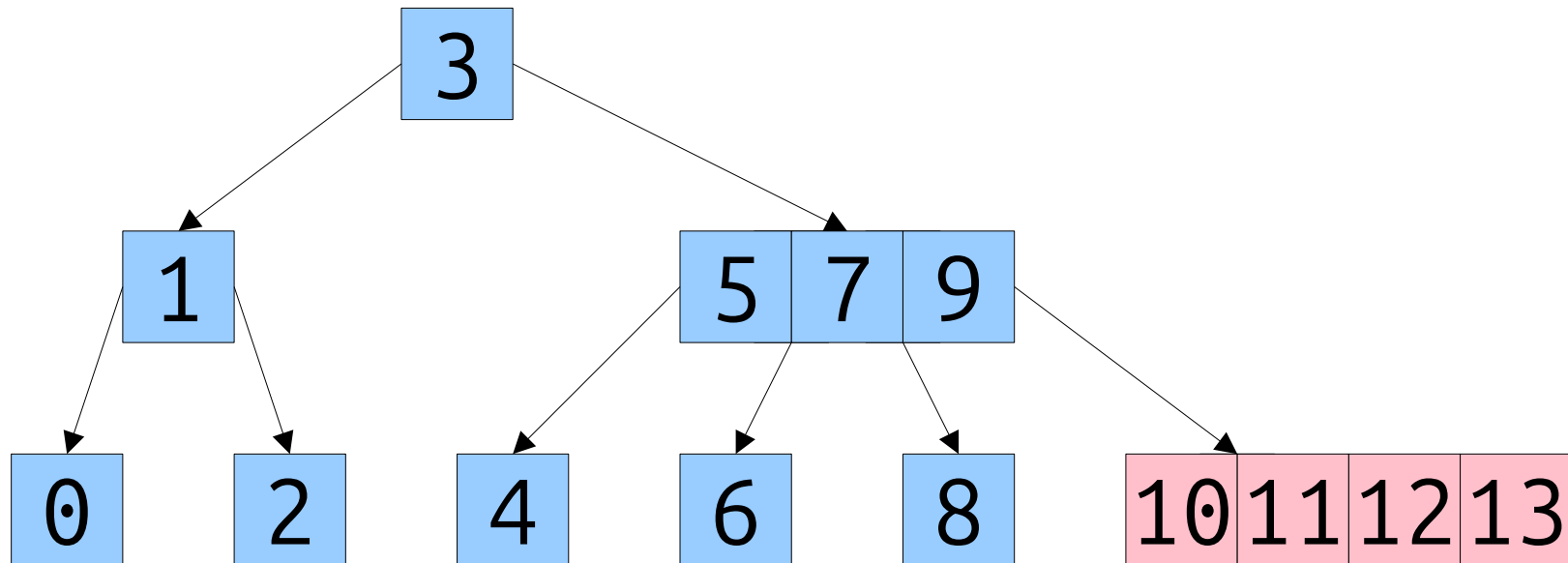
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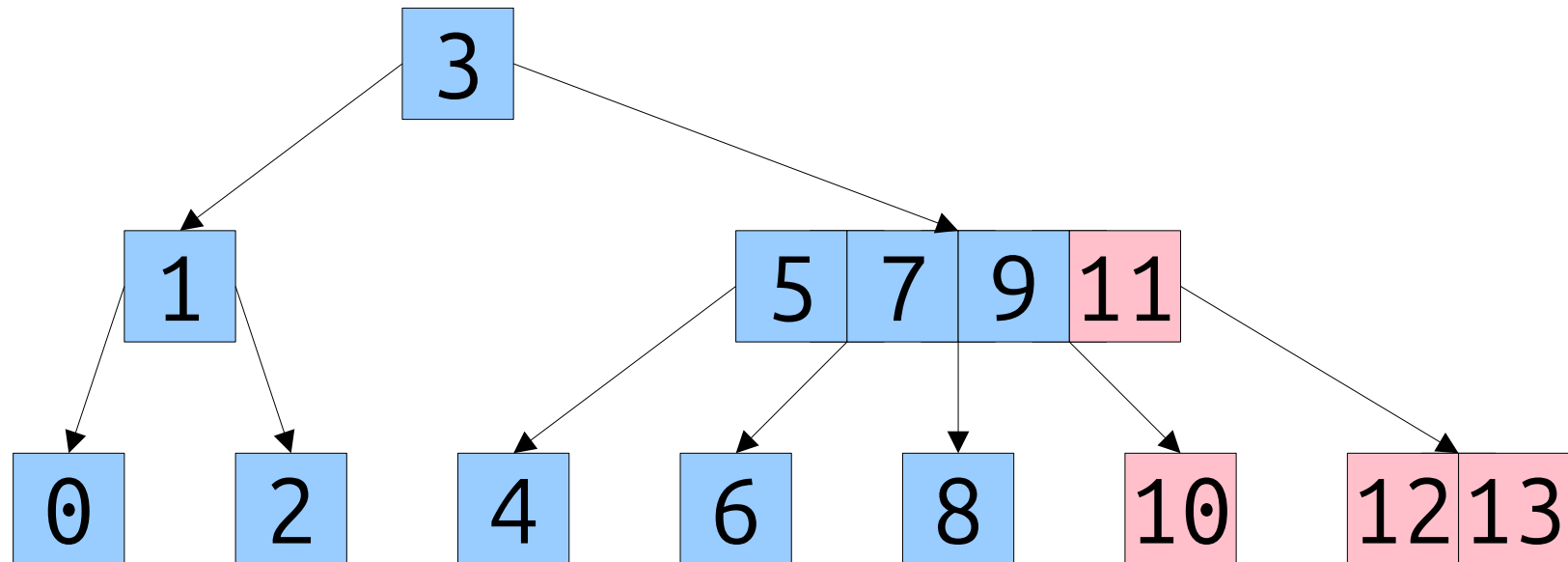
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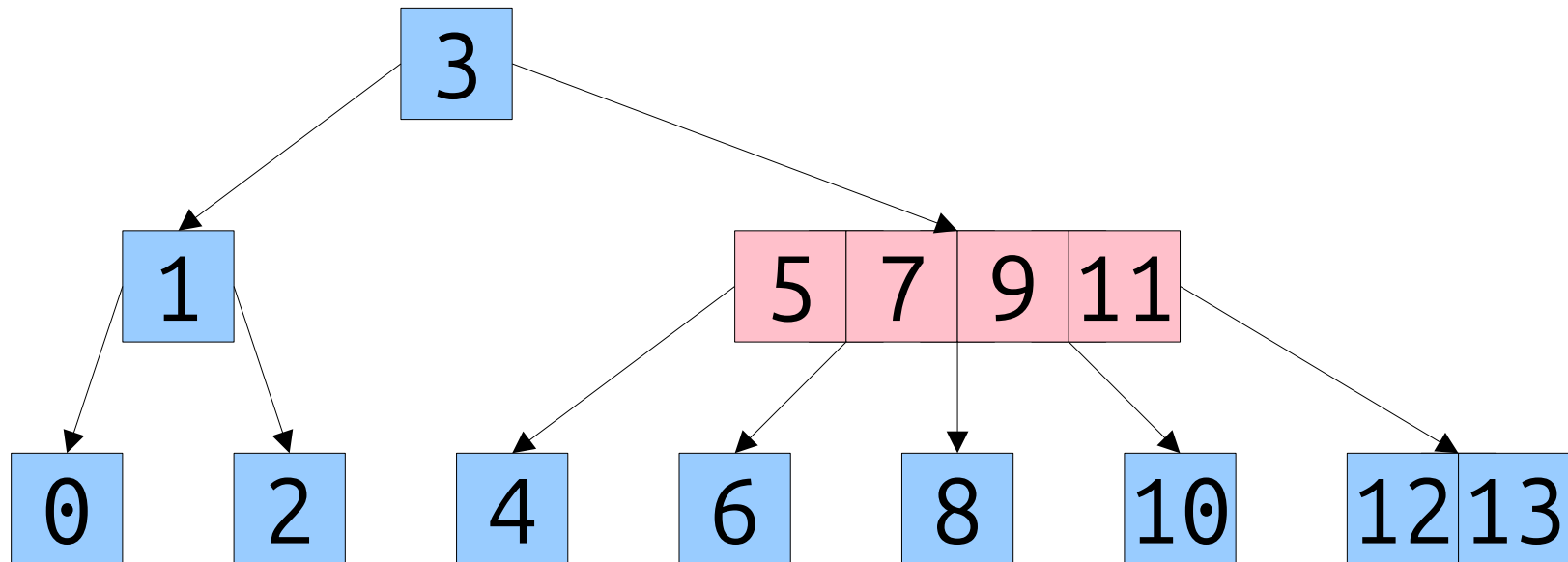
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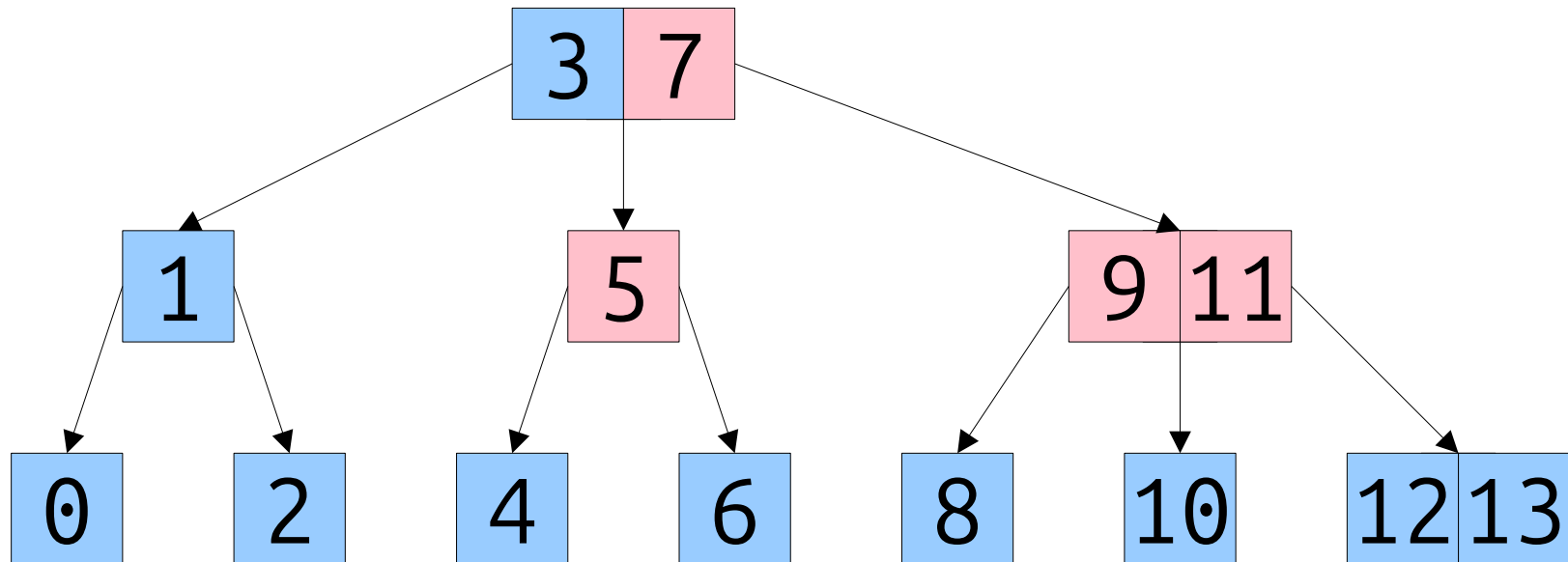
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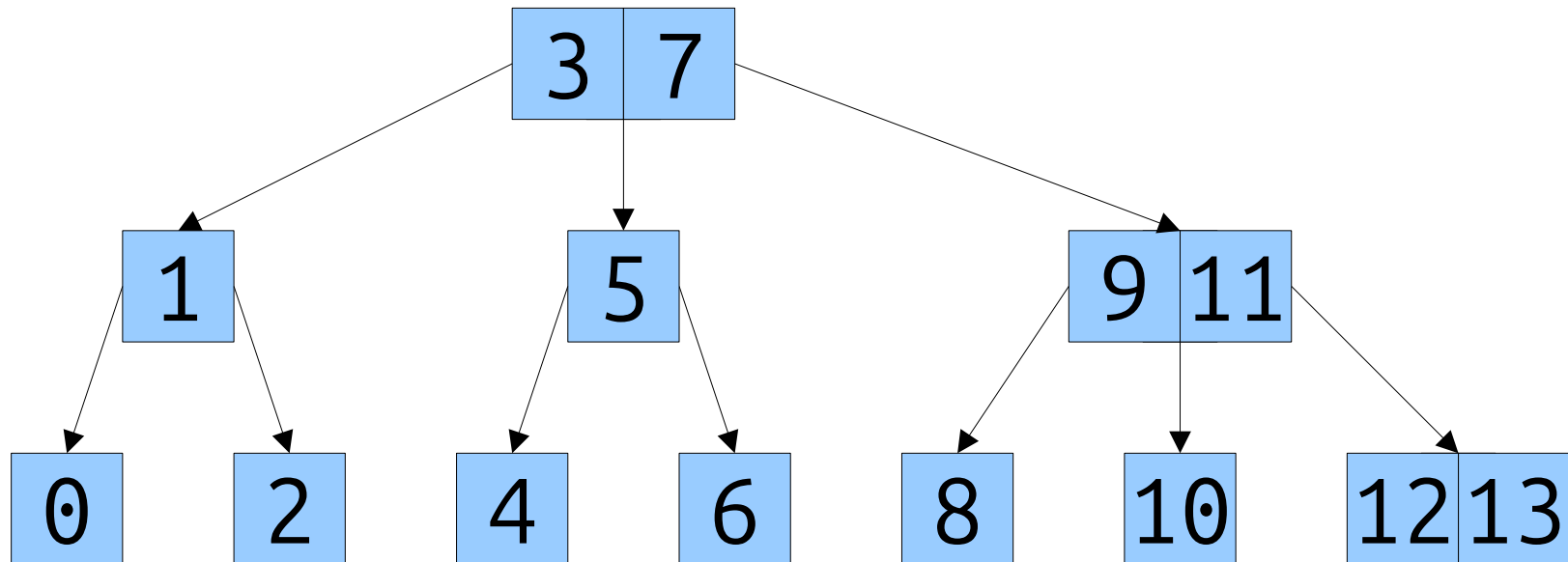
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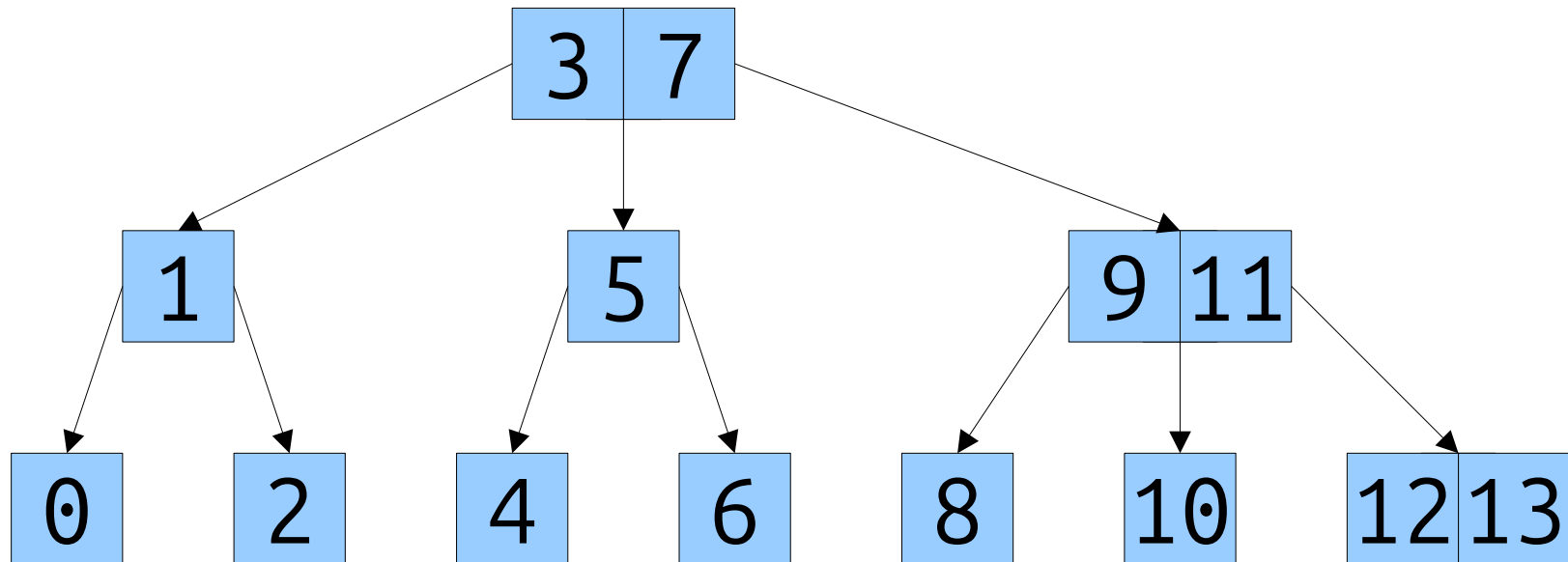
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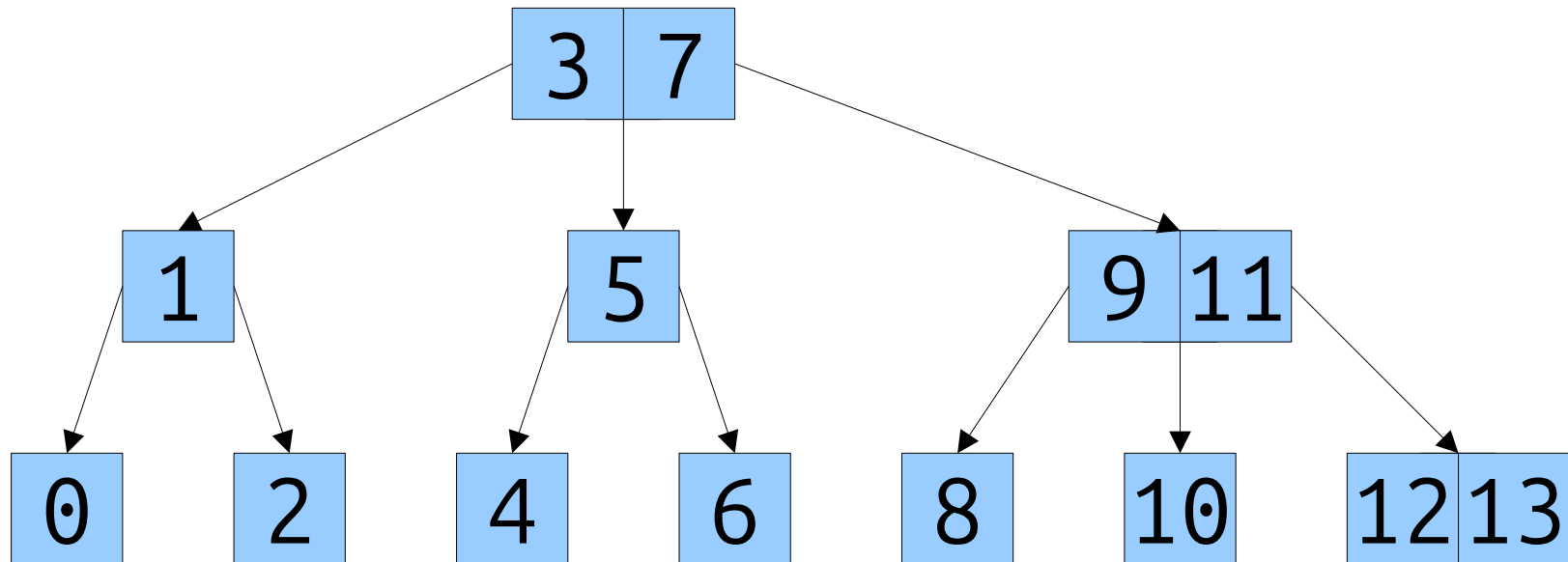
# Building B-Trees

- **Idea 2:** Since all insertions will happen at the rightmost leaf, store a pointer to that leaf. Add new values by appending to this leaf, then doing any necessary splits.
- **Question:** How fast is this?



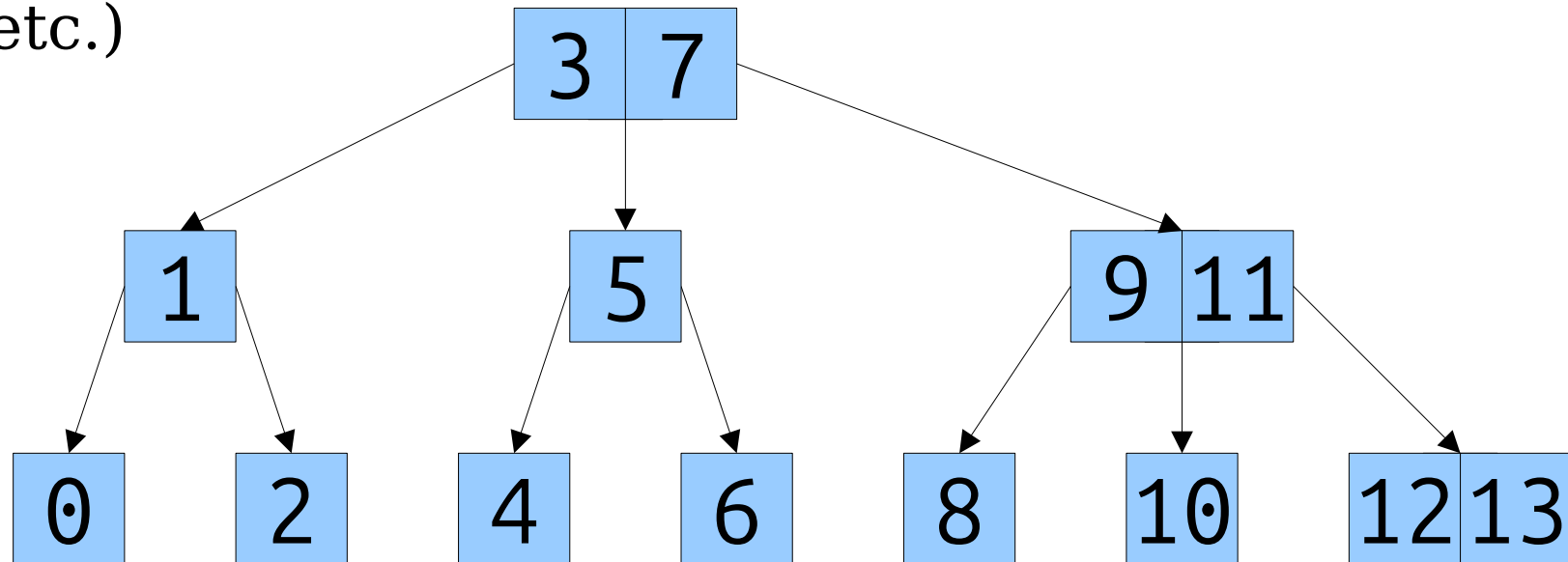
# Building B-Trees

- The cost of an insert varies based on the shape of the tree.
  - If no splits are required, the cost is  $O(1)$ .
  - If one split is required, the cost is  $O(b)$ .
  - If we have to split all the way up, the cost is  $O(b \log_b n)$ .
- Using our worst-case cost across  $n$  inserts gives a runtime bound of  $O(nb \log_b n)$
- **Claim:** The cost of  $n$  inserts is always  $O(n)$ .



# Building B-Trees

- Of all the  $n$  insertions into the tree, a roughly  $1/b$  fraction will split a node in the bottom layer of the tree (a leaf).
- Of those, roughly a  $1/b$  fraction will split a node in the layer above that.
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- (etc.)



# Building B-Trees

- Total number of splits:

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$$\frac{n}{b} \cdot \left(1 + \frac{1}{b} \cdot \left(1 + \frac{1}{b} \cdot \left(1 + \frac{1}{b} \cdot (\dots)\right)\right)\right)$$

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# Building B-Trees

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$$\begin{aligned} & \frac{n}{b} \cdot \left( 1 + \frac{1}{b} \cdot \left( 1 + \frac{1}{b} \cdot \left( 1 + \frac{1}{b} \cdot (\dots) \right) \right) \right) \\ = & \frac{n}{b} \cdot \left( 1 + \frac{1}{b} + \frac{1}{b^2} + \frac{1}{b^3} + \frac{1}{b^4} + \dots \right) \\ = & \frac{n}{b} \cdot \Theta(1) \end{aligned}$$

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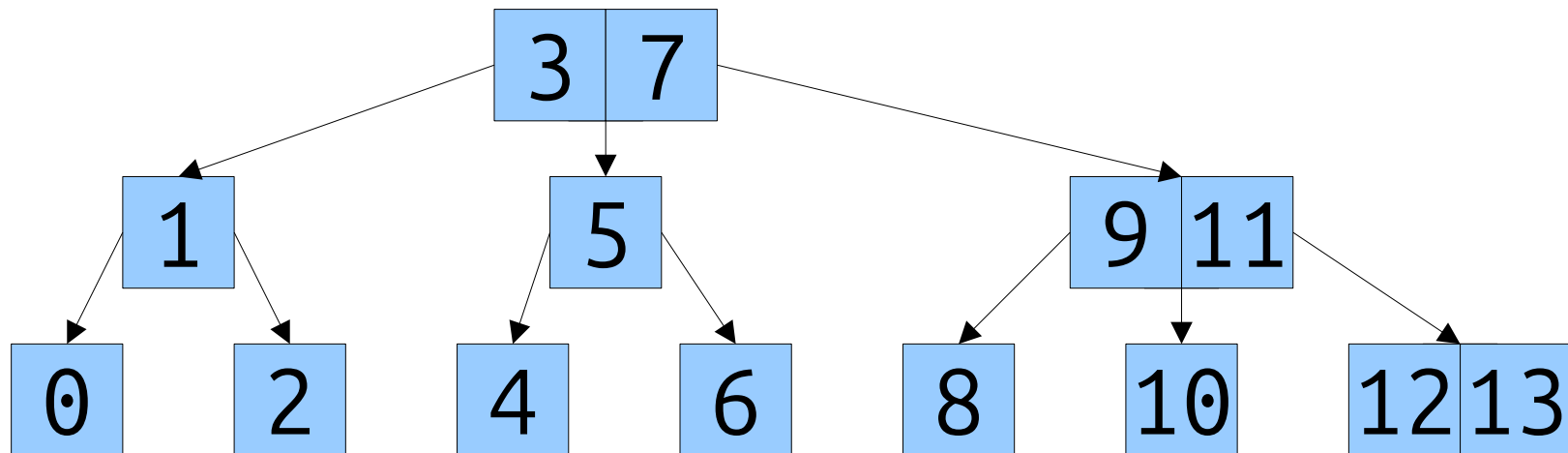
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- Total cost of those splits:  **$\Theta(n)$** .

# Building B-Trees

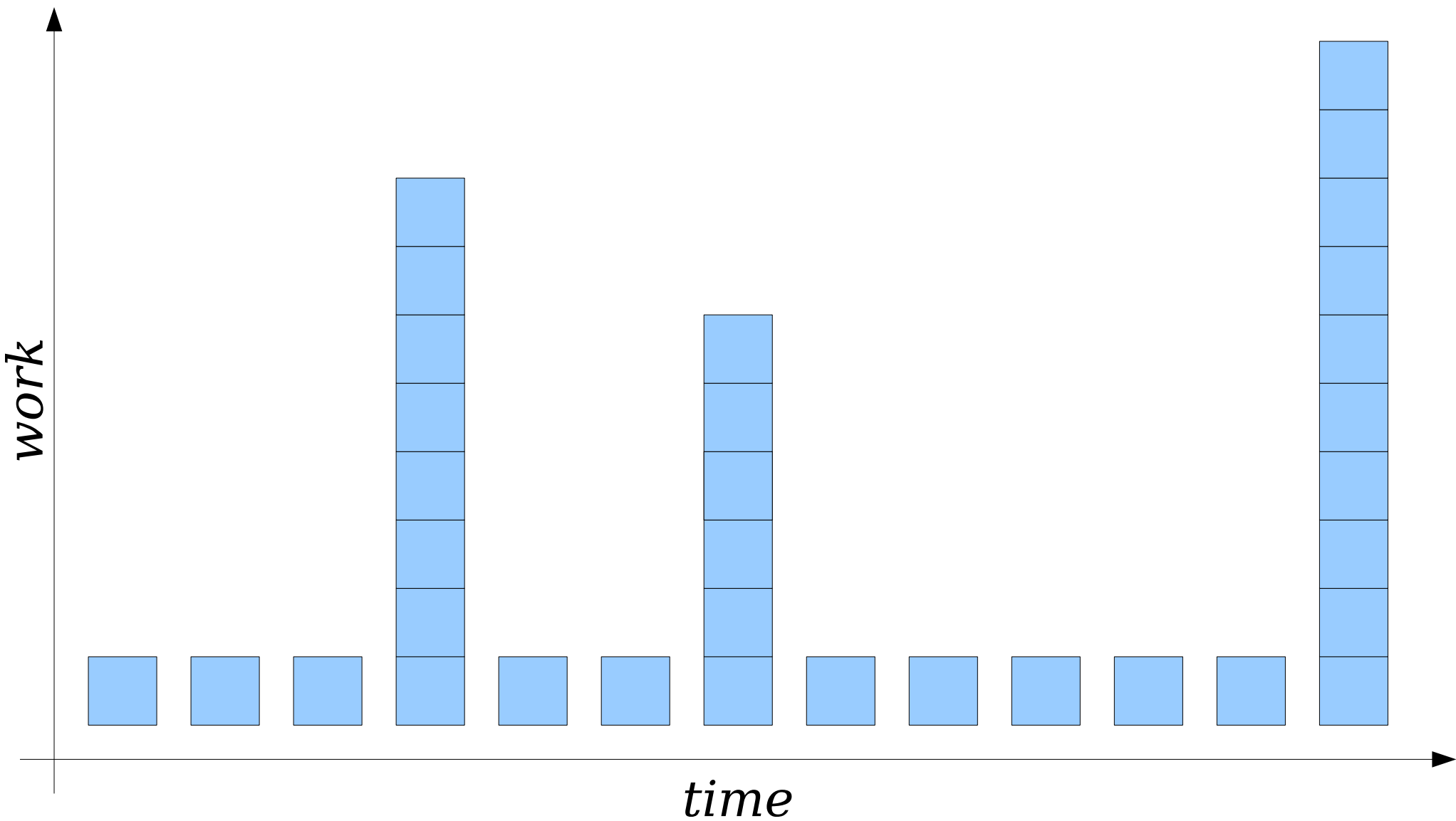
- It is correct but misleading to say the cost of an insert is  $O(b \log_b n)$ .
  - This is comparatively rare.
- It is wrong, but useful, to pretend that the cost of an insert is  $O(1)$ .
  - Some operations take more time than this.
  - However, pretending each insert takes time  $O(1)$  never underestimates the total amount of work done across all operations.
- **Question:** What's an honest, accurate way to describe the cost of inserting one more value?



