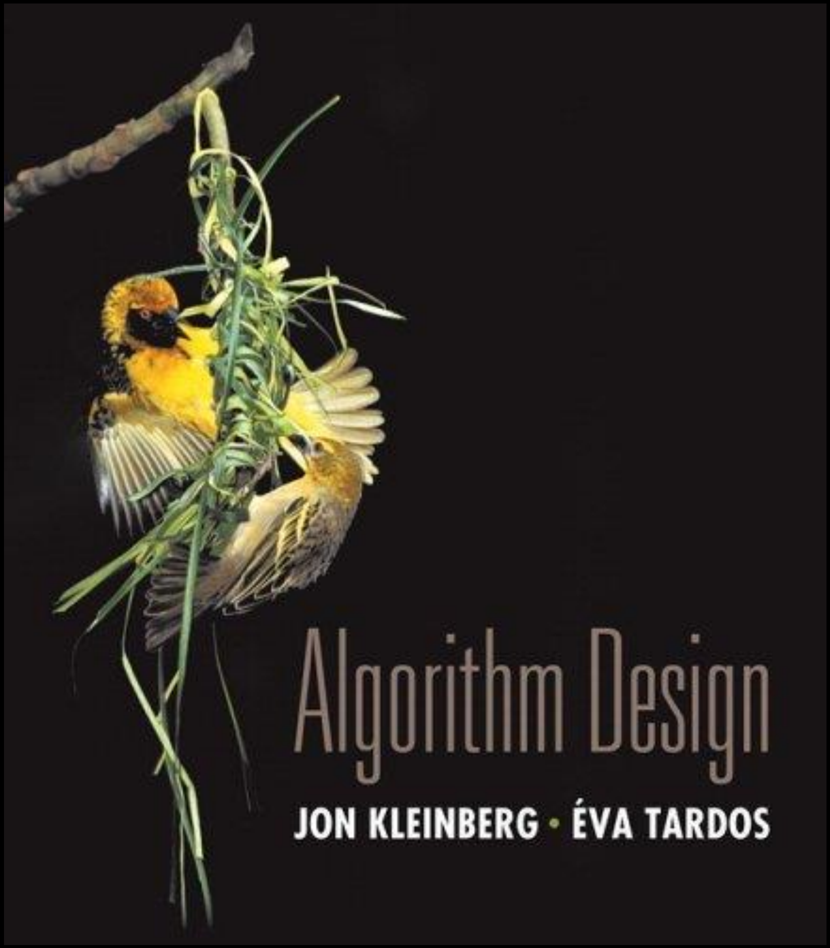


Chapter 9

PSPACE: A Class of Problems Beyond NP

Slides by Kevin Wayne.

Geography Game

Geography. Amy names capital city c of country she is in. Bob names a capital city c' that starts with the letter on which c ends. Amy and Bob repeat this game until one player is unable to continue. Does Amy have a forced win?

Ex. Budapest → Tokyo → Ottawa → Ankara → Amsterdam → Moscow → Washington → Nairobi → …

Geography on graphs. Given a directed graph $G = (V, E)$ and a start node s, two players alternate turns by following, if possible, an edge out of the current node to an unvisited node. Can first player guarantee to make the last legal move?

Remark. Some problems (especially involving 2-player games and AI) defy classification according to P, NP, and NP-complete.

9.1 PSPACE

PSPACE

P. Decision problems solvable in polynomial time.

PSPACE. Decision problems solvable in polynomial space.

Observation. P $\subseteq$ PSPACE.

poly-time algorithm can consume only polynomial space

PSPACE

Claim. 3-SAT is in PSAPCE.

Pf.

- Enumerate all 2^n possible truth assignments.
- Check each assignment to see if it satisfies all clauses. ▪

Theorem. NP $\subseteq$ PSPACE.

Pf. Consider arbitrary problem Y in NP.

