CISC 204 Modelling Project Report

Group 12: Michael Cassidy, Kieran Green, Cooper Moses, Mike Stefan

**Project Summary**

Our project aims to solve the possible different routes a vehicle could take to get to a destination given a grid of intersections which is randomly generated with red-lights, one-way roads, two-way roads, and busy pedestrian traffic. The grid of intersections will be given the number of rows and columns and the number of one-way roads per row and column. This number is easily changeable and will make it easy to test wildly different test cases. The one-way roads will randomly be given a direction based on a boolean value given to them. For one-way roads going north and south, 1 will mean that vehicles can only travel north and 0 means that vehicles can only travel south. For one-way roads going east and west, 1 will mean that vehicles can only travel east and 0 means that vehicles can only travel west.

The rest of the roads will be assumed to be two-way roads. An 2D-array will then be made to fit the size of the grid. This will serve as the map the car will drive through. Each index in the array will serve as an intersection which has generated rules based on the roads that cross there. Some examples of these rules are a light blocking traffic going either North/South or East/West, as well if the intersection is at the edge of the grid the car will also not be able to go off the map.

**Propositions:**

* Mx, y: where x and y correspond to the grid location that car is at.
* Gx, y: position of the goal the car must get to.
* L: the car turns left at the intersection
* R: the car turns right at the intersection
* S: the car goes straight at the intersection
* E: the car has reached a dead end
* W: the car has reached the goal
* C: the light is red in front of the car
* Di: Where i is the direction the car is facing (N, E, S, W)

**Constraints:**

* (G2, 2 M2, 2) W
  + If the car is at the goal, then the car has reached the goal.
* (~C  **~** ((DN Mk,2) (DS Mk,0)( DE M2, k)( DW M0, k))) S
  + The car goes straight if the light is not red, and the direction of the car is not pointed off the map. K represents any value that correlates to the map. The example takes place in 3x3 grid with the bottom left corner being (0, 0) and the top left corner being (2,2), so k is a integer between 0 and 2. If it is at the bottom of the map then it’s position is Mk, 0 and if it is direction is DS (South). That means if it goes straight, it will go off the map so it is not allowed to go straight.
* (~S ~L ~R) E
  + If the car cannot move then it has reached a dead end.

**Jape Proof Ideas:**

NOTE: jape proofs are just if the turns are possible, they do not take into account the path that needs to be taken or that one turn must be selected, they just use the Boolean of if the option is available.

Because we can’t use full words in jape, we define our variables with (some are not used in the examples):

* T = left
* R= right
* S = Straight
* G= green
* B = busy (cars)
* P = busy (people)
* A = left turn advance
* D = lights
* E = stop sign
* H = one-way (no crossroads)
* Q = four-way
* F = four-way (with one way across)
* C = T-shaped road

1. The idea is that: on a four-way road given that a left turn is possible, a right turn is possible and a straight-through is never possible, the light must be an advance on a non-busy street.

This means we get the following using only the necessary constraints:

¬S, T, Q, R, T→(A∨(¬B∧G)), G→S,(A∧B)→¬R ⊢ A∧¬B

Left implies an advance or it's not busy and green.

Green implies you can go straight.

advance and busy implies you cannot turn right as there will be cars turning into that lane.

A screenshot of a computer

Description automatically generated

1. The idea is that: if you can turn both straight and right but not left, there is no light, and it is not people busy, it must be a stop sign on a T-shaped road or a four-way with a one-way street.

The equation for this problem is: S, R, ¬T ,¬D , ¬P, R→¬H, (R∧¬D)→(E∧¬P), (E∧¬P∧¬T)→(C∨F∨H) ⊢ (C∧E)∨(F∧E) with the constraints as ordered:

right turn implies it is not a one-way street with no crossroads.

if you can go right and there are no streetlights, it must be a stop sign and not people busy.

if there’s a stop sign and it is not people busy, but you cannot turn left, it must be the street layout having no lane for left making it either a one-way (with crossroads) or a T-shaped road configuration.

A screenshot of a computer

Description automatically generated

1. The idea is that: at a four-way If you can go straight and right, the road must be car-busy, but not people busy. The light must also be green to go straight.