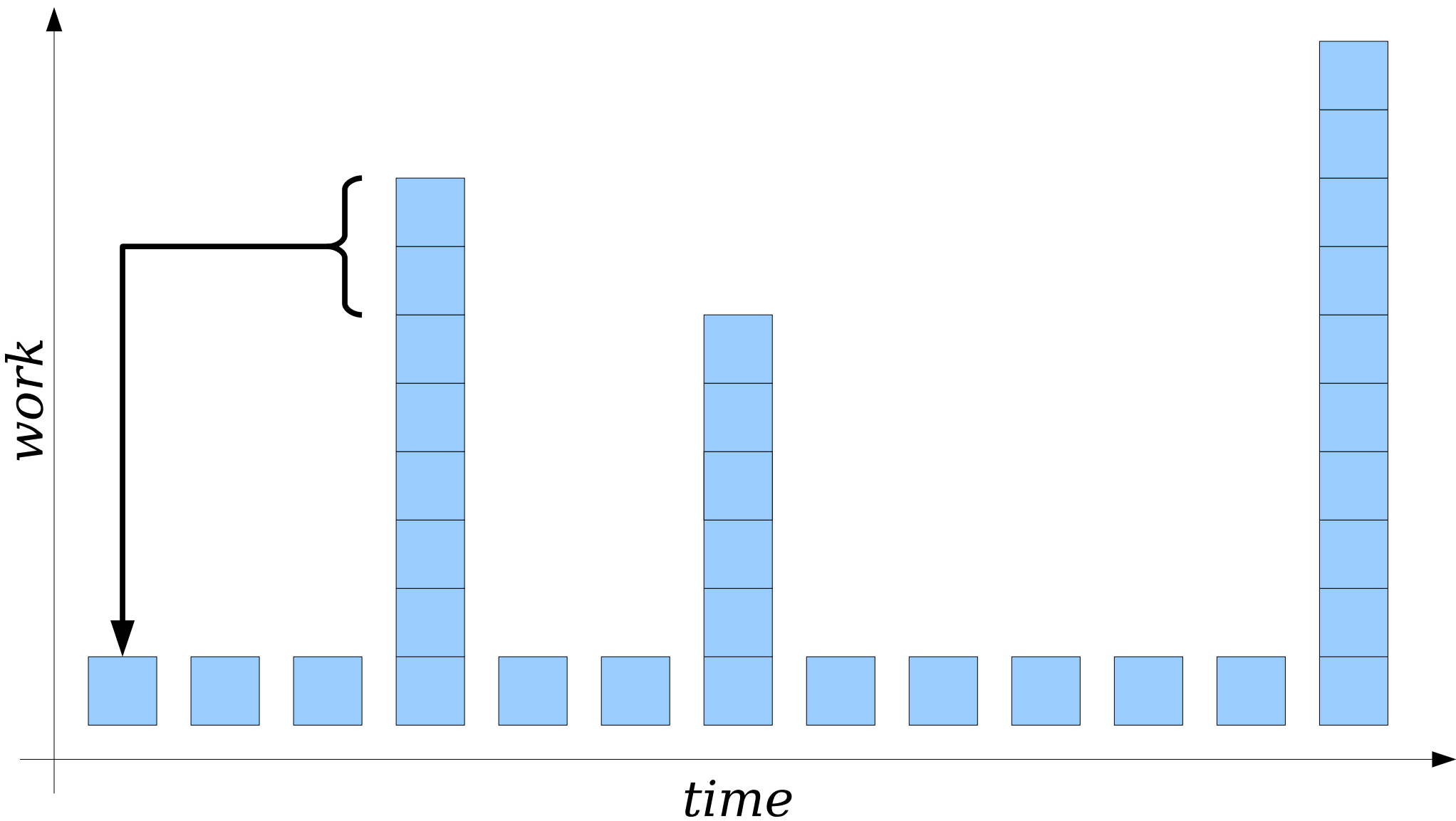
# Amortized Analysis

# The Setup

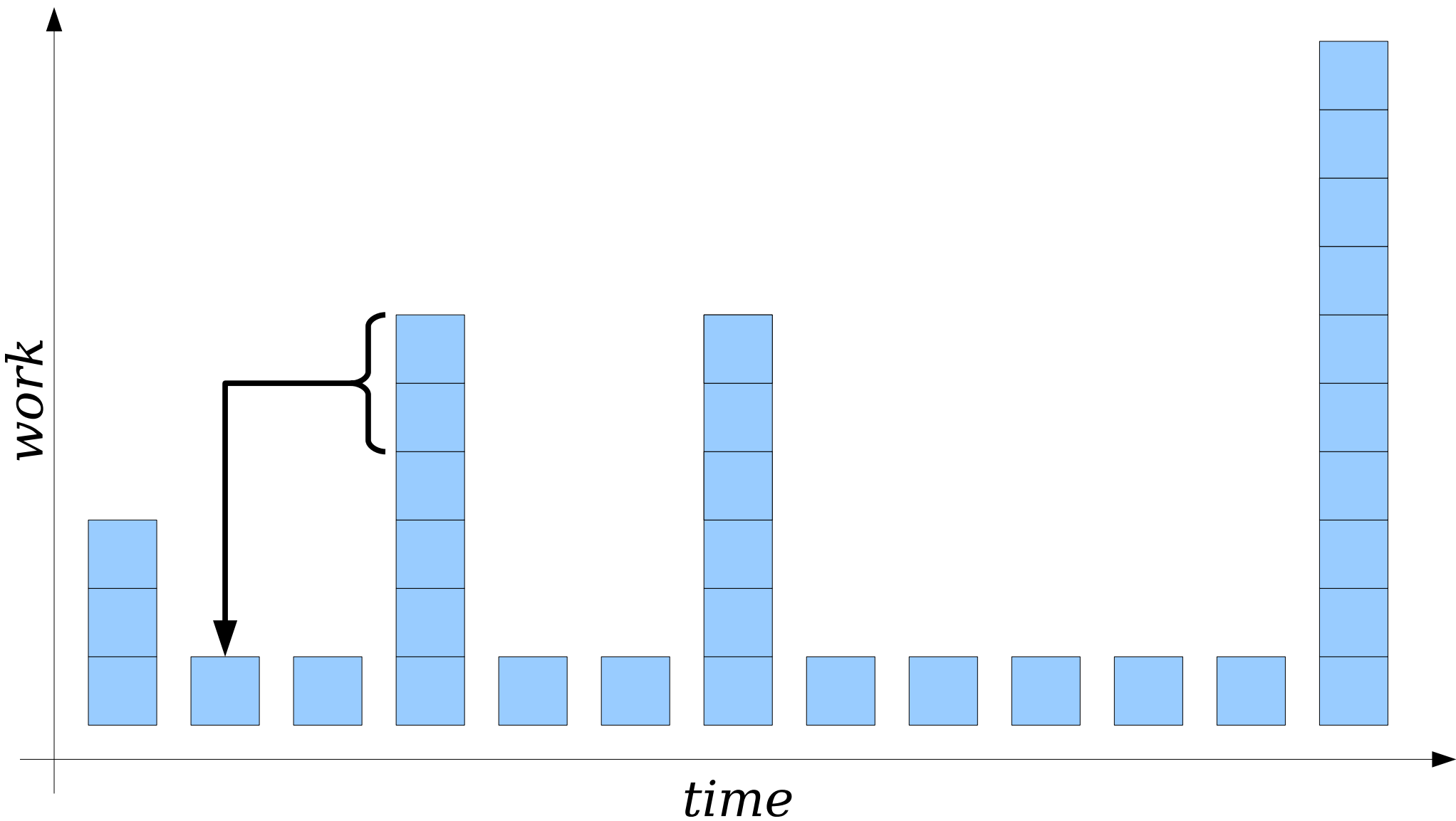
- We now have three examples of data structures where
  - *individual operations may be slow*, but
  - *any series of operations is fast*.
- Giving weak upper bounds on the cost of each operation is not useful for making predictions.
- How can we clearly communicate when a situation like this one exists?



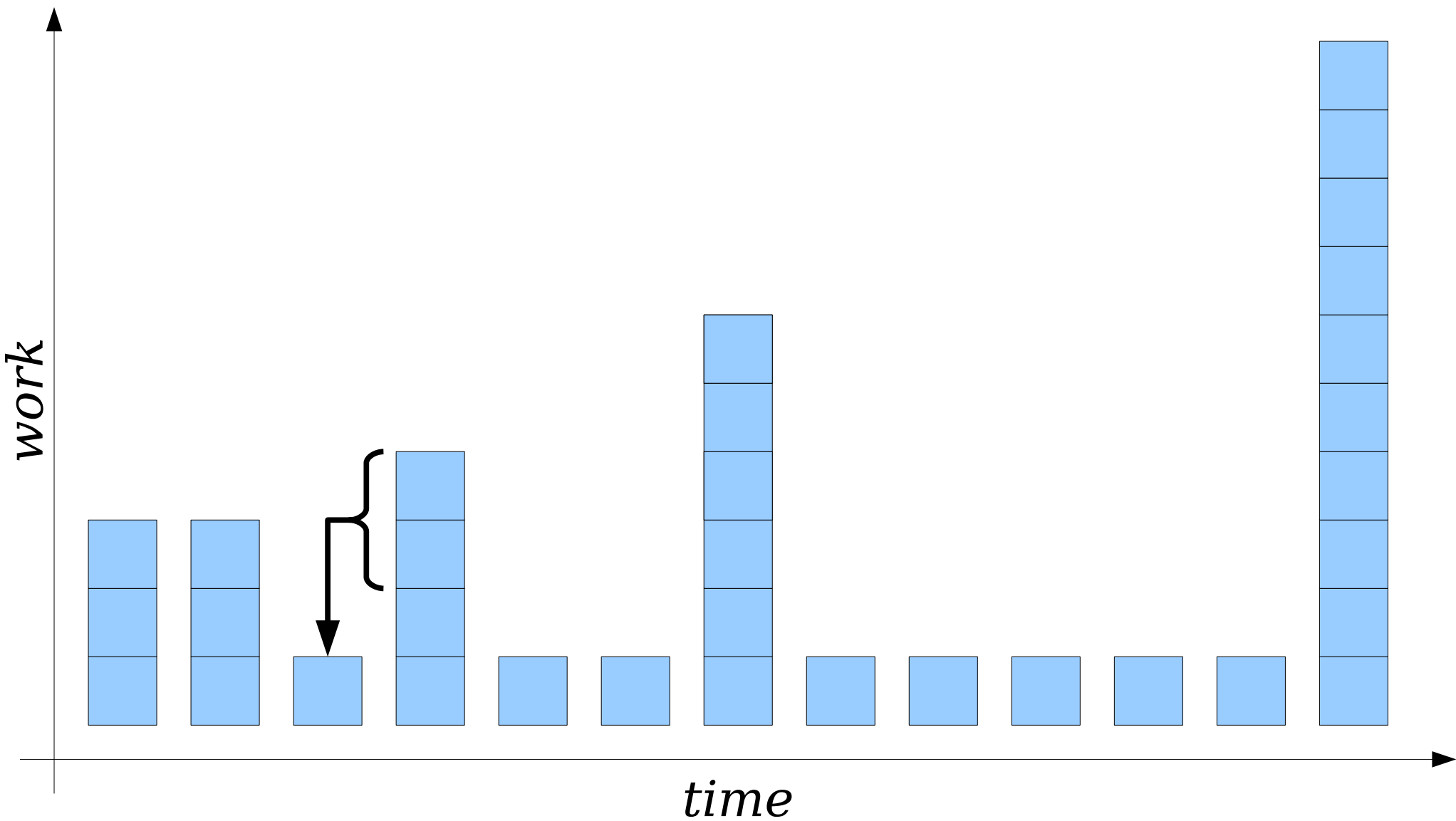
***Key Idea:*** Backcharge expensive operations to cheaper ones.



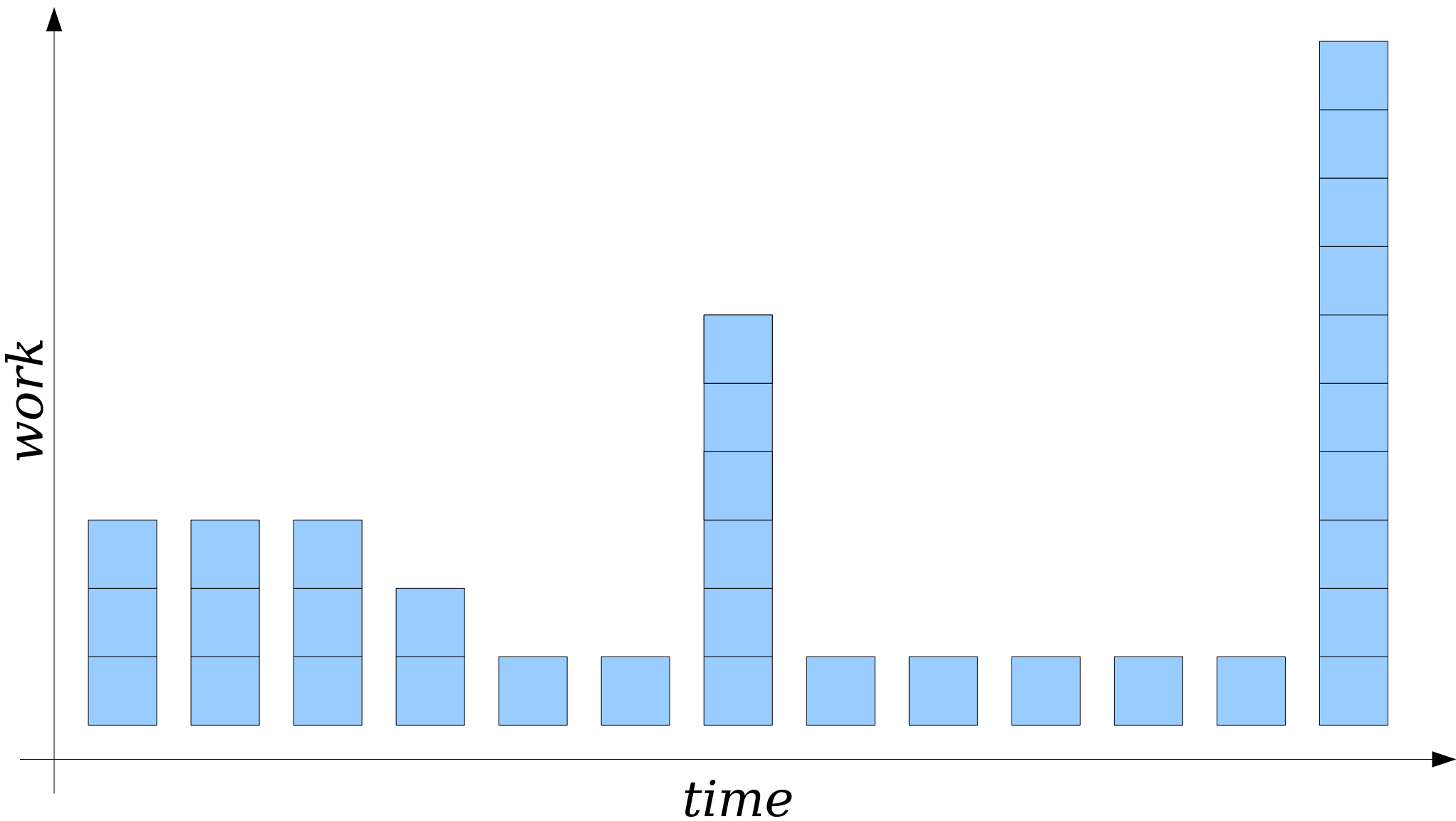
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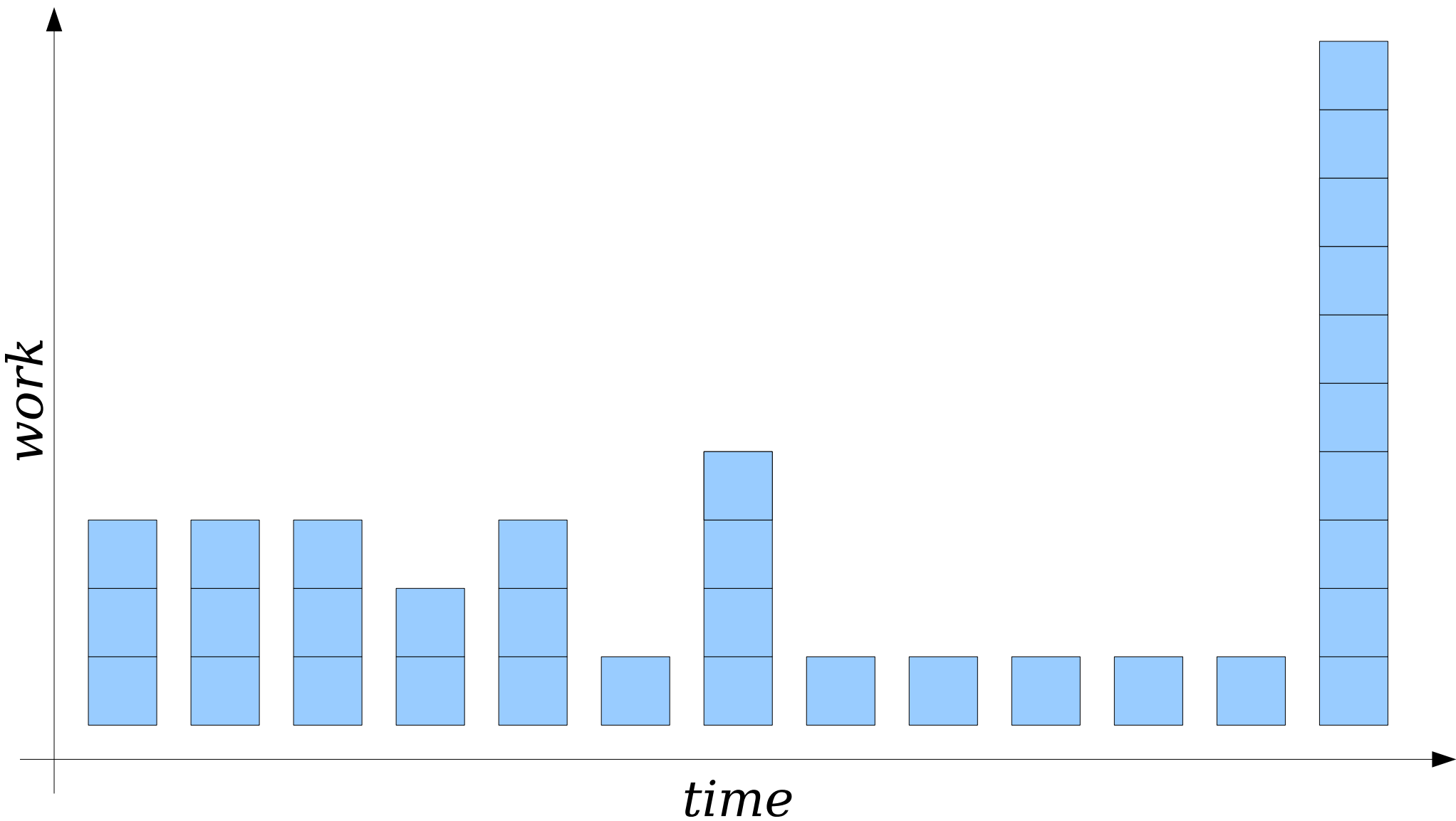
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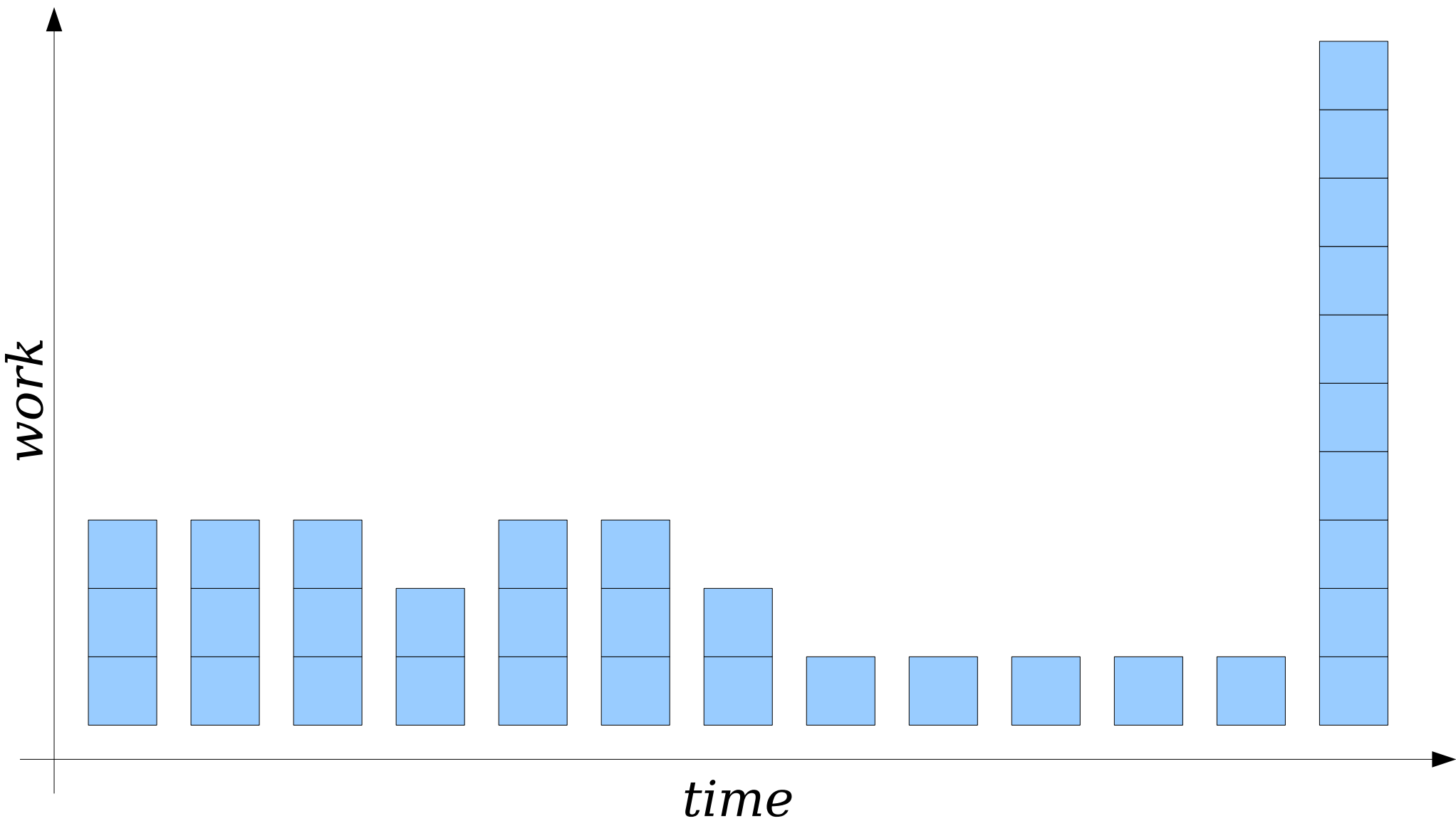
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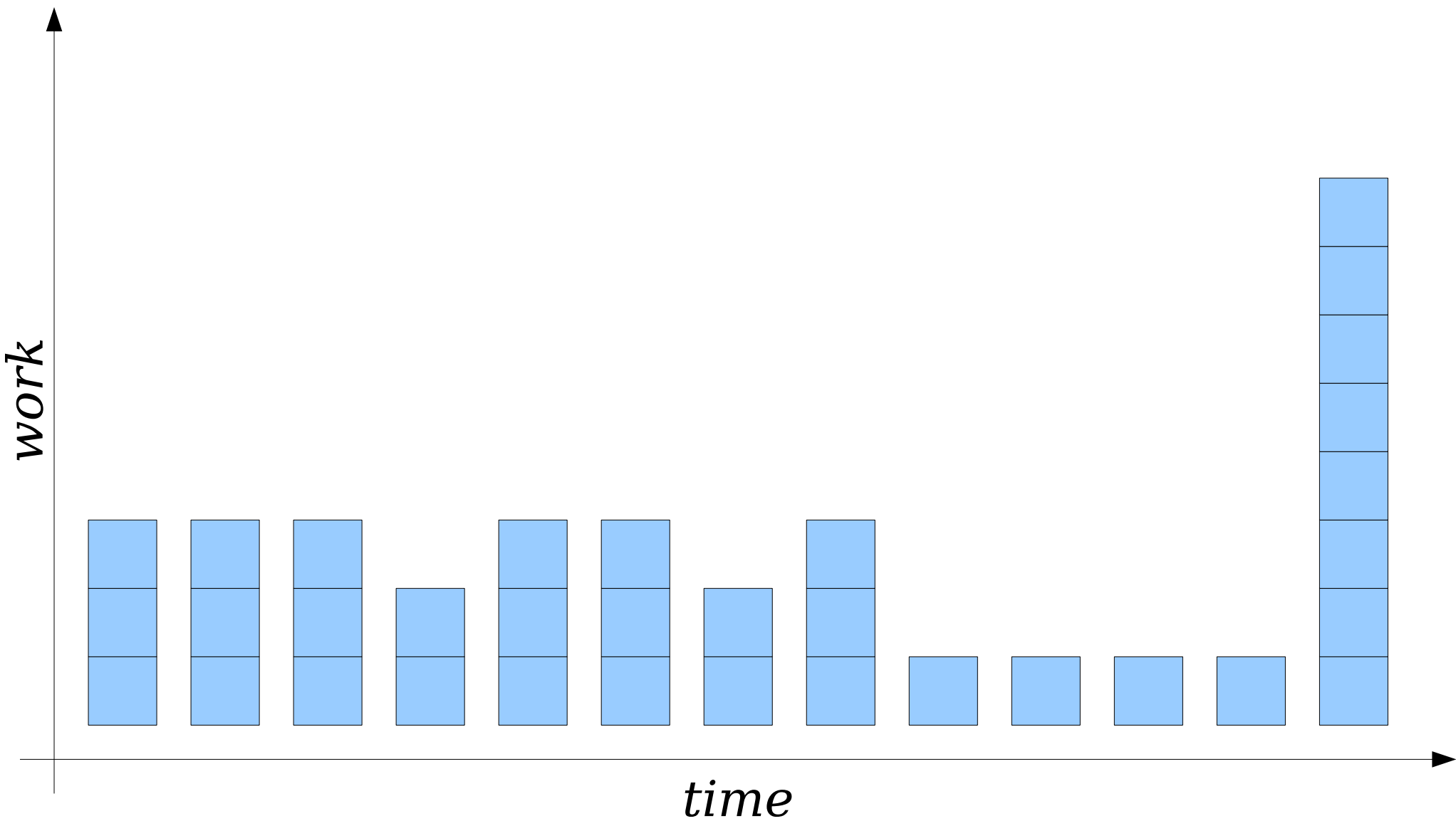
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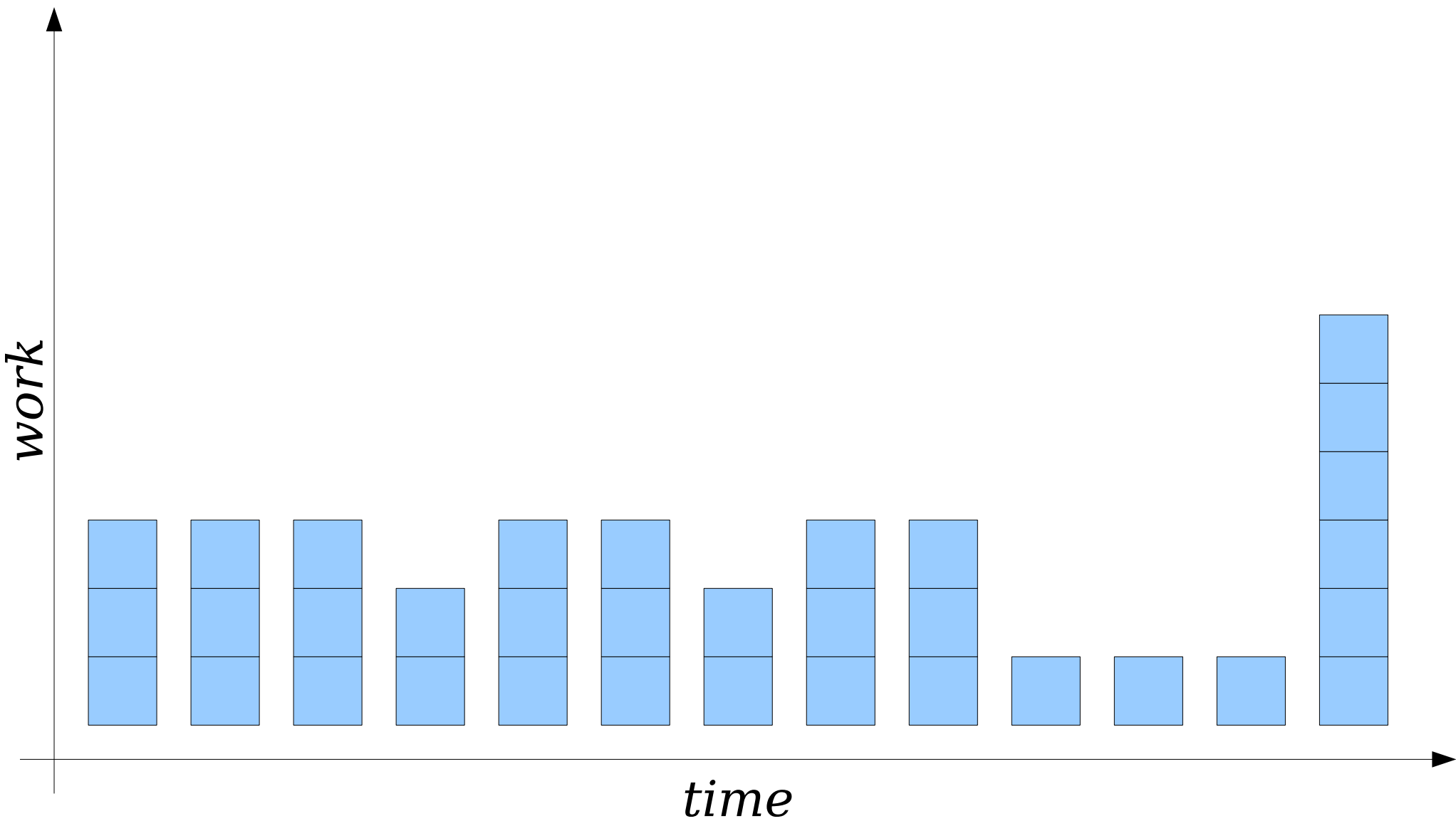
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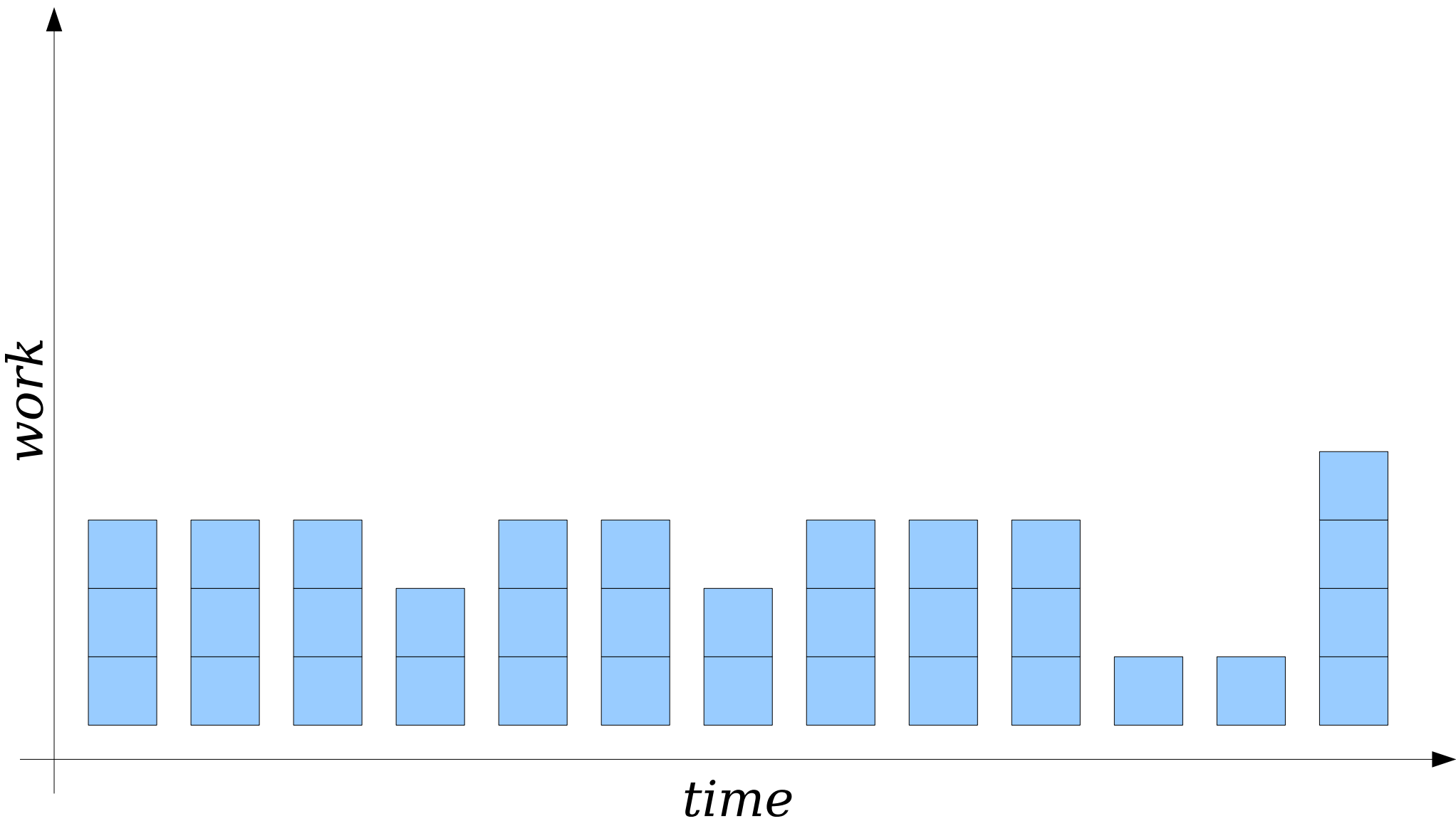
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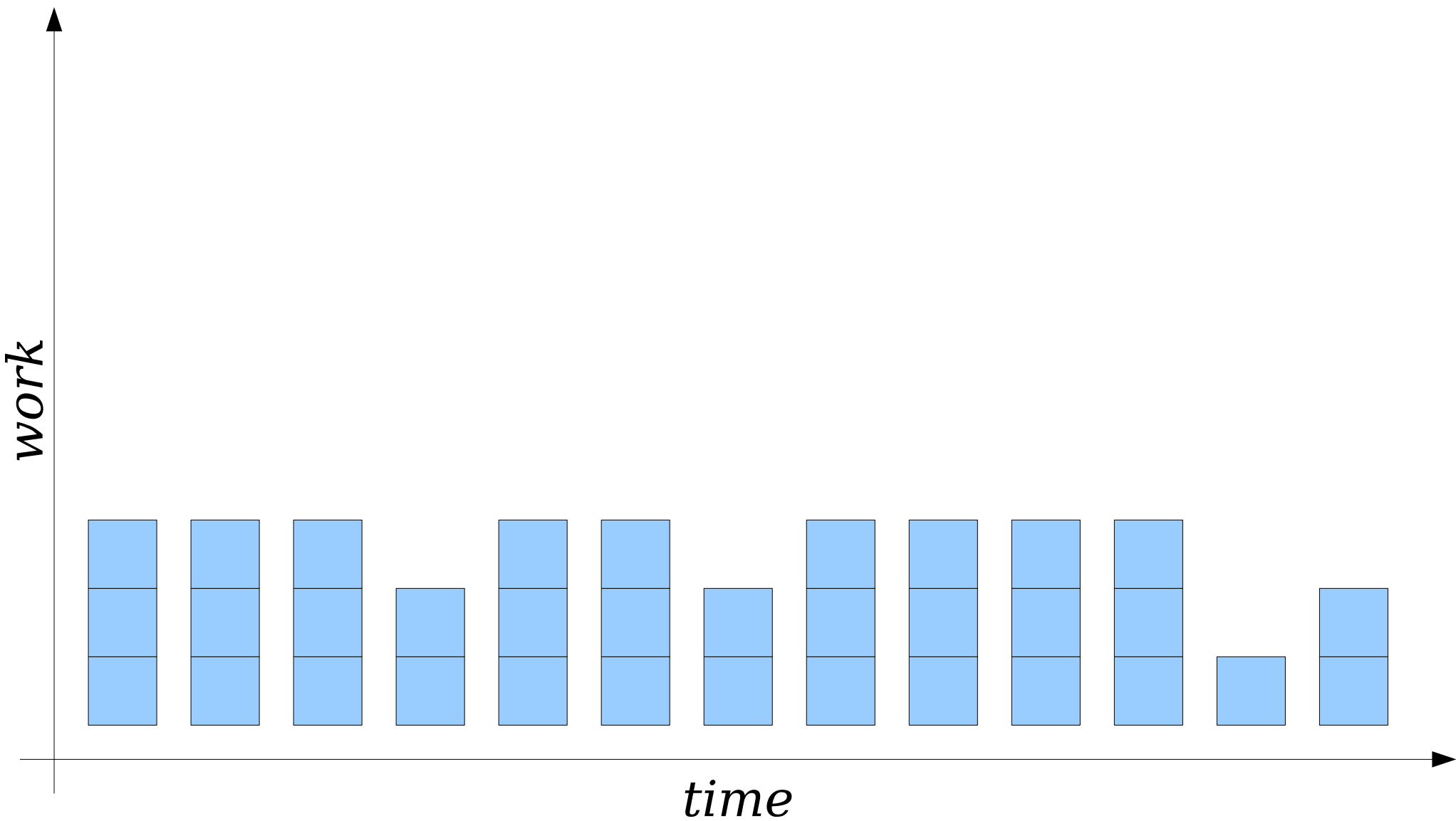
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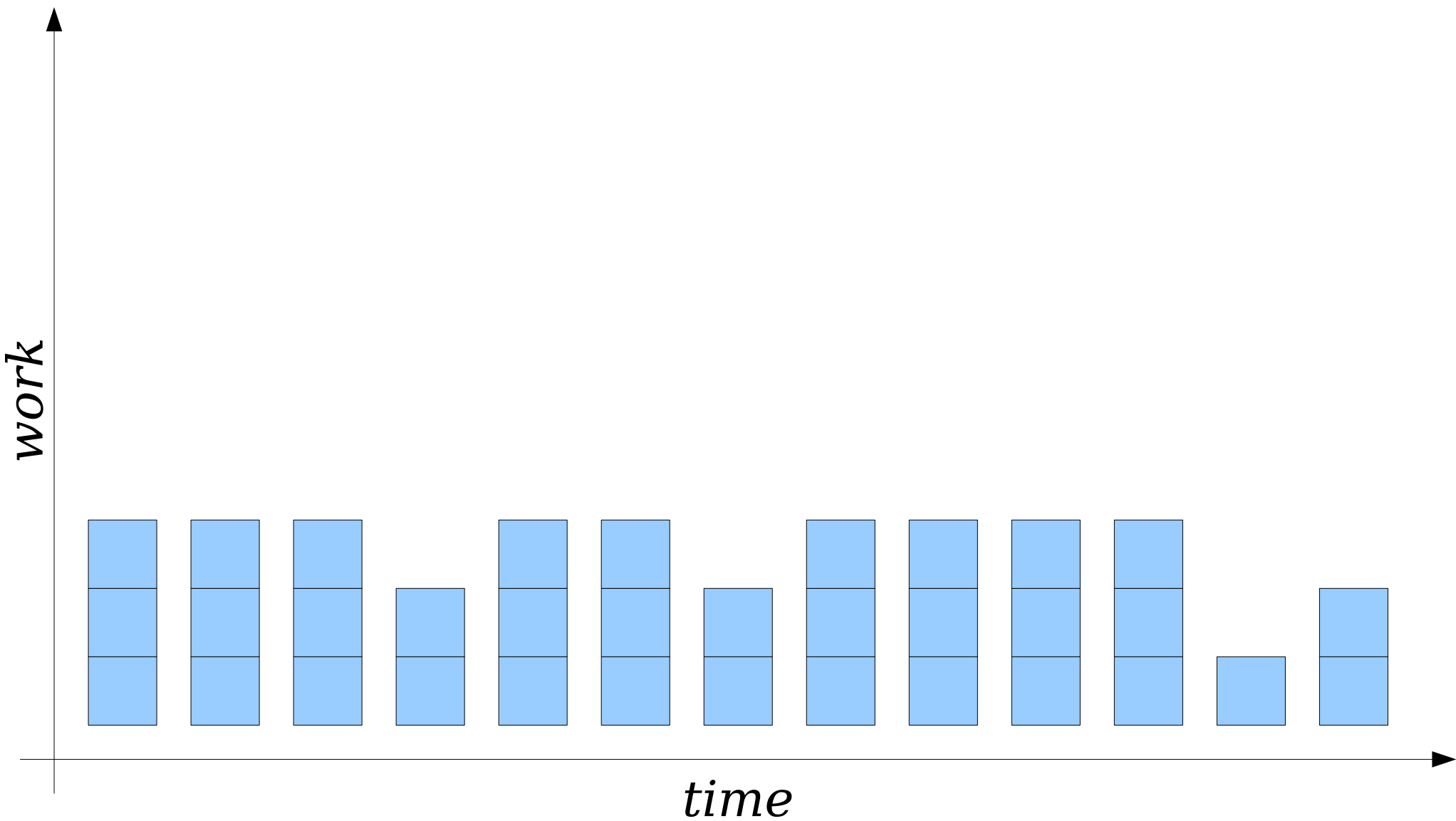
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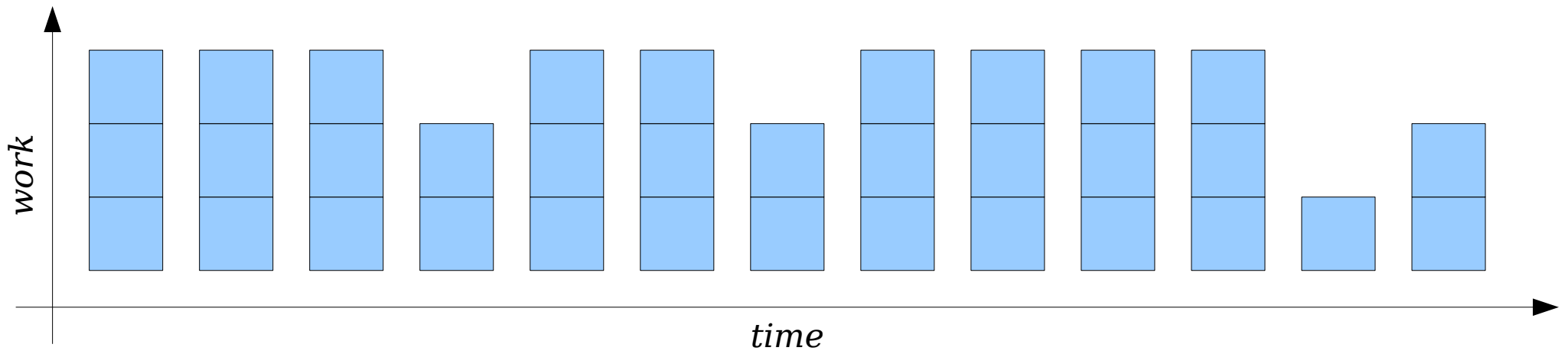


