

Semantic Modeling with Frames

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Introductory Course

Sofia University

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Part 2

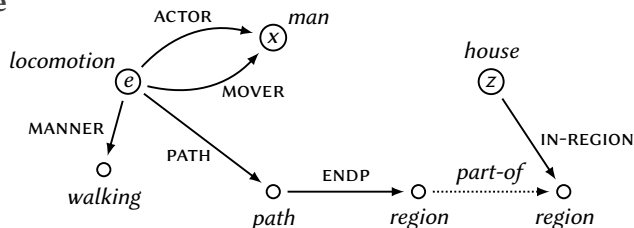
Formal foundations

Topics

- Attribute-value descriptions and formulas
- Translation into predicate logic
- Formal definition of frames
- Frames as models
- Subsumption and unification
- Attribute-value constraints
- Frames versus feature structures
- Type constraints versus type hierarchy

Recap

Example



Ingredients

- Attributes (funct. relations): **ACTOR**, **MOVER**, **PATH**, **MANNER**, **IN-REGION**, ...
- Type symbols: *locomotion*, *man*, *path*, *walking*, *region*, ...
- Proper relation symbols: *part-of*
- Node labels (variables, constants): e , x , z

Core property

- Every node is reachable from some labeled “base” node via attributes.

Attribute-value descriptions

Vocabulary / Signature

Attr	attributes (= dyadic functional relation symbols)		
Rel	(proper) relation symbols		
Type	type symbols (= monadic predicates)		
Nname	node names (“nominals”)	}	Nlabel node labels
Nvar	node variables		

Attribute-value descriptions

Vocabulary / Signature

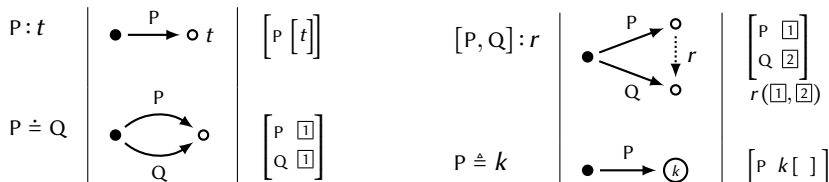
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Primitive attribute-value descriptions (pAVDesc)

$$t \mid p : t \mid p \doteq q \mid [p_1, \dots, p_n] : r \mid p \triangleq k$$

$(t \in \text{Type}, r \in \text{Rel}, p, q, p_i \in \text{Attr}^*, k \in \text{Nlabel})$

Semantics



Translation into first-order predicate logic

Vocabulary / Signature

Attr	dyadic relation symbols (attributes)
Rel	relation symbols
Type	monadic predicates (type symbols)
Nname	constants (node names)
Nvar	variables

Important Functionality of attributes has to be enforced axiomatically!

Primitive attribute-value descriptions as predicates:

$$p : t \quad \lambda x \exists y (p(x, y) \wedge t(y))$$

$$p \doteq q \quad \lambda x \exists y (p(x, y) \wedge q(x, y))$$

$$[p_1, \dots, p_n] : r \quad \lambda x \exists y_1 \dots \exists y_n (p_1(x, y_1) \wedge \dots \wedge p_n(x, y_n) \wedge r(y_1, \dots, y_n))$$

$$p \triangleq k \quad \lambda x (p(x, k))$$

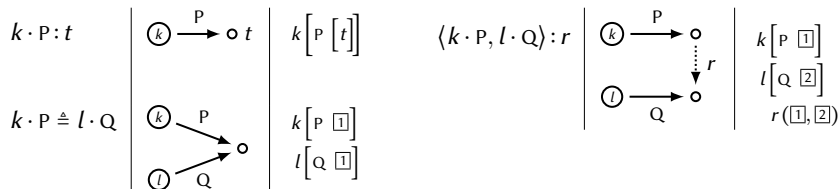
Attribute-value formulas

Primitive attribute-value formulas (pAVForm)

$$k \cdot p : t \mid k \cdot p \triangleq l \cdot q \mid \langle k_1 \cdot p_1, \dots, k_n \cdot p_n \rangle : r$$

