An Extension of Datalog for Graph Queries

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- Motivations
- 2 Datalog^{FS}
- 3 Applications
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- 5 Conclusion and Future Work

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Motivation

• A resurgence of interest in Datalog in many research areas—in particular "Big Data".

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 $\mathsf{Datalog}^{\mathit{FS}}$

From Datalog to Datalog FS



 $\mathsf{Datalog}^{\mathit{FS}}$

Datalog

• A program P is a finite set of rules.

Datalog^{FS}

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- Reachability Example

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\begin{array}{ll} \text{path}(\mathtt{X},\mathtt{Y}) \leftarrow & \text{arc}(\mathtt{X},\mathtt{Y}) \\ \text{path}(\mathtt{X},\mathtt{Y}) \leftarrow & \text{path}(\mathtt{X},\mathtt{Z}), \text{path}(\mathtt{Z},\mathtt{Y}). \end{array}
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- and define a new type of predicates called Multi-Occuring Predicates.



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Frequency Support goal

- K: [Bexpr(X, Y)] where:
 - K is a positive integer variable and
 - Bexpr(X, Y) is a conjunction of positive literals with variables X and Y.

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- Example about friends that will come to the party.

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\label{eq:willcome} \begin{split} \text{willcome}(X) &\leftarrow & \text{sure}(X). \\ \text{willcome}(X) &\leftarrow & 3 \colon [\text{friend}(X,Y), \text{willcome}(Y)]. \end{split}
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Semantics by using FS-goal and Negation:

$$\mathtt{K}: [\mathtt{Bexpr}(\mathtt{X}, \mathtt{Y})], \neg \mathtt{K} + \mathtt{1}: [\mathtt{Bexpr}(\mathtt{X}, \mathtt{Y})].$$

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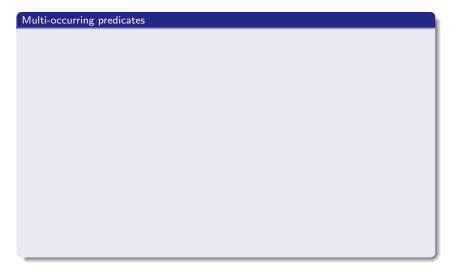
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Final-FS goal

- K =![Bexpr(X,Y)]
- Example about person that has exactly 10 friends: p(X) ← 10 =![friend(X, Y)].
- Semantics by using FS-goal and Negation:

$$K : [Bexpr(X,Y)], \neg K + 1 : [Bexpr(X,Y)].$$

• It is not monotone and requires stratified negation.



Multi-occurring predicates

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Rule example

```
 \begin{split} & \texttt{ref("Bob2012")} : 6. \\ & \texttt{tref(Author)} : \texttt{N} \leftarrow & \texttt{N} : [\texttt{author(Author, Pno)}, \texttt{ref(Pno)}]. \end{split}
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$$total_ref(A) = \sum_{Pno \in paper(A)} reference(Pno)$$

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Semantics by using Datalog.

```
\begin{split} & \texttt{ref("Bob2012", J)} \leftarrow & \texttt{lessthan(J, 6)}. \\ & \texttt{tref(Author, N)} \leftarrow & \texttt{N}: [\texttt{author(Author, Pno)}, \texttt{ref(Pno, J)}]. \end{split}
```

```
\begin{split} \text{lesstham}(\textbf{1},\textbf{K}) \leftarrow & \quad \textbf{K} \geq \textbf{1}. \\ \text{lesstham}(\textbf{J}\textbf{1},\textbf{K}) \leftarrow & \quad \text{lesstham}(\textbf{J},\textbf{K}), \textbf{K} > \textbf{J}, \textbf{J}\textbf{1} = \textbf{J} + \textbf{1}. \end{split}
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Datalog^{FS}

Applications

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Example

Number of paths between two nodes in a Direct Acyclic Graph (DAG).

$$\begin{array}{lll} \mathtt{path}(\mathtt{X},\mathtt{Y}) : \mathtt{1} \leftarrow & \mathtt{edge}(\mathtt{X},\mathtt{Y}) \\ \mathtt{path}(\mathtt{X},\mathtt{Y}) : \mathtt{K} \leftarrow & \mathtt{K} \colon [\mathtt{path}(\mathtt{X},\mathtt{Z}),\mathtt{path}(\mathtt{Z},\mathtt{Y})]. \end{array}$$

Example

$$n_path(X,Y) = \sum_{Z \neq X,Y} n_path(X,Z) \times n_path(Z,Y)$$

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Example

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Reachability in a directed hyper graph.
```

A hyperedge $(\{a,b\},c)$ is represented by the following facts:

```
\begin{array}{cccc} \text{hedgeS}(1,a). & \text{hedgeS}(1,b). & \text{hedgeT}(1,c). \\ & \text{node}(a). & \text{node}(b). & \text{node}(c). \end{array}
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```
S(1,a). hedgeS(1,b). hedgeT(1,c) node(a). node(b). node(c).
```

```
\begin{split} \texttt{reach}(\texttt{X}, \texttt{X}) \leftarrow & \texttt{node}(\texttt{X}). \\ \texttt{reach}(\texttt{X}, \texttt{Y}) \leftarrow & \texttt{K} : [\texttt{hedgeS}(\texttt{ID}, \texttt{Z}), \texttt{reach}(\texttt{X}, \texttt{Z})], \\ & \texttt{hedgeT}(\texttt{ID}, \texttt{Y}), \texttt{K} = ! [\texttt{hedgeS}(\texttt{ID}, \_)]. \end{split}
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Bill of Material

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- Path of minimum and maximum cost (more probable path)

Example

Number of paths between two nodes in a Direct Acyclic Graph (DAG).

