Positive Logic Is 2-Exptime Hard

Aleksy Schubert Paweł Urzyczyn Daria Walukiewicz-Chrząszcz University of Warsaw

TYPES, Toulouse, April 26, 2013

Work in Progress...

Positive Logic Is 2-UExptime Hard

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Positive Logic Is 2-co-NExptime Hard

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Motivation

Foundational research on:

- ► Expressive power of "weak" intuitionistic logics.
- High-level properties of proof tactics.

In classical logic:

Every formula is classically equivalent to one of the form:

 $Q_1x_1Q_2x_2\ldots Q_kx_k$. Body (x_1x_2,\ldots,x_k) ,

where *Body* has no quantifiers.

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Classification:

Formulas may be classified according to the quantifier prefix, e.g. universal (\forall^*) formulas are in Π_1 , and Π_2 is $\forall^* \exists^*$.

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In intuitionistic logic:
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In intuitionistic logic:

The prenex fragment is decidable in Pspace.

To make things simpler, we consider first-order formulas

- with universal quantifiers and implications;
- without function symbols

This fragment is known to be undecidable.

Mints Hierarchy

Can we restore the prenex classification in intuitionistic logic?

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Grigori Minc (1968): Yes, consider the quantifier prefix a formula *would get* if classically normalized.

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Grigori Minc (1968): Yes, consider the quantifier prefix a formula *would get* if classically normalized.

For example, \forall quantifiers occurring at *positive* positions will remain \forall in the prefix.

Positive and Negative



Mints Hierarchy

- Π_1 All quantifiers at positive positions.
- Σ_1 All quantifiers at negative positions.
- Π_2 One alternation: some negative quantifiers in scope of some positive ones.
- Σ_2 One alternation: some positive quantifiers in scope of some negative ones.

And so on.

Lower bounds for Mints Hierarchy

- Π_1 2-UExptime-hard
- Σ_1 At least **Exptime**-hard
- Π_2 Undecidable
- $\Sigma_2 \ \ Undecidable$

Work in progress: with function symbols

- Class Σ_1 becomes undecidable.
- Class Π_1 is of the same complexity as before.

Let $\varphi = (I \to Tv) \to Ap(x)$, $\psi = I \to (D \to Tv) \to Ap(x)$ and $\vartheta = D \to Ap(x)$, and prove the formula

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The Assumptions	The Goal
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Τv

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$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Τv
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	$\forall x (\varphi ightarrow \psi ightarrow artheta ightarrow Ap(x))$

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$\forall x (\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Τv
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$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	$arphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)$
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Ap(x)
$arphi,\psi,artheta$	

The Assumptions	The Goal
$orall x(arphi o \psi o artheta o {Ap}(x)) o {Tv}$	Ap(x)
$\varphi = (I \rightarrow Tv) \rightarrow Ap(x), \vartheta = D \rightarrow Ap(x)$	
$\psi = I ightarrow (D ightarrow Tv) ightarrow Ap(x)$	

