

CS311 Computational Structures

Computational Complexity

Lecture 16

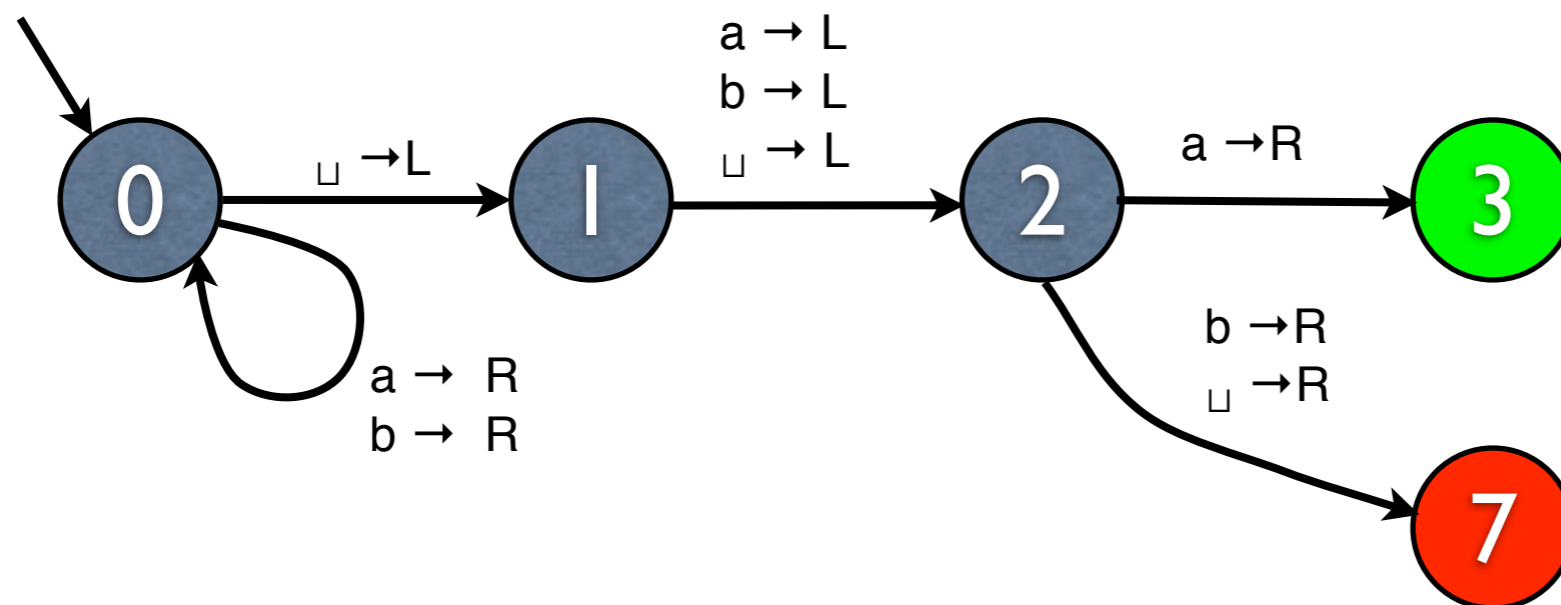
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So, it's computable!

- But at what cost?
 - ▶ Some things that are computable in principle are in practice *intractable* because of the high “cost”
 - ▶ “Cost” can be measured in time, or in space, or in other resources ...
- Simple time measure of decision algorithm is **number of steps taken by a (one-tape, deterministic) Turing Machine**

Counting TM Steps

- $L_{ax} = \{w \in \{a,b\}^* \mid \text{next to last symbol of } w \text{ is } a\}$

