

Basic Model

- Single lane
- Car, pedestrians
 - ↳ Move in one direction
 - ↳ Generated randomly

Rules

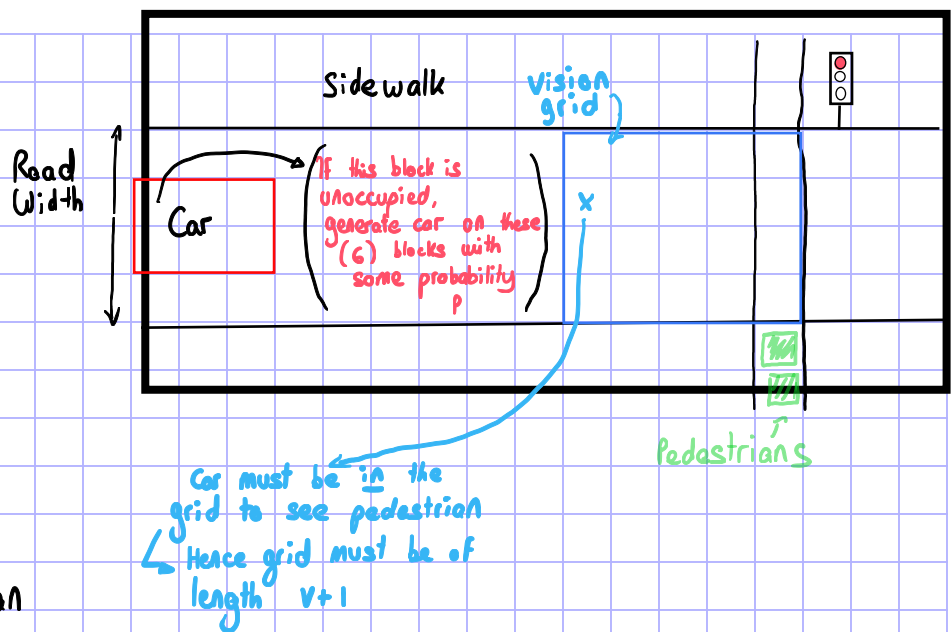
- Both sets of agents go or stop corresponding light says to

Unless: (i) Car

- Both car and pedestrian in "vision grid"
 - ↳ Stop

(ii) Pedestrians

- No car in vision grid
 - ↳ Could (should?) be a different grid



Consideration

Should vision have a vertical aspect?

e.g. If pedestrian is already halfway across road and will make it across before car gets there, should the car stop / make a decision based on this

↳ Equivalent to pedestrian decision to cross with a narrow miss from car

(any case?) ↳ In this case do pedestrians have perfect perception of the car's speed?

General thought process for basic model

- We should implement most/all of the parameters that will be important for the continuous positioning in later models
- ↳ Set these parameters to "agree" with this "discrete" model
 - e.g. Speed = 1 block
- ↳ Focus on having an idealised road crossing system, then make more realistic with stochasticity and finer movement

{ Aside: Road should be quite long so we can observe congestion }

Question: What do we hope to achieve with a median and a second lane? Should just produce a symmetrical result in either lane?