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Semantics



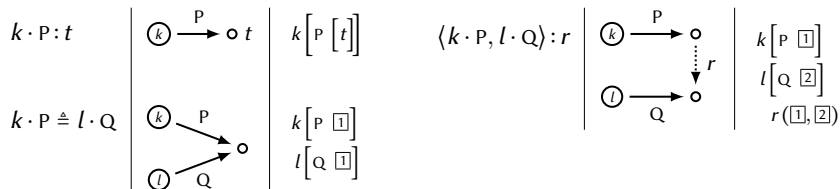
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Semantics



Formal definitions (fairly standard)

Set/universe of “nodes” V

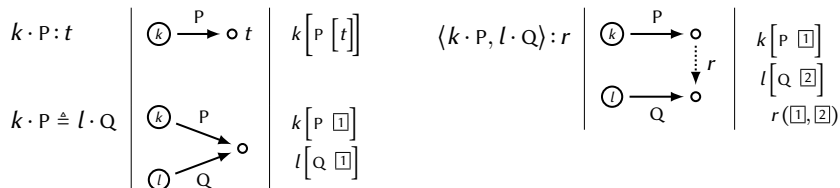
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Semantics



Formal definitions (fairly standard)

Set/universe of “nodes” V

Interpretation function $\mathcal{I} : \text{Attr} \rightarrow [V \rightarrow V]$,

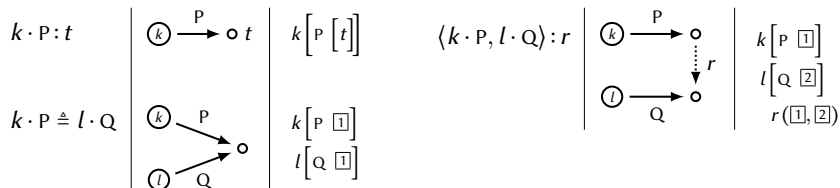
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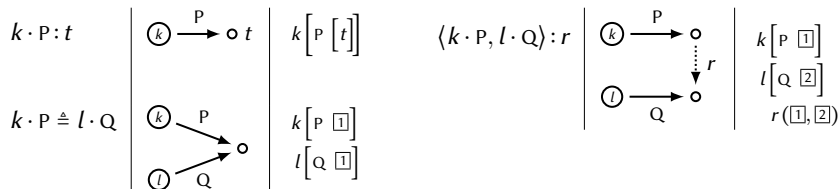
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Semantics



Formal definitions (fairly standard)

Set/universe of “nodes” V

Interpretation function $\mathcal{I} : \text{Attr} \rightarrow [V \rightarrow V]$, $\text{Type} \rightarrow \wp(V)$,
 $\text{Rel} \rightarrow \bigcup_n \wp(V^n)$, $\text{Nname} \rightarrow V$

(Partial) variable assignment $g : \text{Nvar} \rightarrow V$

Satisfaction of AV descriptions and formulas

Formal definitions (cont'd)

Abbreviation: $\mathcal{I}_g(k) = v$ for $k \in \text{Nlabel}$ iff $\mathcal{I}(k) = v$ if $k \in \text{Nname}$ and
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Satisfaction of primitive descriptions

$\langle V, \mathcal{I}, g \rangle, v \models t$ iff $v \in \mathcal{I}(t)$

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$\langle V, \mathcal{I}, g \rangle, v \models t$ iff $v \in \mathcal{I}(t)$
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- $\langle V, \mathcal{I}, g \rangle \models k \cdot p : t$ iff $\mathcal{I}(p)(\mathcal{I}_g(k)) \in \mathcal{I}(t)$

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Satisfaction of **Boolean combinations** as usual.

Frames defined

Frame F over $\langle \text{Attr}, \text{Type}, \text{Rel}, \text{Nname}, \text{Nvar} \rangle$:

$F = \langle V, \mathcal{I}, g \rangle$, with V finite, such that every node $v \in V$ is reachable from some labeled node $w \in V$ via an attribute path,

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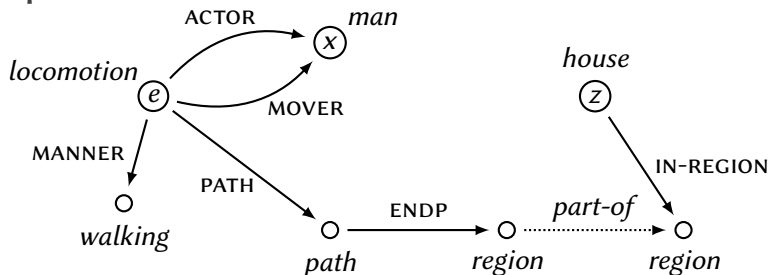
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Example