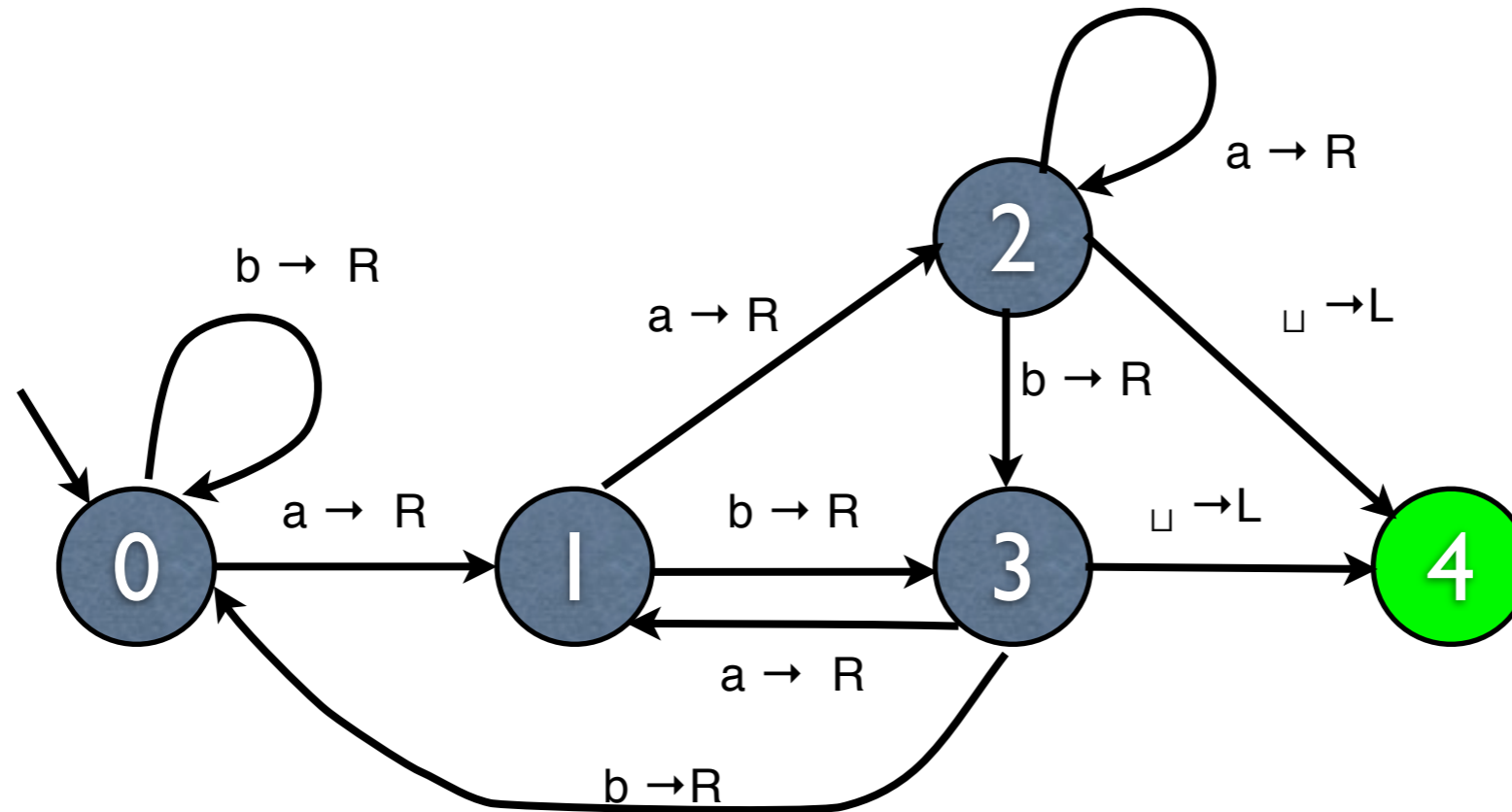


- Machine always takes exactly $n+3$ steps on input of length n

Time complexity class

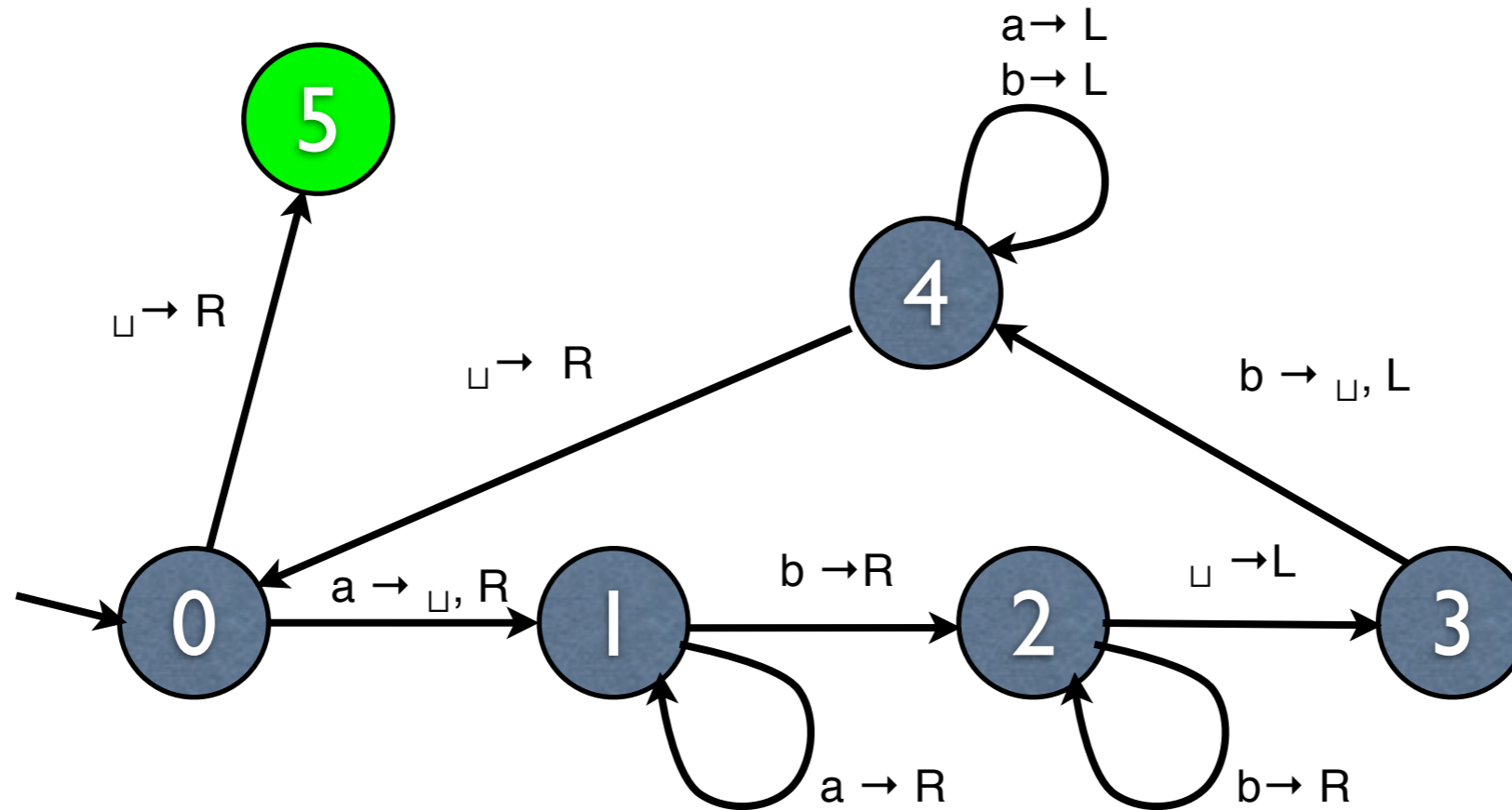
- $\text{STEPS}(t(n))$ is the class of all languages that are decidable by a (one tape deterministic) Turing machine in at most $t(n)$ steps.
 - ▶ Given input of size n , machine must halt within $t(n)$ steps with definite answer *accept* or *reject*.
- So $L_{ax} \in \text{STEPS}(n+3)$

A smarter machine for L_{ax}



- Machine takes at most $n+1$ steps on input of length n
- So $L_{ax} \in STEPS(n+1)$

A machine for $\{a^k b^k \mid k \geq 0\}$



- Main loop matches a from start and b from end.
 - e.g. $0aabb \rightarrow 1abb \rightarrow a1bb \rightarrow ab2b \rightarrow abb2 \rightarrow ab3b \rightarrow a4b \rightarrow 4ab \rightarrow 4\text{␣}ab \rightarrow 0ab$

