Event Calculus with duration

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Abstract

TODO

1 MAPF in event Calculus

Given a graph $G =< V, E >$, a list of agent R, a starting point and a goal for each agent $O =< A, V, V >$.

1.1 Fluents and Events

Event calculus is a sorted predicate calculus (with equality). There are the sorts:

- Timepoints : $\mathcal{T} = [0, 1, ...h]$.
- Fluents : $\forall r \in R, \forall v \in V, on(r, v) \in \mathcal{F}$.
- Event : $\forall r \in R, \forall < v_o, v_d > \in E, move(r, v_o, v_d) \in \mathcal{E}$.

1.2 The four predicates

- $happens \subseteq \mathcal{E} * \mathcal{T}$
- $holds\_at \subseteq \mathcal{F} * \mathcal{T}$
- $initiates \subseteq \mathcal{E} * \mathcal{F} * \mathcal{T}$
- $terminates \subseteq \mathcal{E} * \mathcal{F} * \mathcal{T}$

1.3 E : Domain independant axioms

1.3.1 Efect of events on fluents

If an event e happens, and this event has the effect of starting f, then f holds the moment after the event.

$$[happens(e, t-1) \ \wedge \ initiates(e, f, t-1)] \Rightarrow holds\_at(f, t) \tag{E.1}$$

If an event e happens, and this event has the effect of ending f, then f don't holds the moment after the event.

$$[happens(e, t-1) \ \wedge \ terminates(e, f, t-1)] \Rightarrow \neg holds\_at(f, t) \tag{E.2}$$

1.3.2 Inertia

If a fluent f holds and is not terminated, it continue to hold the next moment.

$$[holds\_at(f, t-1) \;\wedge\; \neg\exists e(happens(e, t-1) \;\wedge\; terminates(e, f, t-1))] \\ \Rightarrow holds\_at(f, t) \quad \text{(E.3)}$$

If a fluent f don't holds and is not started, it continue to not hold the next moment.

$$[\neg holds\_at(f, t-1) \;\wedge\; \neg\exists e(happens(e, t-1) \;\wedge\; initiates(e, f, t-1))] \\ \Rightarrow \neg holds\_at(f, t) \quad \text{(E.4)}$$

1.4 Σ : Effects

If an agent move, it goes to another vertice.

$$\forall move(r, v_o, v_d) \in \mathcal{E}, initiates(move(r, v_o, v_d), on(r, v_d), t) \quad (\Sigma.1)$$

If an agent move, he left his vertice.

$$\forall move(r, v_o, v_d) \in \mathcal{E}, terminates(move(r, v_o, v_d), on(r, v_o), t) \quad (\Sigma.2)$$

1.5 Γ : Observations

The agents have their starting vertices.

$$\forall < r, v_s, v_g > \;\; in\ O, holds\_at(on(r, v_s), 0) \quad (\Gamma_i)$$

The agents have their goals.

$$\forall < r, v_s, v_g > \;\; in\ O, holds\_at(on(r, v_g), h) \quad (\Gamma_f)$$

1.6 Ψ : Actions preconditions and State constraints

For an agent to move, he must be on the vertice.

$$happens(move(r, v_o, v_d), t) \Rightarrow holds\_at(on(r, v_o), t) \quad (\Psi.1)$$

An agent is on one vertice max at each time.

$$[holds\_at(on(r, v), t) \;\wedge\; v \neq v'] \Rightarrow \neg holds\_at(on(r, v'), t) \quad (\Psi.2)$$

1.7 Ω : Unique names

List of the unique names. [1]

$$U[move, on] \quad (\Omega)$$

[1] This is just to say that every on(something) is different to each move(something)

1.8 Domain description

$$CIRC[\Sigma; initiates, terminates] \wedge CIRC[\Delta; happens] \wedge \Omega \wedge \Psi \wedge \Gamma \wedge E \quad (\Phi)$$

- $\Sigma = \Sigma.1 \wedge \Sigma.2$
- Δ being the cojunction of all event occurence formulas (aka the "happens facts")
- Ω
- $\Psi = \Psi.1 \wedge \Psi.2 \wedge \Psi.3 \wedge \Psi.4$
- Γ being the cojunction of all observations (aka the "holds_at facts") counting Γ_i and Γ_f
- $E = E.1 \wedge E.2 \wedge E.3 \wedge E.4$

1.9 Planning

A planning problemm consist of taking Σ, Ω, Ψ, Γ (without Γ_f), Γ_f, and E as input, and producing as output zero or more Δ (our plan) such as Φ is consistant and $\Phi \models \Gamma_f$.

2 Approach

2.1 Without touching Event Calculus

2.2 With changes in Event Calculus

3 Discussion

Paper used :
mostly : [1].
`potassco.org`

References

[1] Erik T Mueller. *Commonsense Reasoning.* Elsevier, 2010.

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