## Reductions

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A central question is to place individual problems in the introduced hierarchy.

The goal is to determine the location/complexity of an important problem as accurately as possible.

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Providing an upper estimate of the complexity of a language/problem L (i.e., proving that L ∈ C<sub>1</sub>) requires giving an algorithm and analyzing it to show membership in class C<sub>1</sub>. Such results, predating the advent of computers, constitute the starting point of algorithm theory.

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- (1) is easy: Designing efficient algorithms.

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Difficulty, Relative Difficulty

Reductions of Problems

Completeness

## Proving Difficulty

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(a) Replace the general model of Turing machines with a simpler computational model (which is not a universal computational concept), and try to prove lower estimates there. For example, for the SORTING problem (sorting *n* numbers in ascending order), we might work with just two comparisons of input numbers and branch based on the result. It is natural since most algorithms work this way. It can be demonstrated that at least *n* log *n* comparisons are needed to compute the output.

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- (b) Do not investigate (absolute) difficulty; instead, focus on relative difficulty. The goal is to prove only that a problem is at least as difficult as another.

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 $\widetilde{L}$  must be complex enough to allow us to formulate any problem described by L as a problem of  $\widetilde{L}$ .

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#### Karp Reductions of Languages

Let  $L, \widehat{L} \subset \Sigma^*$  be two languages and  $\mathcal{C}$  a complexity class. L is reducible to  $\widehat{L}$  in  $\mathcal{C}$ , denoted:  $L \preccurlyeq_{\mathcal{C}} \widehat{L}$ , if there exists a computable Turing machine R such that

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- (i) R is a C-complexity machine/procedure,
- (ii)  $\omega \in L$  if and only if  $\widetilde{\omega} \in \widehat{L}$ , where  $\widetilde{\omega}$  is the sequence calculated by R from  $\omega$ .

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Other reduction concepts exist. The above definition lies in the work of Karp and is generally referred to as Karp reductions. If emphasis is needed, we use the notation  $\preccurlyeq^{\text{Karp}}_{\mathcal{C}}$ . In this course, we mostly encounter such reductions, and most of the time, we omit the upper index.

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## The first examples

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#### Note

The tasks above are reducible to each other in both directions.

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### Example

## Example CLIQUE $\preccurlyeq_{\mathcal{P}}$ INDEPENDENT-VERTEX-SET.

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#### Example

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The reduction is extremely simple: Given an input  $\omega = \lceil G, k \rceil$  for the CLIQUE problem.

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## Example of a Reduction

### Example

## Example INDEPENDENT-VERTEX-SET $\preccurlyeq_{\mathcal{P}}$ VERTEX-COVER.

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#### Example

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The reduction is extremely simple: Given an input  $\omega = \lceil G, k \rceil$  for the INDEPENDENT-VERTEX-SET problem. We compute |V(G)| - k from the codes of G and k. The new sequence  $\tilde{\omega}$  is  $\lceil G, |V(G)| - k \rceil$ . From our earlier graph theory studies, the new *question* is equivalent to the original one.

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The reduction is extremely simple: Given an input  $\omega = \lceil G, k \rceil$  for the VERTEX-COVER problem. We compute the complement and |V(G)| - k from the codes of G and k. The new sequence  $\tilde{\omega}$  is  $\lceil \overline{G}, |V(G)| - k \rceil$ . From our earlier graph theory studies, the new *question* is equivalent to the original one.

The complexity of computing  $\tilde{\omega}$  is polynomial (actually solvable in logarithmic space).

Note that for CLIQUE, VERTEX-COVER, and INDEPENDENT-VERTEX-SET, no efficient algorithm is known.

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Note that for CLIQUE, VERTEX-COVER, and INDEPENDENT-VERTEX-SET, no efficient algorithm is known. If there were one for any of them, it would have significant implications for the others.