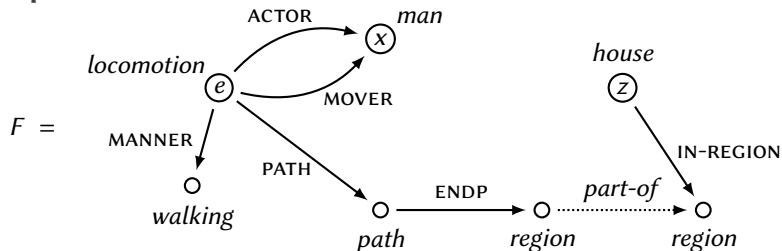
Frames as models of AV formulas

A frame $F = \langle V, \mathcal{I}, g \rangle$ is a **model** of an AV formula ϕ iff $F \vDash \phi$.

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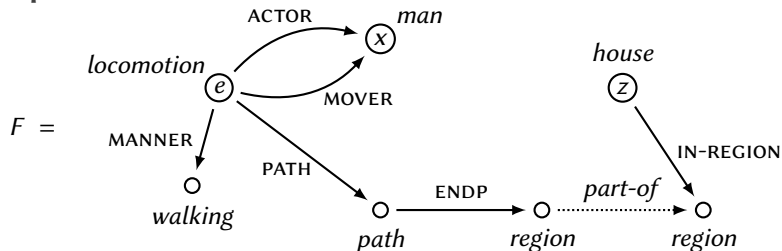
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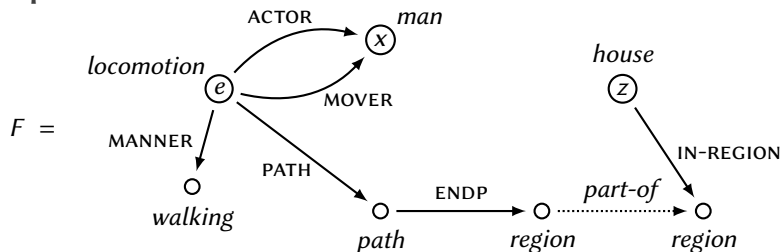


$F \models$

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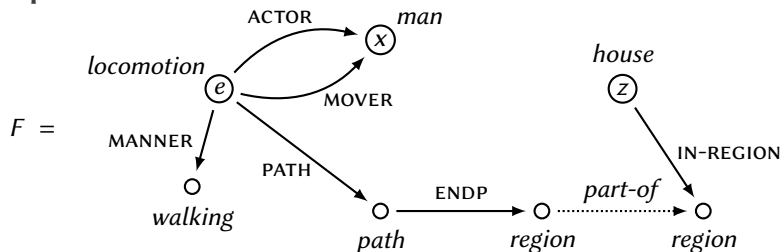


$F \models e \cdot locomotion$

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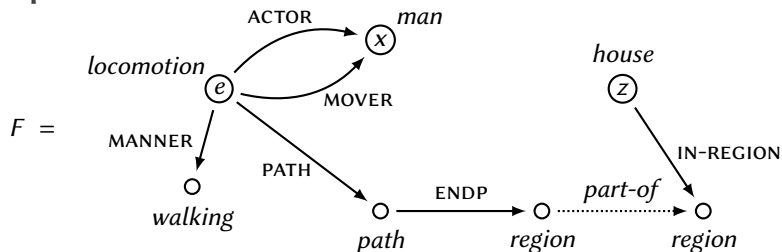
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$F \models e \cdot (locomotion \wedge ACTOR : man)$