The Equation for this is: R, S, D, ¬T, (R∧G)→¬P, (¬T∧G)→(P∨B), (S∧D)→G ⊢ B∧¬P

The constraints are as follows:

If you can go right and it is green, it cannot be people busy

If you cannot go left and its green, it must be people or car busy

If you can go straight and there's lights, the light must be green

A white background with black text

Description automatically generated

**Model Exploration**

We take the robots current position and evaluate all three possible answers, checking can the robot turn left, turn right or go straight. We then make that step, simulating the car has made that move, then complete the same checks for the new intersection. Due to the nature of this problem, we decided that solving this recursively was the best option. Our program will keep checking every possible route recursively until a route finds the target or an invalid route. A route doesn’t find a route if it ends in some position that all possible movements (left, right or straight) are all invalid, or it reaches an intersection it has already been in from the same direction you entered it the first time. For example, you entered intersection [1,1] from the south as the second move, make 4 right turns and enter [1,1] from the south as the 6th move. This would create a loop, which would cause us to have infinite possible paths. The moment an end is found, either the target point, or an invalid route the recursion branch is ended. Any path the end in an invalid answer is ignored, and all valid paths are combined into a giant constraint by performing an exclusive or on all the paths (path1 xor path2 xor path3). For all relevant places in this document xor will be used rather than the equation to maintain readability. Really, each path is a combination of our left, right and straight propositions. For example, a winning path that took 2 lefts and no other turn would look like this: (left0 & ~right0 & ~straight0 & left1 & ~right1 & ~straight1). To translate that, your first move was to turn left, not turn right and not go straight and your second move was the same, but with a second set of propositions. With this system programmed in a basic example we discovered a logical issue; this system will over count the number of possible routes if there are routes that are different lengths. For this testing we defined a simplified example, our car will reach the goal the moment it makes a left turn and lose if it makes 1 straight movement or 2 right turns. This would create the constraint of ((left0 & ~right0 & ~straight0) xor (~left0 & ~right0 & straight0 & left1 & ~right1 & ~straight1)). To translate this into English, you turned left on your first movement, winning that path or you went straight then turned left. The issue with this system stems from the different number of propositions. The left side of the xor does not constraint ANY of the possible movement propositions from a second movement. This creates several truth tables which satisfy this constraint but would not be valid car actions. For example, both left0 and right1 could be true and that equation would be satisfied, but turning right on the second motion would not actually satisfy the system.

This issue was not evident to use until we after we ran the program. To help figure out why this was an issue we used the Bauhaus pprint() function which prints a nicely formatted string representing our constraint in NNF form. Unfortunately, this function has a slight bug in the docker terminal, instead of printing the logical operator characters “∧” and “∨” it errored and prints the ascii missing character “�”. We fixed this issue by locating the bauhaus/core.py as installed by pip file in the docker, force giving us read/write/execute permissions on this file with chmod 777 and editing the file to replace the broken characters with “&” and “|” respectively. This fixed the bug in the function and allowed us to print a full NNF version of our constraint which we could use to generate a truth table and see what caused our logical issue mentioned above.

We spent a significant portion of time trying to debug this issue, but we eventually concluded that there was no good way to solve it for this test case. This is because depending on what we set the win and loss conditions to, there are infinite numbers of possible propositions. Instead, we pivoted to using our actual use case as the testing grounds for our code. We set up the map but ignored factors like traffic lights and one-way streets to keep things simple in the beginning. Since we have a map of a pre-specified size, we know exactly how many propositions there can possibly be for a given run of our code. There will be three propositions per direction we can enter each intersection, since we can move left right or straight. There are four directions per intersection and the intersection are on an M by N grid. This means there are (M\*N\*4\*3) propositions for a given map. In our new approach, we predefined all the possible propositions, then used our same recursive algorithm for the car to move around. As the car moves around, we store a list of all the positions it’s been to and the proposition which would have to be satisfied for that movement to work. We then conjunct all the propositions from a given path. We then conjunct that with the negation of all the other propositions in the grid. Finally, we disjunct our current constraint with every other possible path. This leaves us with a constraint which is only satisfied when exactly one correct path is taken. Our current implementation of this has a logic error during the assembly of the constraint, but this will be fixed for later versions of the project.

**First-Order Extension**

Our code in its current state has yet to implement all the features in our original plans. The first thing we want to add is for the car to consider the red lights at an intersection which will limit where it is allowed to turn. We want to do this with propositions and constraints rather than hard coded. Another thing we want to turn into using propositions is the way we generate our grid. Currently, we are just using hard code but we want to try to use propositions. We also want to add busy pedestrian crosswalks at an intersection. These will act like a red light but will block turns on a green light. There will also be advanced lefts where the car is only able to turn left or right.