The Assumptions	The Goal
$\forall x (\varphi ightarrow \psi ightarrow artheta ightarrow Ap(x)) ightarrow Tv$	Ap(x)
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The Assumptions	The Goal
$orall x(arphi o \psi o artheta o Ap(x)) o Tv$	Ap(x)
$\varphi = (I \to Tv) \to Ap(x), \vartheta = D \to Ap(x)$	
$\psi = I ightarrow (D ightarrow Tv) ightarrow Ap(x)$	
$\forall x (\varphi ightarrow \psi ightarrow \vartheta ightarrow A p(x)) ightarrow T v$	I ightarrow Tv
$\varphi = (I \rightarrow Tv) \rightarrow Ap(x), \vartheta = D \rightarrow Ap(x)$	
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The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x)
$\varphi = (I \rightarrow Tv) \rightarrow Ap(x), \vartheta = D \rightarrow Ap(x)$	
$\psi = I ightarrow (D ightarrow Tv) ightarrow Ap(x)$	
$orall x(arphi o \psi o artheta o A p(x)) o T v$	I ightarrow Tv
$\varphi = (I \rightarrow Tv) \rightarrow Ap(x), \vartheta = D \rightarrow Ap(x)$	
$\psi = I ightarrow (D ightarrow Tv) ightarrow Ap(x)$	
$I, \forall x (\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow A p(x)) \rightarrow T v$	Tv
$\varphi = (I \rightarrow Tv) \rightarrow Ap(x), \vartheta = D \rightarrow Ap(x)$	
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The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Tv
$\varphi = (I ightarrow Tv) ightarrow Ap(x)$	
$I, \qquad \vartheta = D \to Ap(x)$	
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The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Tv
$\varphi = (I ightarrow Tv) ightarrow Ap(x)$	
$I, \qquad \vartheta = D \to Ap(x)$	
$\psi = I \rightarrow (D \rightarrow Tv) \rightarrow Ap(x)$	
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x))$
$\varphi(x) = (I \rightarrow Tv) \rightarrow Ap(x)$	
$I, \qquad \vartheta(x) = D \to Ap(x)$	
$\psi(x) = I \to (D \to Tv) \to Ap(x)$	

The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Tv
arphi = (I ightarrow Tv) ightarrow Ap(x)	
$I, \qquad \vartheta = D \to Ap(x)$	
$\psi = I \to (D \to Tv) \to Ap(x)$	
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x))$
$\varphi(x) = (I \rightarrow Tv) \rightarrow Ap(x)$	
$I, \qquad \vartheta(x) = D \to Ap(x)$	
$\psi(x) = I \to (D \to Tv) \to Ap(x)$	
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	$\varphi(\mathbf{x}') \rightarrow \psi(\mathbf{x}') \rightarrow \vartheta(\mathbf{x}') \rightarrow Ap(\mathbf{x}')$
$I, \qquad \varphi(x), \ \vartheta(x), \ \psi(x)$	

The Assumptions	The Goal
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Tv
$\varphi = (I ightarrow Tv) ightarrow Ap(x)$	
$I, \qquad \vartheta = D \to Ap(x)$	
$\psi = I \rightarrow (D \rightarrow Tv) \rightarrow Ap(x)$	
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	$orall x(arphi o \psi o artheta o Ap(x))$
$\varphi(x) = (I \rightarrow Tv) \rightarrow Ap(x)$	
$I, \qquad \vartheta(x) = D \to Ap(x)$	
$\psi(x) = I \to (D \to Tv) \to Ap(x)$	
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	$\varphi(\mathbf{x}') \rightarrow \psi(\mathbf{x}') \rightarrow \vartheta(\mathbf{x}') \rightarrow Ap(\mathbf{x}')$
$I, \qquad \varphi(x), \ \vartheta(x), \ \psi(x)$	
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Ap(x')
$ I, \qquad \varphi(x), \ \vartheta(x), \ \psi(x)$	
$\varphi(\mathbf{x}'), \ \vartheta(\mathbf{x}'), \ \psi(\mathbf{x}')$	

The Assumptions	The Goal
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Tv
$\varphi = (I ightarrow Tv) ightarrow Ap(x)$	
$I, \qquad \vartheta = D \to Ap(x)$	
$\psi = I \rightarrow (D \rightarrow Tv) \rightarrow Ap(x)$	
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	$orall x(arphi o \psi o artheta o Ap(x))$
$\varphi(x) = (I \rightarrow Tv) \rightarrow Ap(x)$	
$I, \qquad \vartheta(x) = D \to Ap(x)$	
$\psi(x) = I \to (D \to Tv) \to Ap(x)$	
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	$\varphi(\mathbf{x}') \rightarrow \psi(\mathbf{x}') \rightarrow \vartheta(\mathbf{x}') \rightarrow Ap(\mathbf{x}')$
$I, \qquad \varphi(x), \ \vartheta(x), \ \psi(x)$	
$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x)) \rightarrow Tv$	Ap(x')
$I, \qquad \varphi(x), \ \vartheta(x), \ \psi(x)$	
$\varphi(\mathbf{x}'), \ \vartheta(\mathbf{x}'), \ \psi(\mathbf{x}')$	