## Break



Difficulty, Relative Difficulty

Reductions of Problems

Completeness

# Turing Reductions

Peter Hajnal Reductions, SzTE, 2023

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#### Definition

Turing Reductions of Languages Let  $L, \widehat{L} \subset \Sigma^*$  be two languages and  $\mathcal{C}$  a complexity class. L is Turing reducible to  $\widehat{L}$  in  $\mathcal{C}$ , denoted:  $L \leq_{\mathcal{C}} \widehat{L}$ , if there exists a  $\mathcal{C}$ -complexity oracle Turing machine Othat decides L using  $\widehat{L}$  as an oracle, i.e., for any input  $\omega \in \Sigma^*$ :

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(i) If  $\omega \in L$ , then  $O^{\widehat{L}}(\omega) = 1$ .

(ii) If 
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, then  $O^{L}(\omega) = 0$ .

Difficulty, Relative Difficulty

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# **Turing Reduction**

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The term in (i) involves an unknown concept that needs clarification.

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# Oracle Turing Machine

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#### Definition: Oracle Turing Machine (Continued)

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• The set of states is of the form

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\{\text{ORACLE-YES}, \text{ORACLE-NO}\} \times S_0
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where  $S_0$  is the set of states in the original Turing machine.

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From these, the run (a sequence of configurations generated from the initial configuration), and the defined language, are naturally derived. The cost of the question is 1 time unit and 0 space.

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The essence of the reduction is that if someone can efficiently write the  $\hat{L}$  subroutine, then *L* can be efficiently decided (assuming the contribution of *R* is considered efficient, i.e., it belongs to *C*).

We do not require the implementation of the subroutine, we only count the *invocation* of the subroutine and the reception of the result as a single step.

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Finally, we mention an important property of some reductions.

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Transitivity of reductions

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#### Transitivity of reductions

- (i)  $\preccurlyeq_{\mathcal{P}}$  is transitive.
- (ii)  $\preccurlyeq_{\mathcal{L}}$  is transitive.
- (iii) Let  $s(n) \ge \log n$  be a nice space function. If  $L_1 \preccurlyeq_{SPACE(\mathcal{O}(s(n)))} L_2$  and  $L_2 \preccurlyeq_{\mathcal{L}} L_3$ , then  $L_1 \preccurlyeq_{SPACE(\mathcal{O}(s(n)))} L_3$

Reductions of Problems

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#### Transitivity of Polynomial Time Reductions

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Assume that  $L_1 \preccurlyeq_{\mathcal{P}} L_2$  and  $L_2 \preccurlyeq_{\mathcal{P}} L_3$ .

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Assume that  $L_1 \preccurlyeq_{\mathcal{P}} L_2$  and  $L_2 \preccurlyeq_{\mathcal{P}} L_3$ . Let  $R_1$  and  $R_2$  be the two algorithms verifying the two reductions.

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Specifically,  $R_1$  and  $R_2$  are both polynomial.

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Specifically,  $R_1$  and  $R_2$  are both polynomial. Let  $p_1$  and  $p_2$  be the two polynomials giving the time bounds of  $R_1$  and  $R_2$ . We can assume that  $p_2$  is monotonically increasing.

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Run  $R_1$  on input  $\omega$ , which calculates the character sequence  $\widetilde{\omega}$ .

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Run  $R_1$  on input  $\omega$ , which calculates the character sequence  $\widetilde{\omega}$ . Then run  $R_2$  on  $\widetilde{\omega}$ , leading to the computation of  $\widetilde{\widetilde{\omega}}$ .

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The resulting Turing machine is denoted as R.

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The resulting Turing machine is denoted as R. We will show that R verifies the  $L_1 \preccurlyeq_{\mathcal{P}} L_3$  reduction.

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# Transitivity of Polynomial Time Reductions (Continued)

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#### Transitivity of Polynomial Time Reductions (Continued)

 $\omega \in L_1$  if and only if  $\widetilde{\omega} \in L_2$ .

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Thus, for input  $\omega$ , the upper bound on the runtime becomes

$$p_1(|\omega|) + p_2(|\widetilde{\omega}|) \leq p_1(|\omega|) + p_2(p_1(|\omega|)).$$

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Thus, for input  $\omega$ , the upper bound on the runtime becomes

$$p_1(|\omega|) + p_2(|\widetilde{\omega}|) \leq p_1(|\omega|) + p_2(p_1(|\omega|)).$$

This is a polynomial upper bound.