- Since Y $\leq_P$ 3-SAT, there exists algorithm that solves Y in poly-time plus polynomial number of calls to 3-SAT black box.
- Can implement black box in poly-space. ▪

9.3 Quantified Satisfiability

Quantified Satisfiability

QSAT (Quantified 3-SAT). Let $\Phi(x_1, \ldots, x_n)$ be a Boolean CNF formula. Is the following propositional formula true?

$$\exists x_1 \; \forall x_2 \; \exists x_3 \; \forall x_4 \ldots \; \forall x_{n-1} \; \exists x_n \; \Phi(x_1, \ldots, x_n)$$

assume n is odd

Intuition. Amy picks truth value for x_1, then Bob for x_2, then Amy for x_3, and so on. Can Amy satisfy Φ no matter what Bob does?

Ex. $(x_1 \vee x_2) \wedge (x_2 \vee \overline{x_3}) \wedge (\overline{x_1} \vee \overline{x_2} \vee x_3)$

Yes. Amy sets x_1 true; Bob sets x_2; Amy sets x_3 to be same as x_2.

Ex. $(x_1 \vee x_2) \wedge (\overline{x_2} \vee \overline{x_3}) \wedge (\overline{x_1} \vee \overline{x_2} \vee x_3)$

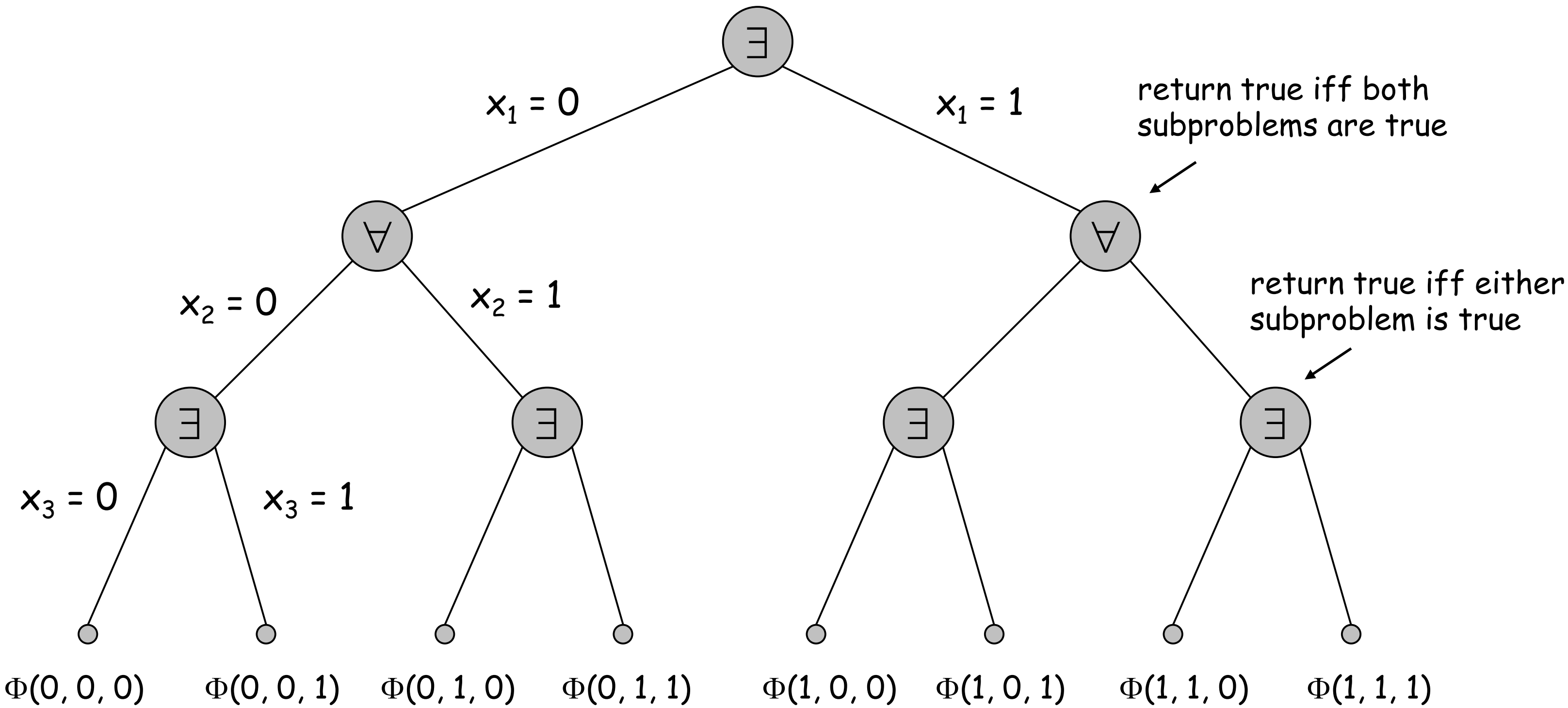
No. If Amy sets x_1 false; Bob sets x_2 false; Amy loses;
if Amy sets x_1 true; Bob sets x_2 true; Amy loses.

