The algebra of alternation and synchronisation of finite dynamical systems

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Finite, discrete-time dynamical systems

Just a finite set with a transition function (A, f)



Finite, discrete-time dynamical systems

Just a finite set with a transition function (A, f) modulo isomorphism



A few limit cycles















Isomorphism of dynamical systems is easy

2009 24th Annual IEEE Conference on Computational Complexity **Deltar Graph Isomorphism is in Log-Space** Samir Datta*, Nutan Limaye[†], Prajakta Nimbhorkar[†], Thomas Thierauf[‡], Fabian Wagner[§] *Chennai Mathematical Institute Email: sdatta@cmi.ac.in [†]The Institute of Mathematical Sciences, Chennai [‡]Fakultät für Elektronik und Informatik, HTW Aalen Email: fakultät für Theoretische Informatik, Universität Ulm [§]Institut für Theoretische Informatik, Universität Ulm Email: fabian.wagner@uni-ulm.de

Abstract

Graph Isomorphism is the prime example of a computational problem with a wide difference between the best known lower and upper bounds on its complexity. There is a significant gap between extant lower and upper bounds for a significant graphs as well. We bridge the gap for this natural planar graphs as well. We bridge the gap for this natural and important special case by presenting an upper bound [JKMT03]. In

The problem is clearly in NP and by a group theoretic proof also in SPP [AK06]. This is the current frontier of our knowledge as far as upper bounds go. The inability to give efficient algorithms for the problem would lead one to believe that the problem is provably hard. NP-hardness to believe that the problem is provably hard. NP-hard then is precluded by a result that states if GI is NP-hard then [BHZ87], [Sch88]. What is more surprising is that not even believe that GI is hard for DET [Tor04], the class of problems is that GI is hard for DET [Tor04], the class of problems and hard believe to the determinant, defined by Cook [Coo85].

Isomorphism of dynamical systems is easy



Planar Graph Isomorphism is in Log-Space

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Abstract

Graph Isomorphism is the prime example of a computational problem with a wide difference between the best known lower and upper bounds on its complexity. There is a significant gap between extant lower and upper bounds for planar graphs as well. We bridge the gap for this natural and important special case by presenting an upper bound log space hardness [JKMT03]. In

The problem is clearly in NP and by a group theoretic proof also in SPP [AK06]. This is the current frontier of our knowledge as far as upper bounds go. The inability to give efficient algorithms for the problem would lead one to believe that the problem is provably hard. NP-hardness is precluded by a result that states if GI is NP-hard then the polynomial time hierarchy collapses to the second level [BHZ87], [Sch88]. What is more surprising is that not even P-hardness is known for the problem. The best we know is that GI is hard for DET [Tor04], the class of problems 1. this to the determinant, defined by Cook [Coo85].

INTERMISSION

How to efficiently generate dynamical systems, aka functional digraphs

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How to efficiently generate dynamical systems, aka functional digraphs

- In theory: Antonio E. Porreca, Ekaterina Timofeeva, Polynomial-delay generation of functional digraphs up to isomorphism, arXiv:2302.13832
- In practice: funkdigen2, a fast implementation of the above, github.com/aeporreca/funkdigen2

A toy example from engineering

Traffic lights



A toy example from science

A planetary system



A planetary system


































What if our instruments are less sophisticated?

Abstract evolution of the system



Abstract evolution of the system



Product of dynamical systems

Product of systems



Give temporary names to the states



Compute the Cartesian product



Add the arcs between states



Forget the names once again











Back to our planetary system

Decomposition





Decomposition



Any other decomposition?

Another decomposition



Another decomposition



Another decomposition









Untangling complex systems











More abstractly...





• Commutative: X + Y = Y + X and $X \times Y = Y \times X$

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- Neutral elements: $\emptyset + X = X$ and $\heartsuit \times X = X$
The operations + and × are a commutative semiring

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- Distributive: $X \times (Y + Z) = X \times Y + X \times Z$
- Multiplication by zero: $\emptyset \times X = \emptyset$



Multiplication table

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Equations for decomposing systems

Eqns over dynamical systems

 $Y + Y^2 = Z + I$

Eqns over dynamical systems



 $X = \bigvee Y = \bigvee Z = \bigvee$

$\ensuremath{\mathbb{N}}$ is a subsemiring of D

• There is an injective homomorphism $\varphi \colon \mathbb{N} \to \mathbb{D}$

$$\varphi(n) = \underbrace{\mathbf{1} + \mathbf{1} + \dots + \mathbf{1}}_{n \text{ times}} = \underbrace{\bigcirc_{\bullet} + \bigcirc_{\bullet} + \dots + \bigcirc_{\bullet}}_{n \text{ times}}$$

- *n* fixed points behave exactly as the integer *n*
- So \mathbf{D} contains a isomorphic copy of \mathbb{N}

Natural polynomial equations

- Let $p(X, Y) = 2X^2$ and q(X, Y) = 3Y with $p, q \in \mathbb{N}[X, Y] \le \mathbb{D}[X, Y]$
- Then $2X^2 = 3Y$ has the non-natural solution

$$X = \bigvee Y = 2 \bigvee$$

- But, of course, it also has the natural solution X' = 3, Y' = 6
- Notice how X' = |X| and Y' = |Y|
- This is not a coincidence!