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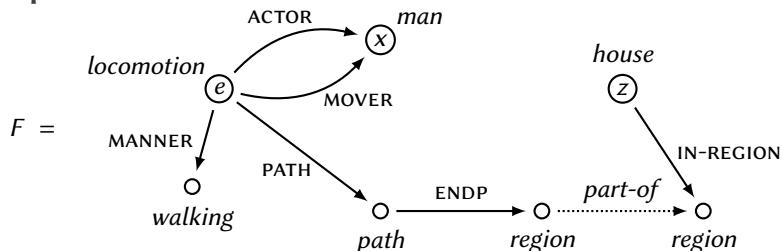
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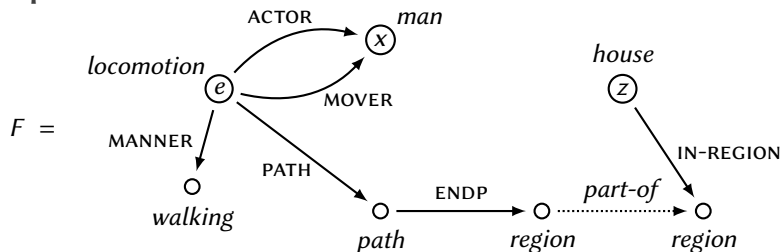
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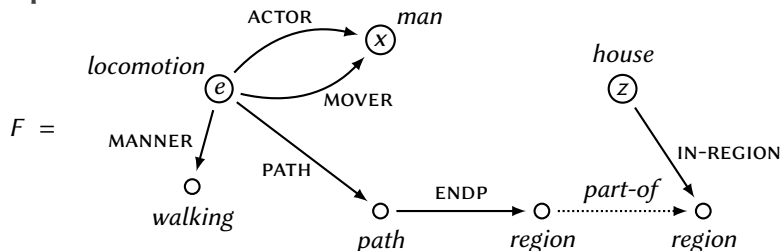
$F \models e \cdot (locomotion \wedge ACTOR \triangleq x)$

$F \models x \cdot man \wedge z \cdot house$

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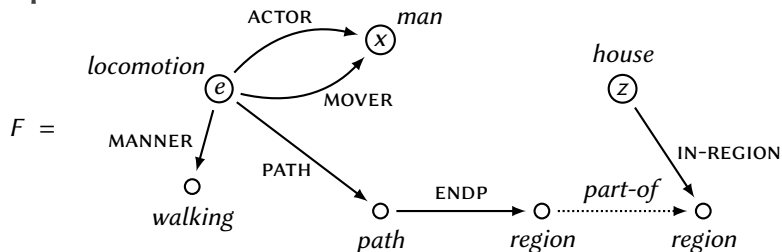
$F \models x \cdot man \wedge z \cdot house$

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$F \models e \cdot locomotion$

$F \models e \cdot (locomotion \wedge \text{ACTOR} : man)$

$F \models e \cdot (locomotion \wedge \text{ACTOR} \triangleq x)$

$F \models x \cdot man \wedge z \cdot house$

$F \models e \cdot (\text{ACTOR} \triangleq \text{MOVER})$

$F \models \langle e \cdot \text{PATH ENDP}, z \cdot \text{IN-REGION} \rangle : \text{part-of}$

Subsumption and unification

Subsumption

$F_1 = \langle V_1, \mathcal{I}_1, g_1 \rangle$ **subsumes** $F_2 = \langle V_2, \mathcal{I}_2, g_2 \rangle$ ($F_1 \sqsubseteq F_2$) iff there is a (necessarily unique) **morphism** $h : F_1 \rightarrow F_2$, i.e., a function $h : V_1 \rightarrow V_2$ such that

- (i) $\mathcal{I}_2(f)(h(v)) = h(\mathcal{I}_1(f)(v))$, if $\mathcal{I}_1(f)(v)$ is defined, $f \in \text{Attr}$, $v \in V_1$,
- (ii) $h(\mathcal{I}_1(t)) \subseteq \mathcal{I}_2(t)$, for $t \in \text{Type}$
- (iii) $h(\mathcal{I}_1(r)) \subseteq \mathcal{I}_2(r)$, for $r \in \text{Rel}$
- (iv) $h(\mathcal{I}_1(n)) = \mathcal{I}_2(n)$, for $n \in \text{Nname}$
- (v) $h(g_1(x)) = g_2(x)$, for $x \in \text{Nvar}$, if $g_1(x)$ is defined

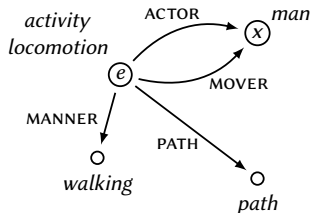
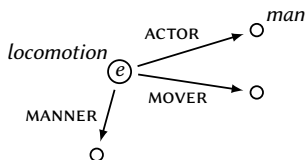
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$F_1 = \langle V_1, \mathcal{I}_1, g_1 \rangle$ **subsumes** $F_2 = \langle V_2, \mathcal{I}_2, g_2 \rangle$ ($F_1 \sqsubseteq F_2$) iff there is a (necessarily unique) **morphism** $h : F_1 \rightarrow F_2$, i.e., a function $h : V_1 \rightarrow V_2$ such that