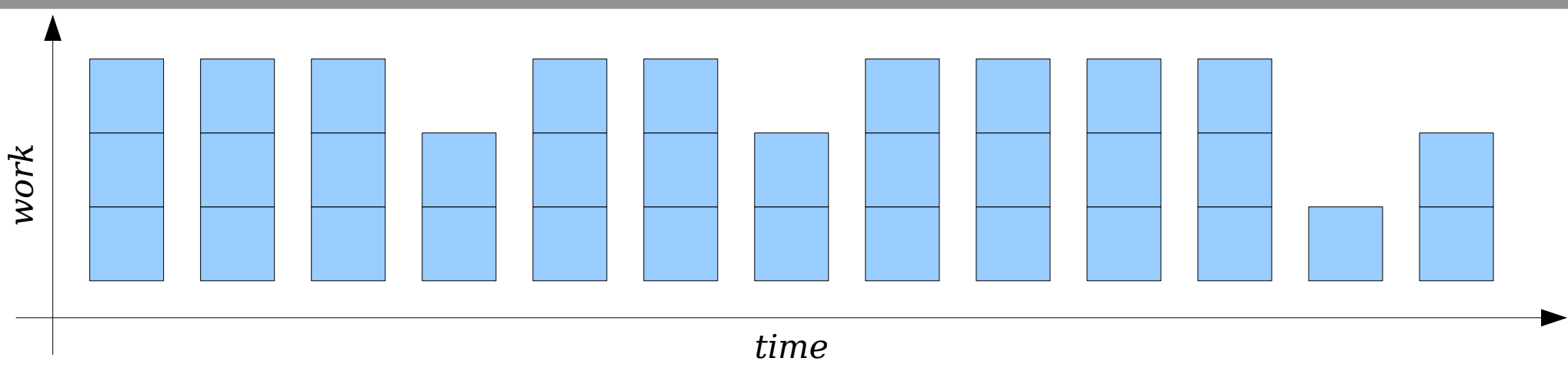
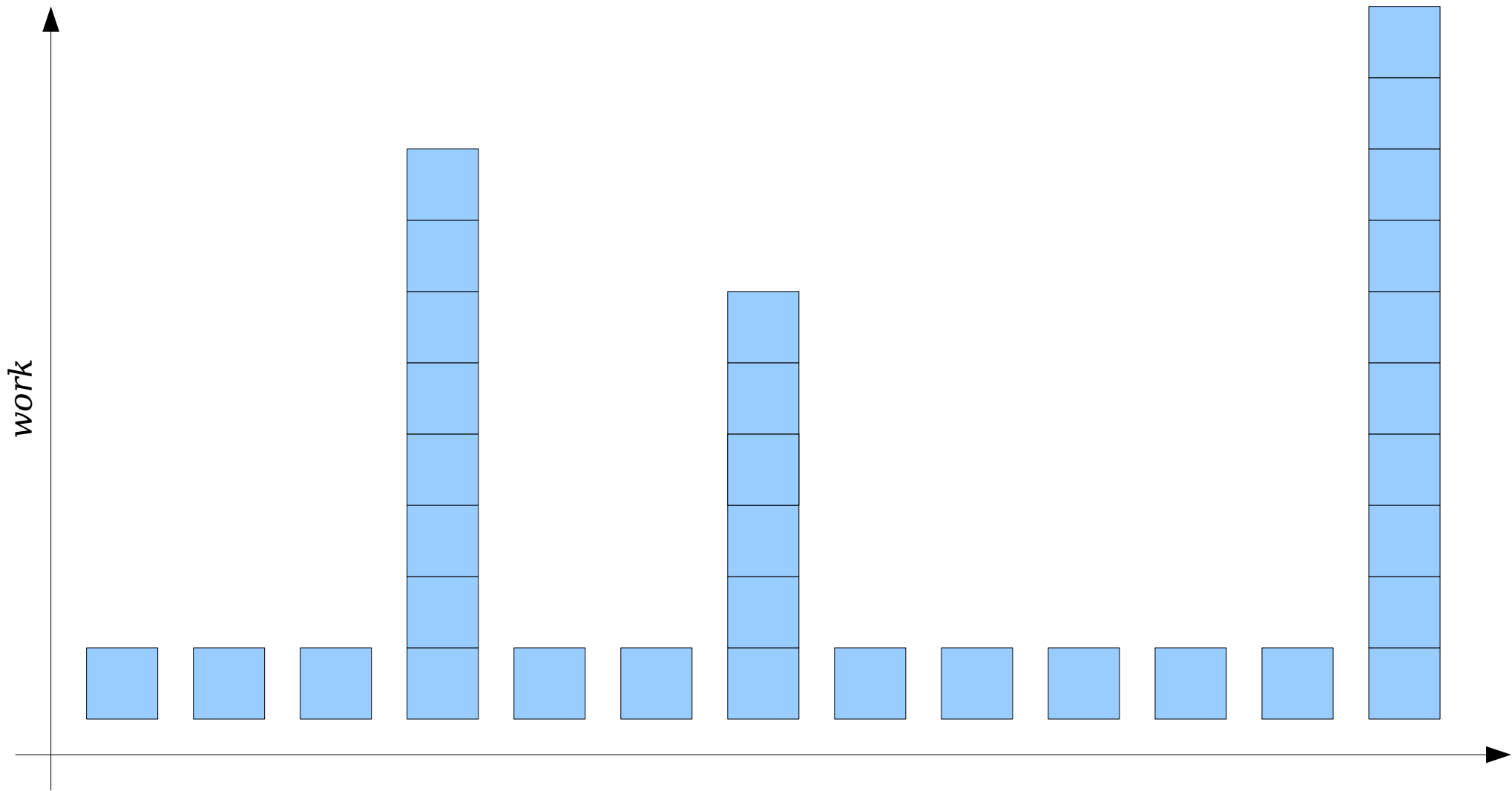
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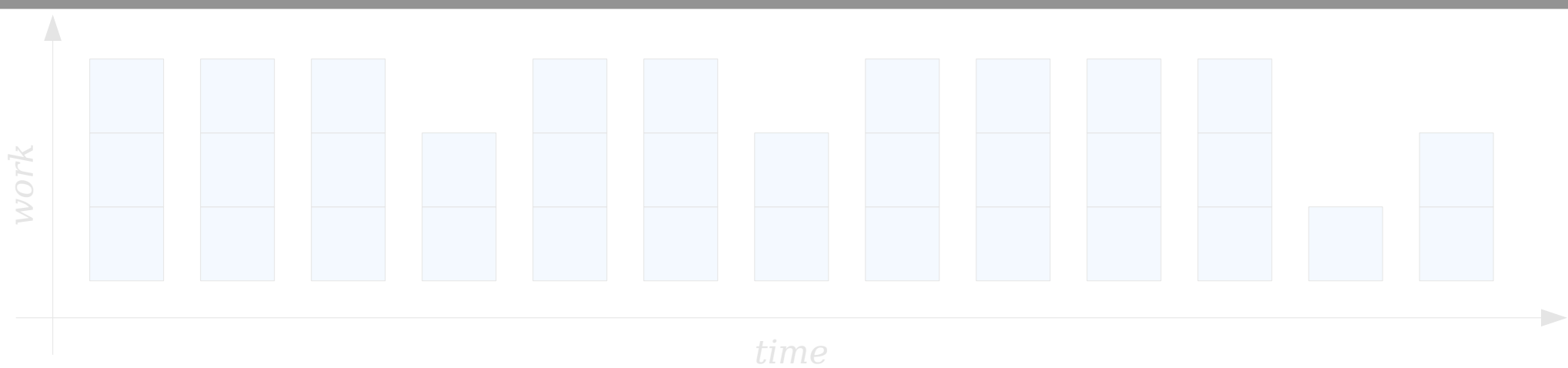
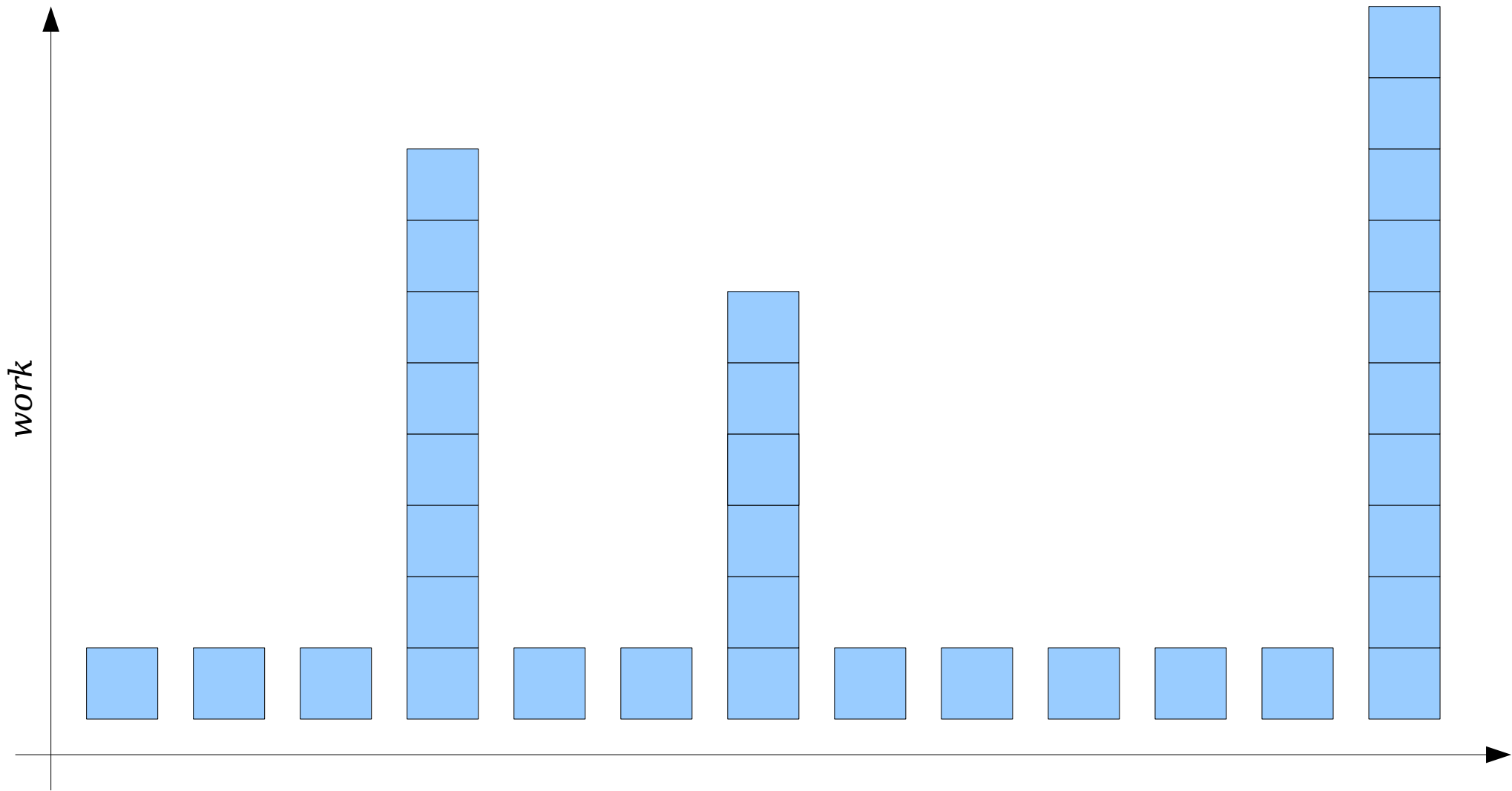


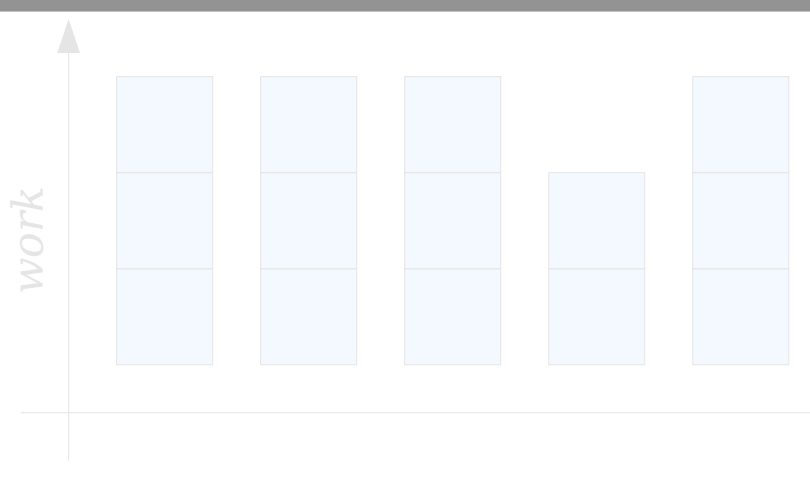
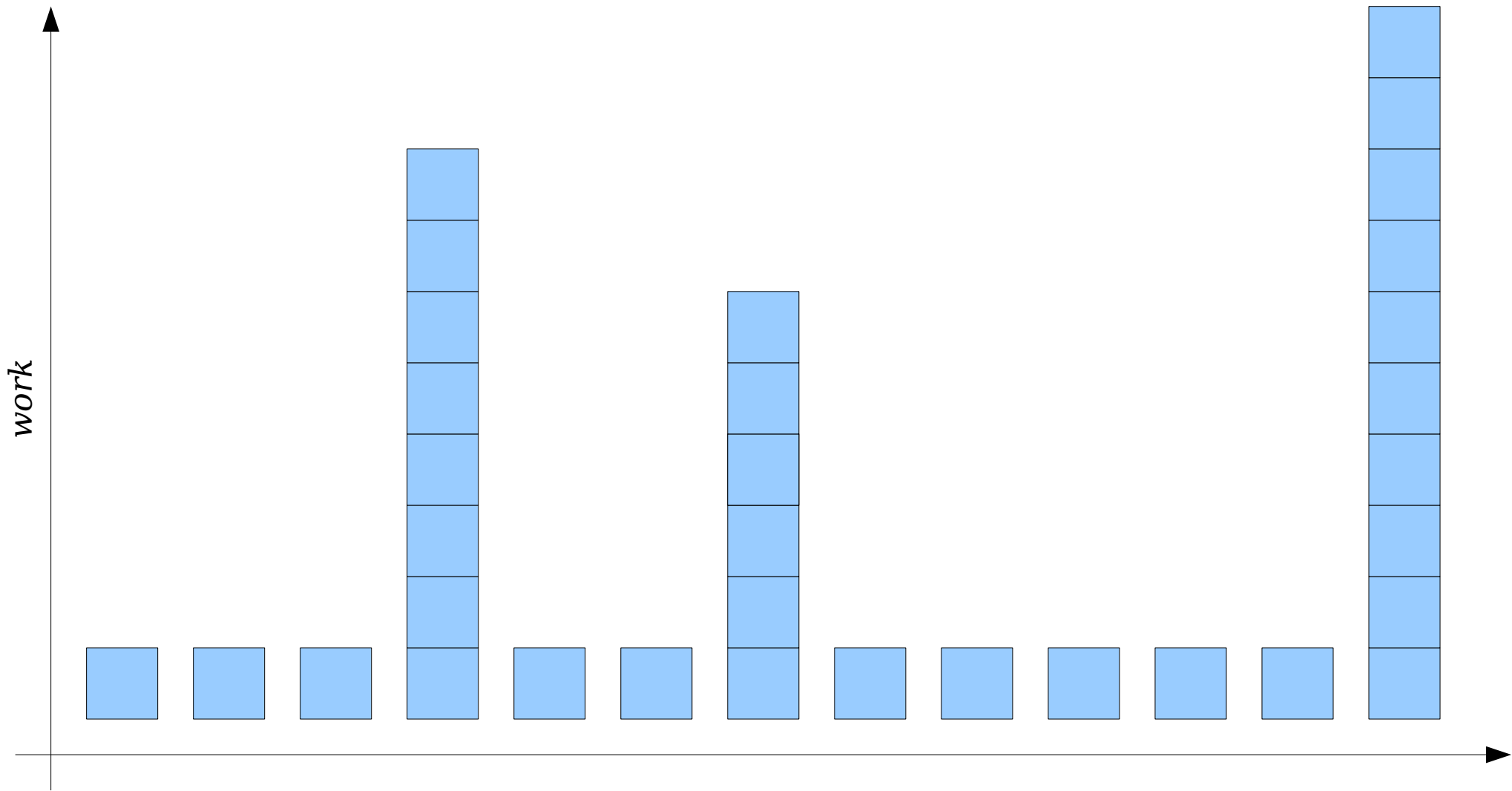
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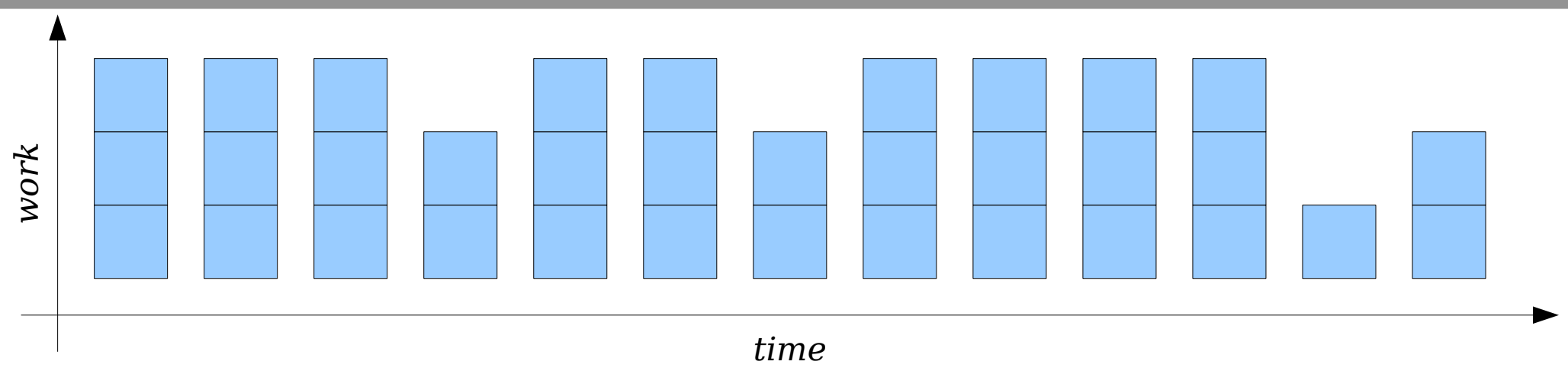
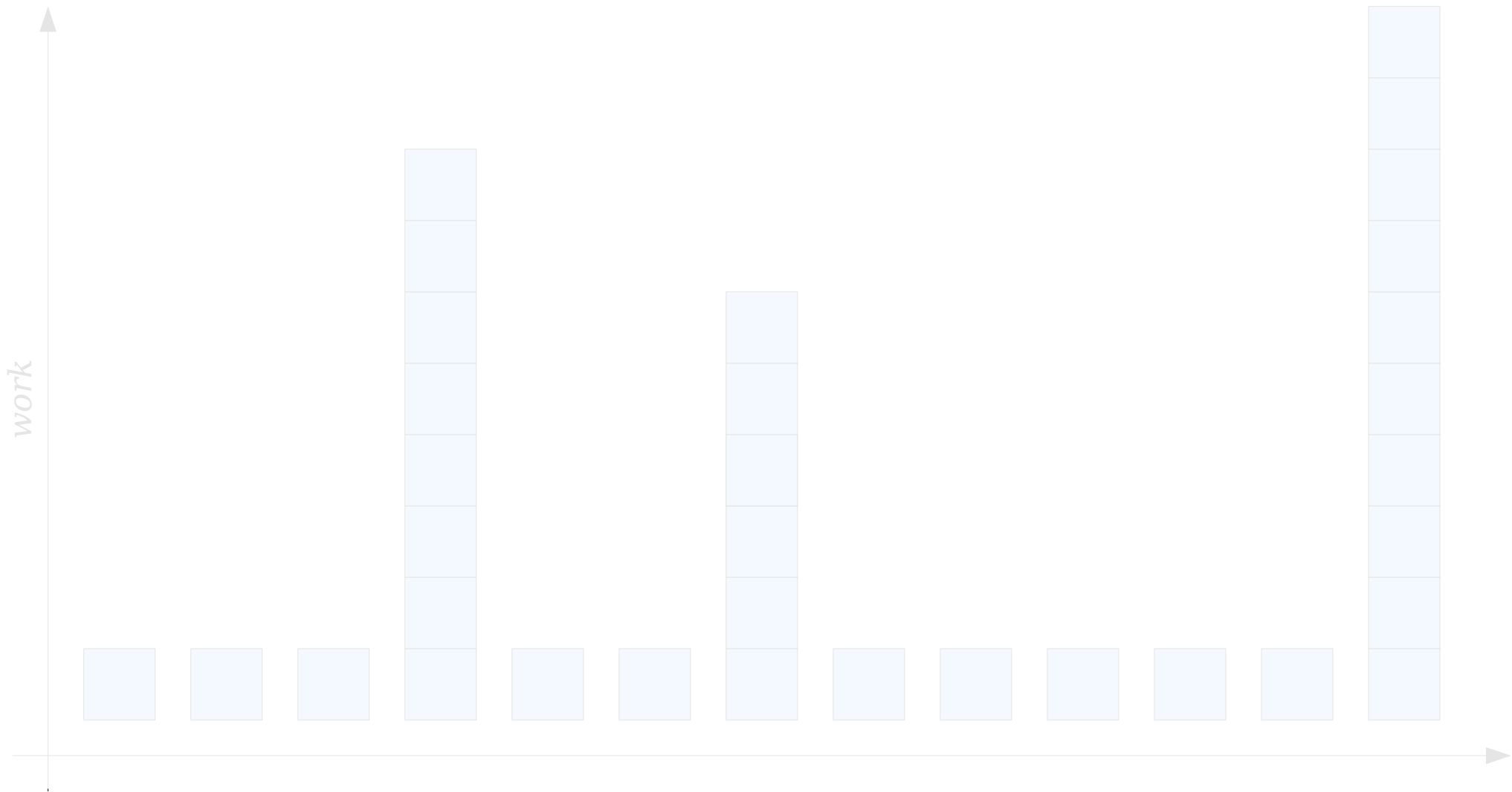






These are the *real* costs of the operations. Most operations are fast, but we can't get a nice upper bound on any one operation cost.

*time*





# Amortized Analysis

- **Key Idea:** Assign each operation a (fake!) cost called its **amortized cost** such that, *for any series of operations performed*, the following is true:

$$\sum \text{amortized-cost} \geq \sum \text{real-cost}$$

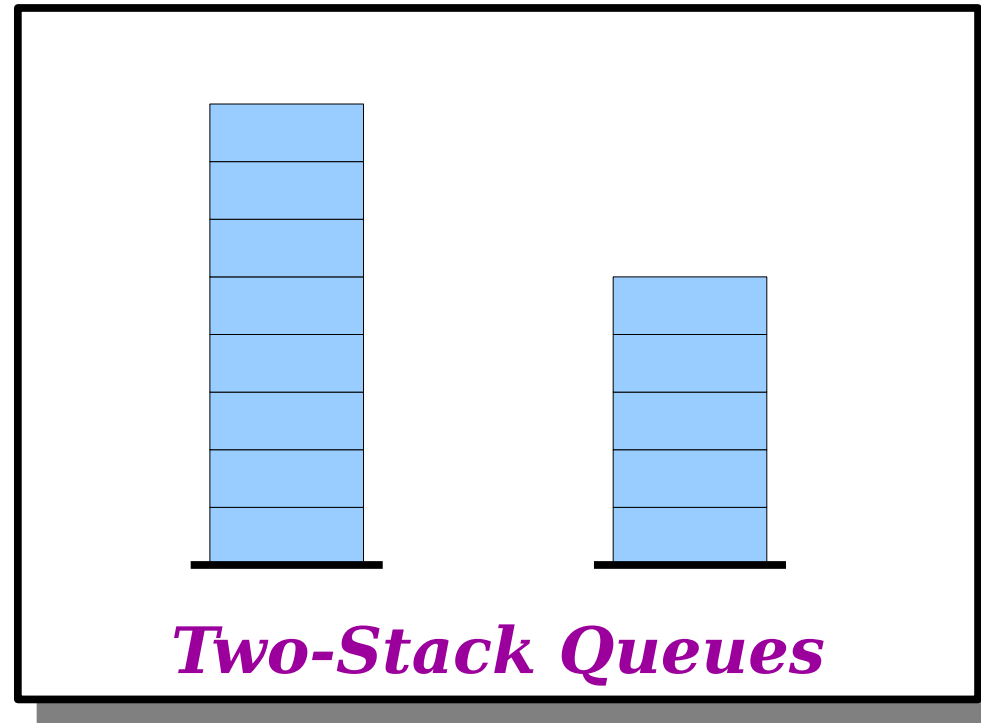
- Amortized costs shift work backwards from expensive operations onto cheaper ones.
  - Cheap operations are artificially made more expensive to pay for future cleanup work.
  - Expensive operations are artificially made cheaper by shifting the work backwards.

# Where We're Going

- The ***amortized*** cost of an enqueue or dequeue into a two-stack queue is  $O(1)$ .
- Any sequence of  $n$  operations on a two-stack queue will take time

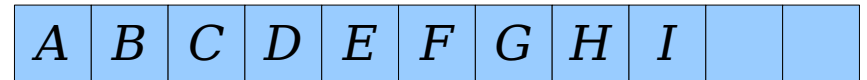
$$n \cdot O(1) = O(n).$$

- However, each individual operation may take more than  $O(1)$  time to complete.



