

Class	Complete SAT Problem	
$\Sigma_1 = NP$	$\exists X_1 : \varphi(X_1)$	SAT
$\Pi_1 = coNP$	$\forall X_1 : \varphi(X_1)$	UNSAT
$\Sigma_2$	$\exists X_1 : \forall X_2 : \varphi(X_1, X_2)$	PH
$\Pi_2 = co\Sigma_2$	$\forall X_1 : \exists X_2 : \varphi(X_1, X_2)$	
$\Sigma_k$	$\exists X_1 : \forall X_2 : \dots X_k : \varphi(X_1, \dots, X_k)$	PH
$\Pi_k = co\Sigma_k$	$\forall X_1 : \exists X_2 : \dots X_k : \varphi(X_1, \dots, X_k)$	
PSPACE	$\exists X_1 : \forall X_2 : \dots X_n : \varphi(X_1, \dots, X_n)$	QSAT
	or $\forall X_1 : \exists X_2 : \dots X_n : \varphi(X_1, \dots, X_n)$	

Complements:  $\exists \equiv \neg \forall \neg$  &  $\forall = \neg \exists \neg$   
 $\Rightarrow \neg \exists X_1 : \varphi(X_1)$  UNSAT  
 $\Leftrightarrow \forall X_1 : \neg \varphi(X_1)$

$\Sigma_2$ -complete: [Schaefer & Umans - SIGACT News 2002 + www]

- $L_{1,2}$  -  $\exists : \forall : 3SAT$  -  $\exists : \forall : NAE 3SAT$
- SP5 -  $\exists S_1 \subseteq M_1 : \forall S_2 \subseteq M_2 : S_1 \cup S_2$  is a 3DM
- L13 - is circuit A = circuit B with some inputs fixed?
- GT19 -  $\exists k$ -coloring: no maximal clique is monochromatic
- L21 -  $\exists : \exists !$ : planar 3SAT or planar 1-in-3SAT
- $\exists k$  "clues" to force unique answer to:
  - planar 3SAT - planar 1-in-3SAT
  - Akari - Shakashaka - Sudoku

[Demaine, Ma, Schwartzman, Waingarten, Aaronson - TCS 2018]

Gadget general model: (for robot motion planning)

- locations (entrances/exits)

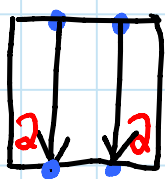
- states

- transitions  $(\underline{l}_1, \underline{s}_1) \rightarrow (\underline{l}_2, \underline{s}_2)$  }  $\underline{s}_1: \textcircled{l_1} \xrightarrow{s_2} \textcircled{l_2}$   
transition graph } visual notation

[Demaine, Grosz, Lynch, Rudoy - FUN 2018]

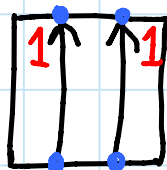
[Demaine, Hendrickson, Lynch - arXiv 2018]

Examples:



states:

1



2

2-toggle

[Demaine, Grosz, Lynch - CIAC 2017]

Gadget types:

- k-tunnel = all transitions are along edges of perfect matching on locations  
(states can control traversability & directions)

- deterministic = transition determines state change

- reversible = every move can be then undone

Characterization: motion planning with deterministic reversible k-tunnel gadgets is PSPACE-complete iff:

- some gadget has interacting tunnels:  
traversal of some tunnel affects traversability of another tunnel

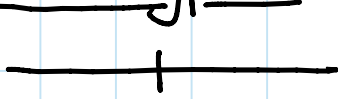
- even with planar connections of gadgets

[Demaine, Hendrickson, Lynch - arXiv 2018]

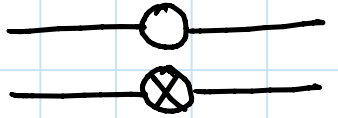
# 2-state characterization:

[Demaine, Groszof, Lynch, Rudoy - FUN 2018]

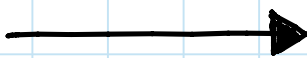
## Tunnel types:



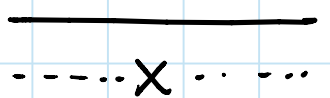
tripwire: always bitraversable & traversal flips state



} lock: bitraversable in one state not in other



toggle: traversal in one direction & toggles state + direction



} trivial: always/never bitraversable

## Hard 2-tunnel gadgets:

