

Lenguajes Formales y Computabilidad

Definiciones y Convenciones: Combo 13

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Defina:

1. $i^{n,m}$
2. $E_{\#}^{n,m}$
3. $E_{*}^{n,m}$
4. $E_{\#j}^{n,m}$
5. $E_{*j}^{n,m}$
6. $Halt^{n,m}$
7. $T^{n,m}$
8. $AutoHalt^{\Sigma}$
9. Los conjuntos A y N

Respuestas:

1. Sean $n, m \in \omega$ fijos. Definamos

$$i^{n,m} : \omega \times \omega^n \times \Sigma^{*m} \times \text{Pro}^{\Sigma} \rightarrow \omega$$

$$E_{\#}^{n,m} : \omega \times \omega^n \times \Sigma^{*m} \times \text{Pro}^{\Sigma} \rightarrow \omega^{[\mathbf{N}]}$$

$$E_{*}^{n,m} : \omega \times \omega^n \times \Sigma^{*m} \times \text{Pro}^{\Sigma} \rightarrow \Sigma^{*[\mathbf{N}]}$$

de la siguiente manera

$$\begin{aligned} & (i^{n,m}(0, \vec{x}, \vec{\alpha}, \mathcal{P}), E_{\#}^{n,m}(0, \vec{x}, \vec{\alpha}, \mathcal{P}), E_{*}^{n,m}(0, \vec{x}, \vec{\alpha}, \mathcal{P})) \\ &= (1, (x_1, \dots, x_n, 0, \dots), (\alpha_1, \dots, \alpha_m, \varepsilon, \dots)) \\ & (i^{n,m}(t+1, \vec{x}, \vec{\alpha}, \mathcal{P}), E_{\#}^{n,m}(t+1, \vec{x}, \vec{\alpha}, \mathcal{P}), E_{*}^{n,m}(t+1, \vec{x}, \vec{\alpha}, \mathcal{P})) \\ &= S_{\mathcal{P}}(i^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P}), E_{\#}^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P}), E_{*}^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P})) \end{aligned}$$

2. Definamos para cada $j \in \mathbf{N}$, funciones

$$\begin{aligned} E_{\#j}^{n,m} &: \omega \times \omega^n \times \Sigma^{*m} \times \text{Pro}^\Sigma \rightarrow \omega \\ E_{*j}^{n,m} &: \omega \times \omega^n \times \Sigma^{*m} \times \text{Pro}^\Sigma \rightarrow \Sigma^* \end{aligned}$$

de la siguiente manera:

$$\begin{aligned} E_{\#j}^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P}) &= j - \text{ésima coordenada de } E_{\#}^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P}) \\ E_{*sj}^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P}) &= j - \text{ésima coordenada de } E_*^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P}) \end{aligned}$$

3. Dados $n, m \in \omega$, definamos:

$$\text{Halt}^{n,m} = \lambda t \vec{x} \vec{\alpha} \mathcal{P} [i^{n,m}(t, \vec{x}, \vec{\alpha}, \mathcal{P}) = n(\mathcal{P}) + 1]$$

4. Dados $n, m \in \omega$, $T^{n,m} = M(\text{Halt}^{n,m})$

5. Cuando $\Sigma \supseteq \Sigma_p$, definimos:

$$\text{AutoHalt}^\Sigma = \lambda \mathcal{P} [(\exists t \in \omega) \text{Halt}^{0,1}(t, \mathcal{P}, \mathcal{P})]$$

6. Cuando $\Sigma \supseteq \Sigma_p$, definimos:

$$\begin{aligned} A &= \{\mathcal{P} \in \text{Pro}^\Sigma : \text{AutoHalt}^\Sigma(\mathcal{P}) = 1\} \\ N &= \{\mathcal{P} \in \text{Pro}^\Sigma : \text{AutoHalt}^\Sigma(\mathcal{P}) = 0\} \end{aligned}$$