ME/SE/EC 734 Hybrid Systems, Fall 2015

Instructor:

Calin Belta Office: Room 414, 110 Cummington St. Tel: 617 353 9586 Email: cbelta@bu.edu Office hours: MW 10:00-12:00

Course web resources:

Lecture notes, homework, and project assignments will be available in the BU blackboard.

Prerequisites:

There are no specific prerequisites for this course. The necessary background will be provided in the class. However, a certain level of mathematical maturity is necessary, such as familiarity with linear algebra and differential equations. Background in control theory and/or automata theory is helpful, but not required.

Course schedule:

Mon & Wed 10:00 - 12:00

Textbook:

None required. Reading material will be provided in the class.

Course learning objectives:

At the end of this course, the students will (1) understand nontrivial problems that occur when continuous and discrete dynamics are combined, (2) know the principles of formal verification and abstraction, (3) understand stability issues specific to hybrid systems, and (4) be able to use off-the-shelf software packages for simulation and verification of hybrid systems

Policy on Collaboration:

Collaboration is not allowed for homework assignments. It is allowed for team projects.

Grading policy:

Homework (40%) & Project (60%)

Tentative Schedule

Lecture 1: Introduction, motivation, and examples Lectures 2, 3: Models of hybrid systems (syntax) Lecture 4: Trajectories of hybrid systems (semantics) Lecture 5: Numerical simulation of hybrid systems Lectures 6, 7: Stability of hybrid systems Lecture 8: Propositional logics and first order logics Lectures 9, 10: Transition systems, languages, simulations, bisimulations Lecture 11, 12, 13, 14: Abstractions for continuous and hybrid systems Lecture 15: Temporal logics and model checking Lectures 16, 17: Formal analysis for some classes of hybrid systems Lectures 17, 18, 19: Formal synthesis of control strategies for hybrid systems Lecture 20: Modeling and analysis of biochemical networks Lecture 21, 22: Symbolic motion planning and control Lectures 23, 24: Project presentations