The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x')
$I, \qquad \varphi(\mathbf{x}), \vartheta(\mathbf{x}), \psi(\mathbf{x})$	
arphi(x') = (I o Tv) o Ap(x')	
$artheta(x')=D o {\cal Ap}(x')$	
$\psi(x') = I ightarrow (D ightarrow Tv) ightarrow Ap(x')$	

The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x')
$I, \qquad \varphi(\mathbf{x}), \vartheta(\mathbf{x}), \psi(\mathbf{x})$	
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$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Tv
$I, D, \qquad \varphi(x), \vartheta(x), \psi(x)$	
$\varphi(x') = (I ightarrow Tv) ightarrow Ap(x')$	
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$\psi(x') = I \to (D \to Tv) \to Ap(x')$	

The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x')
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$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Tv
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arphi(x') = (I o Tv) o Ap(x')	
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$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x')
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$\psi(x') = I \rightarrow (D \rightarrow Tv) \rightarrow Ap(x')$	
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$I, D, \varphi(x), \vartheta(x), \psi(x)$	
arphi(x') = (I ightarrow Tv) ightarrow Ap(x')	
artheta(x')=D o Ap(x')	
$\psi(x') = I \rightarrow (D \rightarrow Tv) \rightarrow Ap(x')$	
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x))$
$I, D, \qquad \varphi(x), \vartheta(x), \psi(x)$	
$arphi({f x}'), \hspace{0.2cm} artheta({f x}'), \hspace{0.2cm} \psi({f x}')$	
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x'')
$I, D, \varphi(x), \vartheta(x), \psi(x), \varphi(x'),$	
$artheta(\mathbf{x}'),\psi(\mathbf{x}'),arphi(\mathbf{x}''),artheta(\mathbf{x}''),\psi(\mathbf{x}'')$	

The Assumptions	The Goal
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x')
$I, \qquad \varphi(\mathbf{x}), \vartheta(\mathbf{x}), \psi(\mathbf{x})$	
arphi(x') = (I o Tv) o Ap(x')	
artheta(x') = D o A p(x')	
$\psi(x') = I \rightarrow (D \rightarrow Tv) \rightarrow Ap(x')$	
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Tv
$I, D, \varphi(x), \vartheta(x), \psi(x)$	
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$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	$\forall x(\varphi \rightarrow \psi \rightarrow \vartheta \rightarrow Ap(x))$
$I, D, \qquad \varphi(\mathbf{x}), \vartheta(\mathbf{x}), \psi(\mathbf{x})$	
$arphi(\mathbf{x}'), \hspace{0.2cm} \vartheta(\mathbf{x}'), \hspace{0.2cm} \psi(\mathbf{x}')$	
$\forall x(\varphi ightarrow \psi ightarrow \vartheta ightarrow Ap(x)) ightarrow Tv$	Ap(x'')
$I, D, \ arphi(x), artheta(x), \psi(x), arphi(x'), arphi(x'), arphi(x'), arphi(x'), arphi(x'), arphi(x'), arphi(x), arphi($	
$\vartheta(\mathbf{x}'), \psi(\mathbf{x}'), \varphi(\mathbf{x}''), \vartheta(\mathbf{x}''), \psi(\mathbf{x}'')$	

Nested quantifiers



Nested quantifiers



The tree of knowledge



The tree of knowledge



There may be different assumptions about each of the variables.

In other words, every node in the tree has a different "knowledge".



Assume *n* unary predicates.







Eden automaton

The proof-search procedure can be interpreted as a computation of an automaton.

The automaton operates on the tree of knowledge; nodes of the tree correspond to the various eigenvariables.