Calculating machine time

- Main loop on $a^k b^k$ takes $4k+1$ steps and reduces k by 1

e.g. for $k = 2$: $0aabb \rightarrow 1abb \rightarrow a1bb \rightarrow ab2b \rightarrow abb2 \rightarrow ab3b \rightarrow a4b \rightarrow 4ab \rightarrow 4\sqcup ab \rightarrow 0ab$

- So overall time for “yes” decision on $a^k b^k$ is

$$(4k+1) + (4(k-1)+1) + \dots + (4+1) + 1$$

$$= 4(k+(k-1)+\dots+1) + k + 1 = 4k(k+1)/2 + k+1$$

$$= (2k+1)(k+1) = 2k^2 + 3k + 1$$

- By inspection, reaching “no” can’t take longer than “yes”, so machine decides in at most $(1/2)n^2 + (3/2)n + 1$ steps

Problems vs. Algorithms

- So $\{a^k b^k \mid k \geq 0\} \in \text{STEPS}((1/2)n^2 + (3/2)n + 1)$.
- Does this mean that deciding $\{a^k b^k \mid k \geq 0\}$ always takes this much time?
- No! There are faster algorithms (machines) for deciding this language.
 - ▶ *e.g.*, can be done in time proportional to $n \log n$

Let's approximate

- We'd like to discuss time for algorithms even if they are only described informally
 - ▶ And even when we do have a precise TM, counting steps exactly is tedious!
- Also, we often care only about the asymptotic ("big O") behavior of an algorithm or problem.
- From now on, we'll be loose about describing and counting steps
 - ▶ e.g. $\{a^k b^k \mid k \geq 0\} \in \text{TIME}(n^2)$

Review

from Hein textbook for CS250

The Meaning of Big Oh

(5.42)

The notation $f(n) = O(g(n))$ means that there are positive numbers c and m such that

$$|f(n)| \leq c|g(n)| \text{ for all } n \geq m.$$

The Meaning of Big Omega

(5.44)

The notation $f(n) = \Omega(g(n))$ means that there are positive numbers c and m such that

$$|f(n)| \geq c|g(n)| \text{ for all } n \geq m.$$

In other words...

- $O(g)$ is the set of functions whose asymptotic behavior is **bounded above** by that of g
- $\Omega(g)$ is the set of functions whose asymptotic behavior is **bounded below** by that of g
- Also, we define $\Theta(g)$ to be the set of functions with the **same** asymptotic behavior as g — *i.e.*, both $O(g)$ and $\Omega(g)$

Avoiding Exponential Time

- Algorithms requiring exponential time are too slow to be practical except for very small input sizes.
- Indeed, problems requiring more than polynomial time are often called **intractable**.
 - ▶ Note: this is just a convenient term. A “tractable” problem that requires $O(n^{100})$ time is likely not practically solvable.

Another problem: PATH

- $PATH = \{ \langle G, s, t \rangle \mid G \text{ is a directed graph that has a directed path from } s \text{ to } t \}$
 - ▶ We assume $\langle G \rangle$ is encoded as an adjacency matrix of size $O(n^2)$. (Any other **reasonable** encoding will also work.)
- There's an obvious **brute force** algorithm to decide this language: try **each** possible sequence of nodes in G of length up to n , and see if it forms a path in G
 - ▶ We consider each possible path only once
 - ▶ But there are still $n!$ possible paths, so time of this algorithm is $\Omega(2^n)$.

A faster PATH finder

- $PATH = \{ \langle G, s, t \rangle \mid G \text{ is a directed graph that has a directed path from } s \text{ to } t \}$
- A faster algorithm operates like this:
 - ▶ 1. Place a mark on node s
 - ▶ 2. Repeat until no additional nodes are marked
 - 2.1. Scan all edges of G . If an edge (a, b) is found from a marked node a to an unmarked node b , mark b .
 - ▶ 3. If t is marked *accept*; otherwise *reject*.
 - ▶ Time: step 2 repeats $O(n)$ times; each step takes $O(n^2)$ time, so overall time is $O(n^3)$. PATH is tractable after all.