The function "size" $| \cdot | : D \rightarrow \mathbb{N}$

It's a semiring homomorphism

- $\bullet | \emptyset | = 0$
- $|\mathbf{Q}| = 1$
- Since + is the disjoint union, we have

$$|A+B| = |A| + |B|$$

• Since X is the cartesian product, we have

$$|AB| = |A| \times |B|$$

Notation for polynomials $p \in \mathbf{D}[\vec{X}]$

Of degree $\leq d$ over the variables $\overrightarrow{X} = (X_1, \dots, X_k)$



Theorem Solvability of natural equations

- If a polynomial equation over $\mathbb{N}[X_1, \dots, X_k]$ has a solution in \mathbb{D}^k , then it also has a solution in \mathbb{N}^k
- In the larger semiring ${\bf D}$ we may find extra solutions, but only if the equation is already solvable over the naturals
- Then, by reduction from Hilbert's 10th problem, we obtain the undecidability in **D** of equations over $\mathbb{N}[\overrightarrow{X}]$...
- ...and thus of arbitrary equations over $\mathbf{D}[\vec{X}]$

Proof Consider $p(\vec{X}) = q(\vec{X})$ with $p, q \in \mathbb{N}[\vec{X}]$

 $\sum_{i \in \{0,...,d\}^k} a_{\vec{i}} \overrightarrow{X^i} = \sum_{i \in \{0,...,d\}^k} b_{\vec{i}} \overrightarrow{X^i}$

Proof Suppose that $\overrightarrow{A} \in \mathbf{D}^k$ is a solution

 $\sum_{i \in \{0,...,d\}^k} a_{\vec{i}} \overrightarrow{A^i} = \sum_{i \in \{0,...,d\}^k} b_{\vec{i}} \overrightarrow{A^i}$

Proof Apply the size function | · |

 $\sum_{i \in \{0,...,d\}^k} a_{\vec{i}} \overrightarrow{A^{i}} = \sum_{i \in \{0,...,d\}^k} b_{\vec{i}} \overrightarrow{A^{i}}$

Proof

The size function | · | is a homomorphism

 $\sum_{i \in \{0,...,d\}^k} \left| \overrightarrow{a_i} \overrightarrow{A^i} \right| = \sum_{i \in \{0,...,d\}^k} \left| b_{\overrightarrow{i}} \overrightarrow{A^i} \right|$

Proof

The size function | · | is a homomorphism

$\sum_{i \in \{0,...,d\}^k} |a_{\vec{i}}| |\vec{A}^{\vec{i}}| = \sum_{i \in \{0,...,d\}^k} |b_{\vec{i}}| |\vec{A}^{\vec{i}}|$

Proof The coefficients are natural

$\sum_{i \in \{0,...,d\}^k} a_{\vec{i}} | \overrightarrow{A^i} | = \sum_{i \in \{0,...,d\}^k} b_{\vec{i}} | \overrightarrow{A^i} |$

Proof We have $\vec{A}^{i} = \prod_{j=1}^{k} A_{j}^{i_{j}}$

 $\sum_{i \in \{0,...,d\}^k} a_{\vec{i}} \left| \prod_{j=1}^k A_j^{i_j} \right| = \sum_{i \in \{0,...,d\}^k} b_{\vec{i}} \left| \prod_{j=1}^k A_j^{i_j} \right|$

Proof

The size function | · | is a homomorphism

 $\sum_{i \in \{0,...,d\}^k} a_{\vec{i}} \prod_{j=1}^k |A_j^{i_j}| = \sum_{i \in \{0,...,d\}^k} b_{\vec{i}} \prod_{j=1}^k |A_j^{i_j}|$

Proof

The size function | · | is a homomorphism

 $\sum a_{\vec{i}} \prod |A_j|^{i_j} = \sum b_{\vec{i}} \prod |A_j|^{i_j}$ $i \in \{0, ..., d\}^k$ j=1 $i \in \{0, ..., d\}^k$ j=1

Proof So $|\vec{A}| = (|A_1|, ..., |A_k|)$ is also a solution, QED

$p(|A_1|, ..., |A_k|) = q(|A_1|, ..., |A_k|)$

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- Equations without variables on one side admit an algorithm, but even linear ones of this form are NP-complete:

$$A_1X_1 + A_2X_2 + \dots + A_nX_n = B$$

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- Equations without variables on one side admit an algorithm, but even linear ones of this form are NP-complete:

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• We are still unsure if equations in one single variable, like AX = B, can be solved efficiently (conjecture: no)

Reducibility of dynamical systems

Most dynamical systems are irreducible

• Formally:

 $\lim_{n \to \infty} \frac{\text{number of reducible systems over} \le n \text{ states}}{\text{total number of systems over} \le n \text{ states}} = 0$

 Notice that this is the opposite of N, where irreducible (aka prime) integers are scarce

No unique factorisation into irreducibles!

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Multiple factorisations


Multiple factorisations



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- In other words, if P divides $A \times B$ then it divides A or B
- If a prime appears in one factorisation of a system, then it appears in all the others as well (it is irreplaceable)

An example of nonprime



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- A counterexample to the primality of *P* is two systems *A*, *B* such that *P* divides *A* × *B* but neither *A* nor *B*
- Those *A* and *B* can be bigger than *P*, but we don't know how much, so no algorithm yet...



Connected



- Connected
- Fixed point (no cycles of length > 1)



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- gcd of the number of predecessors across all states must be 1



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 E.g., AX = B has at most one if X is connected (recent result by É. Naquin and M. Gadouleau)

- Find more solvable equations, and at least one class of equations that is solvable efficiently
- How many solutions for a given equation?
 E.g., AX = B has at most one if X is connected (recent result by É. Naquin and M. Gadouleau)
- Find out if prime systems exist, or at least find a primality algorithm!

Bibliography

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- É. Naquin, M. Gadouleau, Factorisation in the semiring of finite dynamical systems
- A.E. Porreca, E. Timofeeva, Polynomial-delay generation of functional digraphs up to isomorphism

Thanks for your attention! Merci de votre attention !

Any questions?