QSAT is in PSPACE

Theorem. QSAT $\in$ PSAPCE.

Pf. Recursively try all possibilities.

- Only need one bit of information from each subproblem.
- Amount of space is proportional to depth of function call stack.

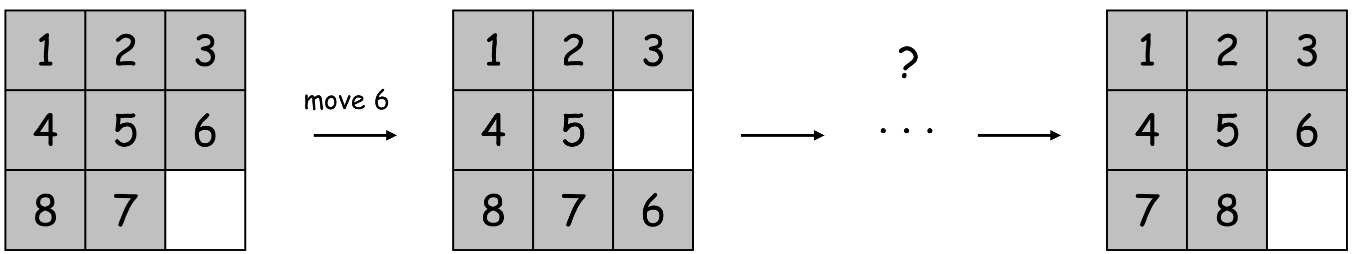


9.4 Planning Problem

15-Puzzle

8-puzzle, 15-puzzle. [Sam Loyd 1870s]

- Board: 3-by-3 grid of tiles labeled 1-8.
- Legal move: slide neighboring tile into blank (white) square.
- Find sequence of legal moves to transform initial configuration into goal configuration.



initial configuration

goal configuration

Planning Problem

Conditions. Set $C = \{ C_1, \ldots, C_n \}$.
Initial configuration. Subset $c_0 \subseteq C$ of conditions initially satisfied.
Goal configuration. Subset $c^* \subseteq C$ of conditions we seek to satisfy.
Operators. Set $O = \{ O_1, \ldots, O_k \}$.

- To invoke operator O_i, must satisfy certain prereq conditions.
- After invoking O_i certain conditions become true, and certain conditions become false.

PLANNING. Is it possible to apply sequence of operators to get from initial configuration to goal configuration?

Examples.

- 15-puzzle.
- Rubik's cube.
- Logistical operations to move people, equipment, and materials.

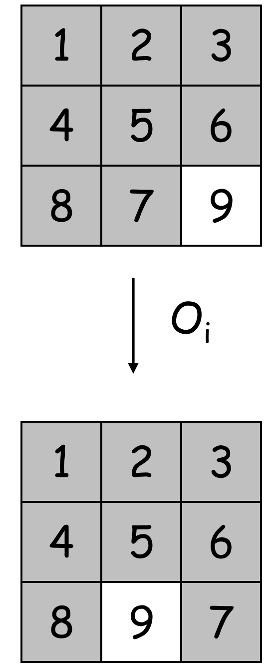
Planning Problem: 8-Puzzle

Planning example. Can we solve the 8-puzzle?

Conditions. C_{ij}, $1 \le i, j \le 9$. ← C_{ij} means tile i is in square j

Initial state. $c_0 = \{C_{11}, C_{22}, \ldots, C_{66}, C_{78}, C_{87}, C_{99}\}$.

Goal state. $c^* = \{C_{11}, C_{22}, \ldots, C_{66}, C_{77}, C_{88}, C_{99}\}$.



Operators.

- Precondition to apply $O_i = \{C_{78}, C_{99}\}$.
- After invoking O_i, conditions C_{79} and C_{98} become true.
- After invoking O_i, conditions C_{78} and C_{99} become false.

(This is the most straightforward cast of 8-puzzle to planning, though better cast exists.)

Planning Problem: In Exponential Time

Configuration graph G.

- Include node for each of 2^n possible configurations.
- Include an edge from configuration c' to configuration c'' if one of the operators can convert from c' to c''.

PLANNING. Is there a path from c_0 to c^* in configuration graph?

Claim. PLANNING is in EXPTIME.

Pf. Run BFS to find path from c_0 to c^* in configuration graph. ▪

Note. Configuration graph can have 2^n nodes, and shortest path can be of length = $2^n - 1$.

Planning Problem: In Polynomial Space

Theorem. PLANNING is in PSPACE.

Pf.

- Suppose there is a path from c_1 to c_2 of length $\leq L$.
- Path from c_1 to midpoint and from midpoint to c_2 are each $\leq L/2$.
- Enumerate all possible midpoints.
- Apply recursively. Depth of recursion = $\log_2 L$. ▪

```
boolean hasPath(c1, c2, L) {
   if (L = 1) return correct answer

   foreach configuration c' {
      boolean x = hasPath(c1, c', ⌈L/2⌉)
      boolean y = hasPath(c', c2, ⌊L/2⌋)
      if (x and y) return true
   }
   return false
}
```

9.5 PSPACE-Complete

PSPACE-Complete

PSPACE. Decision problems solvable in polynomial space.

PSPACE-Complete. Problem Y is PSPACE-complete if (i) Y is in PSPACE and (ii) for every problem X in PSPACE, $X \leq_P Y$.

Theorem. [Stockmeyer-Meyer 1973] QSAT is PSPACE-complete.

Theorem. PSPACE $\subseteq$ EXPTIME.
Pf. Previous algorithm solves QSAT in exponential time, and QSAT is PSPACE-complete. ▪

Summary. P $\subseteq$ NP $\subseteq$ PSPACE $\subseteq$ EXPTIME.

it is known that P $\neq$ EXPTIME, but unknown which inclusion is strict;
conjectured that all are

PSPACE-Complete Problems

More PSPACE-complete problems.

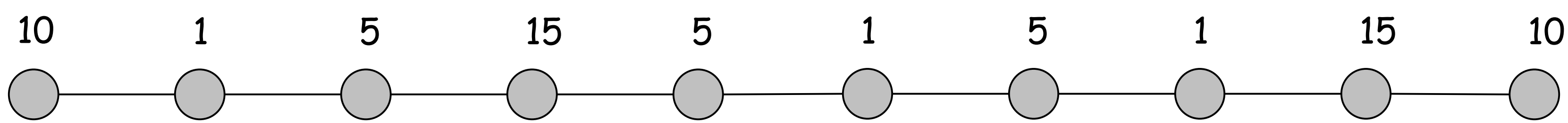
- Competitive facility location.
- Natural generalizations of games.
  - Othello, Hex, Geography, Rush-Hour, Instant Insanity
  - Shanghai, go-moku, Sokoban
- Given a memory restricted Turing machine, does it terminate in at most k steps?
- Do two regular expressions describe different languages?
- Is it possible to move and rotate complicated object with attachments through an irregularly shaped corridor?
- Is a deadlock state possible within a system of communicating processors?