# Where We're Going

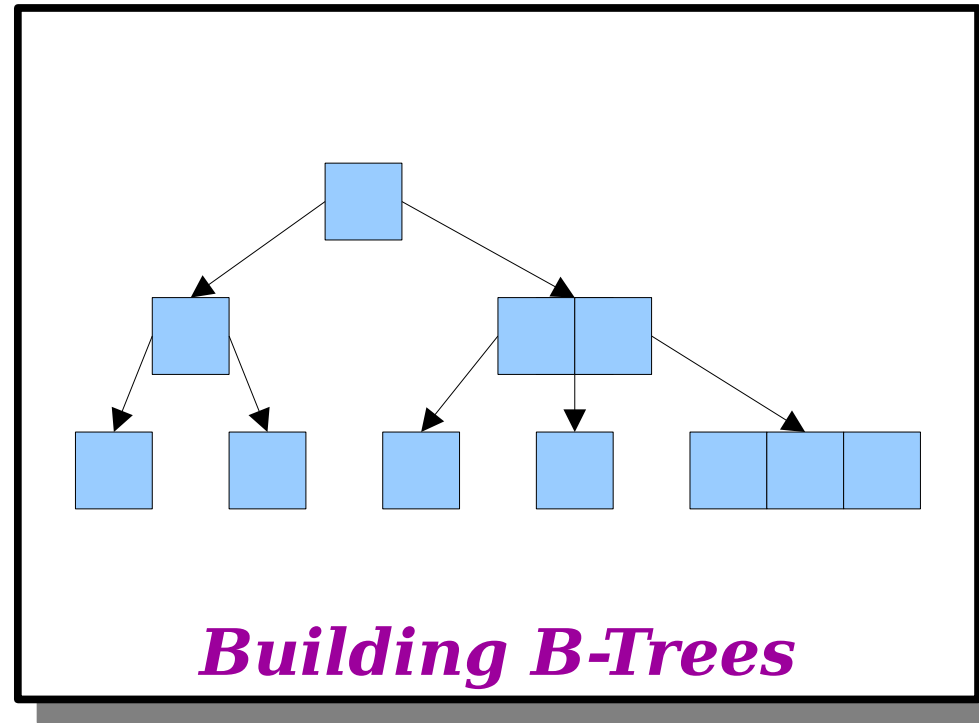
- The *amortized* cost of appending to a dynamic array is  $O(1)$ .
- Any sequence of  $n$  appends to a dynamic array will take time  $n \cdot O(1) = O(n)$ .
- However, each individual operation may take more than  $O(1)$  time to complete.



*Dynamic Arrays*

# Where We're Going

- The ***amortized*** cost of inserting a new element at the end of a B-tree, assuming we have a pointer to the rightmost leaf, is  $O(1)$ .
- Any sequence of  $n$  appends will take time  $n \cdot O(1) = O(n)$ .
- However, each individual operation may take more than  $O(1)$  time to complete.



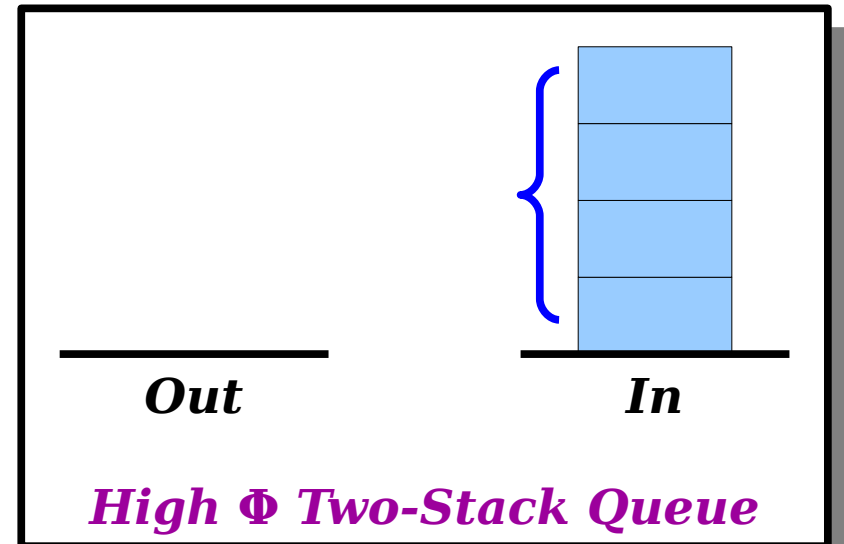
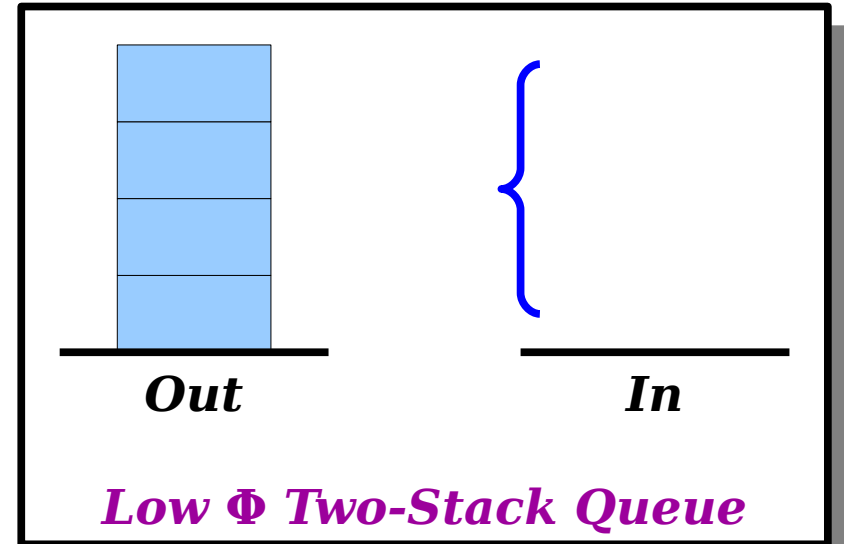
Formalizing This Idea

# Assigning Amortized Costs

- The approach we've taken so far for assigning amortized costs is called an **aggregate analysis**.
  - Directly compute the maximum possible work done across any sequence of operations, then divide that by the number of operations.
- This approach works well here, but it doesn't scale well to more complex data structures.
  - What if different operations contribute to / clean up messes in different ways?
  - What if it's not clear what sequence is the worst-case sequence of operations?
- In practice, we tend to use a different strategy called the **potential method** to assign amortized costs.

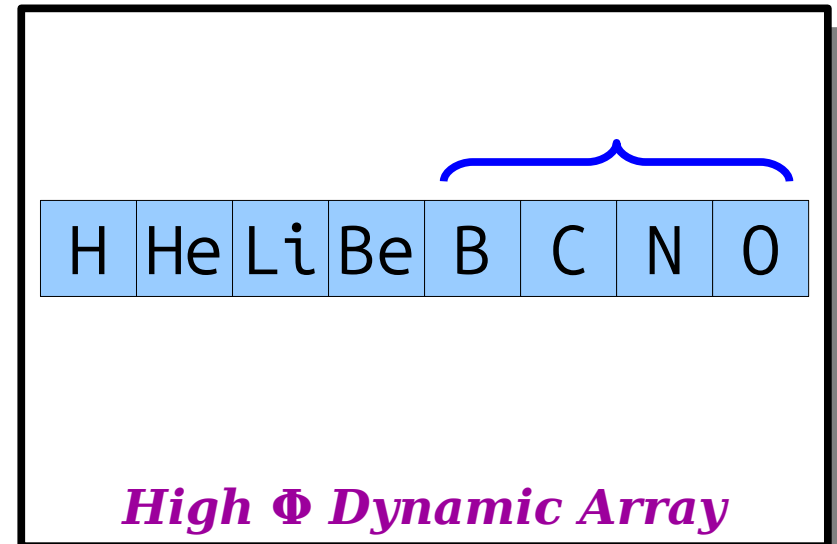
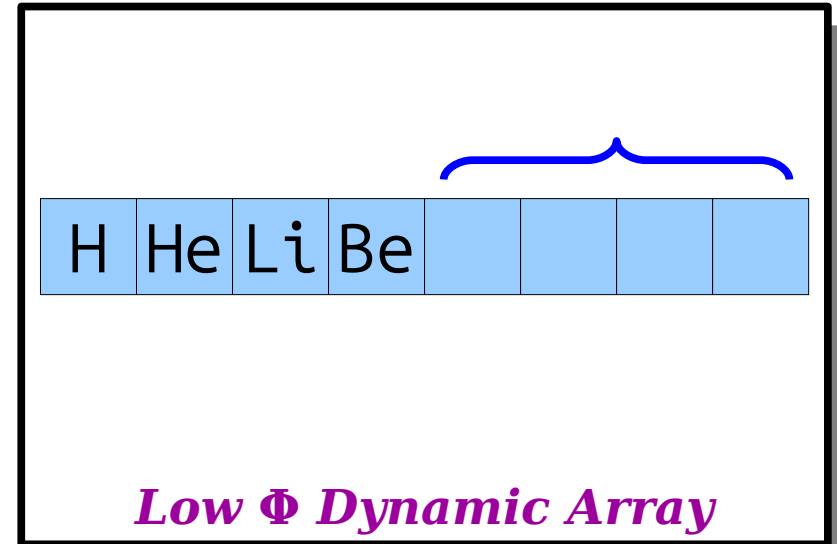
# Potential Functions

- To assign amortized costs, we'll need to measure how “messy” the data structure is.
- For each data structure, we define a **potential function**  $\Phi$  that, in a sense, “quantifies messiness.”
  - $\Phi$  is small when the data structure is “clean,” and
  - $\Phi$  is large when the data structure is “messy.”



# Potential Functions

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  - $\Phi$  is large when the data structure is “messy.”



# Potential Functions

- The intuition:
  - If  $\Phi$  **increases**, the data structure got “**messier**,” and the amortized cost should be **higher** than the real cost to account for future cleanup costs.
  - If  $\Phi$  **decreases**, the data structure got “**cleaner**,” and the amortized cost should be **lower** than the real cost.
- Think “carbon credits.”
- How do we formalize this?

# Potential Functions

- Define the amortized cost of an operation to be

$$\mathbf{amortized-cost = real-cost + k \cdot \Delta\Phi}$$

where  $k$  is a constant under our control and  $\Delta\Phi$  is the difference between  $\Phi$  just after the operation finishes and  $\Phi$  just before the operation started:

$$\Delta\Phi = \Phi_{after} - \Phi_{before}$$

- Intuitively:
  - If  $\Phi$  **increases**, the data structure got “**messier**,” and the amortized cost is **higher** than the real cost to account for future cleanup costs.
  - If  $\Phi$  **decreases**, the data structure got “**cleaner**,” and the amortized cost is **lower** than the real cost.

# Why This Works

$$\sum \textit{amortized-cost} = \sum (\textit{real-cost} + k \cdot \Delta\Phi)$$

# Why This Works

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Think “fundamental theorem of calculus,”  
but for discrete derivatives!

$$\int_a^b f'(x) dx = f(b) - f(a) \qquad \sum_{x=a}^b \Delta f(x) = f(b+1) - f(a)$$

Look up ***finite calculus*** if you're curious to learn more!

# Why This Works

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Let's make two assumptions:

$$\Phi \geq 0.$$

$$\Phi_{\textit{start}} = 0.$$

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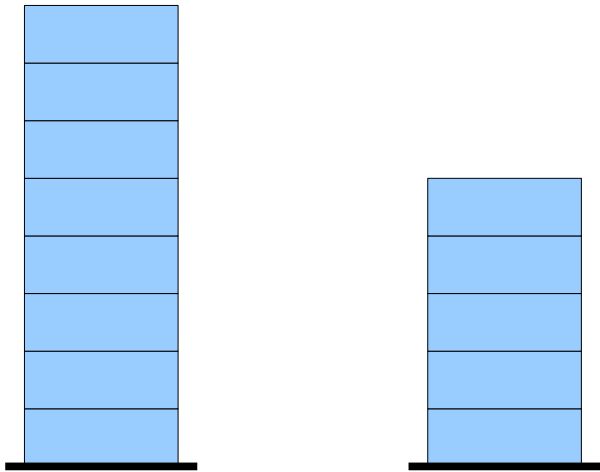
Assigning costs this way will never, in any circumstance, overestimate the total amount of work done.

# The Story So Far

- We will assign amortized costs to each operation such that

$$\sum \textit{amortized-cost} \geq \sum \textit{real-cost}$$

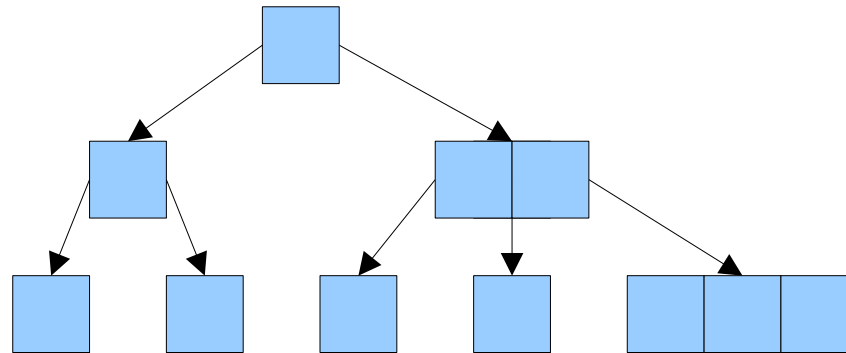
- To do so, define a **potential function**  $\Phi$  such that
  - $\Phi$  measures how “messy” the data structure is,
  - $\Phi_{start} = 0$ , and
  - $\Phi \geq 0$ .
- Then, define amortized costs of operations as
$$\textit{amortized-cost} = \textit{real-cost} + k \cdot \Delta\Phi$$
for a choice of  $k$  under our control.



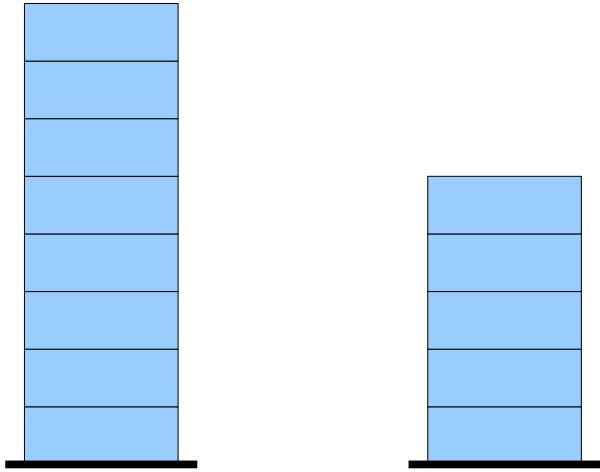
*Two-Stack Queues*



*Dynamic Arrays*



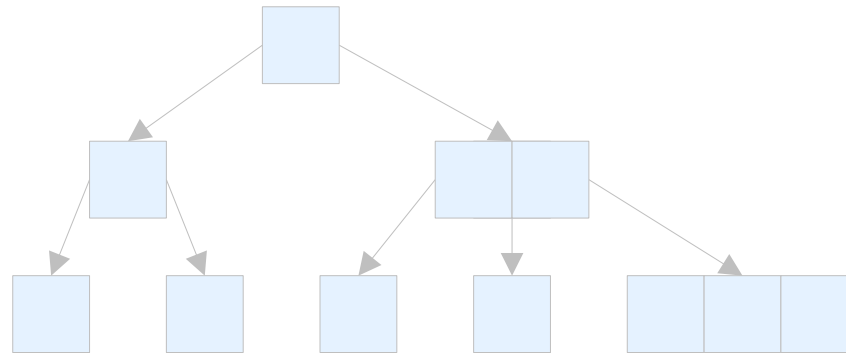
*Building B-Trees*



*Two-Stack Queues*



*Dynamic Arrays*



*Building B-Trees*

# The Two-Stack Queue



**Out**



**In**

# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

**Out**

**In**

# The Two-Stack Queue

$\Phi$  = height of *In* stack

**Out**

**1**  
**In**

# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

\_\_\_\_\_

**Out**

\_\_\_\_\_

**1**

**In**

$$\textit{amortized-cost} = \textit{real-cost} + k \cdot \Delta\Phi$$

# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$



$$\begin{aligned} \textit{amortized-cost} &= \textit{real-cost} + k \cdot \Delta\Phi \\ &= O(1) + k \cdot 1 \end{aligned}$$

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$\Phi = \text{height of } \mathbf{In} \text{ stack}$

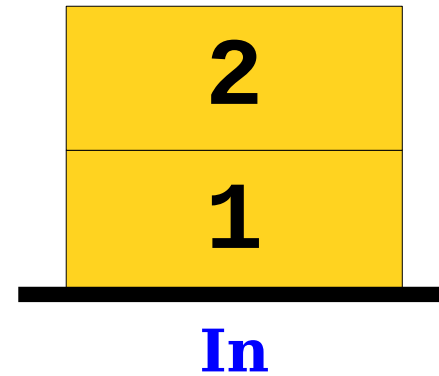


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**Out**



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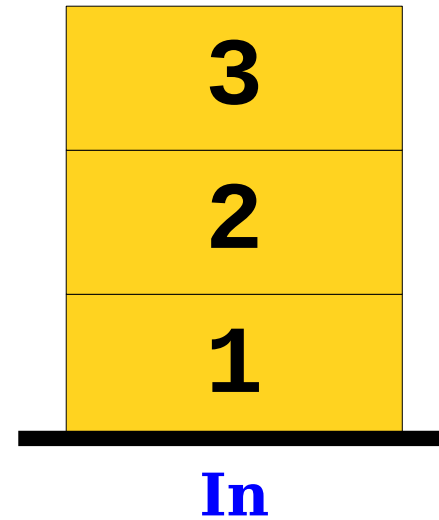


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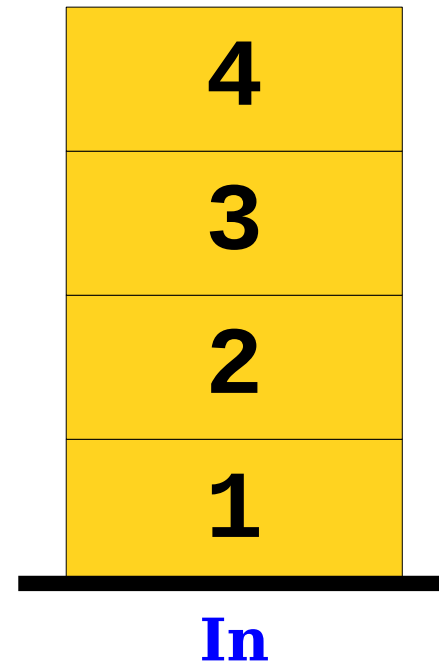


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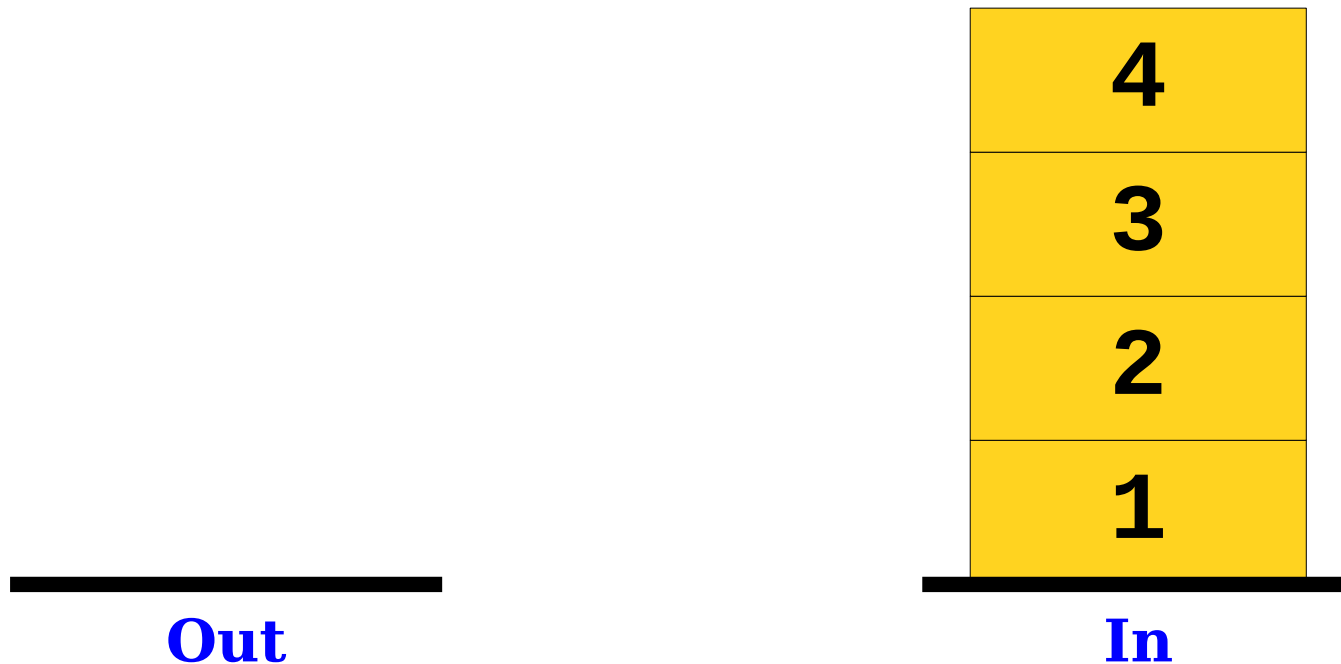
$\Phi$  = height of *In* stack

**Out**



# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

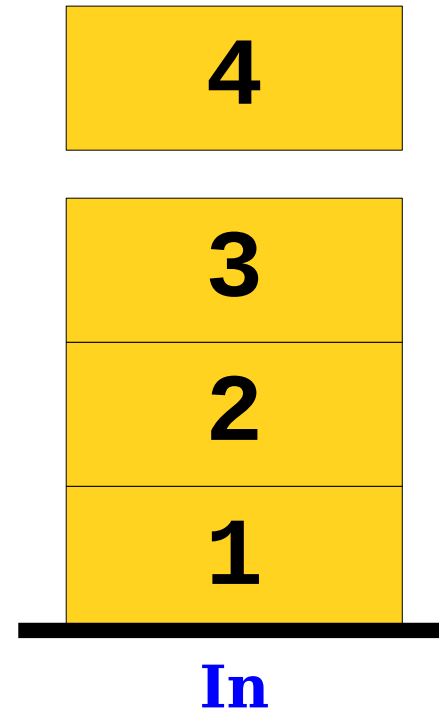


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# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

**Out**



# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

4

**Out**

3

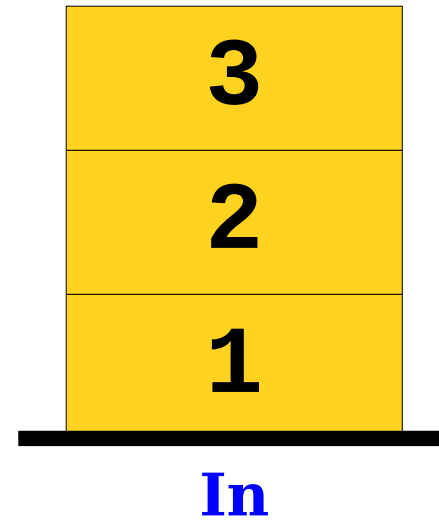
2

1

**In**

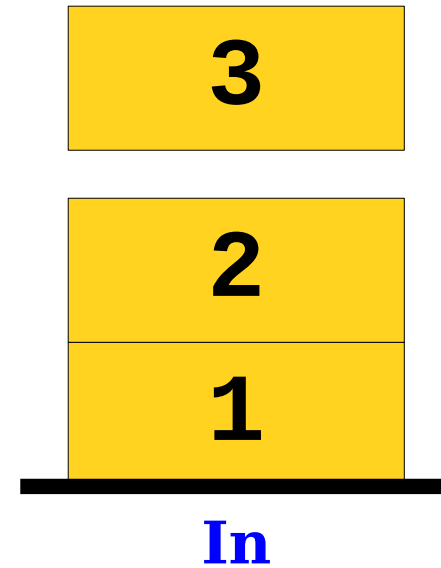
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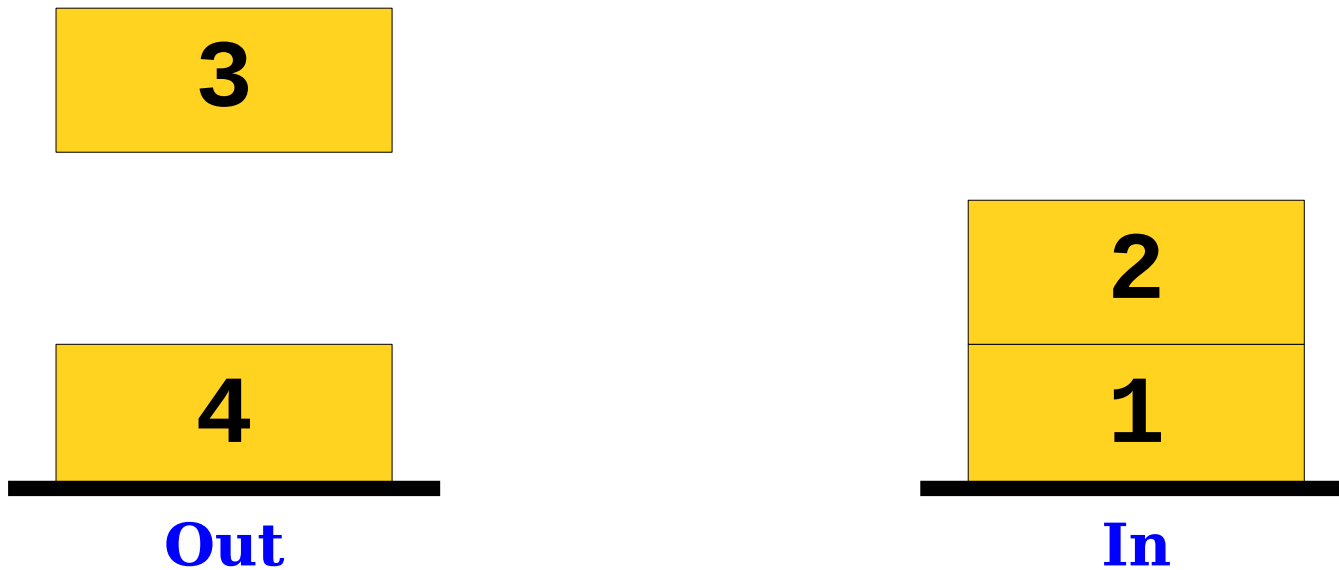
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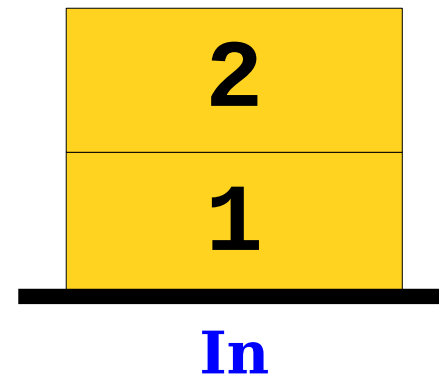
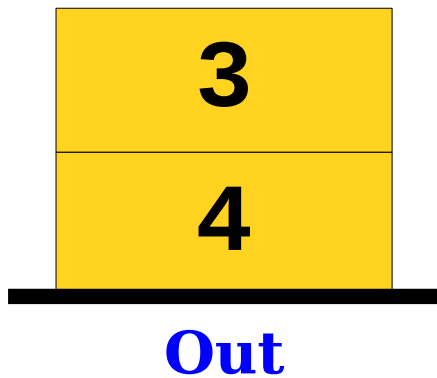
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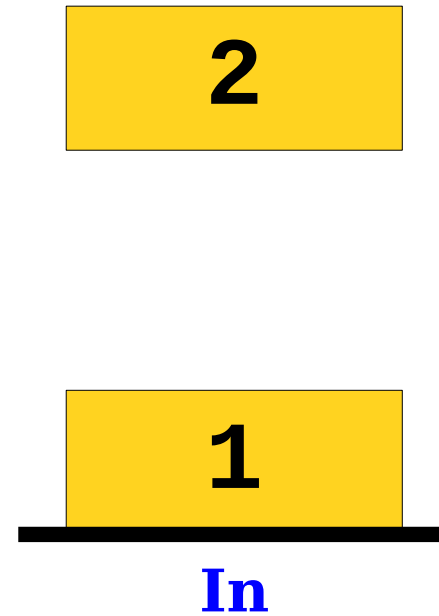
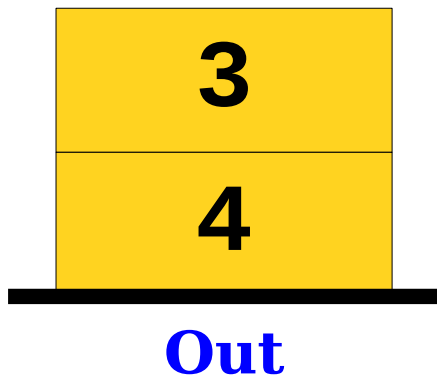
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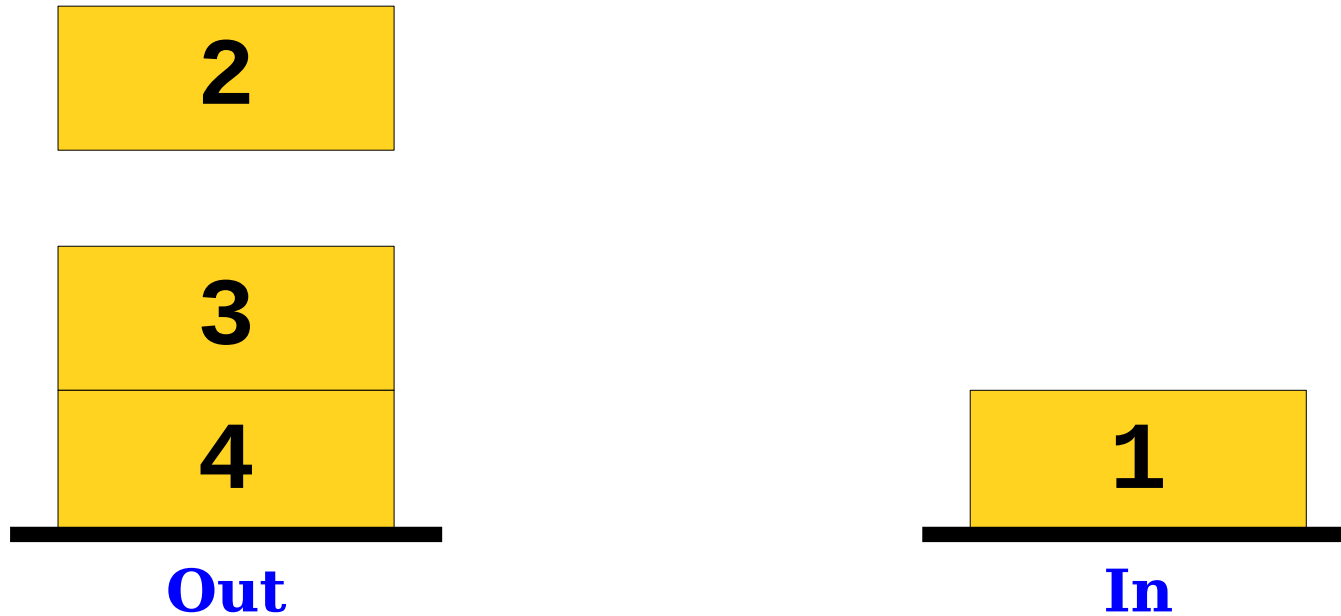
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$\Phi$  = height of *In* stack



