

# **PROMETHEUS AI PHASE 1**

Sean Stappas  
260639512

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**Abstract**

**Acknowledgments**

# Contents

<b>1</b>	<b>Introduction</b>	<b>3</b>
<b>2</b>	<b>Background</b>	<b>3</b>
2.1	Neural Network . . . . .	3
2.2	Knowledge Node Network . . . . .	3
2.3	Expert System . . . . .	3
2.4	Meta Reasoner . . . . .	3
<b>3</b>	<b>Problem</b>	<b>3</b>
3.1	Specifications . . . . .	3
3.1.1	Expert System . . . . .	3
3.1.2	Knowledge Node Network . . . . .	4
<b>4</b>	<b>Design</b>	<b>4</b>
4.1	Abstraction . . . . .	4
4.2	Speed . . . . .	4
4.3	Object Oriented Design . . . . .	4
4.4	Documentation . . . . .	4
4.5	Layer Design . . . . .	4
4.5.1	Expert System . . . . .	4
4.5.2	Knowledge Node Network . . . . .	5
<b>5</b>	<b>Plan for Next Semester</b>	<b>5</b>
5.1	Finalization of the Knowledge Node Network . . . . .	5
5.2	Finalization of the Expert System . . . . .	5
5.3	Integration . . . . .	5
5.4	Simulation Testing . . . . .	5
5.5	Physical Testing . . . . .	5
<b>6</b>	<b>Impact on Society and the Environment</b>	<b>5</b>
6.1	Use of Non-renewable Resources . . . . .	5
6.2	Environmental Benefits . . . . .	5
6.3	Safety and Risk . . . . .	5
6.4	Benefits to Society . . . . .	5
<b>7</b>	<b>Conclusion</b>	<b>5</b>
	<b>References</b>	<b>7</b>

## Abbreviations

NN	Neural Network
KNN	Knowledge Node Network
ES	Expert System
META	Meta Reasoner
OOP	Object-Oriented Programming

## 1 Introduction

The goal of this project is to create an AI model of the human brain to coordinate and control multiple robots. Applications for this type of system include robots in hazardous environments, such as in outer space (Mars, Moon, etc.), in nuclear plants after a nuclear disaster, and in military zones.

The design of this model consists of four main layers: the Neural Network (NN), the Knowledge Node Network (KNN), the Expert System (ES), and the Meta Reasoner (META). These will be described in Section 2.

## 2 Background

### 2.1 Neural Network

The NN layer consists of a network of neurons with a similar structure to neurons in the human brain. In the context of this project, it is the interface between the robots' sensors and the rest of the AI system. Informational tags are generated by this layer based on observations that the robots make in their environment. These tags are passed

### 2.2 Knowledge Node Network

The KNN layer represents memory in the human brain. It takes in the tags provided by the NN and outputs tags based on its knowledge of the environment. These output tags can be simple facts, such as "I see a wall", or can be recommendations for future actions such "Turn left". These tags are passed on to the next layer, the Expert System (ES).

### 2.3 Expert System

The ES layer is a decision maker based on pure facts. It is not aware of its current reality, or any context. It simply has a list of known Facts, in the form of tags, and outputs tags based on known relationships, called Rules. These output tags are passed on to the final layer, the Meta Reasoner (META).

### 2.4 Meta Reasoner

The META layer represents high-level reasoning in human brains. It is aware of its environment and context, and makes decisions based on what it believes to be right. It is paranoid, and constantly checks whether the tags reported by the rest of the AI system make sense based on its expected view of the world. Once it makes a decision, it sends a command to the actuators of the robots to decide how to move.

## 3 Problem

The assigned task was to construct two out of the four layers listed in Section 2: the Expert System (ES), and the Knowledge Node Network (KNN). The other two layers are to be completed by another Honours Thesis student.

As a deliverable for the end of this first semester, it was required to complete a prototype of these two layers, with basic versions of the functionality described in Section 2. This was to be done entirely in Java.

### 3.1 Specifications

The initial specifications provided by Prof. Vybihal on the Expert System and Knowledge Node Network will now be described.

#### 3.1.1 Expert System

According to specifications by Prof. Vybihal [1], the Expert System layer consists of a list of facts, a list of recommendations, and a list of rules.

### 3.1.2 Knowledge Node Network

The Knowledge Node Network consists of a mapping of input tags to their associated knowledge nodes, as well as tags that are known to be active, either from the Neural Network layer, or the KNN layer itself.

## 4 Design

### 4.1 Abstraction

One important design aspect is that the system should be as abstract as possible, while still performing its desired task. For instance, the system should be general enough to perform under simulations, as well as in real-life environments. It should also ideally be able to perform in vastly different environments, with different tasks.