Competitive Facility Location

Input. Graph with positive node weights, and target number B.
Game. Two competing players alternate in selecting nodes. Not allowed to select a node if any of its neighbors has been selected.

Competitive facility location. Can second player guarantee at least B units of profit?

(In general, the graph may not be a chain.)



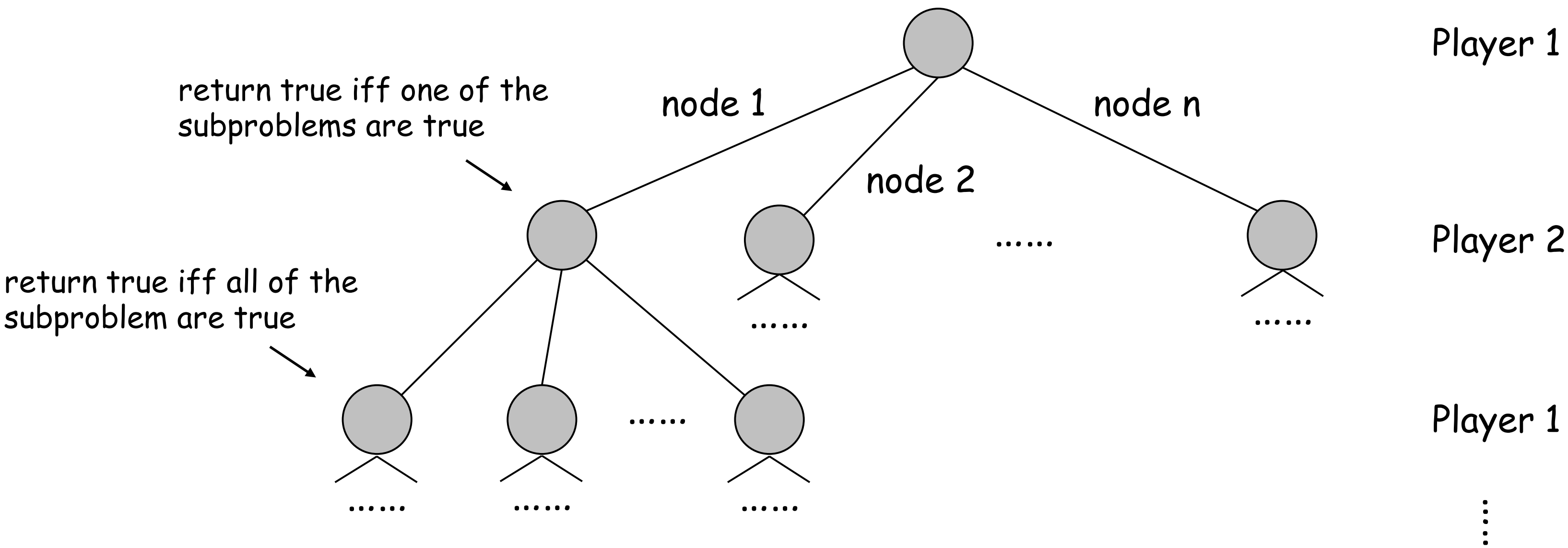
Yes if B = 20; no if B = 25.

Competitive Facility Location

Claim. COMPETITIVE-FACILITY is PSPACE-complete.

Pf.

- To solve it in poly-space, use recursion like QSAT, but at each step there are up to n choices instead of 2.



Competitive Facility Location

Claim. COMPETITIVE-FACILITY is PSPACE-complete.

Pf.

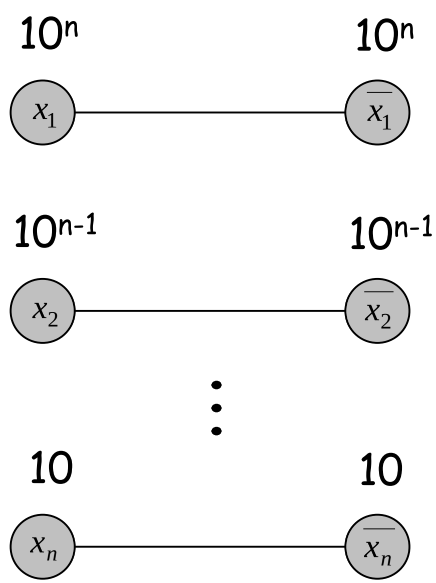
- To show that it's complete, we show that QSAT polynomial reduces to it. Given an instance of QSAT, we construct an instance of COMPETITIVE-FACILITY such that player 2 can force a win iff QSAT formula is false.

Competitive Facility Location

assume n is odd

Construction. Given instance $\Phi(x_1, \ldots, x_n) = C_1 \wedge C_2 \wedge \ldots C_k$ of QSAT.

- Include a node for each literal and its negation and connect them.
  - at most one of x_i and its negation can be chosen
- Choose a large constant c (e.g., $c \geq k+2$), and put weight c^{n-i+1} on literal x_i and its negation;
  set $B = c^{n-1} + c^{n-3} + \ldots + c^4 + c^2 + 1$.
  - This ensures variables are selected in order $x_1, x_2, \ldots, x_n$.
- As is, player 2 will lose by 1 unit: $c^{n-1} + c^{n-3} + \ldots + c^4 + c^2$.

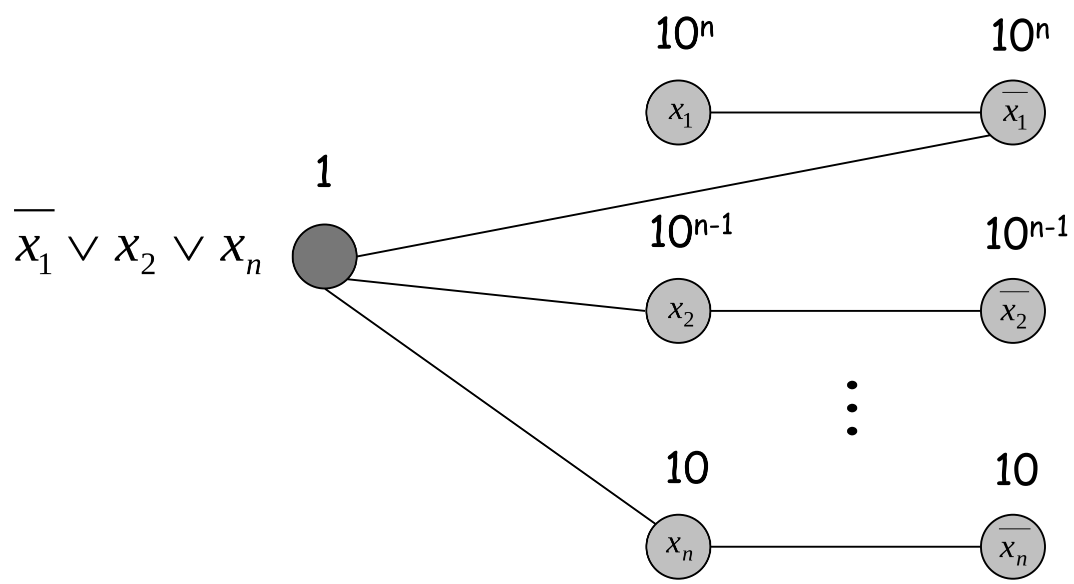


Competitive Facility Location

Construction. Given instance $\Phi(x_1, \ldots, x_n) = C_1 \wedge C_2 \wedge \ldots C_k$ of QSAT.

