MIDTERM REVIEW Wednesday, March 18, 2015 Regular class

MIDTERM EXAM
Open book and notes (not Internet)
Saturday, March 21, 2015
8:00 am - 12:00 pm (4 hours)

Room LW-844

Assignment 6. Due: 03/09/15

14. Consider a modified grammar of Zones. The only difference is the definition of function *ALPHA*:

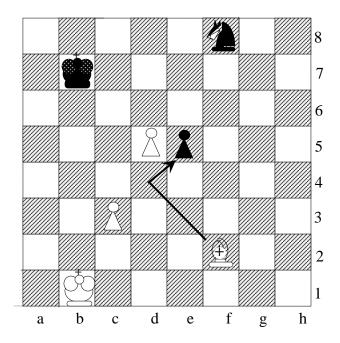
$$\begin{aligned} & D(\textit{ALPHA}) = X \times P \times L_{t}^{\textit{lo}}(S) \times \mathbf{Z}_{+} \\ & \textit{ALPHA}(x, p_{o}, t_{o}, k) = \begin{cases} \textit{min}(\textit{NEXTTIME}(x), k), & \text{if } \textit{DIST}(x, p_{o}, t_{o}) < 2n, \\ & \textit{NEXTTIME}(x), & \text{if } \textit{DIST}(x, p_{o}, t_{o}) = 2n. \end{cases} \end{aligned}$$

What is the impact of this new definition on the Zones to be generated by this grammar? Show examples of such Zones. Explain.

Extra Credit.

Do we have to change function *timer* in this case? See "Translations of Languages" in the textbook on LG. Explain.

Second Negation



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S(u, v, w) \rightarrow A(u, v, w)
                                                                                                                                                                                                                                                                                                             two
                                                                                                                                                                                                                                                                                                                                           Ø
                      Q_2 \quad A(u, v, w) \rightarrow t(h_i^0(u), l_0+1)
                                                                                                                                                                                             TIME(z) = DIST(z, h_i^0(u))
                                                                                                                                                                                                                                                                                                                  3
                                                                                                                                                                                                                                                                                                                                           Ø
                                                                                              A((0, 0, 0), g(h_{i}^{0}(u), w), zero)
                                          A(u, v, w) \rightarrow A(f(u, v), v, w)
                                                                                                                                                                                             NEXTTIME(z)=
                                                                                                                                                                                                                                                                                                           four
                                                                                                                                                                                                                                                                                                                                            5
                                                                                                                                                                                             init(u, NEXTTIME(z))
                                                                                                                                                                                                                                                                                                                 3
                                                                                                                                                                                                                                                                                                                                             3
                      Q_4 A(u, v, w) \rightarrow t(h_i(u), TIME(y))
                                                                                                                                                                                             NEXTTIME(z) =
                                                                                                A(u, v, g(h_i(u), w))
                                                                                                                                                                                              ALPHA(z, h_j(u), TIME(y) - l_j+1)
                                                                                                                                                                                             TIME(z) = NEXTTIME(z)
                      Q_5 = A(u, v, w) \rightarrow A((0, 0, 0), w, zero)
                                                                                                                                                                                                                                                                                                                                             6
                      Q_6 \quad A(u, v, w) \rightarrow e
                                                                                                                                                                                                                                                                                                                                             ø
 \mathbf{Q_1}(u) = (\overrightarrow{\mathrm{ON}}(p_0) = x) \wedge (\mathrm{MAP_{X,p_0}}(y) \leq l \leq l_0) \wedge (\exists q \ ((\mathrm{ON}(q) = y) \wedge (\mathrm{OPPOSE}(p_0,q))))
                                                                                    Q_3(u) = (x \neq n) \lor (y \neq n)
 Q_4(u) = (\exists p ((ON(p) = x) \land (l > 0) \land (x \neq x_0) \land (x \neq y_0)) \land ((\neg OPPOSE(p_0, p) \land (q \neq y_0))) \land ((\neg OPPOSE(p_0, p) \land (q \neq y_0))) \land (q \neq y_0)) \land
                                (\underline{\mathsf{MAP}}_{\mathsf{X},\mathsf{p}}(\mathsf{y})=1)) \vee (\underline{\mathsf{OPPOSE}}(\mathsf{p}_0,\mathsf{p}) \wedge (\underline{\mathsf{MAP}}_{\mathsf{X},\mathsf{p}}(\mathsf{y}) \leq l\;))) \;\; \boldsymbol{Q}_{\mathsf{5}}(w) = \; (w \neq zero) \; : \boldsymbol{Q}_{\mathsf{6}} = T
init(u,r) = \begin{cases} 2n, & \text{if } u = (0,0,0), \\ r, & \text{if } u \neq (0,0,0). \end{cases}
f(u, v) = \begin{cases} (x+1,y,l), & \text{if } ((x \neq n) \land (l > 0)) \lor ((y = n) \land (l \leq 0)) \\ (1, y+1, TIME(y+1) \times v_{y+1}), & \text{if } (x = n) \lor ((l \leq 0) \land (y \neq n)). \end{cases}
 Let t_o \in L_t^{l_0}(S), t_o = a(z_o)a(z_1)...a(z_m), t_o \in t_{D_o}(z_o, z_m, m);
  If ((z_m = y_0) \land (p = p_0) \land (\exists k (1 \le k \le m) \land (x = z_k))) \lor
               (((z_m \neq y_O) \lor (p \neq p_O)) \land (\exists \ k \ (1 \leq k \leq m \text{ - } 1) \land (x = z_k)))
               then DIST(x, p_0, t_0) = k+1 else DIST(x, p_0, t_0) = 2n
                                                                                                                  max (NEXTTIME (x), k), if (DIST (x, p_0, t_0) \neq 2 n)
                                                                                                                                                                                                                                        \wedge (NEXTTIME (x) \neq 2 n);
    ALPHA (x, p_0, t_0, k) =
                                                                                                                                                                                                                   if
                                                                                                                                                                                                                                                 DIST (x, p_0, t_0) \neq 2n
                                                                                                                                                                                                                                        \wedge (NEXTTIME (x) = 2 n);
                                                                                                                   NEXTTIME (x),
                                                                                                                                                                                                                                if DIST(x, p_0, t_0) = 2n).