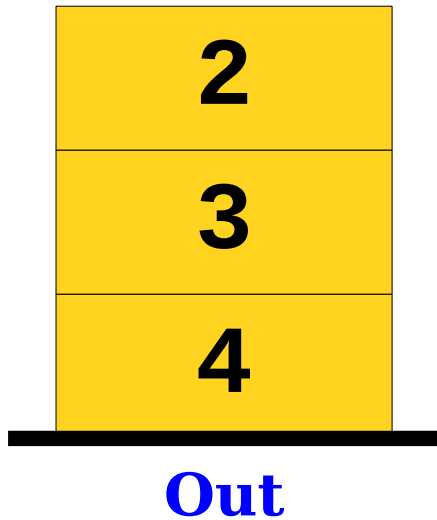
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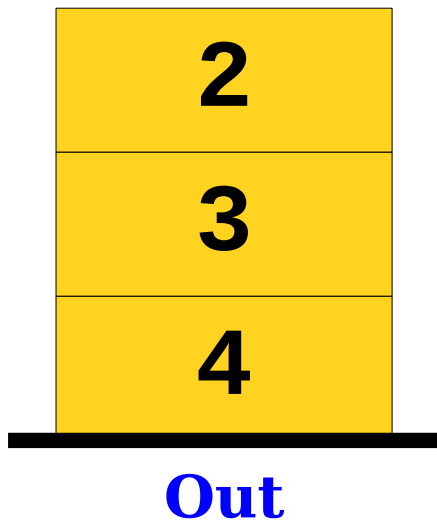
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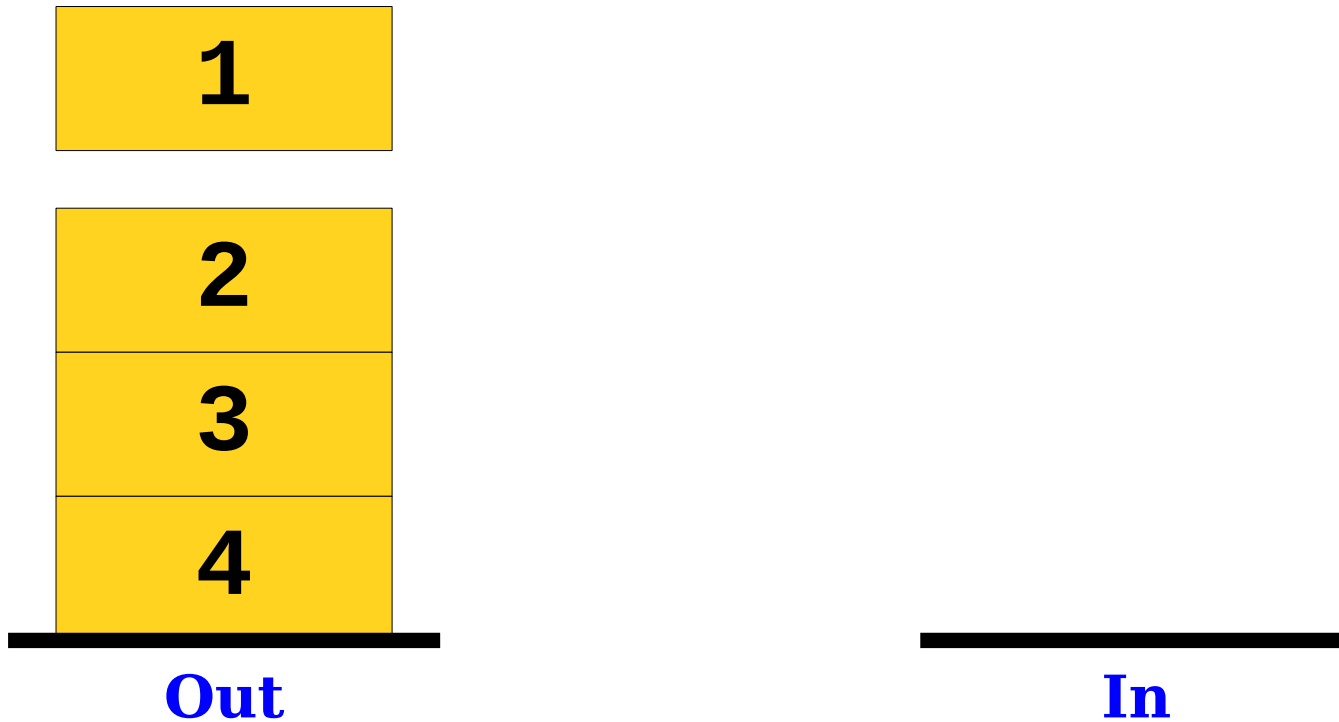
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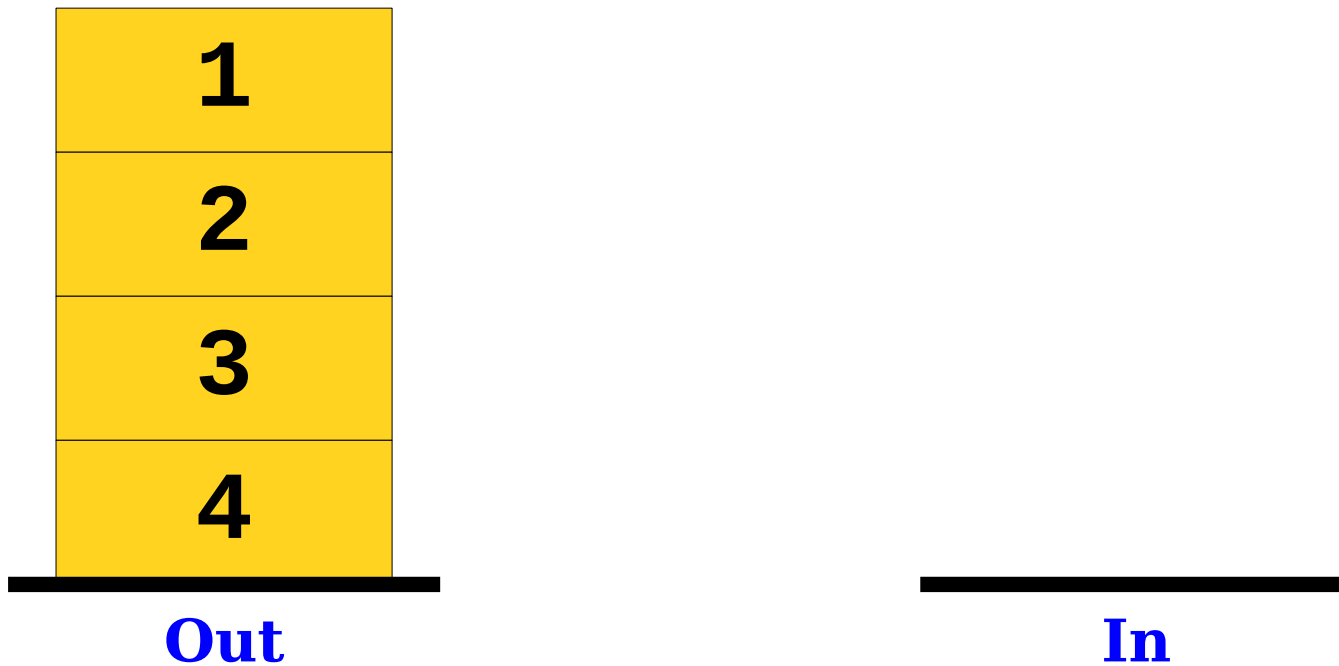
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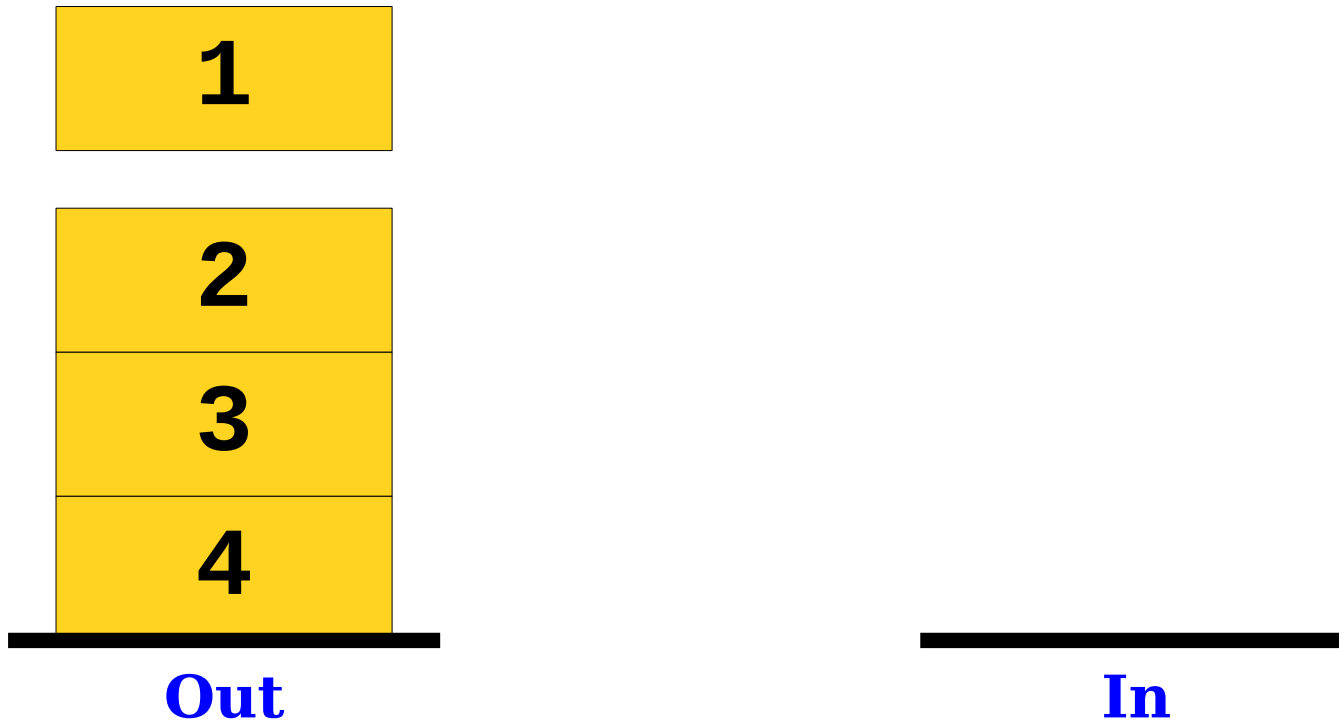
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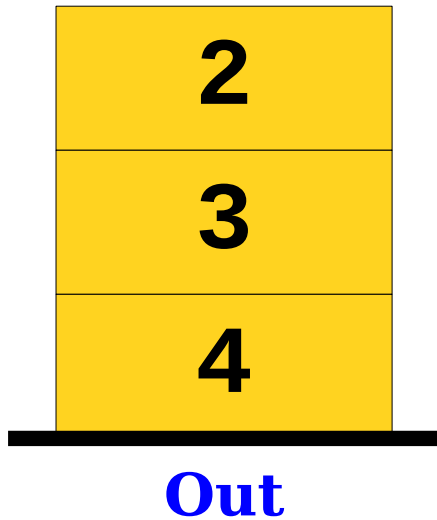
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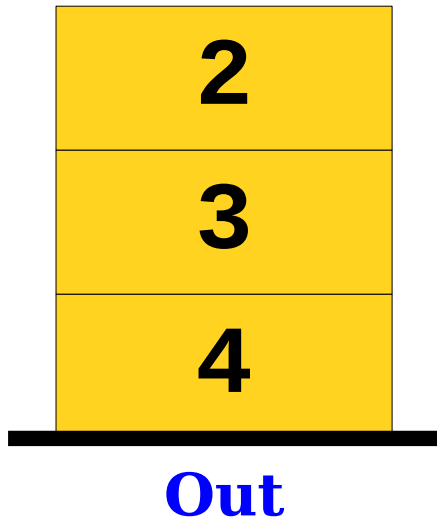
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$$\begin{aligned} \textit{amortized-cost} &= \textit{real-cost} + k \cdot \Delta\Phi \\ &= O(n) + k \cdot -n \\ &= \mathbf{O(1)} // \text{Choose } k \text{ strategically} \end{aligned}$$

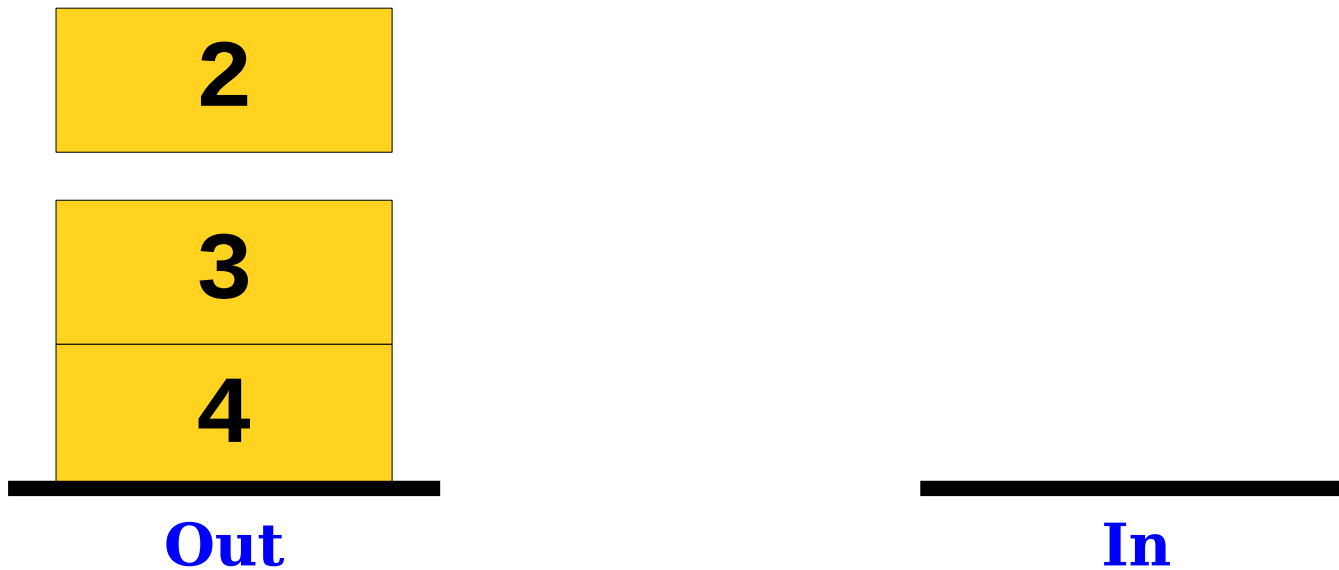
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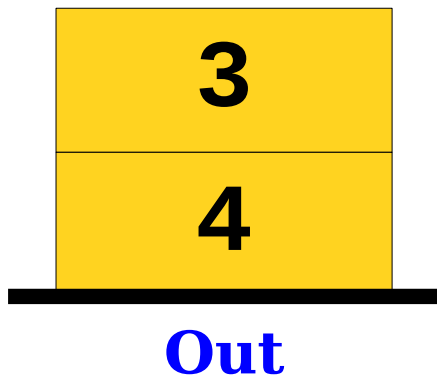
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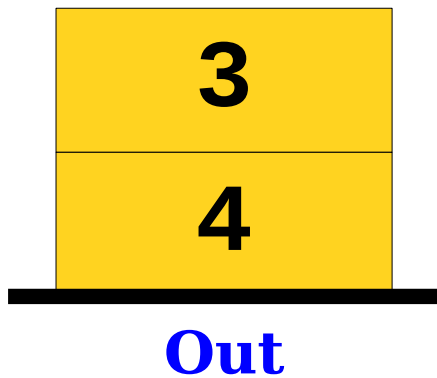
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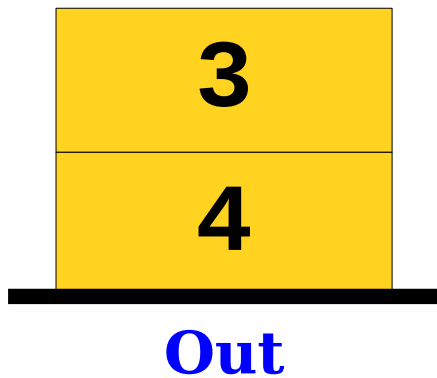
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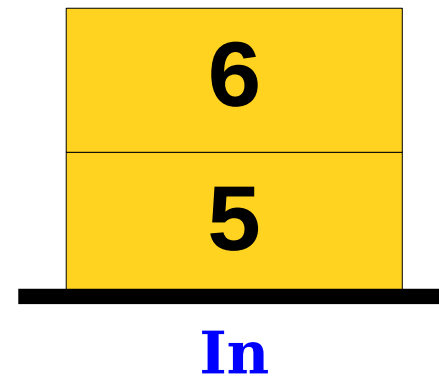
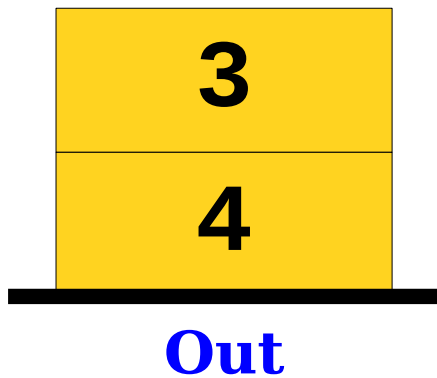
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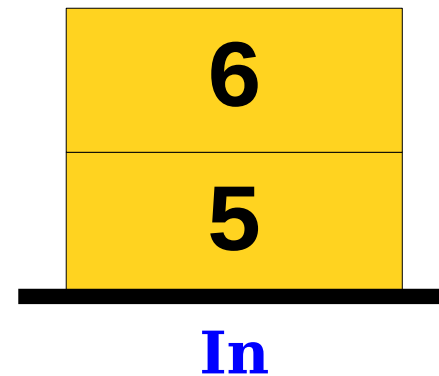
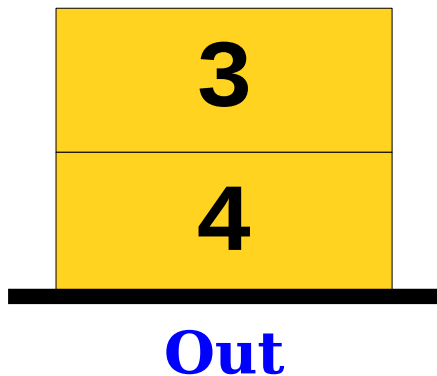
# The Two-Stack Queue

$\Phi$  = height of *In* stack



# The Two-Stack Queue

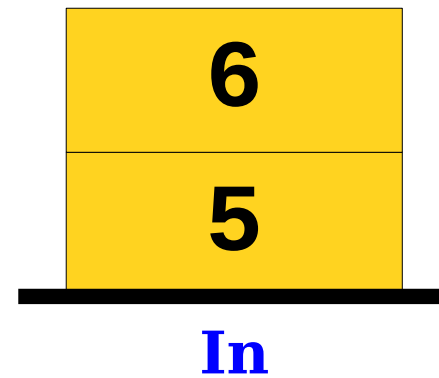
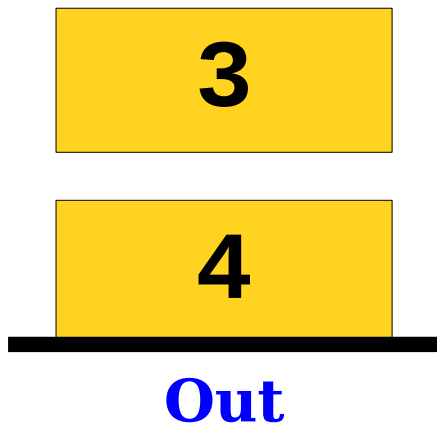
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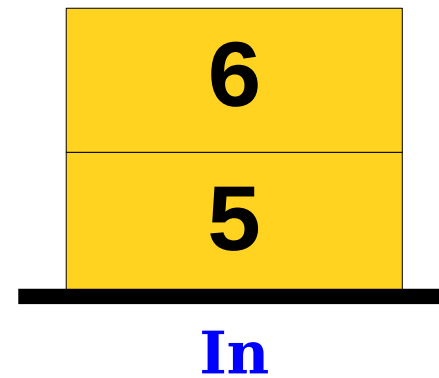
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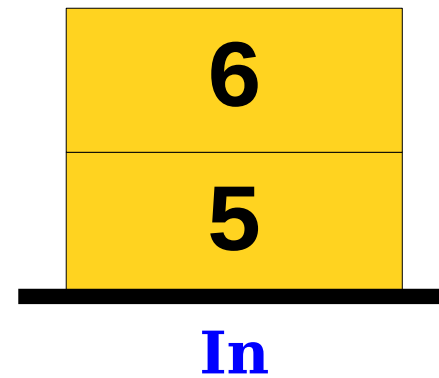
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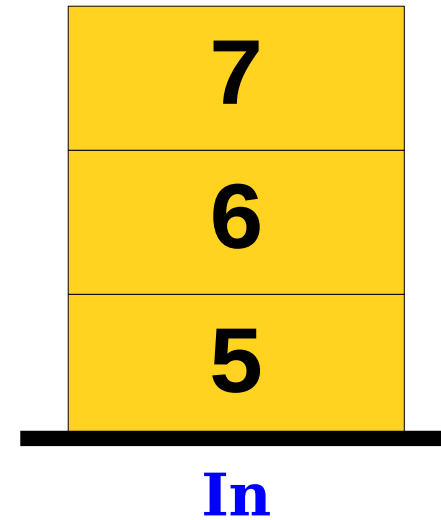
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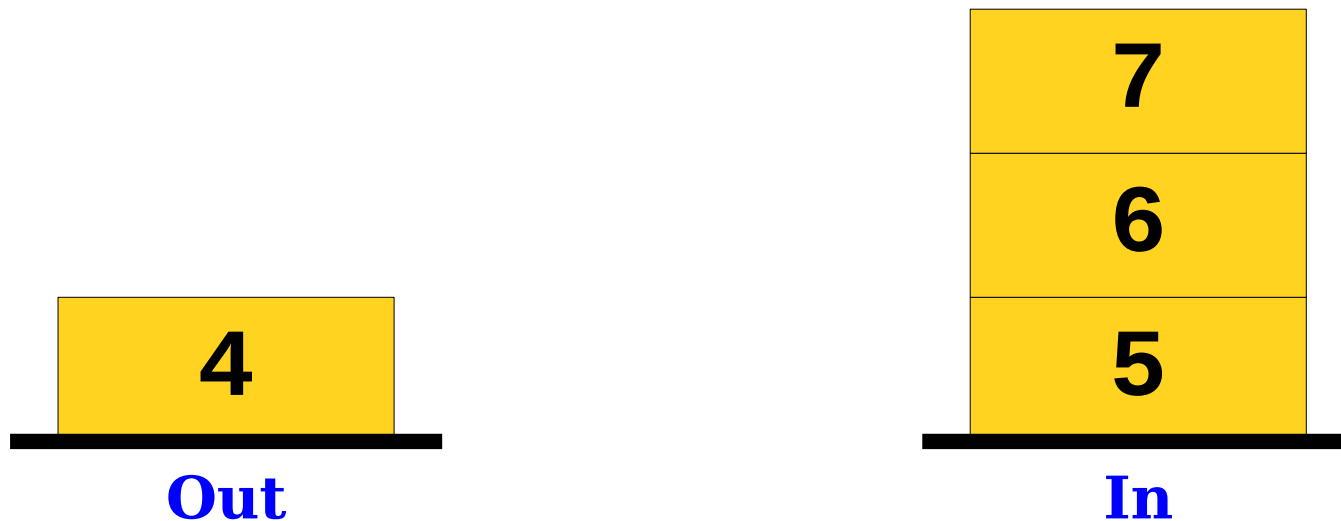
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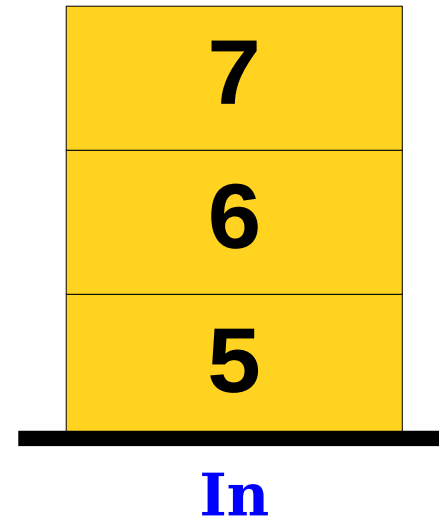
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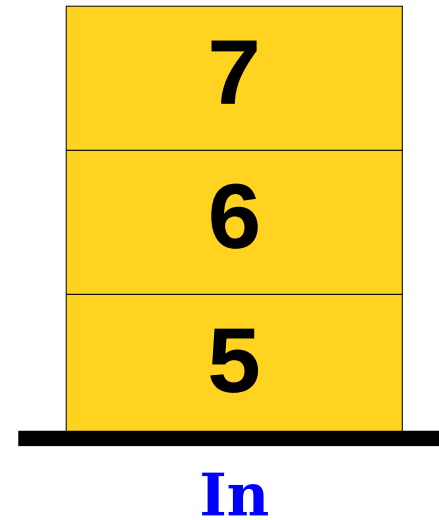
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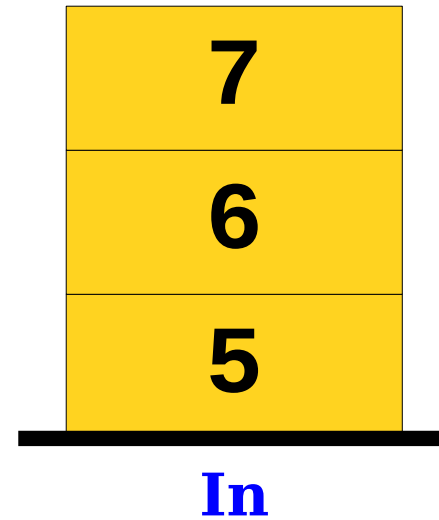
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# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

**Out**



# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

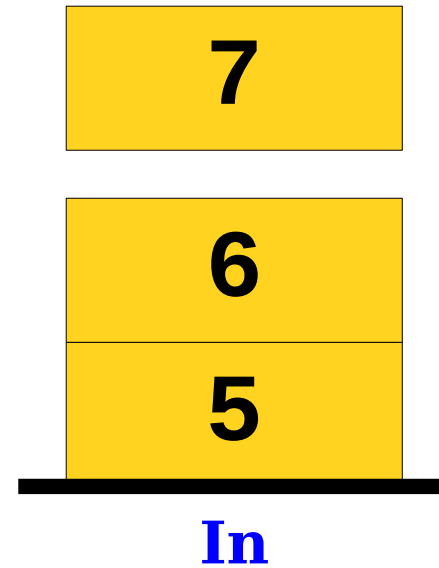


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# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

**Out**



# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$

7

**Out**

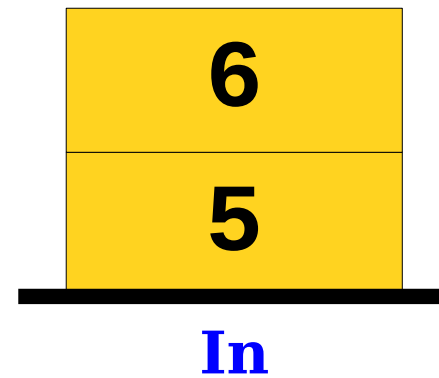
6

5

**In**

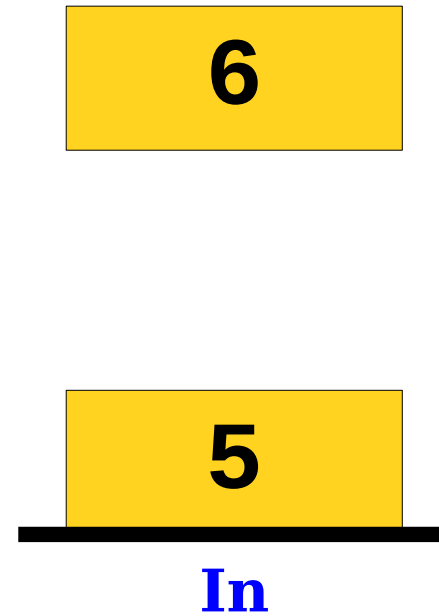
# The Two-Stack Queue

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# The Two-Stack Queue

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6

7

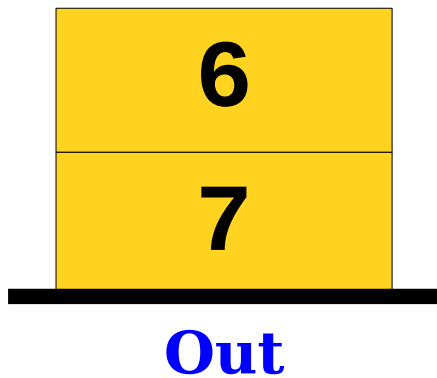
**Out**

5

**In**

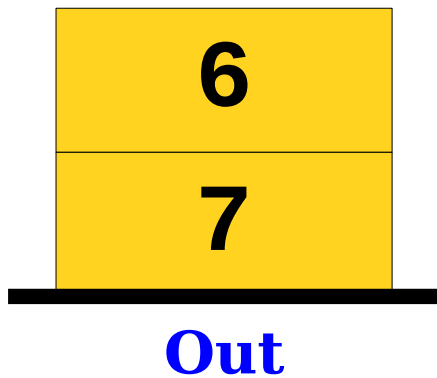
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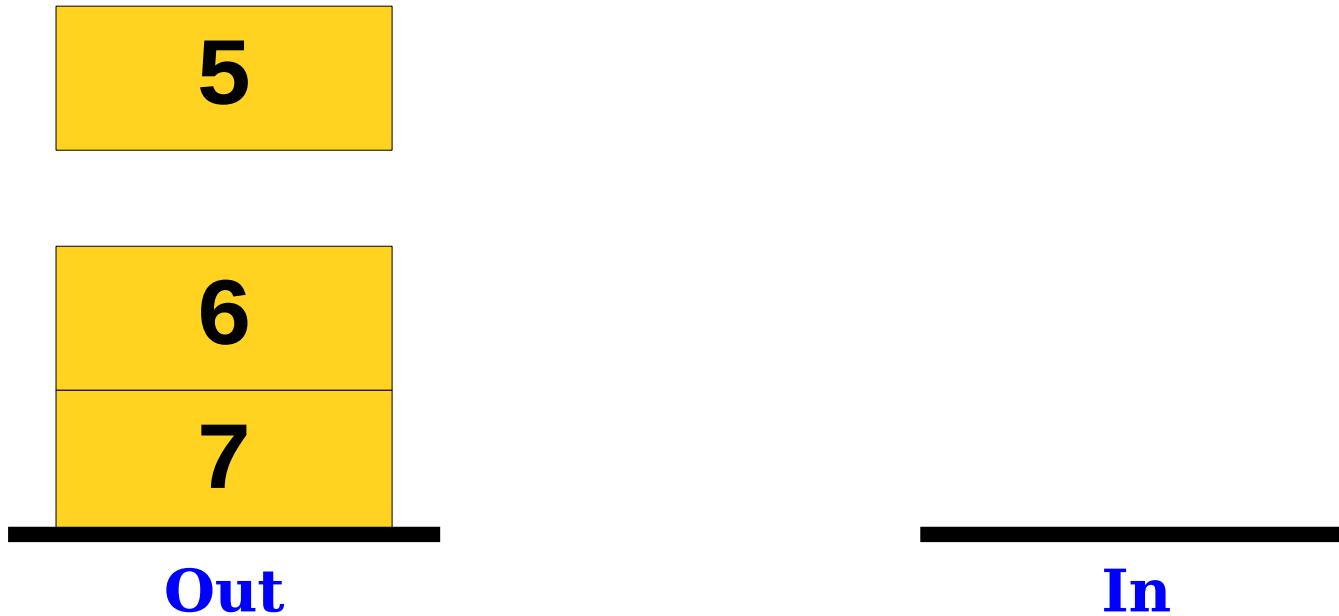
# The Two-Stack Queue

$\Phi$  = height of *In* stack



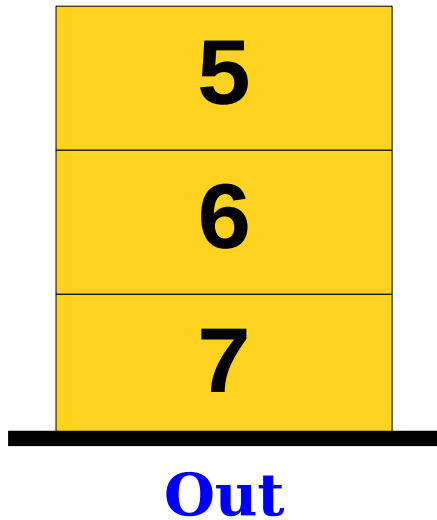
# The Two-Stack Queue

$\Phi = \text{height of } \mathbf{In} \text{ stack}$



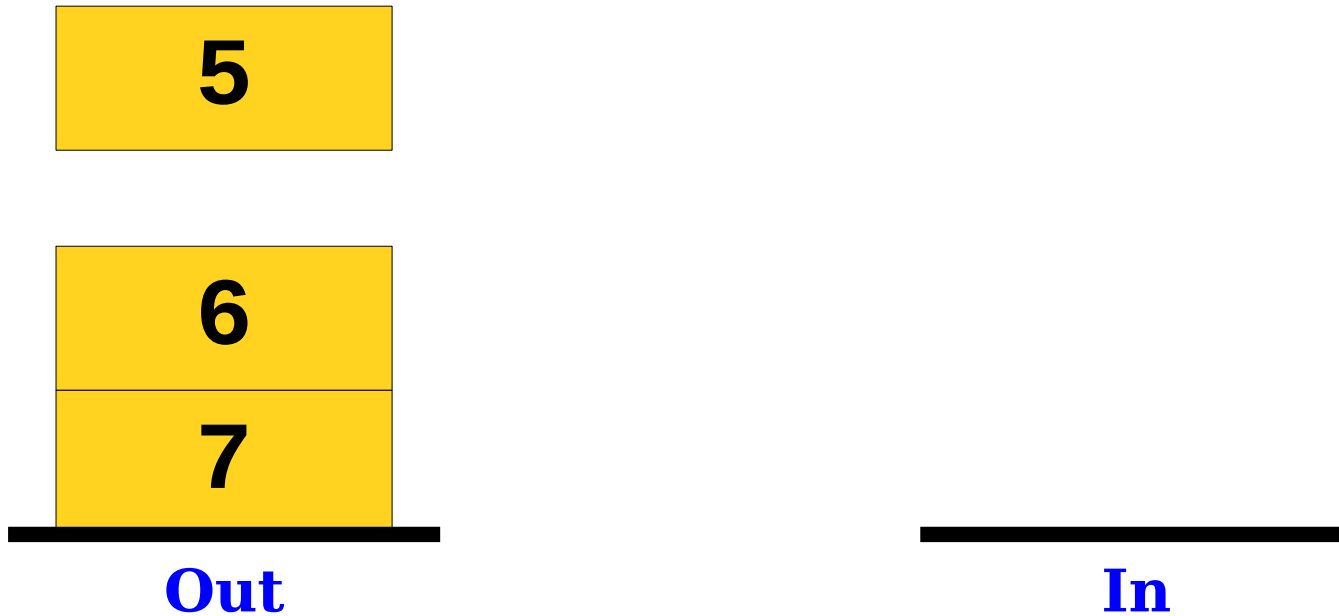
# The Two-Stack Queue

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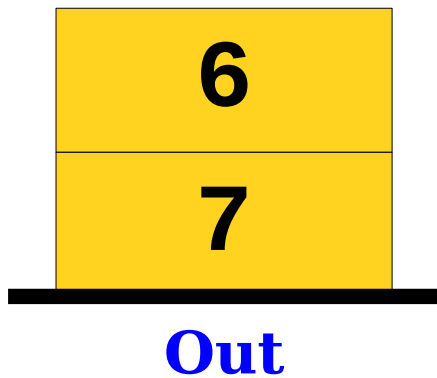
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$$\begin{aligned} \textit{amortized-cost} &= \textit{real-cost} + k \cdot \Delta\Phi \\ &= O(n) + k \cdot -n \\ &= \mathbf{O(1)} // \text{Choose } k \text{ strategically} \end{aligned}$$

**Theorem:** The amortized cost of any enqueue or dequeue operation on a two-stack queue is  $O(1)$ .

**Proof:** Let  $\Phi$  be the height of the *In* stack in the two-stack queue. Each enqueue operation does a single push and increases the height of the *In* stack by one. Therefore, its amortized cost is

$$O(1) + k \cdot \Delta\Phi = O(1) + k \cdot 1 = O(1).$$

Now, consider a dequeue operation. If the *Out* stack is nonempty, then the dequeue does  $O(1)$  work and does not change  $\Phi$ . Its cost is therefore

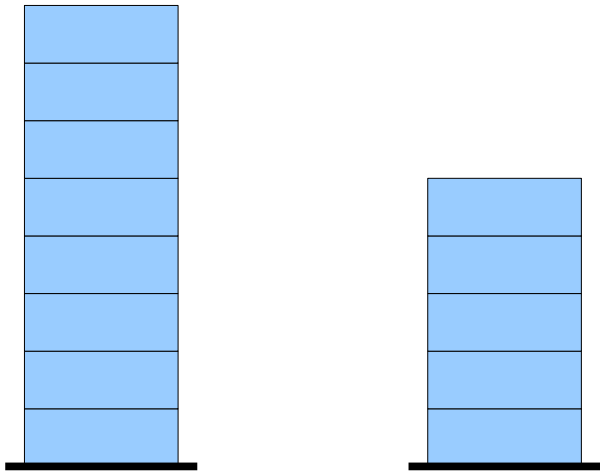
$$O(1) + k \cdot \Delta\Phi = O(1) + k \cdot 0 = O(1).$$

Otherwise, the *Out* stack is empty. Suppose the *In* stack has  $n$  elements. The dequeue does  $O(n)$  work to pop the elements from the *In* stack and push them onto the *Out* stack, followed by one additional pop for the dequeue. This is  $O(n)$  total work.