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The depth of the tree is bounded, the width is not.

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The state of the automaton corresponds to the proof goal.

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The state of the automaton corresponds to the proof goal.

The available assumptions on a variable y'' constitute the "knowledge" of node y'' of the tree. This can be modeled by memory registers associated to every node.

Assumptions about y'' = data written in registers at node y''Present goal P(y'') = machine at node y'' in state P.

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Present goal P(y'') = machine at node y'' in state P.

Using assumptions:

 $Q(x') \rightarrow P(y'')$ = change state from P to Q and move from node y'' to node x'.

Assumptions about y'' = data written in registers at node y''

Present goal P(y'') = machine at node y'' in state P.

Using assumptions:

 $Q(x') \rightarrow P(y'')$ = change state from P to Q and move from node y'' to node x'.

 $(R(x') \rightarrow Q(x')) \rightarrow P(y'') =$ as above; in addition write "1" to register R at node x'.

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 $R(x') \rightarrow Q(x') \rightarrow P(y'') =$ action possible only if register R at node x' is "1".

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 $R(x') \rightarrow Q(x') \rightarrow P(y'') =$ action possible only if register R at node x' is "1".

 $\forall z(T \rightarrow Q_0(z)) \rightarrow P(y'') = \text{create a new child } z' \text{ of } y'';$ enter node z' in initial state Q_0 . The tree of knowledge of good and...

Restricted access to data:

In intuitionistic logic one cannot reason from non-existence of assumptions, or delete assumptions.

The tree of knowledge of good and...

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In intuitionistic logic one cannot reason from non-existence of assumptions, or delete assumptions.

Therefore in an Eden automaton one cannot verify that a register is "0",

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Restricted access to data:

In intuitionistic logic one cannot reason from non-existence of assumptions, or delete assumptions.

Therefore in an Eden automaton one cannot verify that a register is "0",

One cannot also set a register to "0".

The tree of knowledge of good and... no evil

Restricted access to data:

In intuitionistic logic one cannot reason from non-existence of assumptions, or delete assumptions.

Therefore in an Eden automaton one cannot verify that a register is "0",

One cannot also set a register to "0".

In this tree there is only good!

Alternation



Existential choice because there may be more than one usable assumption.

Alternation

Existential choice because there may be more than one usable assumption.

Universal choice because an assumption may have more than one premise.

Alternation

- **Existential choice** because there may be more than one usable assumption.
- **Universal choice** because an assumption may have more than one premise.

(To derive Ap(x) from $\varphi \to \psi \to Ap(x)$ one has to prove both φ and ψ .)

An ID is a triple $\langle q, T, w \rangle$, where q is a state, T is a tree of knowledge, and w is the *current apple* (a node of T).

There is a fixed number of binary registers at every node.

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Possible actions:

Move the apple can up to the father of w or down to a nondeterministically chosen child of w;

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Possible actions:

- Move the apple can up to the father of w or down to a nondeterministically chosen child of w;
- Raise a selected flag at a given ancestor node of w;

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Possible actions:

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An ID is a triple $\langle q, T, w \rangle$, where q is a state, T is a tree of knowledge, and w is the *current apple* (a node of T).

There is a fixed number of binary registers at every node.

Possible actions:

- Move the apple can up to the father of w or down to a nondeterministically chosen child of w;
- Raise a selected flag at a given ancestor node of w;
- Check if a selected flag is up at a given ancestor of w;
- Create a new child of *w* and move the apple there.

The halting problem for Eden Automata is 2-UExptime hard.

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From a universal Turing Machine *M* working in time $2^{2^{O(n)}}$ and an input word *x* of length *n*

we construct (in Logspace) an Eden automaton A such that

M accepts x iff A terminates.



Provability of positive formulas is 2-UExptime hard.

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From an Eden automaton A we define (in Logspace) a positive first-order formula Φ such that

A terminates iff Φ is provable.