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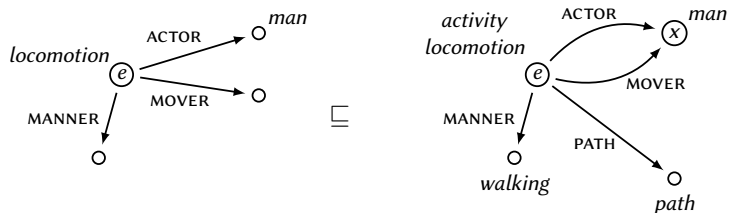
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Intuition

F_1 subsumes F_2 ($F_1 \sqsubseteq F_2$) iff F_2 is **at least as informative** as F_1 .

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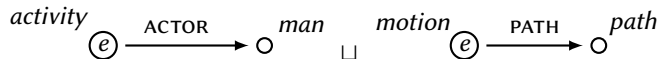
Theorem (Frame unification)

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The worst case time-complexity of frame unification is almost linear in the number of nodes.

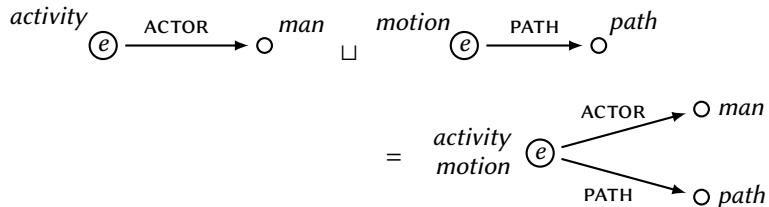
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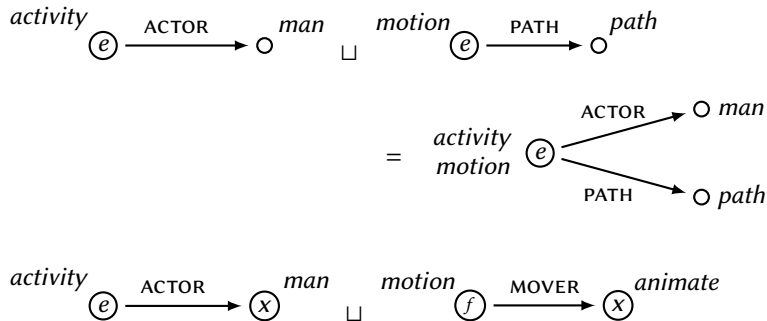
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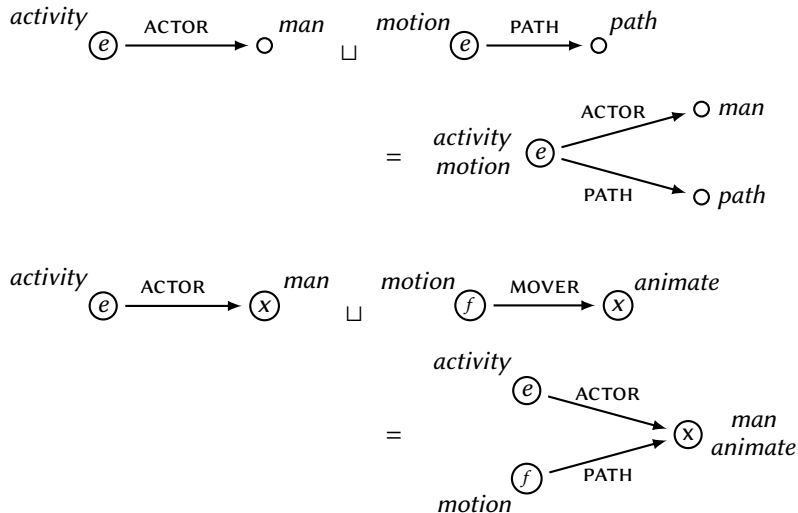
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Frames as minimal models of attribute-value formulas

- (i) Every frame is the minimal model (w.r.t. subsumption) of a finite conjunction of primitive attribute-value formulas.