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Reductions of Problems

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# Transitivity of Logarithmic Space Reductions

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Assume that  $L_1 \preccurlyeq_{\mathcal{L}} L_2$  and  $L_2 \preccurlyeq_{\mathcal{L}} L_3$ . Let  $R_1$  and  $R_2$  be the two algorithms verifying the two reductions.

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reductions as follows: Run  $R_1$  on input  $\omega$ , which calculates the character sequence  $\tilde{\omega}$ . Then run  $R_2$  on  $\tilde{\omega}$ , leading to the computation of  $\tilde{\tilde{\omega}}$ .

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The worktapes of  $\widetilde{R}$  correspond to  $R_1$ 's worktapes plus  $R_2$ 's worktapes. We have two extra tapes instead of the previous tape, one for the output of  $R_1$  and shared with  $R_2$ 's input tape, and the other tape's content is the position index of  $R_1$ 's output tape while the other tape's content is the position index of  $R_2$ 's input tape.

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 $\widetilde{R}$  performs the simulation of  $R_2$  without the content of the  $\widetilde{\omega}$  input tape.

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If the two positions match, we read the unwritten character from the state and stop the  $R_1$  simulation,

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We need to work for every read operation.

Now we know which character of the calculated  $\tilde{\omega}$  we are interested in. We start the simulation of  $R_1$ . During the simulation, we do not write down the calculated characters, only store the position of the output head. If  $R_1$  writes, then we compare the new position with the desired position for reading.

If the two positions match, we read the unwritten character from the state and stop the  $R_1$  simulation, continue the  $R_2$  simulation.

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(iii) The ideas of the previous proof still work here.

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#### Lemma

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#### Lemma

(i) 
$$L \preccurlyeq_{\mathcal{P}} \widehat{L}$$
 and  $\widehat{L} \in \mathcal{P}$ , then  $L \in \mathcal{P}$ .

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#### Lemma

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Difficulty, Relative Difficulty

Reductions of Problems

Completeness

# Proof of the Lemma

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(i) Consider a Turing machine A that performs the reduction from L to  $\hat{L}$ , and  $\hat{A}$ , which decides the membership problem for  $\hat{L}$  in  $\mathcal{P}$ .

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Perform the computation

$$\omega \to A(\omega) \in \Sigma^{p(n)} \to \widehat{A}(A(\omega)) \in \{ \mathsf{ACCEPT}, \mathsf{REJECT} \}$$

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The first step is limited by a polynomial p in the input size n. The longest input that we can compute falls into  $\Sigma^{p(n)}$ . The second step is limited by a polynomial q in the input size. The total time is  $(p + q \circ p)(n)$ , which is a polynomial function of n.

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The combined action of the two algorithms, based on the concept of Karp reduction, decides exactly the language L, which means L is also decidable in polynomial time.

Difficulty, Relative Difficulty

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# Proof of the Lemma

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# Proof of the Lemma

(ii) Based on the ideas of part (i) and the previous lemma, it is obvious.

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# Break



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#### Example

### Let L be an arbitrary language in $\mathcal{NL}$ . Then

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#### Example

Let L be an arbitrary language in  $\mathcal{NL}$ . Then

 $L \preccurlyeq_{\mathcal{L}} \mathsf{DIRECTED}\text{-}\mathsf{REACHABILITY}.$ 

The proof of this example is essentially what has been discussed earlier. We summarize the essential ideas of the previous reasoning in a theorem.

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# The Theorem

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#### Theorem

Let  $L \in_{\mathcal{T}} \mathcal{NL}$ . It can be assumed that the Turing machine proving containment has two different halting configurations on inputs of given length (so accepting runs end in the same configuration). To  $\omega \in \Sigma^*$ , we assign the graph of the (directed) reduced configurations  $\overrightarrow{G} = \overrightarrow{G}_{\mathcal{T},\omega}$  of the Turing machine. This assignment includes  $v_0$  as the vertex corresponding to the initial configuration, and  $v_+$  as the vertex corresponding to the accepting configuration. This assignment has the following properties:

(i) ω ∈ L if and only if [G<sub>ω,T</sub>, v<sub>0</sub>, v<sub>+</sub>] ∈ st-REACHABILITY.
(ii) The assignment is computable and its space complexity is O(log(n)).