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path(X,Y): 1 \leftarrow edge(X,Y)

path(X,Y): K \leftarrow K: [path(X,Z), path(Z,Y)].
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- Bill of Material
- Path of minimum and maximum cost (more probable path)
- Dynamic Programming (Knapsak, Viterbi, ...)

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- a constant *bc* to denote how much an agent is susceptible to make a change.
- a function g denoting how much the number of neighbors influence the change.
- the percentage of neighbors that changed behavior.

```
coeff(X,C) \leftarrow K2 = ![followd(Y,X)], bc(X,V1),
                            g(K2, V3), C = V1 * V3/K2.
          b(X) \leftarrow source(X).
          b(X) \leftarrow coeff(X,C), K \ge 1/C, K : [followd(Y,X), b(Y)].
              u4
  followd
                   followy
                                  follwd(u_1, u_2). bc(u_1, 1). g(1, 1.2).
                                  follwd(u_1, u_3). bc(u_2, 0.9). g(2, 2.3).
u2
                             u3
                                  follwd(u_2, u_4). bc(u_3, 0.5).
      followd
                 followd
                                  follwd(u_3, u_4). bc(u_4, 1).
                                  source(u_1).
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                                  source(u_1).
```

the program derives the following atoms:

```
\begin{array}{lll} \text{coeff}(u_2,1.08), & \text{coeff}(u_3,0.6), & \text{coeff}(u_4,1.15), \\ b(u_1), & b(u_2), & b(u_4). \end{array}
```

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- Given P a vector of stabilized probabilities of cardinality s then for each component we have:

$$p_i = \sum_{j=1}^s w_{ji} \cdot p_j$$

this is the equilibrium condition expressed by the fixpoint equation:

$$P = W \cdot P$$

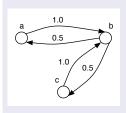
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Used for Page Rank.

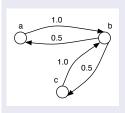


 $p_st(X): K \leftarrow K: [p_st(Y), w_mat(Y, X)].$

w_mat(a, b): 1.0.
w_mat(b, a): 0.5.
w_mat(b, c): 0.5.
w_mat(c, b): 1.0.
p_st(a). p_st(b). p_st(c).

where:

virci C.

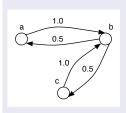


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w_mat(b, a): 0.5.
```

w_mat(b, a): 0.5.
w_mat(b, c): 0.5.
w_mat(c, b): 1.0.
p_st(a). p_st(b). p_st(c).

where:

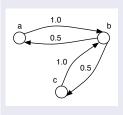
• p_st(X) : K means the probability of staying in state X is K



```
\begin{array}{lll} p\_st(X): K \leftarrow & \text{$K:$ [p\_st(Y), w\_mat(Y, X)]$.} \\ w\_mat(a,b): 1.0. \\ w\_mat(b,a): 0.5. \\ w\_mat(b,c): 0.5. \\ w\_mat(c,b): 1.0. \\ p\_st(a). & p\_st(b). & p\_st(c). \\ \end{array}
```

where:

- p_st(X): K means the probability of staying in state X is K
- w_mat(Y, X): W means the arc from Y to X has weight W



```
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```

where:

- p_st(X): K means the probability of staying in state X is K
- w_mat(Y, X): W means the arc from Y to X has weight W

 $p_st(a): 0.25. p_st(b): 0.5. p_st(c): 0.25.$

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 - Differential Fixpoint.
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- Final-FS goal: its semantics is defined by using the negation.
 The stratified fixpoint for programs with stratified negation is used.
- Multiplicity predicate: we only store the maximum value of multiplicity.

Conclusion and Future Work

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We proposed a simple extension of Datalog, called Datalog^{FS}, with two new constructs (FS goal and Final-FS goal) and a new type of predicate (Multiplicity predicate).

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- Recent works show how it is possible to use parallel paradigms (Map Reduce) to improve Datalog's performances.
 - Datalog^{FS} and in particular the multiplicity predicates can be also combined with such technologies.

Conclusion and Future Work 18/20

Thank you! Any question?

Compact way

Compact way of expressing counting goals:

• in Datalog^{FS}

$$sixsubs(X) \leftarrow detective(X), 6 : [superior(X, Y)].$$

• in Datalog

```
\begin{array}{ll} {\tt sixsubs(X)} \leftarrow & {\tt detective(X), superior(X, Y1),} \\ & {\tt superior(X, Y2), superior(X, Y3),} \\ & {\tt superior(X, Y4), superior(X, Y5),} \\ & {\tt superior(X, Y6), Y1 \neq Y2, Y1 \neq Y3,} \\ & {\tt Y1 \neq Y4, Y1 \neq Y5, Y1 \neq Y6, Y2 \neq Y3,} \\ & {\tt Y2 \neq Y4, Y2 \neq Y5, Y2 \neq Y6, Y3 \neq Y4,} \\ & {\tt Y3 \neq Y5, Y3 \neq Y6, Y4 \neq Y5, Y4 \neq Y6,} \\ & {\tt Y5 \neq Y6.} \end{array}
```