One example of making use of abstraction is the choice to create an interface for both the ES and KNN, since they share some functionality, like the ability to think.

### 4.2 Speed

A very important consideration when designing the system is speed. Since the robots may have to react very quickly to stimulus in the environment, the reasoning in the AI must be as fast as possible. This is especially true in the hazardous environments for which this system could be useful for, as specified in Section 1. An example of a design choice that was made to improve speed is the use of Java Sets for most of the collections in the ES and KNN layers. The original specifications mentioned using ArrayLists, but, since there is no specific iteration order necessary for most operations in the ES and KNN, these collections were changed to Sets.

### 4.3 Object Oriented Design

Another important choice is to leverage object-oriented design as much as possible. Object-oriented programming (OOP) allows extensive planning before even beginning to write

code, which can identify any flaws in the initial design. It also allows the code to be very clean and reusable. Since Java is the programming language chosen for the project, OOP is also the natural way to proceed. To follow OOP, all the structures described in Section 2 will be designed around Java classes and the methods associated with those classes. OOP principles such as polymorphism and encapsulation will be followed closely.

For example, the “tags” described in Section 2 need to be as general as possible. A natural choice for this structure would be a Java String, which would be relatively simple to pass around the system. However, these tags represent various concepts; each tag can either be a Fact, a Recommendation, or a Rule. If implemented as Strings, the tags would have to be encoded on creation to represent each concept and decoded on use to retrieve the important information. This seems like a bad use of the OOP principles of Java. For this reason, the tags are instead implemented using a Tag Java class, with Recommendation, Fact, and Rule subclasses. This should also make manipulating the Tags faster, while incurring a slight memory overhead. To store these Tags in a database, they can be converted to JSON format. On read from the database, they can be easily decoded.

### 4.4 Documentation

Proper documentation of the source code is very important, to ensure that anyone wanting to work with the code which was designed has an easy time doing so. This is achieved through extensive Javadoc of the entire code base.

### 4.5 Layer Design

The details of the specific design choices for the Expert System and Knowledge Node Network will now be discussed.

#### 4.5.1 Expert System

The Expert System layer is based around the ExpertSystem Java class.

#### **4.5.2 Knowledge Node Network**

The Knowledge Node Network layer is based around the KnowledgeNodeNetwork Java class.

### **5 Plan for Next Semester**

The plan for next semester is to finalize the two layers that were started this semester, and to test them on the robots available in Prof. Vybihal's lab.

#### **5.1 Finalization of the Knowledge Node Network**

#### **5.2 Finalization of the Expert System**

#### **5.3 Integration**

One very important task left to be done is to integrate the two layers described in this report (ES and KNN) with the other layers developed separately (NN and META). Ideally, the layers should be able to work together, but there will surely be some conflicts at the interface of the layers. These will have to be resolved when the time comes.

#### **5.4 Simulation Testing**

Once all the layers are functioning together, they can be tested. The first and easiest way to test would be in a simulated environment. One simulator that may be used is Simbad, which is a Java 3D robot simulator [2]. This can allow for some early debugging and fixes.

#### **5.5 Physical Testing**

Once the simulation testing is completed and working properly, the system can be tested in the lab. Prof. Vybihal's lab has multiple robots with ultrasonic sensors, and these will be the test subjects of this phase.

## **6 Impact on Society and the Environment**

As purely a software project, there is little to discuss in the ways of impact on society, and the environment. This section will focus on describing the possible impact if, in its final state, this product were used

### **6.1 Use of Non-renewable Resources**

As a purely software-oriented project, there are no physical materials needed to construct this system.

### **6.2 Environmental Benefits**

The system could be used as a tool to control robots in dangerous environments such as nuclear plants after a radioactive disaster. Indeed, the system could coordinate robots to help contain the damage faster than humans could, thus limiting the risk on the environment.

### **6.3 Safety and Risk**

It is critical that, once this system is completed, it is used in an ethical way, and for the right purposes.

### **6.4 Benefits to Society**

Going back to the example use case in a radioactive disaster, the system could be used to send robots in an area that would otherwise be very dangerous for humans. This would therefore help prevent the unnecessary loss of life in cleaning up these leaks.

## **7 Conclusion**

This semester, prototypes of the Expert System (ES) and Knowledge Node Network (KNN) layers of the AI model were completed in Java. These prototypes were tested individually and together, with positive results.

The main goal for next semester is to finalize the entire system, implementing more complex features that were omitted for this prototype stage.

## References

- [1] J. Vybihal, “Full AI model,” 2016.
- [2] “Simbad 3d robot simulator,” <http://simbad.sourceforge.net/index.php>, (Accessed on 03/27/2017).