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This example is much more general than the previous one. To see this, let's look at some consequences.

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# Corollary If $\overrightarrow{st}$ -REACHABILITY $\in \mathcal{P}$ , then $\mathcal{NL} \subset \mathcal{P}$ .

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The condition is true, this simply follows from descriptions and analysis of graph traversal algorithms, well-known in algorithm theory lectures.

The above corollary is essentially re-proving  $\mathcal{NL}\subset\mathcal{P},$  our earlier result.

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Corollary

### If DIRECTED-REACHABILITY $\in \mathcal{L}$ , then $\mathcal{NL} = \mathcal{L}$ .

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Corollary

### If DIRECTED-REACHABILITY $\in \mathcal{L}$ , then $\mathcal{NL} = \mathcal{L}$ .

The conclusion is actually only  $\mathcal{NL} \subset \mathcal{L}$  (the other direction of containment is obvious).

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#### Corollary

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Here, the truth of the condition is not known, and many believe it is not true.

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# Definition of Completeness

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# Definition of Completeness

The above reasoning is very important. The essence of the argument is that, based on the example, DIRECTED-REACHABILITY encapsulates the complexity of the entire  $\mathcal{NL}$  language class. This leads to the creation of a more general concept:

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# Definition of Completeness

The above reasoning is very important. The essence of the argument is that, based on the example, DIRECTED-REACHABILITY encapsulates the complexity of the entire  $\mathcal{NL}$  language class. This leads to the creation of a more general concept:

#### Definition

A language  $\widehat{L}$  is *complete* in class  $\mathcal{C}$  under complexity  $\mathcal{R}$  reduction if:

(i)  $\widehat{L} \in C$ , (ii) for every  $L \in C$ ,  $L \preccurlyeq_{\mathcal{R}} \widehat{L}$ .



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We highlight four special cases.

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### Definition

The language  $\widehat{L}$  is  $\mathcal{NP}$ -complete if it is complete in  $\mathcal{NP}$  under  $\mathcal{P}$  reduction. That is,  $\widehat{L}$  is  $\mathcal{NP}$ -complete if

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The above convention is an alternative to working with  $\preccurlyeq_{\mathcal{L}}$  reduction. This stricter interpretation will still be true for most later  $\mathcal{NP}$ -completeness-proving reductions. However, we only require the polynomial time complexity of the reductions, as we demand easier verifiability.

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### Hardness

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## A Concrete $\mathcal{NL}$ -Complete Problem

Theorem

DIRECTED-REACHABILITY is  $\mathcal{NL}$ -complete.

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Based on the theorem, our knowledge about DIRECTED-REACHABILITY extends to the entire  $\mathcal{NL}$  class.

We already saw an example of this:  $\overrightarrow{st}$ -REACHABILITY $\in \mathcal{P}$ . This led to  $\mathcal{NL} \subset \mathcal{P}$ .

## Implication of Savitch's Algorithm

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Savitch's algorithm saves space. The DIRECTED-REACHABILITY is solved in  $\log^2$  space. This immediately leads to the following theorem:

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#### Theorem

$$\mathcal{NL} \subset \mathcal{SPACE}(\log^2 n).$$



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## Theorem

For a nice function  $s(n) > \log n$ , any problem in NSPACE(s(n)) can be reduced to a  $\overrightarrow{st}$ -REACHABILITY problem in O(s(n)) space, whose vertex set has size  $2^{O(s(n))}$ .

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#### Theorem

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#### Corollary

Let S be a class of nice space functions that is closed under squaring. Then  $\mathcal{NPSPACE}(\cup_{s \in S} s(n)) = \mathcal{PSPACE}(\cup_{s \in S} s(n)).$ 

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Thus, another special case:  $\mathcal{EXPSPACE} = \mathcal{NEXPSPACE}$ .

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## This is the End!

## Thank you for your attention!

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