\frac{\mathbf{g_r}(\mathbf{p_o}, \mathbf{t_o}, w) = \begin{cases} 1, & \text{if } \mathbf{DIST}(\mathbf{r}, \mathbf{p_o}, \mathbf{t_o}) < 2n, \\ w_r, & \text{if } \mathbf{DIST}(\mathbf{r}, \mathbf{p_o}, \mathbf{t_o}) = 2n. \end{cases}} 
\text{TRACKS}_{p_0} = \{\mathbf{p_o}\} \times (\bigcup L[\mathbf{G_t^{(2)}}(\mathbf{x}, \mathbf{y}, \mathbf{k}, \mathbf{p_o})] 

                                                                                                                                                                                                                                                     1 \le k \le l
 If TRACKS_{po} = e
            then h_i^o(u) = e
            else TRACKS<sub>p<sub>o</sub></sub> = {(p<sub>o</sub>,t<sub>1</sub>), (p<sub>o</sub>,t<sub>2</sub>),..., (p<sub>o</sub>,t<sub>b</sub>)}, (b \le M) and h_i^o(u) = \begin{cases} (p_o,t_i), & \text{if } i \le b, \\ (p_o,t_b), & \text{if } i > b. \end{cases}
                                                                                                                 TRACKS = \cup TRACKS<sub>p</sub>, where TRACKS<sub>p</sub> is the same as for h_i^o
 If TRACKS = e
                                                                                                                                                          ON(p)=x
            then h_i(u) = e
             \textbf{else TRACKS} = \{(p_1, t_1), (p_1, t_2), \dots, (p_m, t_m)\}, \ (m \leq M) \ \textbf{and} \ \textbf{\textit{h}}_i(u) = \begin{cases} (p_i, t_i), & \text{if } i \leq m, \\ (p_m, t_m), & \text{if } i > m. \end{cases}
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At the beginning : $u = (x_0, y_0, l_0)$, w = zero, v = zero, $x_0 \in X$, $y_0 \in X$, $l_0 \in \mathbb{Z}_+$, $p_0 \in P$, and TIME(z)=2n, NEXTTIME(z)=2n for all z from X.