Finding a Hamiltonian path

- $\text{HAMPATH} = \{\langle G, s, t \rangle \mid G \text{ is a directed graph with a path from } s \text{ to } t \text{ passing through each node exactly once}\}$
- The brute force algorithm for PATH works here too, so HAMPATH is in $\text{TIME}(n!)$ (where n is number of nodes in graph).
- Nobody knows for sure whether there is a polynomial-time algorithm for HAMPATH.

What if we vary the model?

- When we're talking about timing, our precise choice of TM model matters.
 - ▶ Unlike for decidability results.
- Example: Given a two-tape TM, we can recognize $\{a^n b^n \mid n \geq 0\}$ in $O(n)$ time. How?
- Example: On a nondeterministic TM, the brute force algorithm for PATH runs in polynomial time. Why?

Time cost of simulation

- We can relate execution times on fancy TM's to those on the standard TM.
- For every multitape TM that runs in time $t(n)$, there is an equivalent single tape TM that runs in time $O(t^2(n))$.
 - ▶ IALC Thm. 8.10
- For every ND TM that decides in time $t(n)$, there is an equivalent single tape TM that decides in time $2^{O(t(n))}$.
 - ▶ Straightforward from simulation method

Summary

- Sometimes there's an algorithm that is asymptotically faster than the "obvious" one.
- Sometimes there isn't (and we may not know).
- The distinction between polynomial and exponential time algorithms matters
- The underlying computation model matters

The class P: Tractable Problems

- P is the class of languages that are decidable in polynomial time on a deterministic single-tape Turing machine. In other words,

$$P = \bigcup_k \text{TIME}(n^k)$$

where the time complexity class $\text{TIME}(t(n))$ is the collection of languages that are decidable by a deterministic single-tape TM in $O(t(n))$ steps

Tractable Problems

- Most of the computer programs in common use solve a problem in P .
 - ▶ If it weren't, the program would probably run too slowly to be useful!
 - ▶ Exception: some problems can be solved for interesting special cases even if they aren't tractable in general
- But sometimes finding a polynomial time algorithm is challenging
 - ▶ And for a large class of problems, we don't know for sure whether such an algorithm exists.

Verifying vs. Solving

- Often, it seems easier to **verify** an alleged solution to a problem than it is to **determine** from scratch whether there is a solution.
 - ▶ Example: Consider the Hamiltonian Path problem; no polynomial time algorithm for this is known.
 - ▶ But if we have a proposed solution (*i.e.*, a path that visits each node once), it is simple to **verify** whether the path is correct in polynomial time. (How ?)
- The proposed solution is described by a **certificate**
 - ▶ *e.g.*, for Hamiltonian Path, the proposed path
- A **verifier** is a TM that takes a problem and a certificate and answers “OK” or “fake”

The Class NP

- The class NP contains all the decision problems that can be *verified* in Polynomial time.

Equivalently

- The class NP contains all the decision problems that can be *solved* in Polynomial time by a *nondeterministic* algorithm
 - ▶ It may make arbitrary (nondeterministic) choices
 - ▶ The number of steps must be bounded by some polynomial in n , where n is the length of the input
 - ▶ $\text{NTIME}(t(n)) = \text{languages decidable in } O(t(n)) \text{ time by a NDTM}$
 - ▶ $\text{NP} = \bigcup_k \text{NTIME}(n^k)$

