# Caractérisation algébrique des relations acceptées par transducteurs bidirectionnels unaires 

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## 1-way automaton over $\Sigma$

$(Q, q-, F, \delta) \stackrel{山^{4}}{\longleftrightarrow}$ transition set: $\subset Q \times \Sigma \times Q$


## 2-way automaton over $\Sigma$

$\left(Q, q_{-}, F, \delta\right) \stackrel{山^{\longleftrightarrow}}{\longleftrightarrow}$ transition set: $\subset Q \times \Sigma_{\triangleright, \triangleleft} \times\{-1,0,1\} \times Q$


## 2-way transducer over $\Sigma$, Г

$\left(Q, q_{-}, F, \delta\right) \stackrel{(A, \phi)}{\longleftrightarrow}$


## A simple example: SQUARE $=\left\{(w, w w) \mid w \in \Sigma^{*}\right\}$



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- copy the input word


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- copy the input word
- rewind the input tape


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## Rational operations

- Union

$$
R_{1} \cup R_{2}
$$

- Componentwise concatenation

$$
R_{1} \cdot R_{2}=\left\{\left(u_{1} u_{2}, v_{1} v_{2}\right) \mid\left(u_{1}, v_{1}\right) \in R_{1} \text { and }\left(u_{2}, v_{2}\right) \in R_{2}\right\}
$$

- Kleene star

$$
R^{*}=\left\{\left(u_{1} u_{2} \cdots u_{k}, v_{1} v_{2} \cdots v_{k}\right) \mid \forall i\left(u_{i}, v_{i}\right) \in R\right\}
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Definition $\left(\operatorname{Rat}\left(\Sigma^{*} \times \Gamma^{*}\right)\right)$
The class of rational relations is the smallest class:

- that contains finite relations
- and which is closed under rational operations


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Theorem (Elgot, Mezei - 1965)
1-way transducers $=$ the class of rational relations.

## Hadamard operations

- H-product

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Example: $\operatorname{SQUARE}=\left\{(w, w w) \mid w \in \Sigma^{*}\right\}=$ Identity $\oplus$ Identity


- copy the input word
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Example: UnaryMult $=\left\{\left(a^{n}, a^{k n}\right) \mid k, n \in \mathbb{N}\right\}=$ Identity $^{H \star}$


## H-Rat relations

Definition
A relation $R$ is in $H-\operatorname{Rat}\left(\Sigma^{*} \times \Gamma^{*}\right)$ if

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R=\bigcup_{0 \leq i \leq n} A_{i} \oplus B_{i}^{H \star}
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where for each $i, A_{i}$ and $B_{i}$ are rational relations.

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\left\{\left(a^{n}, a^{2 n}\right) \mid n \in \mathbb{N}\right\} \oplus\left(\left\{\left(a^{n}, a^{n}\right) \mid n \in \mathbb{N}\right\}^{H \star}\right.
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Theorem ( This talk .-)
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Theorem ( This talk ..)
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Proof

- つ. easy
- $\subseteq$ : difficult part


## Known results

- 2-way functional $=$ MSO definable functions
[Engelfriet, Hoogeboom - 2001]
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When 「 = $\{a\}$ :

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When $\Gamma=\{a\}$ :

- 2-way unambiguous $\longrightarrow$ 1-way
[Anselmo - 1990]
- 2-way unambiguous = 2-way deterministic
[Carnino, Lombardy - 2014]


## From H-Rat to 2-way transducers

> Property
> The family of relations accepted by 2-way transducers is closed under $U,(\leftrightarrow)$ and $H \star$.

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Property
The family of relations accepted by 2-way transducers is closed under \(U,(A)\) and \(H \star\).
Proof.
- \(R_{1} \cup R_{2}\) :
- simulate \(T_{1}\) or \(T_{2}\)
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## From H-Rat to 2-way transducers

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The family of relations accepted by 2-way transducers is closed under $\cup,(H)$ and $H \star$.
Proof.

- $R_{1} \cup R_{2}$ :
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- $R_{1} \oplus R_{2}$ :
- simulate $T_{1}$
- rewind the input tape
- simulate $T_{2}$


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- simulate $T_{2}$
- $R^{H^{\star}}$ :
- repeat an arbitrary number of times:
- simulate $T$
- rewind the input tape
- reach the right endmarker and accept


## From H-Rat to 2-way transducers

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The family of relations accepted by 2-way transducers is closed under $U,(H)$ and $H^{\star}$.

Corollary


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Corollary


## From 2-way transducers to H-Rat (unary case)

A first ingredient, a preliminary result:
Lemma
With arbitrary $\Sigma$ and $\Gamma=\{a\}$ :

$$
\text { H-Rat is closed under } U,(H) \text { and } H^{\star} \text {. }
$$

Proof.
Tedious formal computations. . .

## From 2-way transducers to H-Rat (unary case)

We fix a transducer $\mathcal{T}$.

- Consider border to border run segments;



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R_{1} \oplus R_{2} \oplus R_{3}=\left\{\left(u, v_{1} v_{2} v_{3}\right)\right\}
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## From 2-way transducers to H-Rat (unary case)

We fix a transducer $\mathcal{T}$.

- Consider border to border run segments;
- Compose border to border segments;
- Conclude using the closure properties of H-Rat.


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R_{1} \oplus R_{2} \oplus R_{3}=\left\{\left(u, v_{1} v_{2} v_{3}\right)\right\}
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## From 2-way transducers to H-Rat (unary case)


define a relation $R_{b_{i}}, b_{j}$

## From 2-way transducers to H-Rat (unary case)


define a relation $R$


## From 2-way transducers to H-Rat (unary case)


\(\left.\boldsymbol{H} \boldsymbol{T}=\left(\begin{array}{cccccc}R_{0,0} \& R_{0,1} \& \cdot \& \cdot \& \cdot \& R_{0, k} <br>
R_{1,0} \& R_{1,1} \& \cdot \& \cdot \& \cdot \& R_{1, k} <br>
\cdot \& \& \& R_{i, j} \& \cdot <br>
\cdot \& \& \& \cdot <br>
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| :--- |

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Second ingredient:
The behavior of $\mathcal{T}$ is given by the matrix $H I T^{\text {H* }}$.

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sweeping transducers \subseteqH-Rat
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## Generalizations?

Theorem
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Thank you for your attention.