At the beginning of this operation, we have  $\Phi = n$ . At the end of this operation, we have  $\Phi = 0$ . Therefore,  $\Delta\Phi = -n$ , so the amortized cost of the operation is

$$O(n) + k \cdot -n = O(1),$$

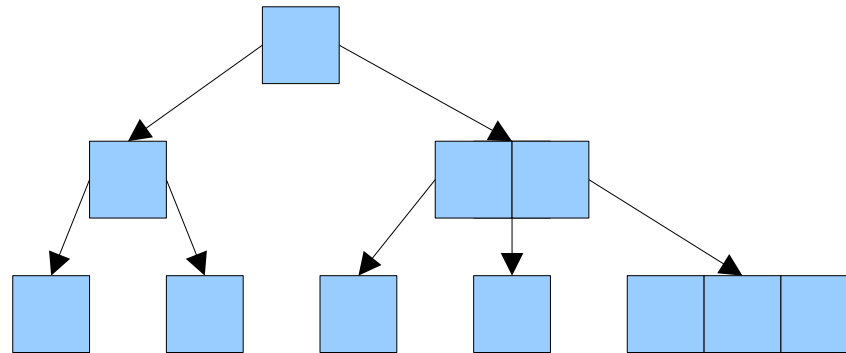
assuming we pick  $k$  to cancel out the constant factor hidden in the  $O(n)$  term. ■



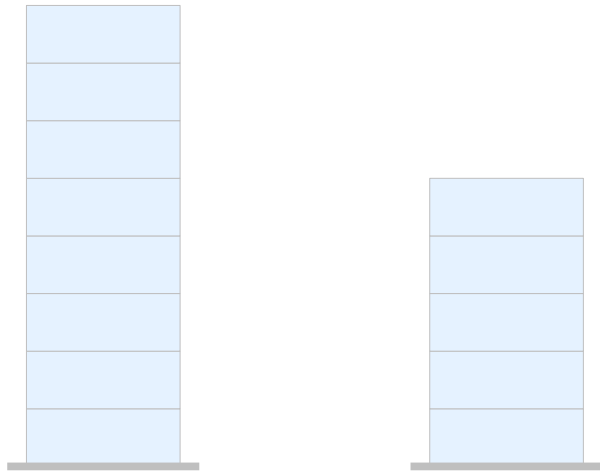
*Two-Stack Queues*



*Dynamic Arrays*



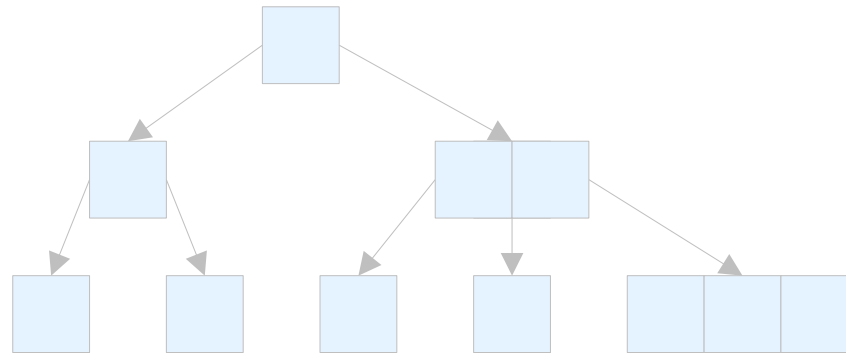
*Building B-Trees*



*Two-Stack Queues*



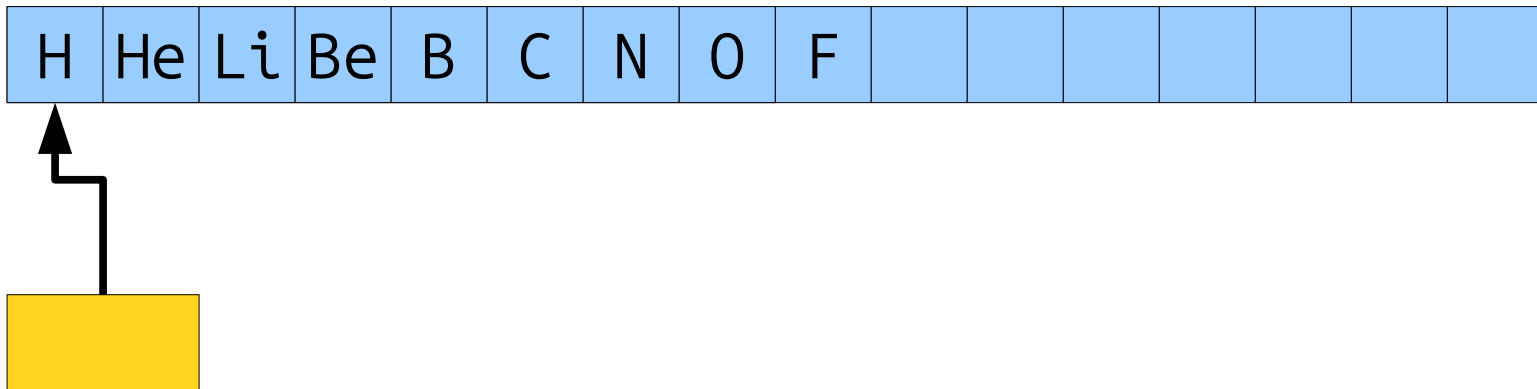
*Dynamic Arrays*



*Building B-Trees*

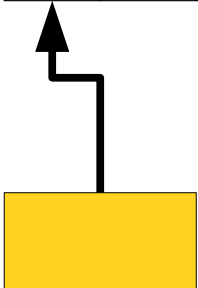
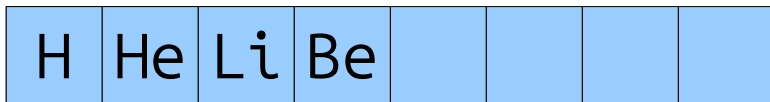
# Analyzing Dynamic Arrays

- **Goal:** Choose a potential function  $\Phi$  such that the amortized cost of an append is  $O(1)$ .
- **Initial (wrong!) guess:** Set  $\Phi$  to be the number of free slots left in the array.



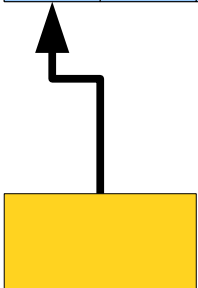
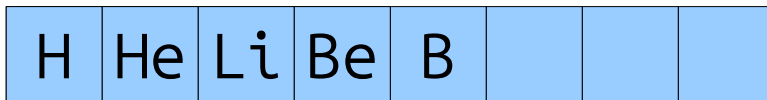
# Dynamic Arrays

$\Phi$  = number of free slots



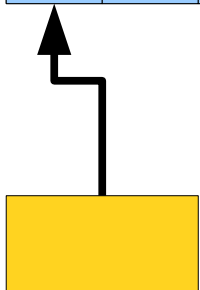
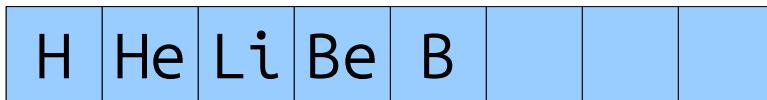
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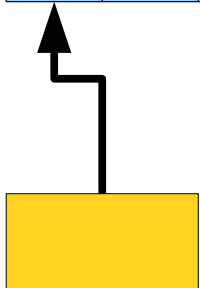
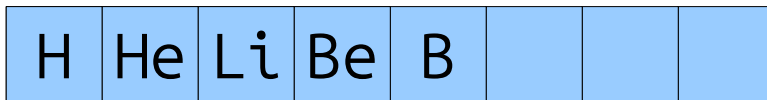
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$$\textit{amortized-cost} = \textit{real-cost} + k \cdot \Delta\Phi$$

# Dynamic Arrays

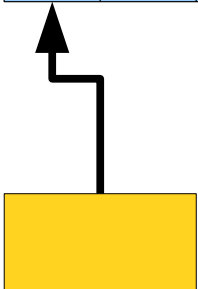
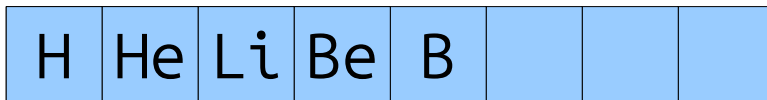
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$$\begin{aligned} \textit{amortized-cost} &= \textit{real-cost} + k \cdot \Delta\Phi \\ &= O(1) + k \cdot -1 \end{aligned}$$

# Dynamic Arrays

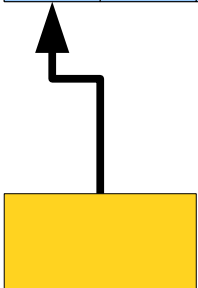
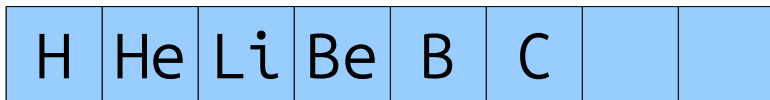
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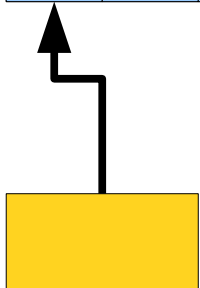
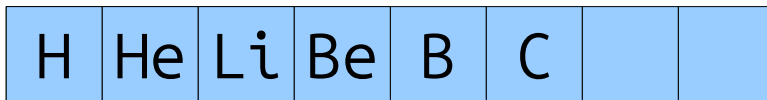
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# Dynamic Arrays

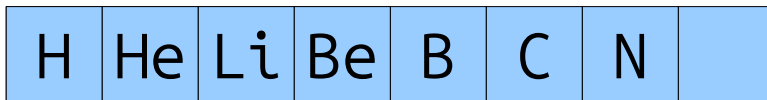
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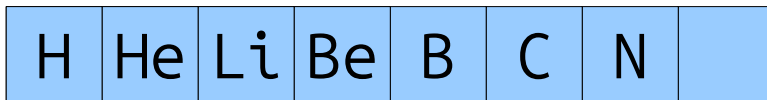
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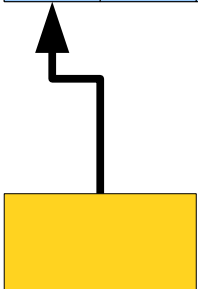
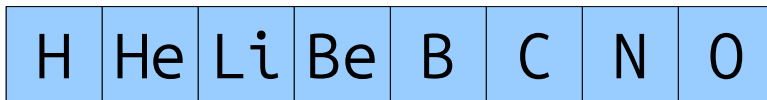
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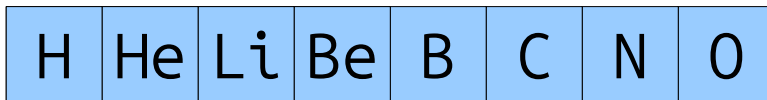
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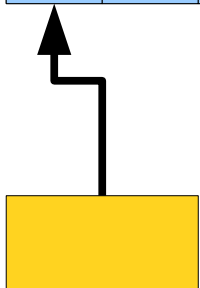
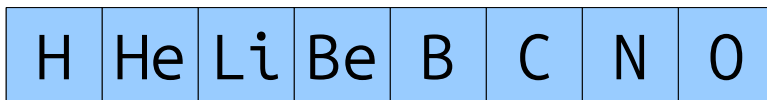
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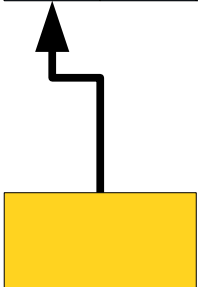
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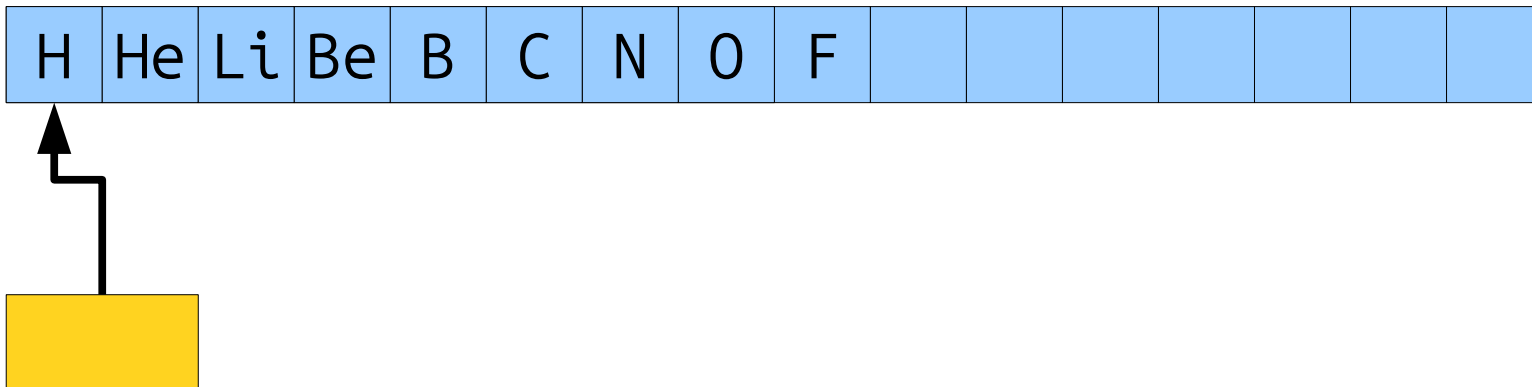
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$\Phi$  = number of free slots



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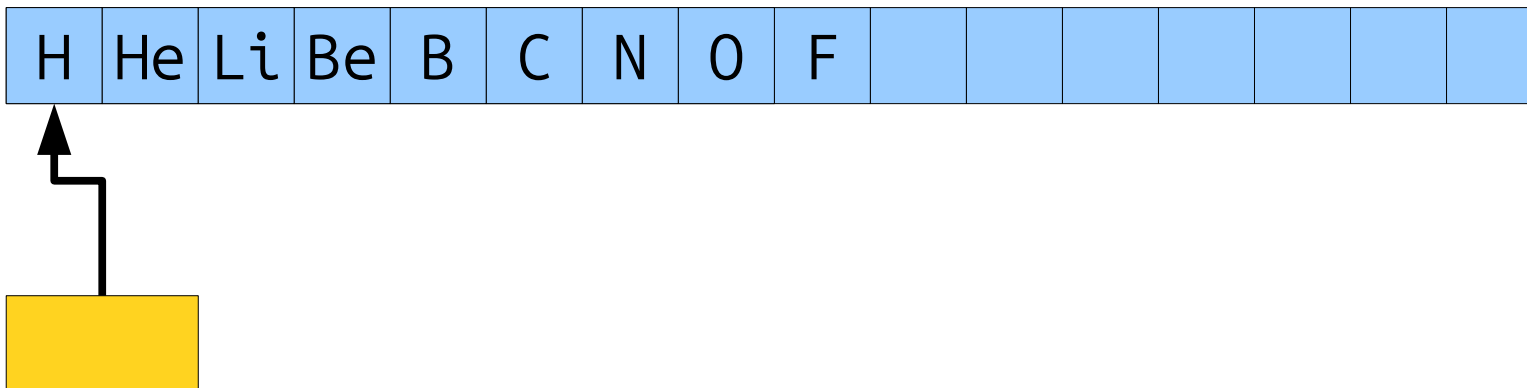


# Dynamic Arrays

$\Phi$  = number of free slots

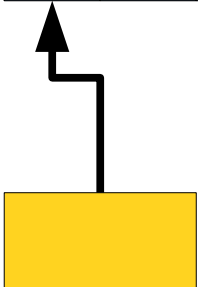
With this choice of  $\Phi$ , what is the amortized cost of an append to an array of size  $n$  when no free slots are left?

Answer at  
<https://cs166.stanford.edu/pollev>



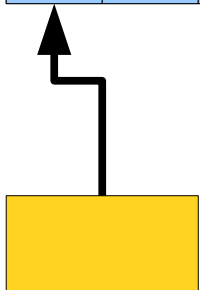
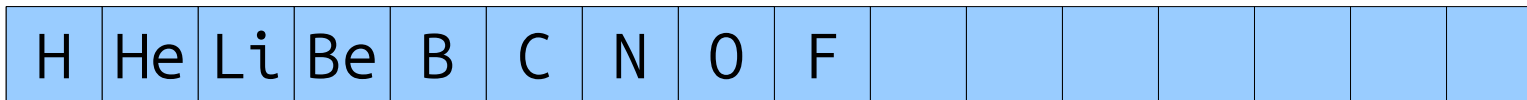
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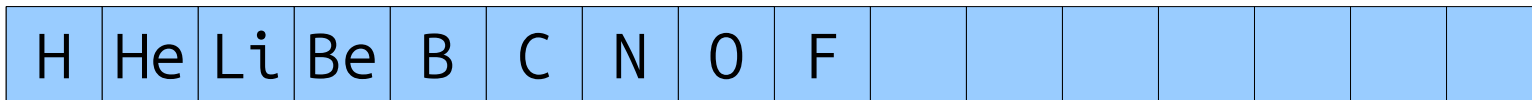
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$$\textit{amortized-cost} = \textit{real-cost} + k \cdot \Delta\Phi$$

# Dynamic Arrays

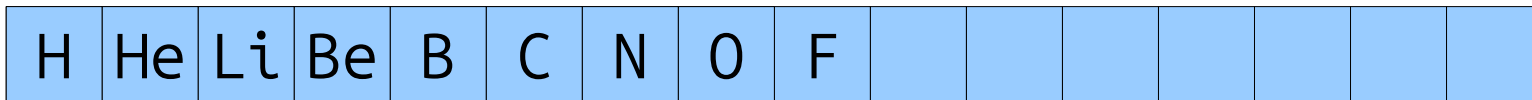
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$$\begin{aligned} \text{amortized-cost} &= \text{real-cost} + k \cdot \Delta\Phi \\ &= O(n) + k \cdot \Theta(n) \end{aligned}$$

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# Analyzing Dynamic Arrays

- **Intuition:**  $\Phi$  should measure how “messy” the data structure is.
  - Having lots of free slots means there’s very little mess.
  - Having few free slots means there’s a lot of mess.
- We basically got our potential function backwards. Oops. 😊
- **Question:** What should  $\Phi$  be?

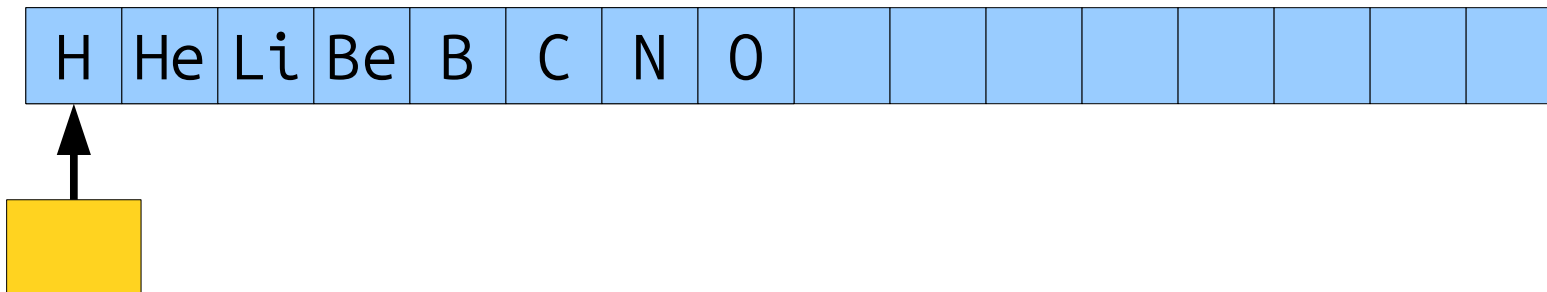
# Analyzing Dynamic Arrays

- The amortized cost of an append is

$$\textit{amortized-cost} = \textit{real-cost} + k \cdot \Delta\Phi.$$

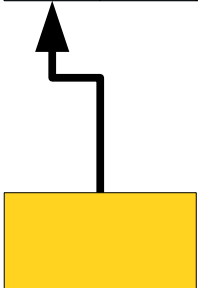
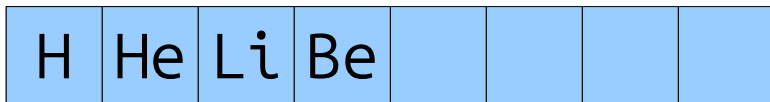
- When we double the array size, our real cost is  $\Theta(n)$ . We need  $\Delta\Phi$  to be something like  $-n$ .
- **Goal:** Pick  $\Phi$  so that
  - when there are no slots left,  $\Phi \approx n$ , and
  - right after we double the array size,  $\Phi \approx 0$ .
- With some trial and error, we can come up with

$$\Phi = \textit{\#elems} - \textit{\#free-slots}$$



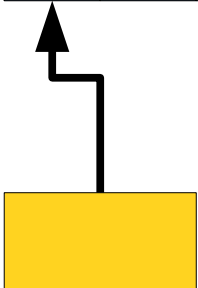
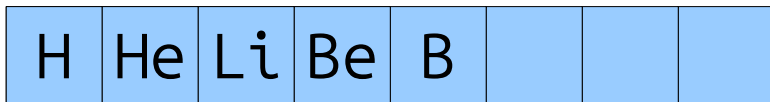
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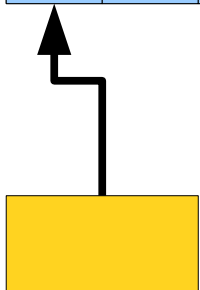
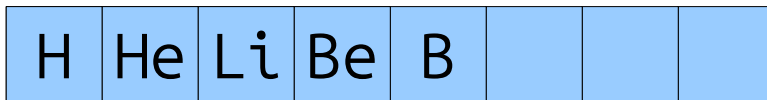
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# Dynamic Arrays

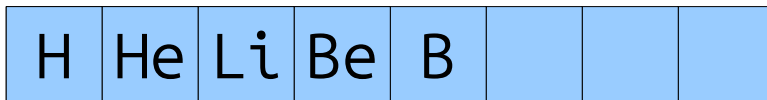
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$$\text{amortized-cost} = \text{real-cost} + k \cdot \Delta\Phi$$

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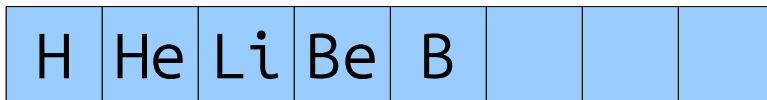
$$\Phi = \#elems - \#free-slots$$



$$\begin{aligned} \text{amortized-cost} &= \text{real-cost} + k \cdot \Delta\Phi \\ &= O(1) + k \cdot 2 \end{aligned}$$

# Dynamic Arrays

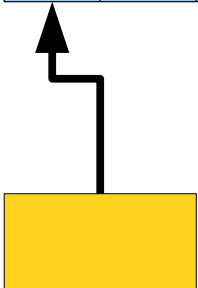
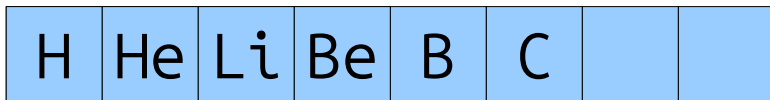
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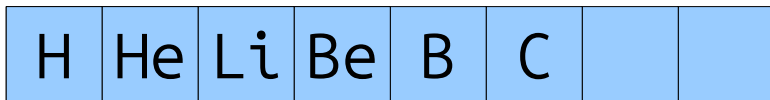
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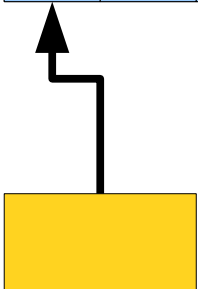
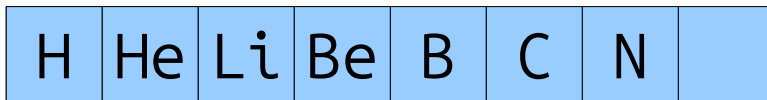
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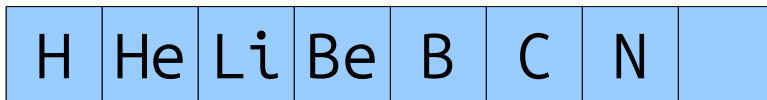
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# Dynamic Arrays

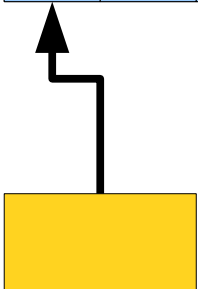
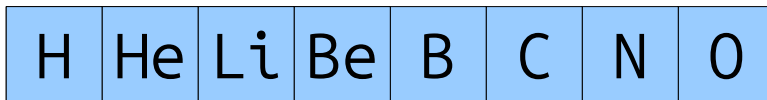
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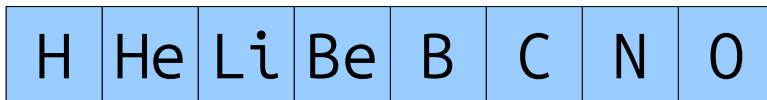
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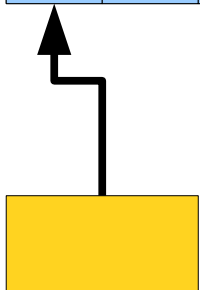
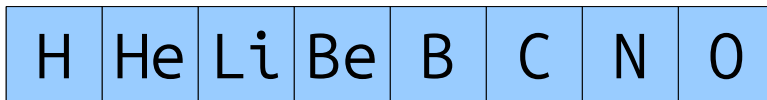
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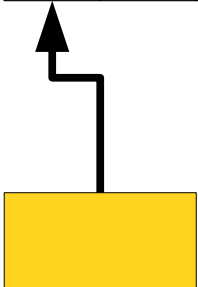
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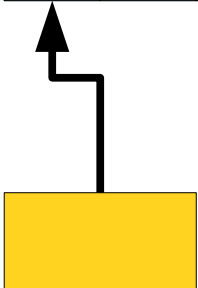
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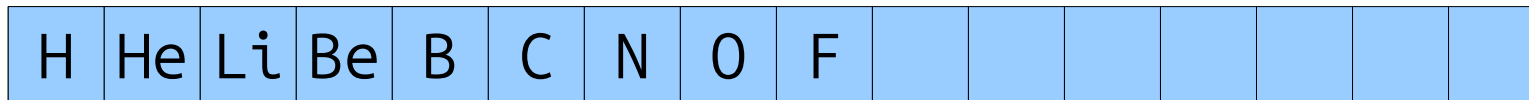
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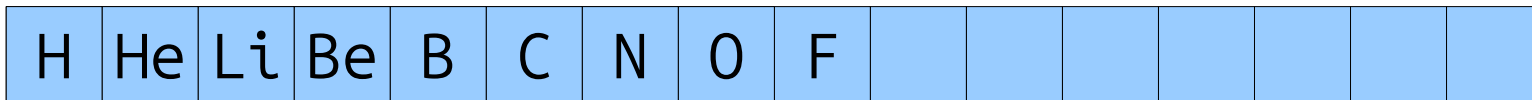
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$$amortized-cost = real-cost + k \cdot \Delta\Phi$$

# Dynamic Arrays

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$$\begin{aligned} \text{amortized-cost} &= \text{real-cost} + k \cdot \Delta\Phi \\ &= O(n) + k \cdot \Theta(n) \end{aligned}$$

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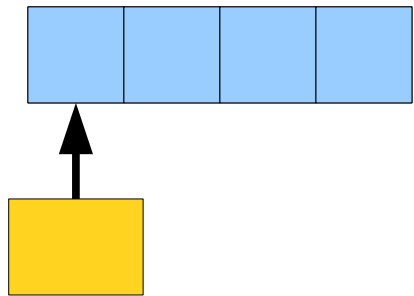
$$\Phi = \#elems - \#free-slots$$



$$\begin{aligned} \text{amortized-cost} &= \text{real-cost} + k \cdot \Delta\Phi \\ &= O(n) + k \cdot -\Theta(n) \\ &= \mathbf{O(1)} // \text{Pick } k \text{ well} \end{aligned}$$

# A Caveat

- We require that  $\Phi_{\text{start}} = 0$  and that  $\Phi \geq 0$ .
- What happens when we have a newly-created dynamic array?



$$\Phi = -4$$

- **Quick fix:** This is an edge case, so set  
$$\Phi = \max\{ 0, \#elems - \#free-slots \}$$

**Theorem:** The amortized cost of an append to a dynamic array is  $O(1)$ .

**Proof:** Suppose the dynamic array has initial capacity  $2C = O(1)$ . Then, define  $\Phi = \max\{0, n - \#free-slots\}$ , where  $n$  is the number of elements stored in the dynamic array. Note that for  $n < C$  that an append simply fills in a free slot and leaves  $\Phi = 0$ , so the amortized cost of such an append is  $O(1)$ . Otherwise, we have  $n > C$  and  $\Phi = n - \#free-slots$ .

Consider any append. If the append does not trigger a resize, it does  $O(1)$  work, increases  $n$  by one, and decreases  $\#free-slots$  by one, so the amortized cost is

$$O(1) + k \cdot \Delta\Phi = O(1) + k \cdot 2 = O(1).$$

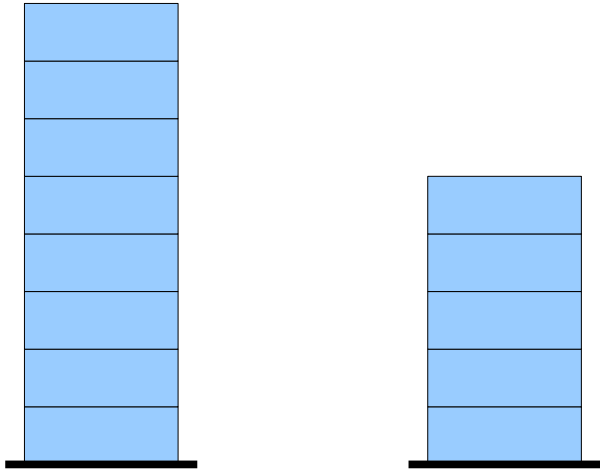
Otherwise, the operation copies  $n$  elements into a new array twice as large as before, increasing the number of free slots to  $n$ , then fills one of those slots. Just before the operation we had  $\Phi = n$ , and just after the operation we have  $\Phi = 2$ . Therefore, the amortized cost is

$$O(n) + k \cdot \Delta\Phi = O(n) + k \cdot (2 - n) = O(n) - nk + 2k,$$

which can be made to equal  $O(1)$  by choosing the the  $k$  term to match the constant hidden in the  $O(n)$  term. ■

# Some Exercises

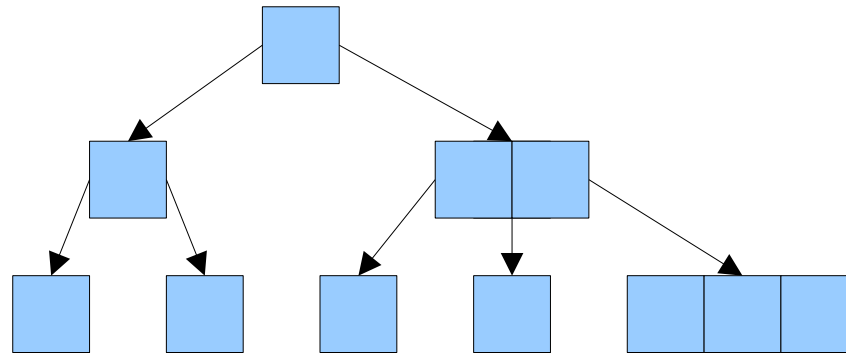
- Suppose we grow the array not by a factor of two, but by a fixed constant  $\alpha > 1$ . Find a choice of  $\Phi$  so that the amortized cost of an append is  $O(1)$ .
- Suppose we also allow elements to be removed from the array, and when it's  $\frac{1}{4}$  full we shrink it by a factor of two. Find a choice of  $\Phi$  so the amortized cost of appending or removing the last element is  $O(1)$ .