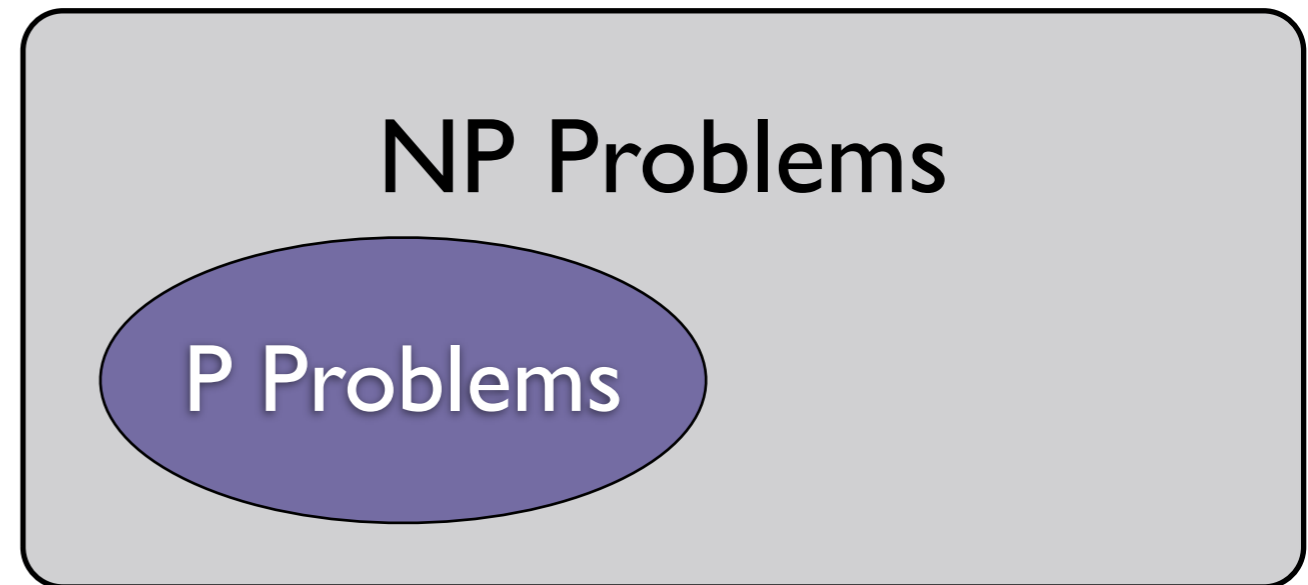
Equivalence of Two Definitions of NP

- Suppose that we have a deterministic verifier ...
- then we build a non-deterministic solver that:
 - ▶ non-deterministically generates all putative certificates (effectively in parallel)
 - ▶ runs the deterministic verifier to check them (each in polynomial time)
 - ▶ if there is a solution, we'll find and approve its certificate

Conversely:

- Suppose we have a non-deterministic solver, e.g., a non-deterministic TM M
 - At each of its polynomially-many steps, it may branch at most a constant number of ways.
 - We can use the path of choices made as the certificate; valid certificates lead to accept states.
- So: we can build a deterministic verifier that, given the certificate, simulates M on that path, and checks that it is an accept path.
 - This takes polynomially-many steps

Relationship



- Anything in P is also in NP
 - ▶ because any deterministic algorithm is also a non-deterministic algorithm
- Does $P = NP$?
 - ▶ currently not known, but widely suspected $P \neq NP$

Beyond NP

- Many interesting and natural problems are in NP
 - ▶ Typically show membership in NP by exhibiting a polynomial-time verifier.
- But some (natural) problems are not...
- $\text{EXPTIME} = \bigcup_k \text{TIME}(2^{n^k})$ is believed to be larger than NP (and known to be larger than P)
- $2\text{-EXPTIME} = \bigcup_k \text{TIME}(2^{2^{n^k}})$ is larger than NP

What about Space?

- We can measure the space use of a TM as the maximum number of tape cells it scans on an input of length n .
- Define $SPACE(f(n))$ as the class of languages decided by a (deterministic) TM using $O(f(n))$ space.
- Define $NSPACE$ similarly for non-deterministic TM.

NP \subseteq PSPACE

- By analogy with time classes, we define $PSPACE = \bigcup_k SPACE(n^k)$ and $NPSPACE = \bigcup_k NSPACE(n^k)$
- Then NP \subseteq PSPACE.
 - ▶ Clearly NP \subseteq NPSPACE, because a machine that takes t steps can access at most t tape squares.
 - ▶ It turns out that NPSPACE = PSPACE
 - Consequence of Savitch's theorem (IALC 11.5)
 - ▶ It also turns out that NPSPACE \subseteq EXPTIME
- But it is unknown whether NP \subseteq PSPACE or NSPACE \subseteq EXPTIME