A General Theory of Motion Planning Complexity: Characterizing Which Gadgets Make Games Hard

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Abstract

We build a general theory for characterizing the computational complexity of motion planning of robot(s) through a graph of "gadgets", where each gadget has its own state defining a set of allowed traversals which in turn modify the gadget's state. We study two families of such

	1-Player Game	2-Player Game	Team Game
Polynomially Bounded (DAG)	**NL** vs. **NP-complete**: full characterization [§5]	**P** vs. **PSPACE-complete**: full characterization [§6]	**P** vs. **NEXPTIME**: full characterization [§7]
Polynomially Unbounded (reversible, deterministic gadgets)	**NL** vs. **PSPACE-complete**: full characterization [§2] **Planar**: equivalent [§2.3]	**P** vs. **EXPTIME-complete**: partial characterization [§3]	**P** vs. **RE-complete** (⇒ **Undecidable**): partial characterization [§4]