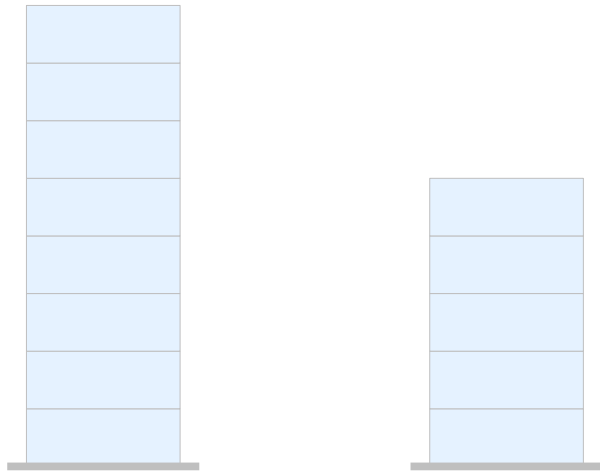
*Two-Stack Queues*



*Dynamic Arrays*



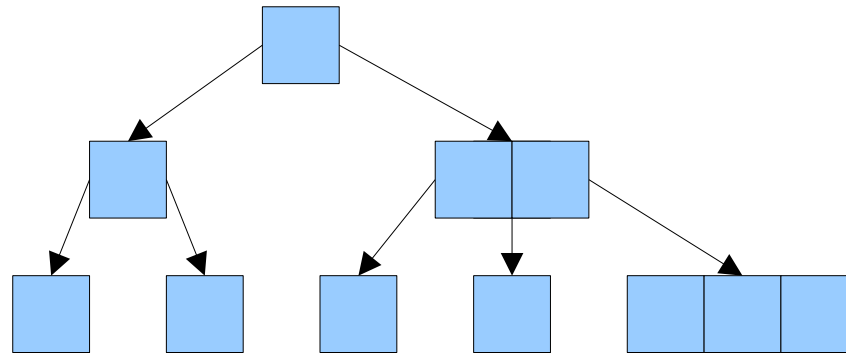
*Building B-Trees*



*Two-Stack Queues*



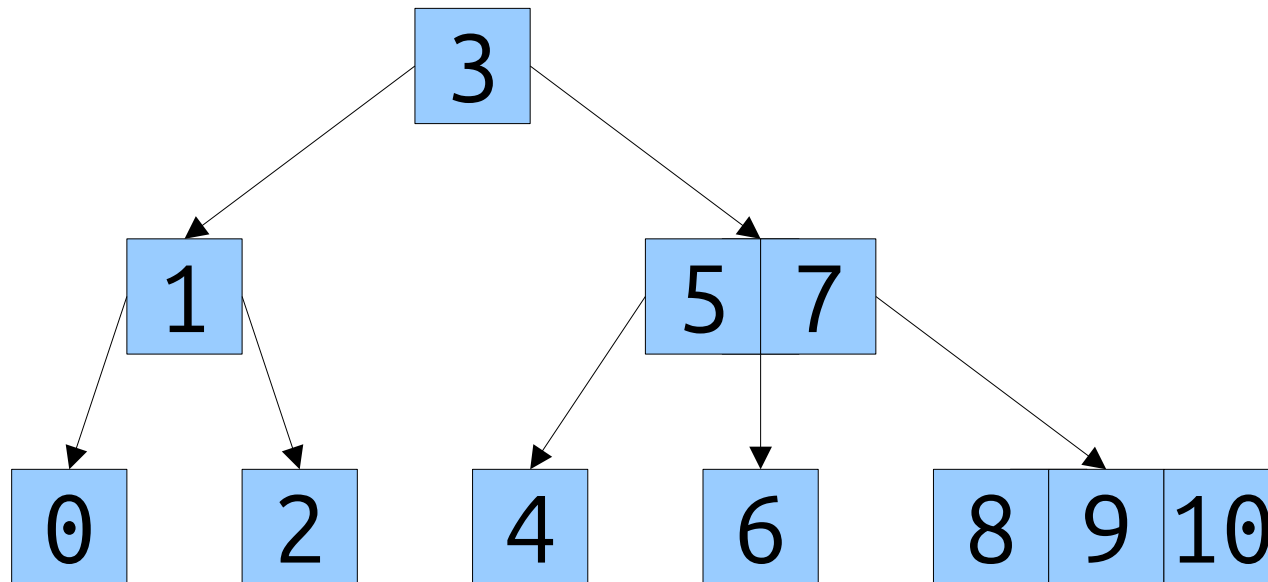
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*Building B-Trees*

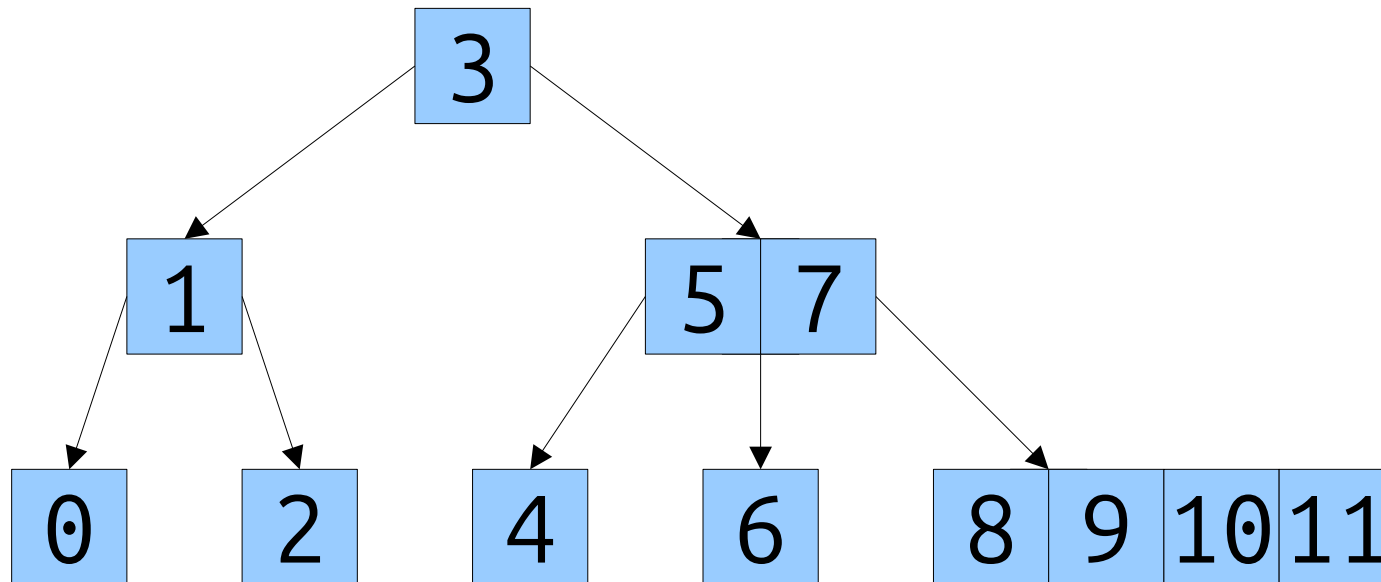
# Building B-Trees

- **Algorithm:** Store a pointer to the rightmost leaf. To add an item, append it to the rightmost leaf, splitting and kicking the median key up if we are out of space.



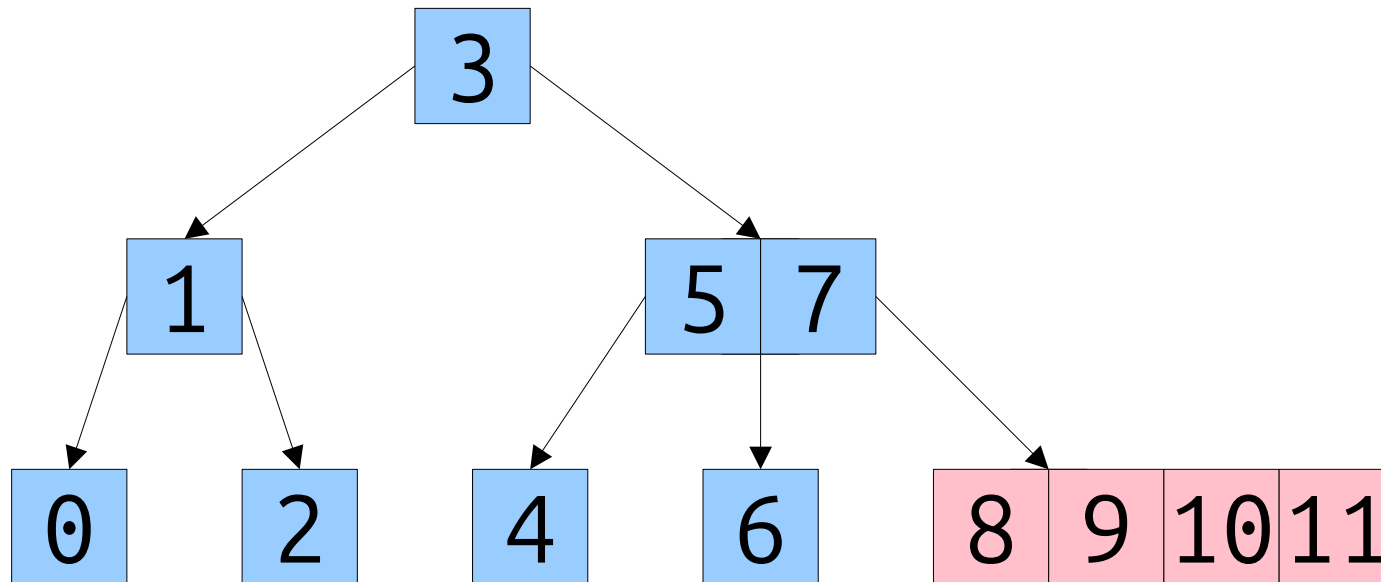
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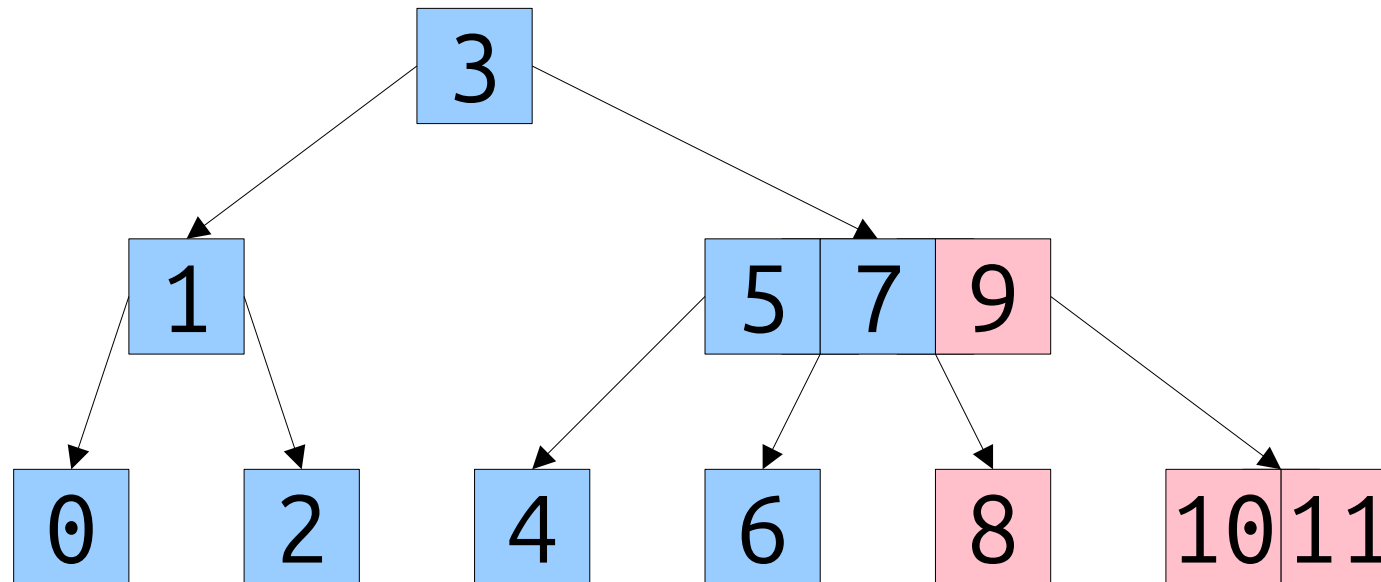
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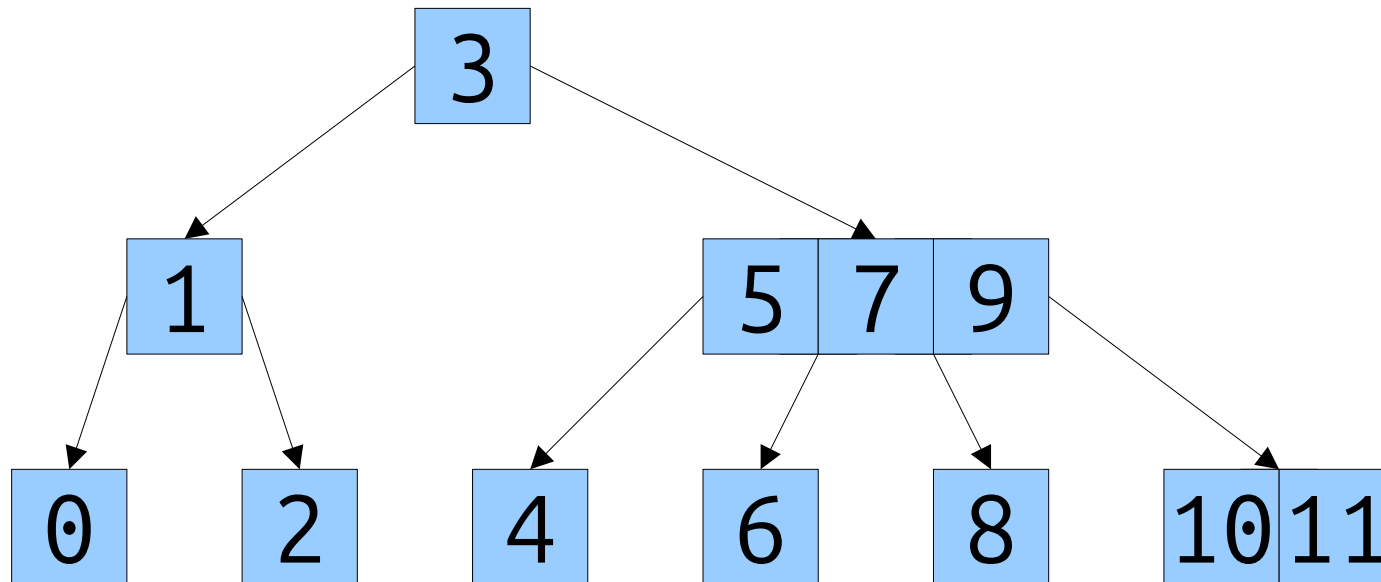
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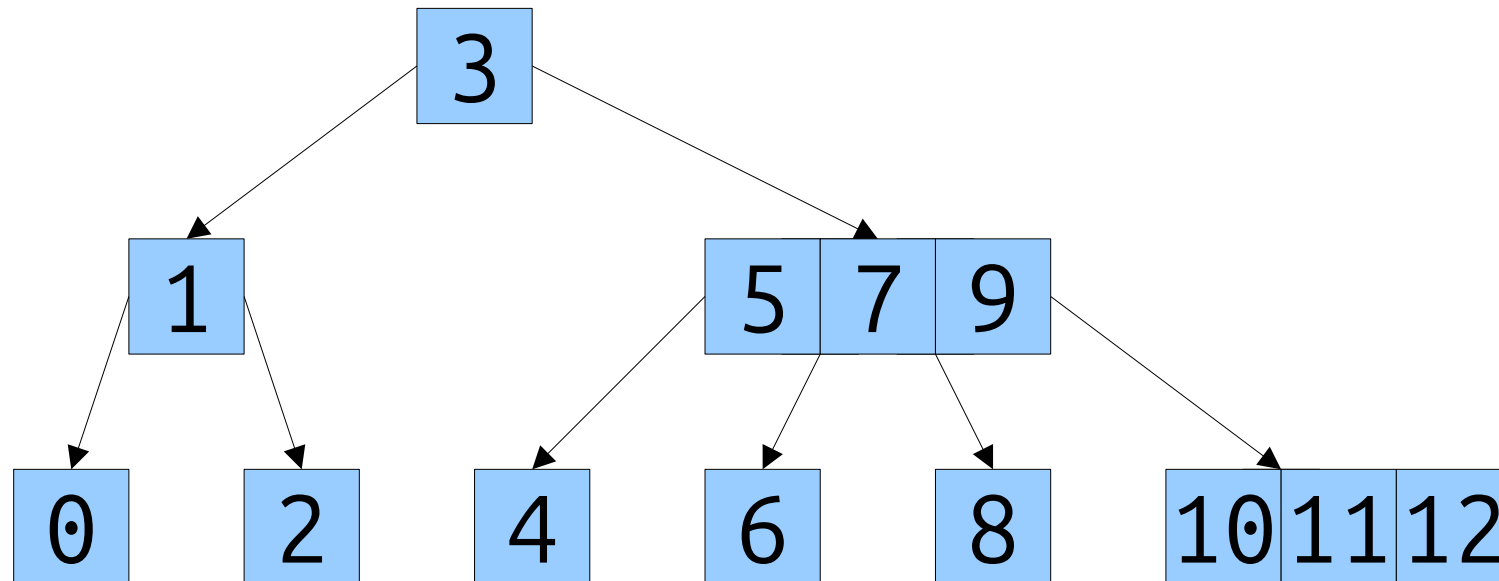
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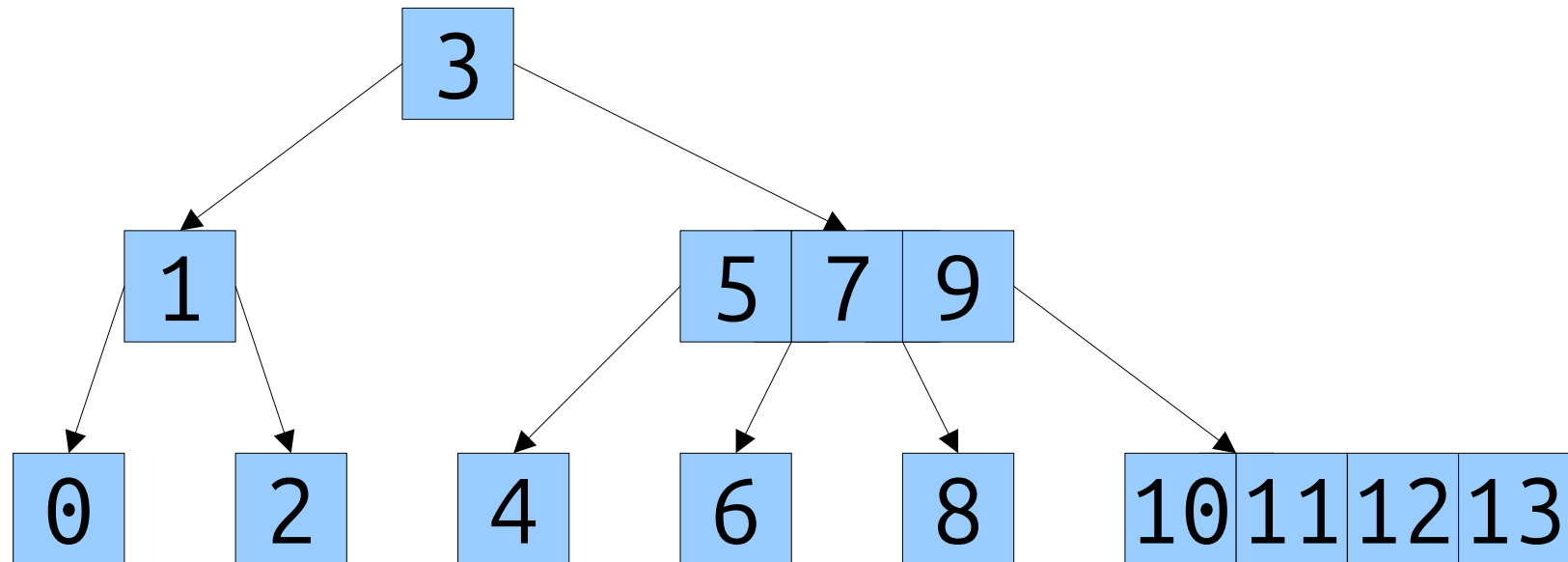
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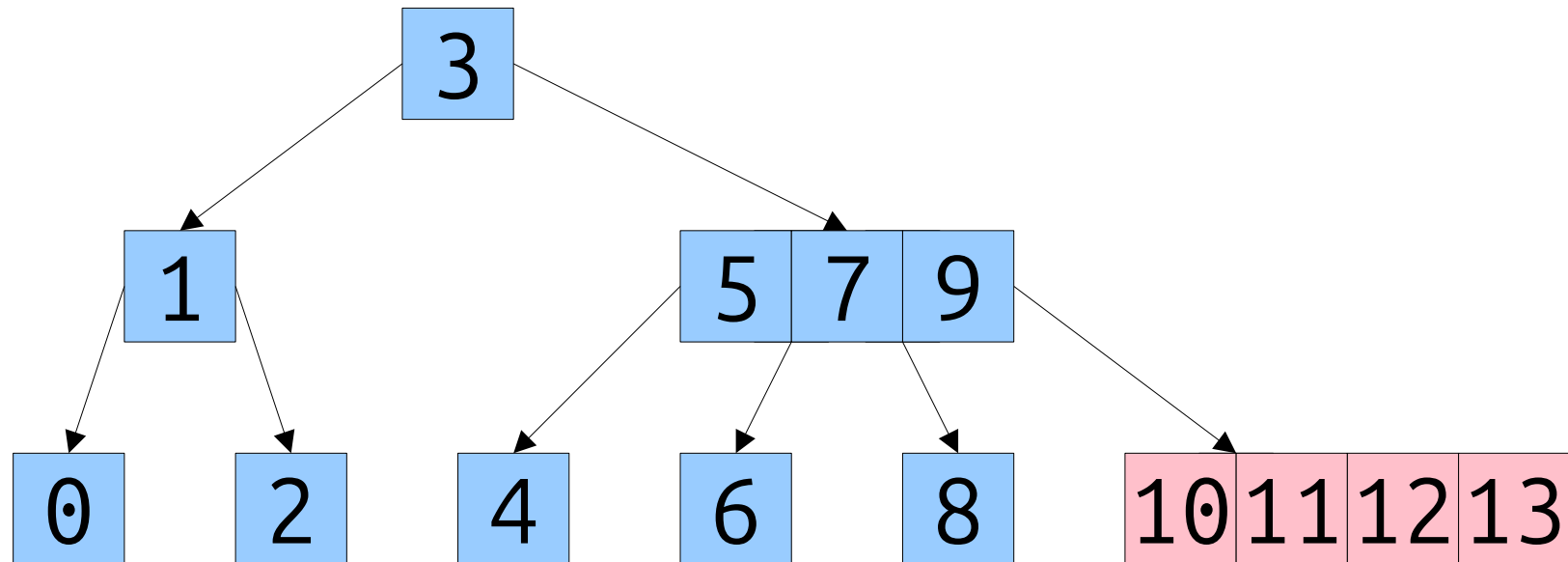
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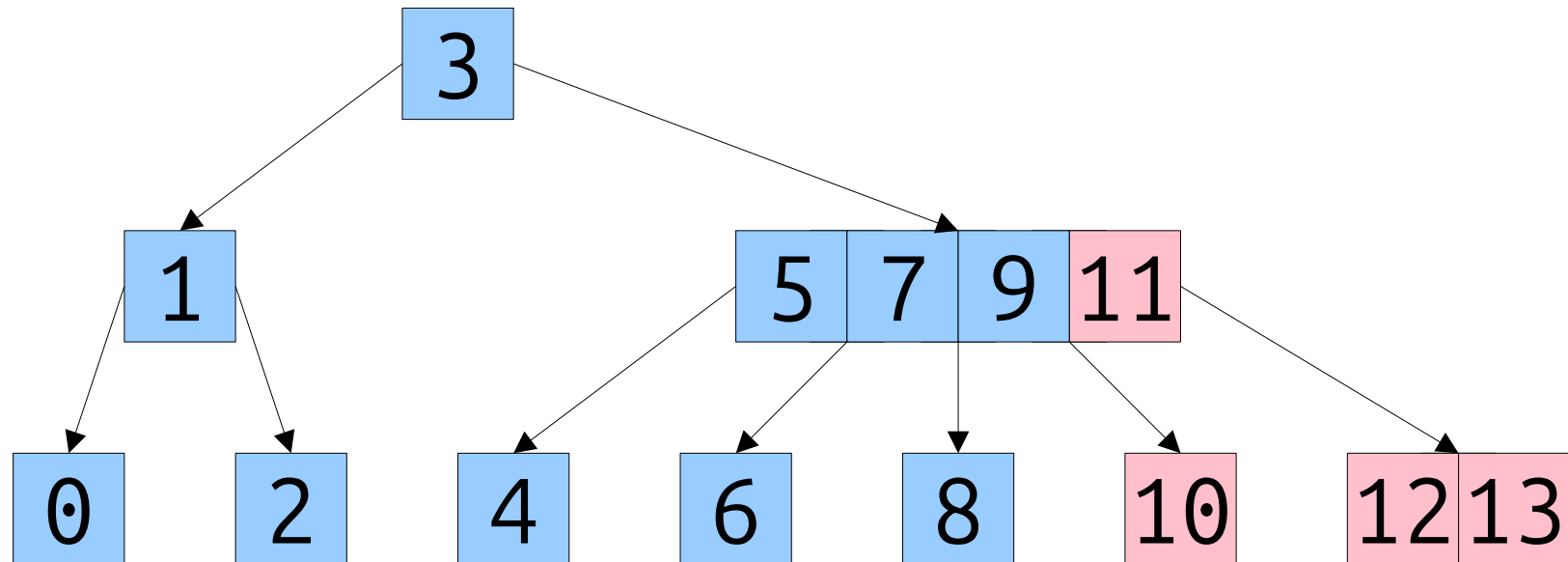
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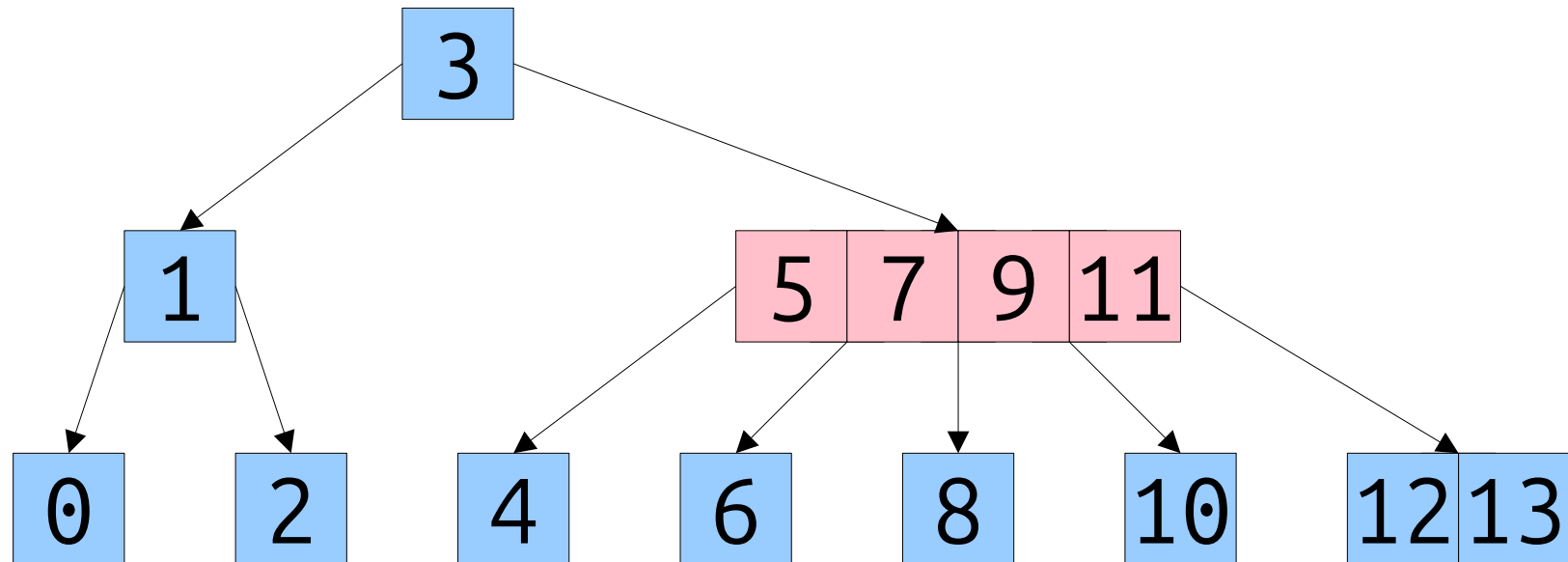
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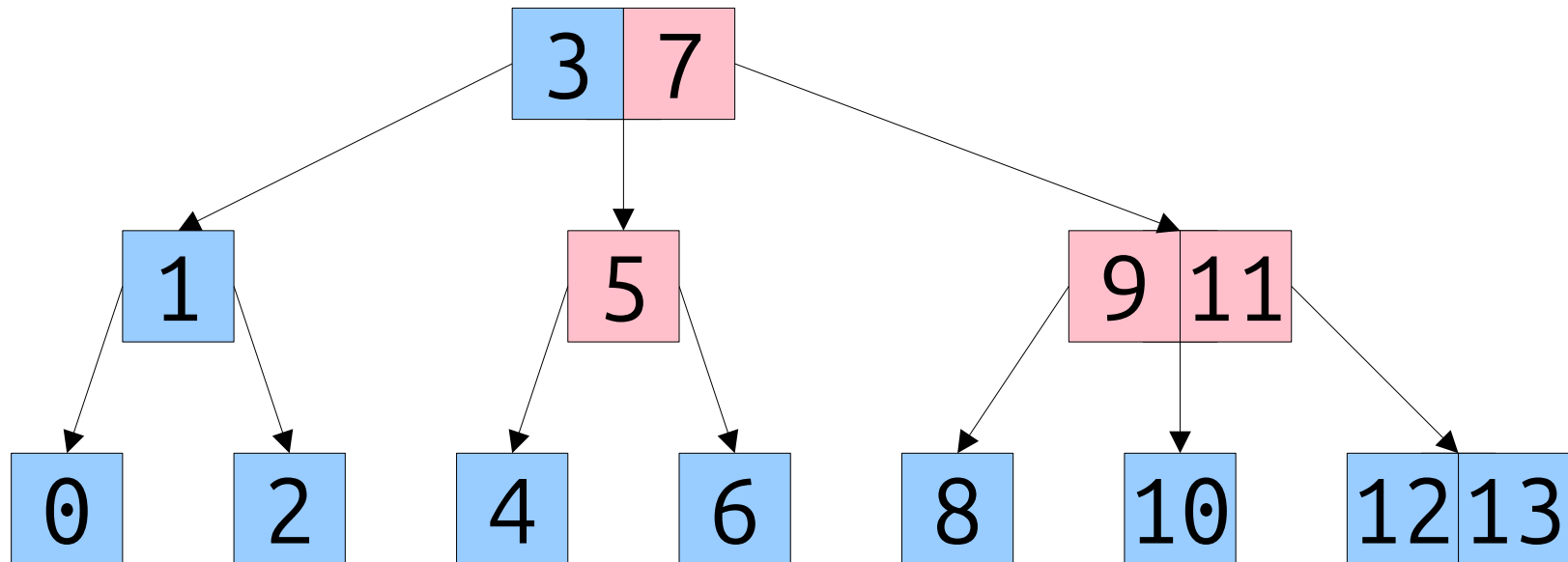
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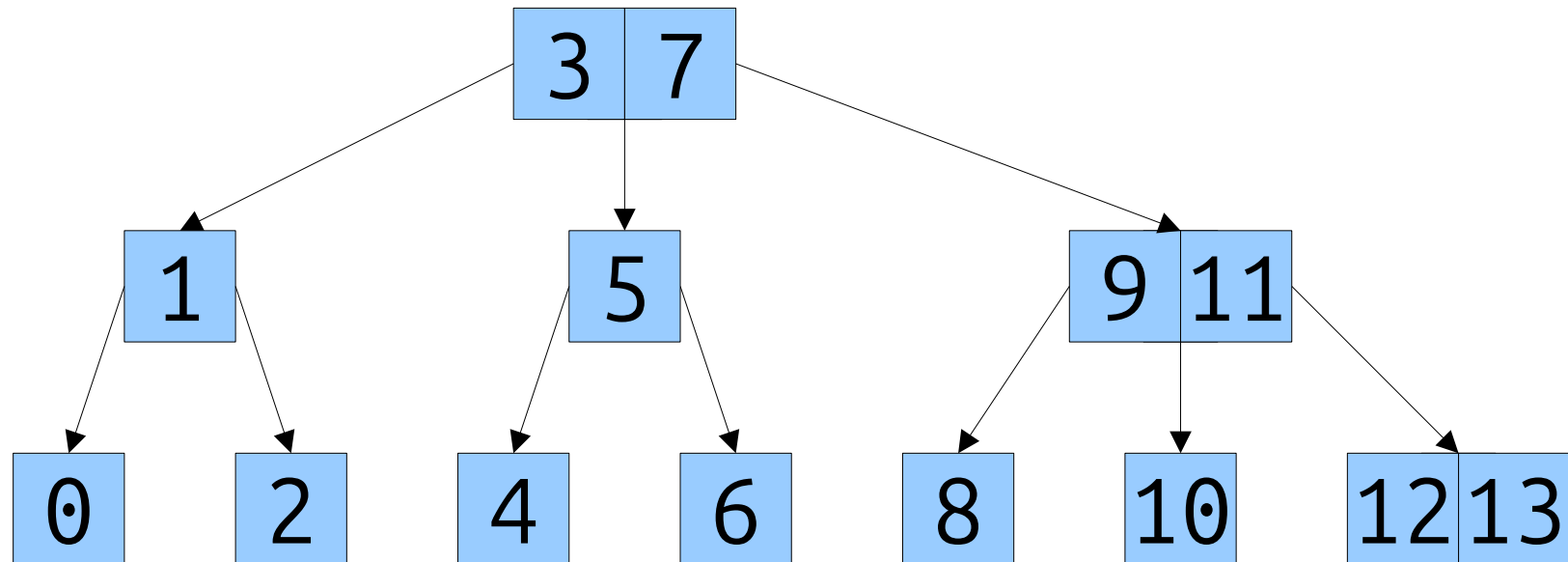
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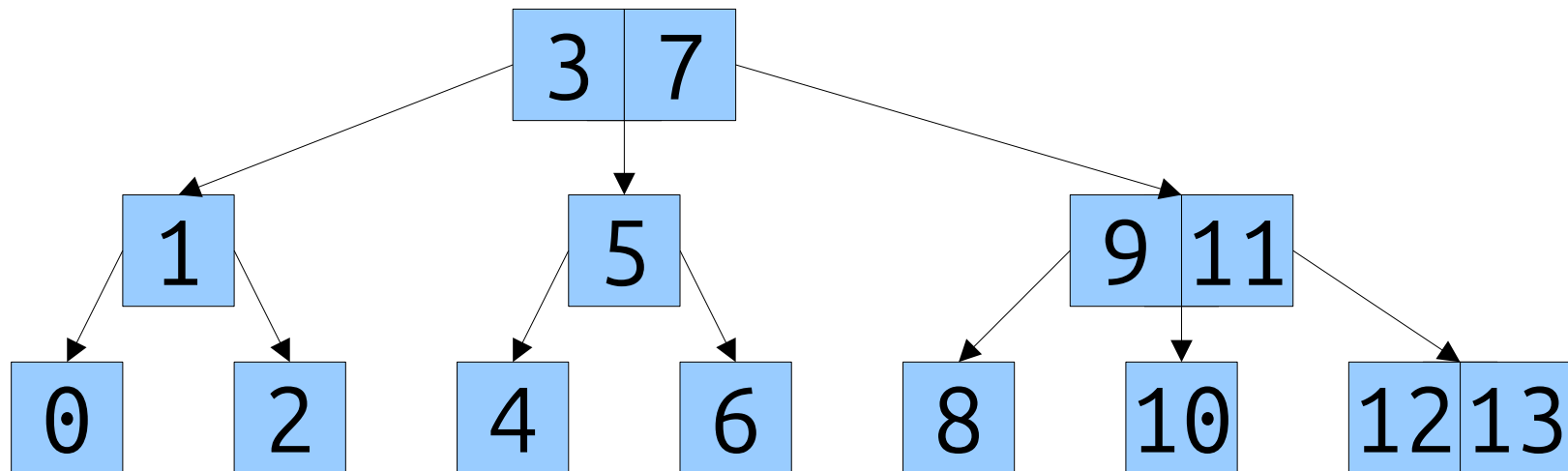
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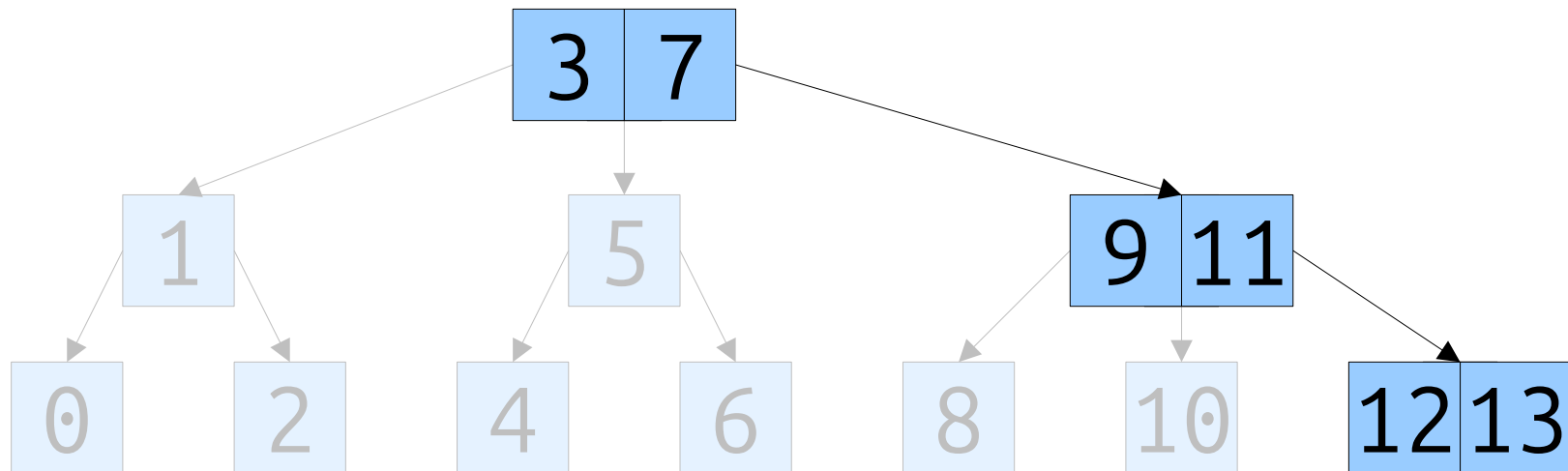
# Building B-Trees

- What is the actual cost of appending an element?
  - Suppose that we perform splits at  $L$  layers in the tree.
  - Each split takes time  $\Theta(b)$  to copy and move keys around.
  - Total cost:  $\Theta(bL)$ .
- **Goal:** Pick a potential function  $\Phi$  so that we can offset this cost and make each append cost amortized  $O(1)$ .



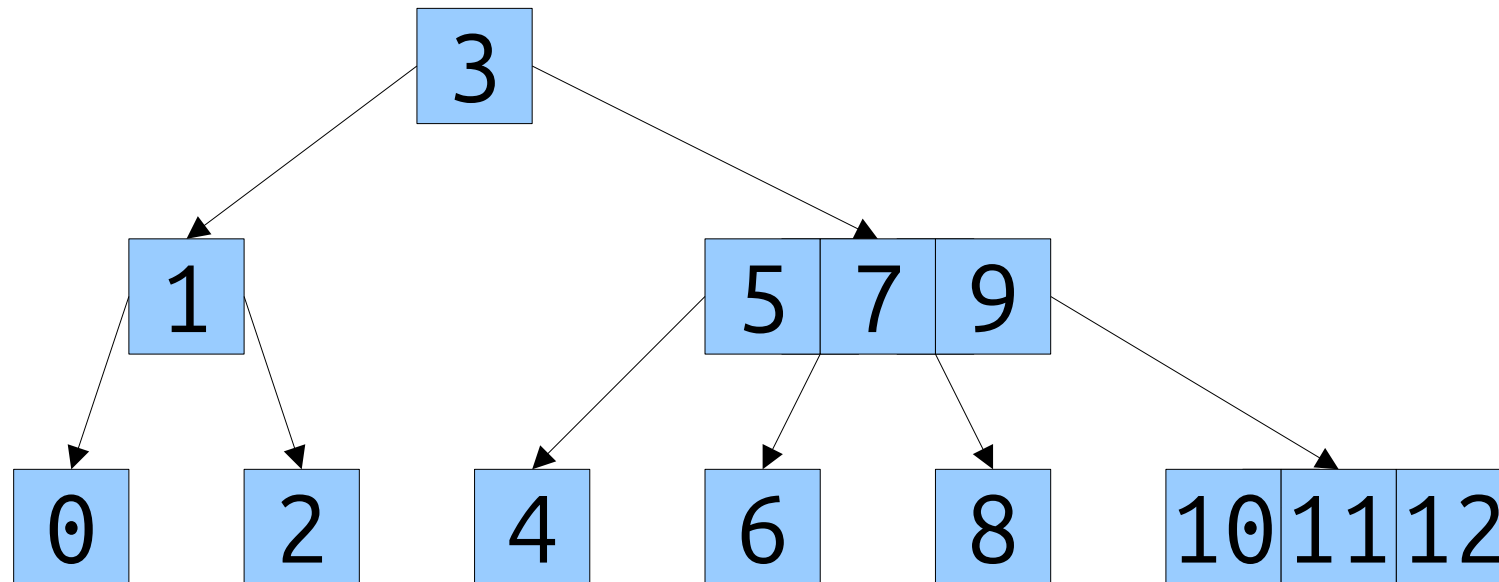
# Building B-Trees

- Our potential function should, intuitively, quantify how “messy” our data structure is.
- Some observations:
  - We only care about nodes in the right spine of the tree.
  - Nodes in the right spine slowly have keys added to them. When they split, they lose (about) half of their keys.
- **Idea:** Set  $\Phi$  to be the number of keys in the right spine of the tree.



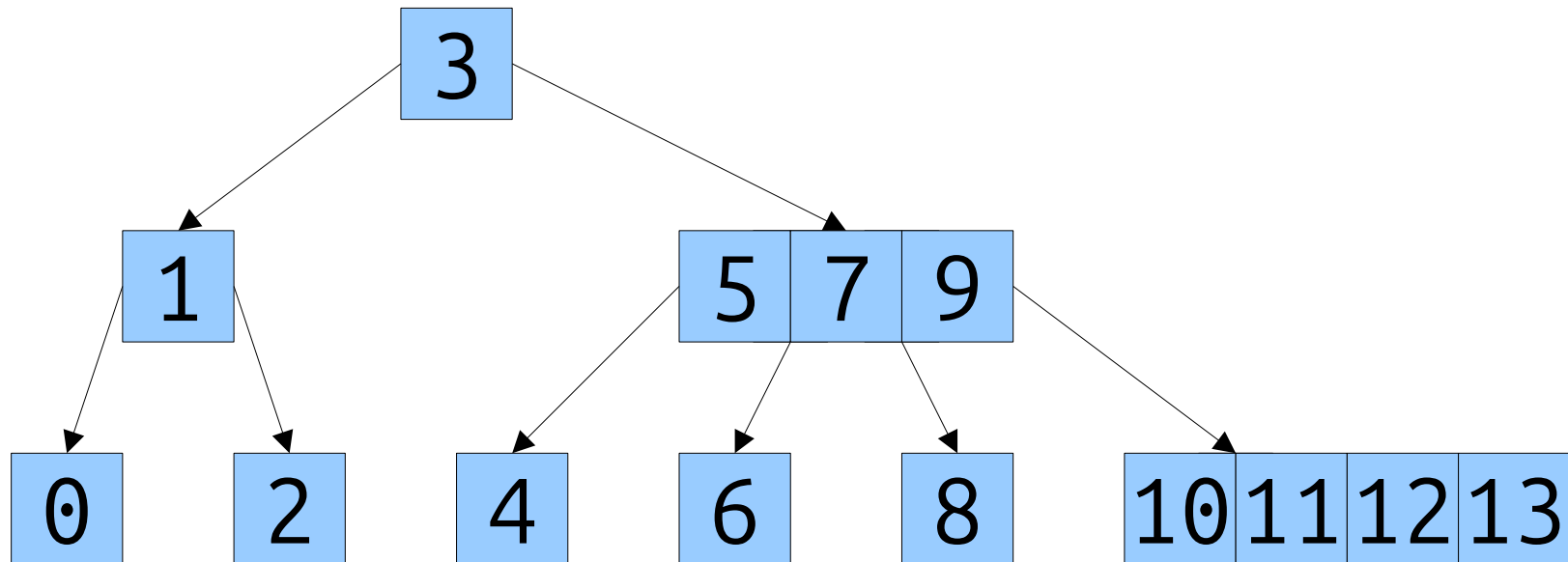
# Building B-Trees

- Let  $\Phi$  be the number of keys on the right spine.
- Each split moves (roughly) half the keys from the split node into a node off the right spine.



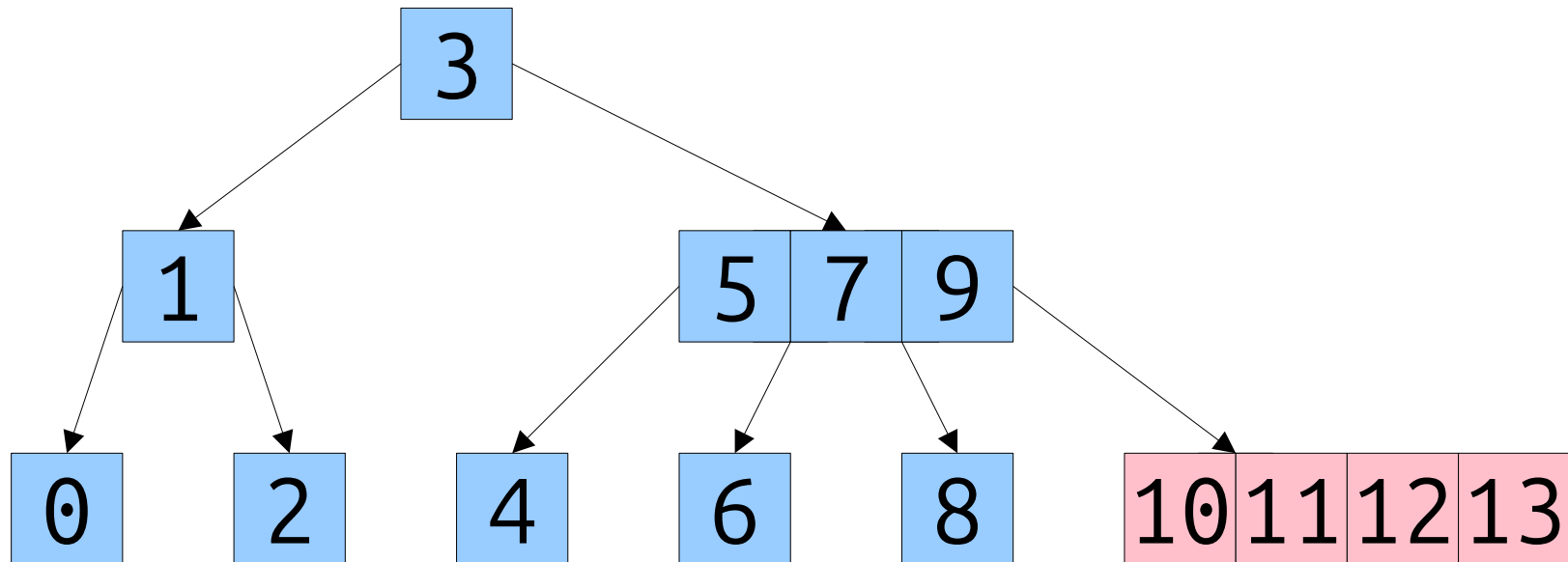
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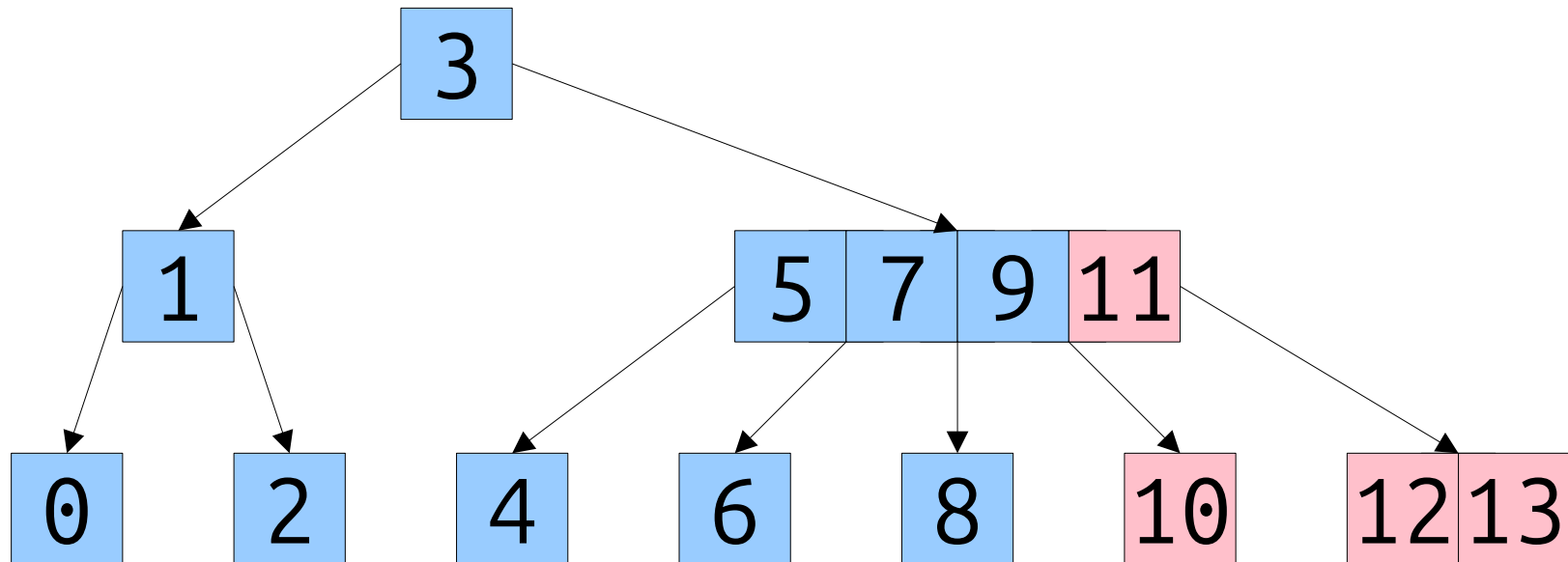
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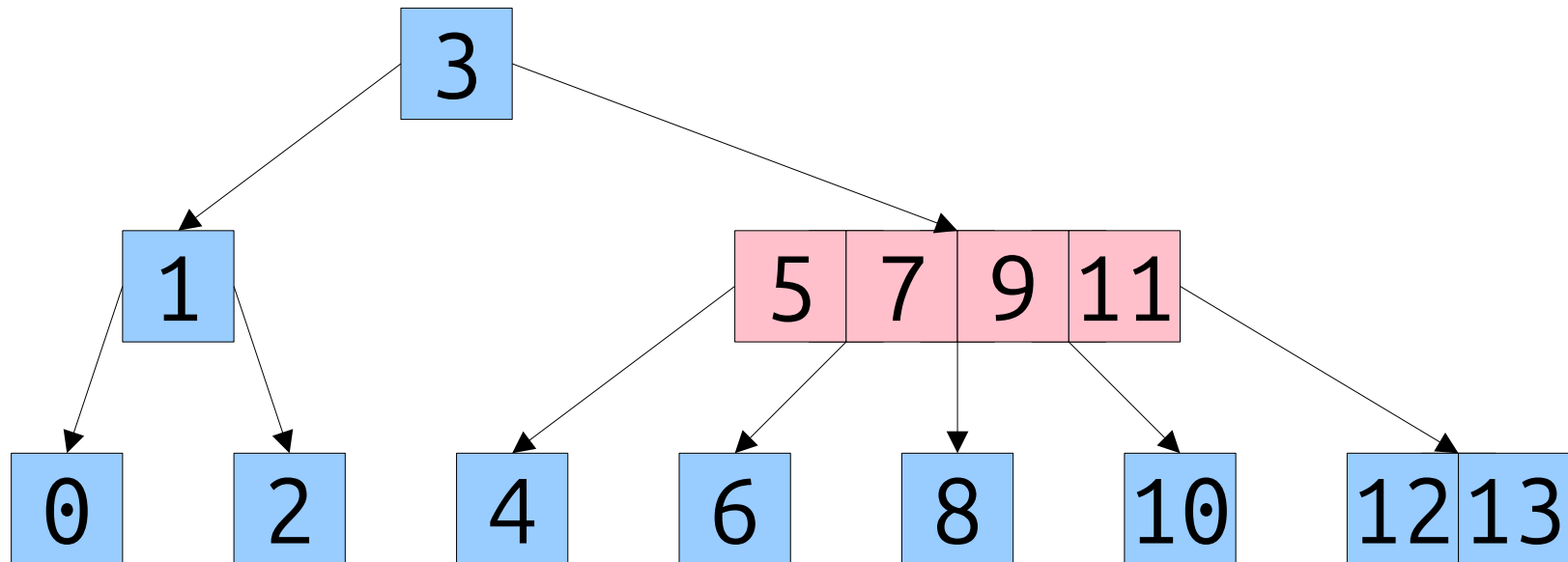
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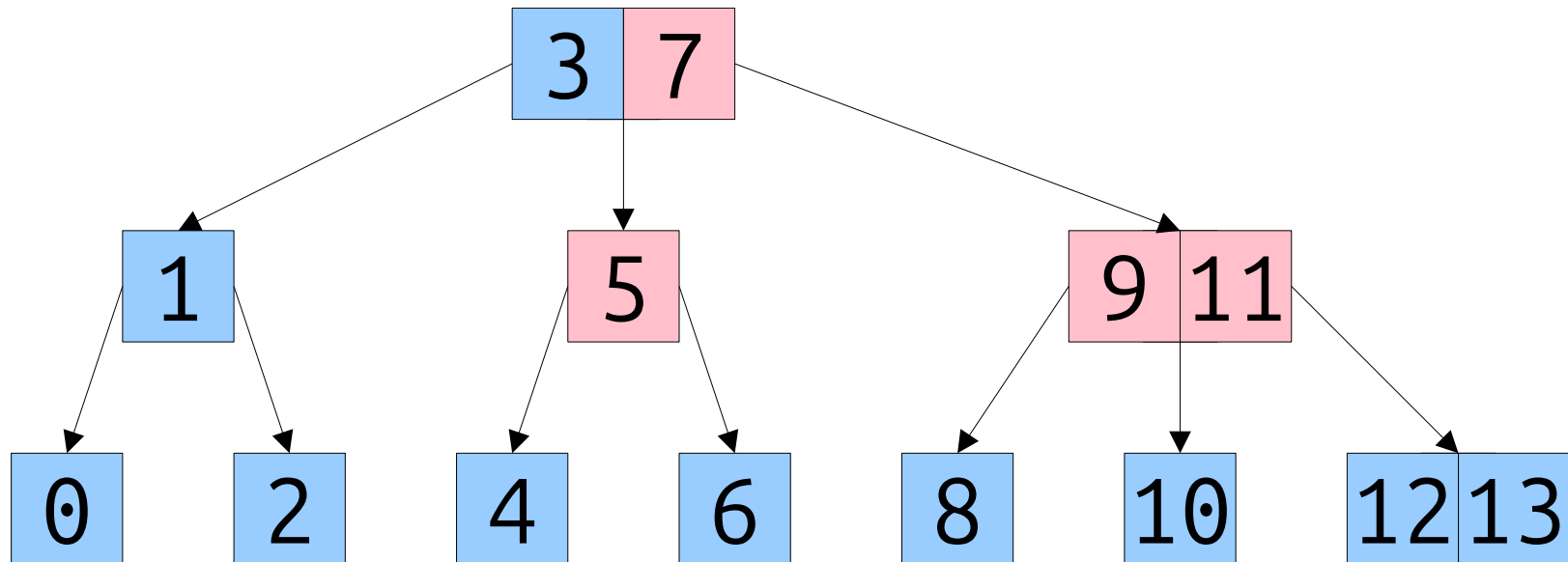
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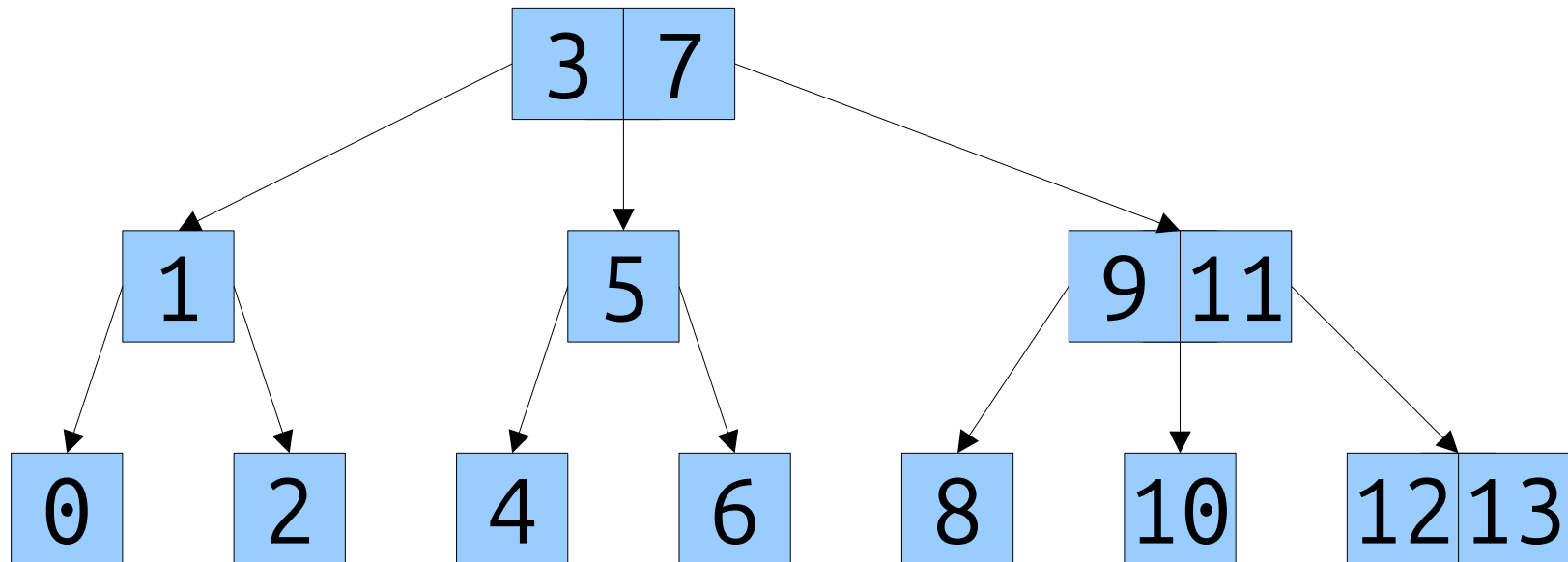
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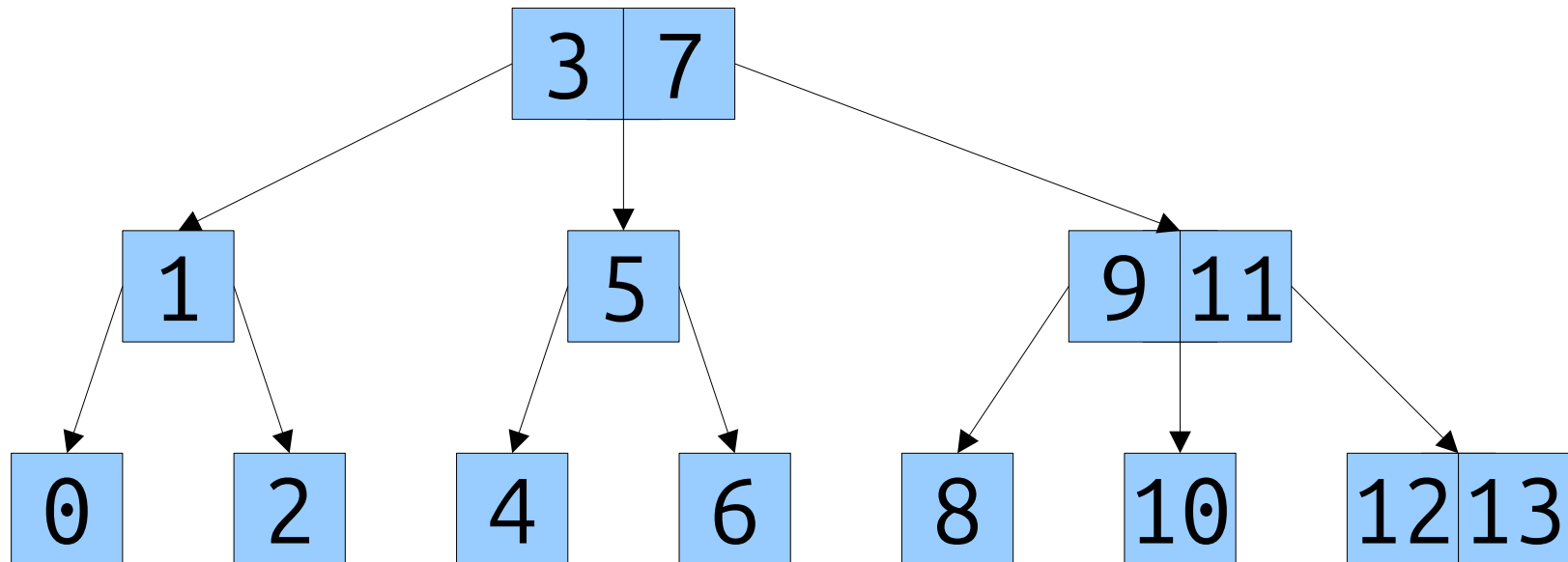
# Building B-Trees

- Let  $\Phi$  be the number of keys on the right spine.
- Each split moves (roughly) half the keys from the split node into a node off the right spine.
- Change in potential per split:  $-\Theta(b)$ .
- Net  $\Delta\Phi$ :  **$-\Theta(bL)$** .



# Building B-Trees

- Actual cost of an append that does  $L$  splits:  $O(bL)$ .
- $\Delta\Phi$  for that operation:  $-\Theta(bL)$ .
- Amortized cost:  **$O(1)$** .



**Theorem:** The amortized cost of appending to a B-tree by inserting it into the rightmost leaf node and applying fixup rules is  $O(1)$ .

**Proof:** Assume we are working with a B-tree of order  $b$ . Let  $\Phi$  be the number of nodes on the right spine of the B-tree.

Suppose we insert a value into the tree using the algorithm described above. Suppose this causes  $L$  nodes to be split. Each of those splits requires  $\Theta(b)$  work for a net total of  $\Theta(bL)$  work.

Each of those  $L$  splits moves  $\Theta(b)$  keys off of the right spine of the tree, decreasing  $\Phi$  by  $\Theta(b)$  for a net drop in potential of  $-\Theta(bL)$ . In the layer just above the last split, we add one more key into a node, increasing  $\Phi$  by one. Therefore,  $\Delta\Phi = -\Theta(bL)$ .

Overall, this tells us that the amortized cost of inserting a key this way is

$$\Theta(bL) + k \cdot \Delta\Phi = \Theta(bL) - k \cdot \Theta(bL),$$

which can be made to be  $O(1)$  by choosing  $k$  to equate the constants hidden in the  $O$  and  $\Theta$  terms. ■

# More to Explore

- You can implement a ***deque*** (a doubly-ended queue) using a B-tree with pointers to the first and last leaves.
  - This is called a ***finger tree***.
  - Finger trees are used extensively in purely functional programming languages.
  - By extending the analysis from here, you can show the amortized cost of appending or removing from each end of the finger tree is  $O(1)$ .
- Red/black trees are modeled on 2-3-4 trees. You can build a red/black tree from  $n$  sorted keys in time  $O(n)$  this way.
  - ***Great exercise:*** Explore how to do this, and work out what choice of  $\Phi$  to make.

To Summarize

# Amortized Analysis

- Some data structures accumulate messes slowly, then clean up those messes in single, large steps.
- We can assign ***amortized*** costs to operations. These are fake costs such that summing up the amortized costs never underestimates the sum of the real costs.
- To do so, we define a potential function  $\Phi$  that, intuitively, measures how “messy” the data structure is. We then set
$$\mathbf{amortized-cost = real-cost + k \cdot \Delta\Phi.}$$
- For simplicity, we assume that  $\Phi$  is nonnegative and that  $\Phi$  for an empty data structure is zero.

# Next Time

- ***Binomial Heaps***
  - A very clever way to build a priority queue.
- ***Lazy Binomial Heaps***
  - Designing for amortization.