- Give player 2 one last move on which she can try to win.
- For each clause C_j, add node with value 1 and an edge to each of its literals.
- Player 2 can make last move iff truth assignment defined alternately by the players failed to satisfy some clause, i.e.,

$$\forall x_1\ \exists x_2\ \forall x_3\ \exists x_4 \ldots \exists x_{n-1}\ \forall x_n\ \neg\Phi(x_1, \ldots, x_n)$$
$$\Leftrightarrow\ \neg\ \exists x_1\ \forall x_2\ \exists x_3\ \forall x_4 \ldots\ \forall x_{n-1}\ \exists x_n\ \Phi(x_1, \ldots, x_n)$$



Chapter Summary

PSPACE

PSPACE. Decision problems solvable in polynomial space.

PSPACE problems

- QSAT
- Planning

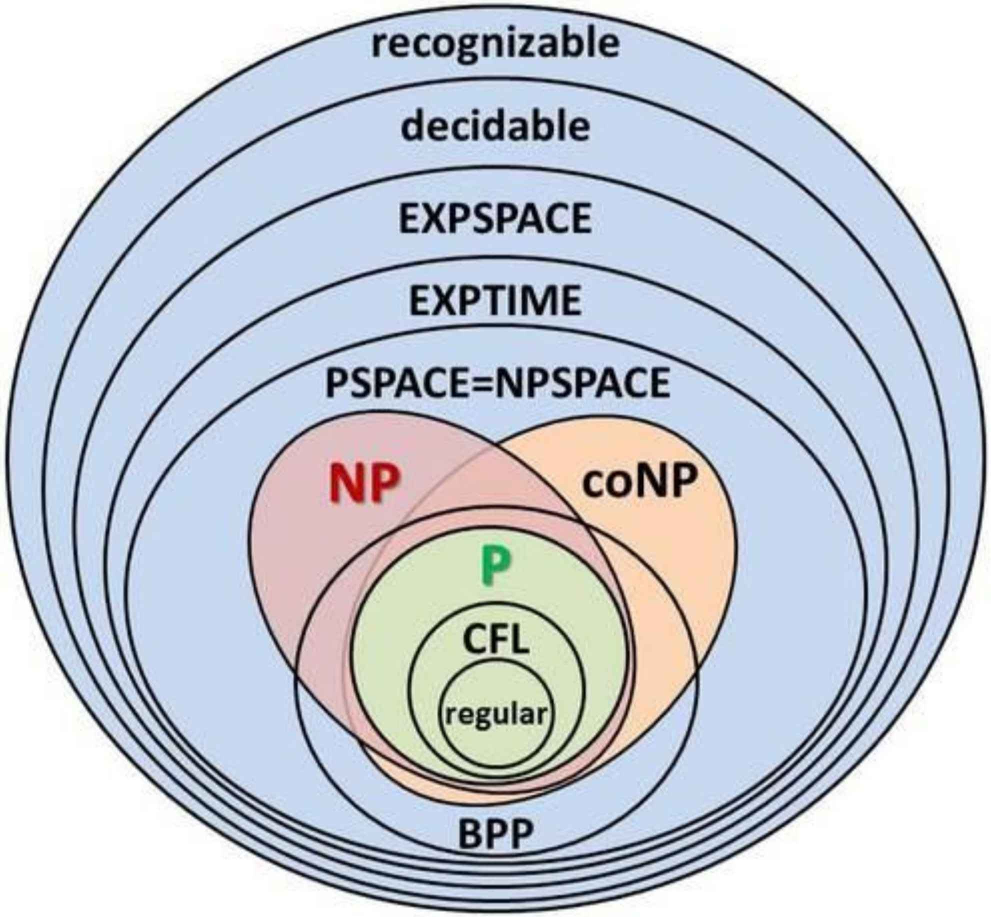
Theorem. NP $\subseteq$ PSPACE $\subseteq$ EXPTIME