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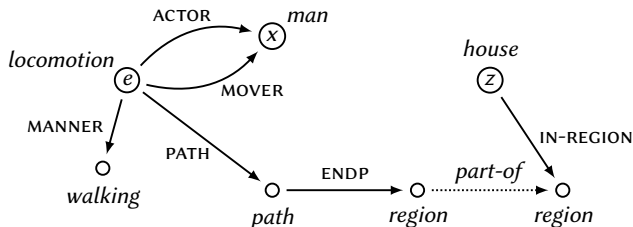
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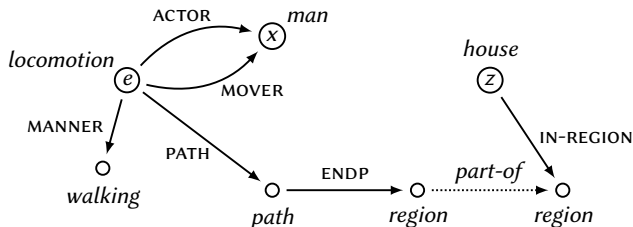


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$$e \cdot (\textit{locomotion} \wedge \textit{MANNER} : \textit{walking} \wedge \textit{ACTOR} \doteq x \\ \wedge \textit{MOVER} \doteq \textit{ACTOR} \wedge \textit{PATH} : (\textit{path} \wedge \textit{ENDP} : \textit{region})) \\ \wedge \langle e \cdot \textit{PATH} \textit{ENDP}, z \cdot \textit{IN-REGION} \rangle : \textit{part-of} \wedge x \cdot \textit{man}$$

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 $\langle V, \mathcal{I}, g \rangle \models \forall\phi$ iff $\langle V, \mathcal{I}, g \rangle, v \models \phi$ for every $v \in V$

Notation:

$\phi \Rightarrow \psi$ for $\forall(\phi \rightarrow \psi)$

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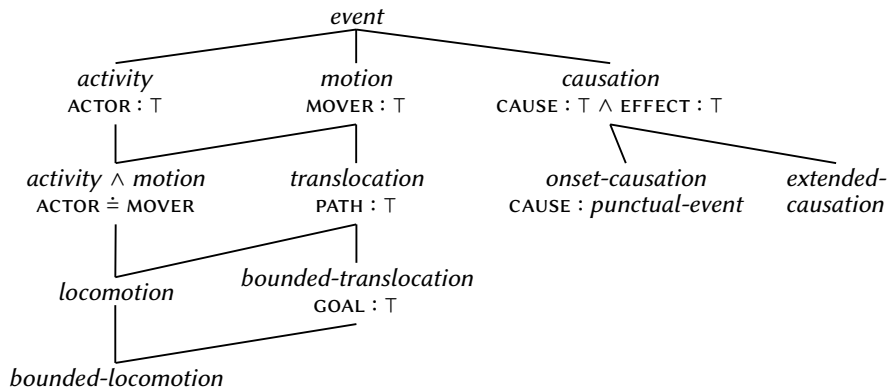
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Attribute-value constraints

Possible graphical presentation of constraints



Caveat: Reading convention required!

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Proposition Given a frame F and a finite set of Horn formulas, then there is a unique least specific frame F' extending F that satisfies the given formulas (if satisfiable at all), and F' can be constructed in almost linear time.

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Theorem (Frame unification under Horn constraints) [\approx Hegner 1994]

The worst case time-complexity of frame unification under a finite set of Horn formulas is almost linear in the number of nodes.

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Digression: A general view on semantic processing

Semantic processing as the **incremental construction** of **minimal (frame) models** (by unification under constraints) based on the input, the context, and background knowledge (lexicon, ...).

Frames versus feature structures

[→ Carpenter 1992, Rounds 1997, and many others]

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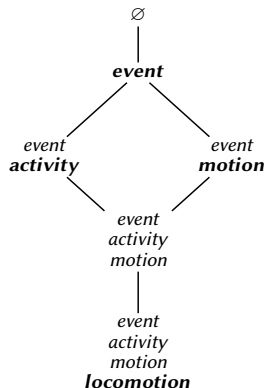
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Next topic

- Combining frame semantics with Lexicalized Tree Adjoining Grammars (LTAG)
- Elementary constructions as elementary trees with semantic frames
- Linguistic applications
- Brief outlook: factorization of elementary constructions in the metagrammar.