

# Discrete Event Systems

## Exercise 6

### 1 Chomsky Normal Form

Convert the following CFGs into an equivalent CFGs in *Chomsky normal form*.

$$A \rightarrow BAB \mid B \mid \varepsilon$$

$$B \rightarrow 00 \mid \varepsilon.$$

### 2 CFL Closure Properties

Prove that the class of CFLs is closed under the regular operators union, catenation, and Kleene star. Formally, let  $L$  and  $L'$  be languages generated by the context free grammars  $G$  and  $G'$ , respectively. Show that the languages  $L \cup L'$ ,  $LL'$ , and  $L^*$  are context free languages.

### 3 Context Sensitive Languages

In this exercise you will study a sample language which is not context-free:  $L = \{zz \mid z \in \{0, 1\}^*\}$ .

- Prove that  $L$  is not context-free.  
Hint: Tandem pumping!
- Show that  $L$  is context-sensitive by providing a corresponding grammar.

## 4 Transducer-Robot

The goal of this exercise is to program a robot to follow a wall. This is an example for a *transducer*. See Figure 1. The robot's world is a grid, any square is either free or occupied by a wall. The robot, shown as an arrow, is placed on an arbitrary free square facing one of the four possible directions. The robot has two binary sensors (inputs): **h** (head) signals whether the square in front of the robot is free ( $h = 0$ ) or occupied by a wall ( $h = 1$ ). **r** (right) provides the same information for the square to the right of the robot. The robot is capable of two primitive actions: **R** turns right by  $90^\circ$  while remaining on the same square; **F** (forward) advances one square in the robot's current direction. Note that the robot's actions correspond to an output alphabet, hence the robot is a *transducer*.

The robot must be programmed to find a piece of wall, then endlessly cycle along the inside of the wall, touching it with its right side!

Program the robot as a transducer that solves this task!

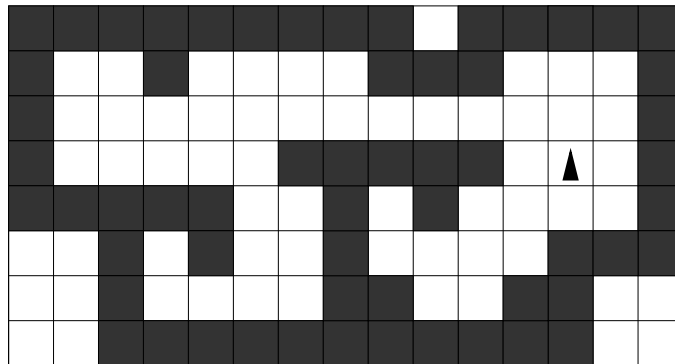


Figure 1: The robot's world is limited!