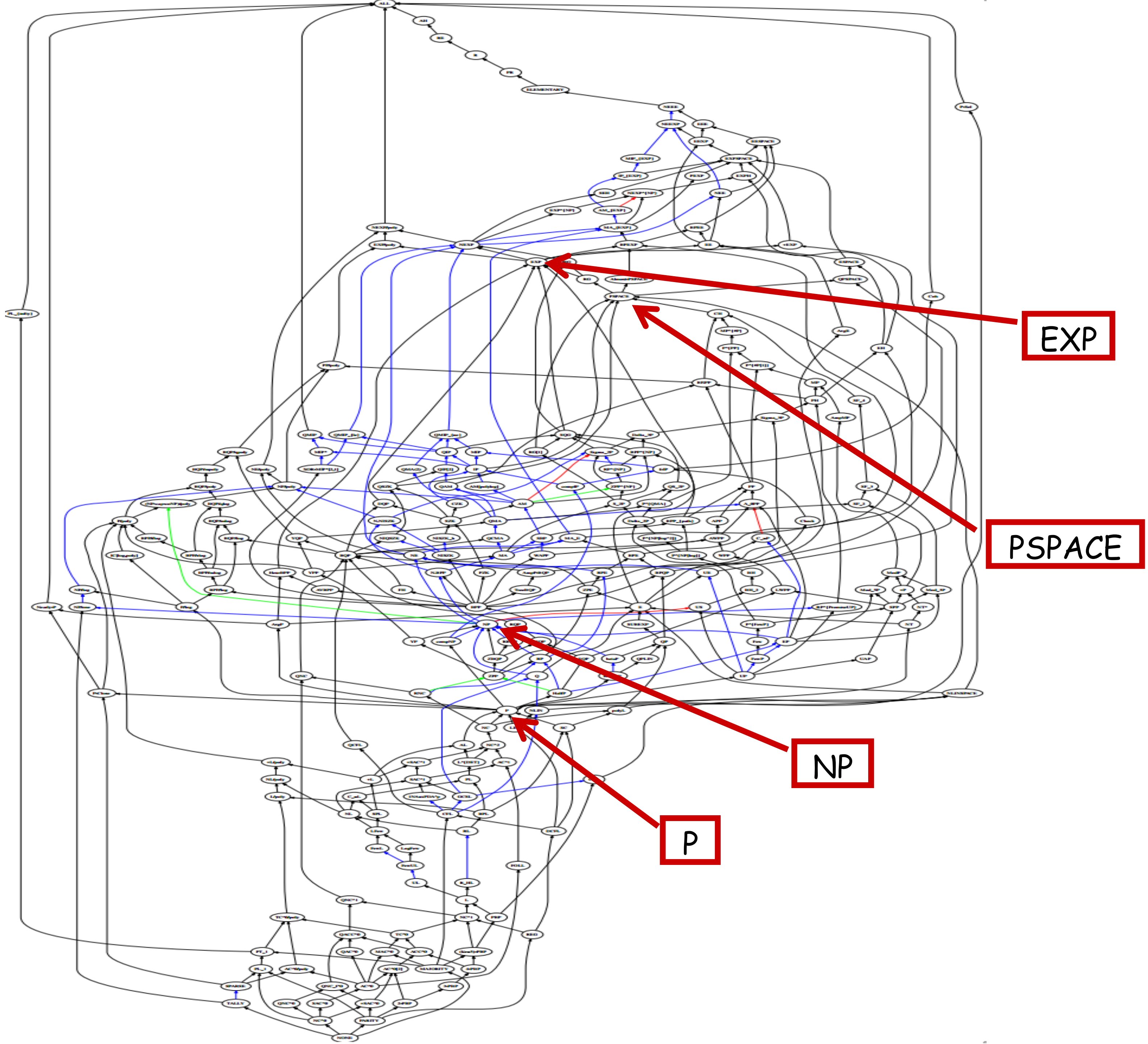
PSPACE-Complete. Problem Y is PSPACE-complete if (i) Y is in PSPACE and (ii) for every problem X in PSPACE, $X \leq_P Y$.

PSPACE-Complete problems

- QSAT
- Competitive Facility Location

Complexity Classes


recognizable
decidable
EXPSPACE
EXPTIME
PSPACE=NPSPACE
NP
coNP
P
CFL
regular
BPP


EXP
PSPACE
NP
P