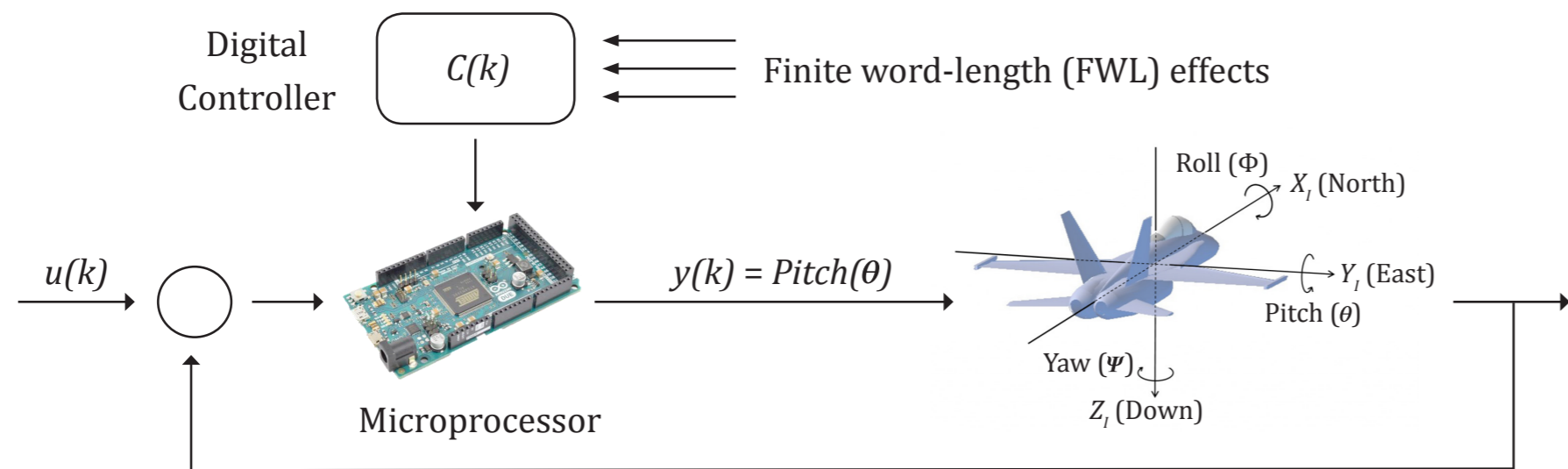


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I Motivation



"...guaranteeing the correctness of cyber-physical systems (CPS) remains an outstanding challenge"

Xi Zheng et al., 2014

"Simulation alone is not sufficient to support verification and validation of CPS"

Sayan Mitra et al., 2013

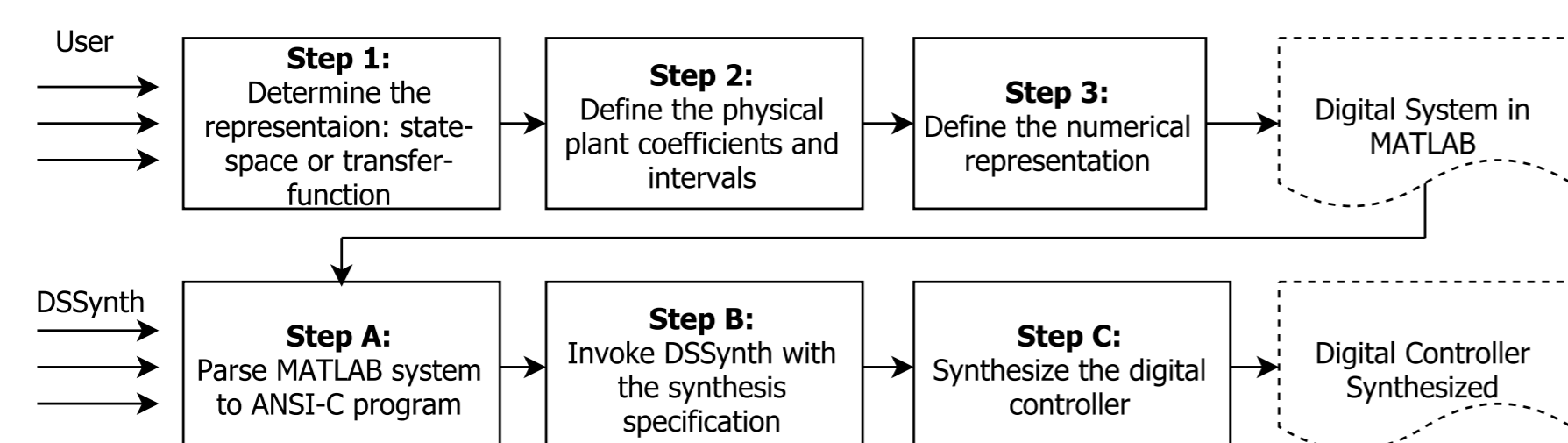
$$\begin{cases} x(k+1) = Ax(k) + Bu(k) \\ y(k) = Cx(k) + Du(k) \end{cases} \quad \leftarrow \text{State-space model}$$

$$H(z) = \frac{b_0 + b_1 z^{-1} + \dots + b_m z^{-m}}{a_0 + a_1 z^{-1} + \dots + a_n z^{-n}} \quad \leftarrow \text{Transfer-function model}$$

II Approach and Uniqueness

Counter-Example Guided Inductive Synthesis (CEGIS)

Generate sound digital controllers for stability and safety specifications with a very high degree of automation



Step 1

Determine the representation

- State-space model
- Transfer-function model

Step 2

Define the physical plant coefficients and intervals

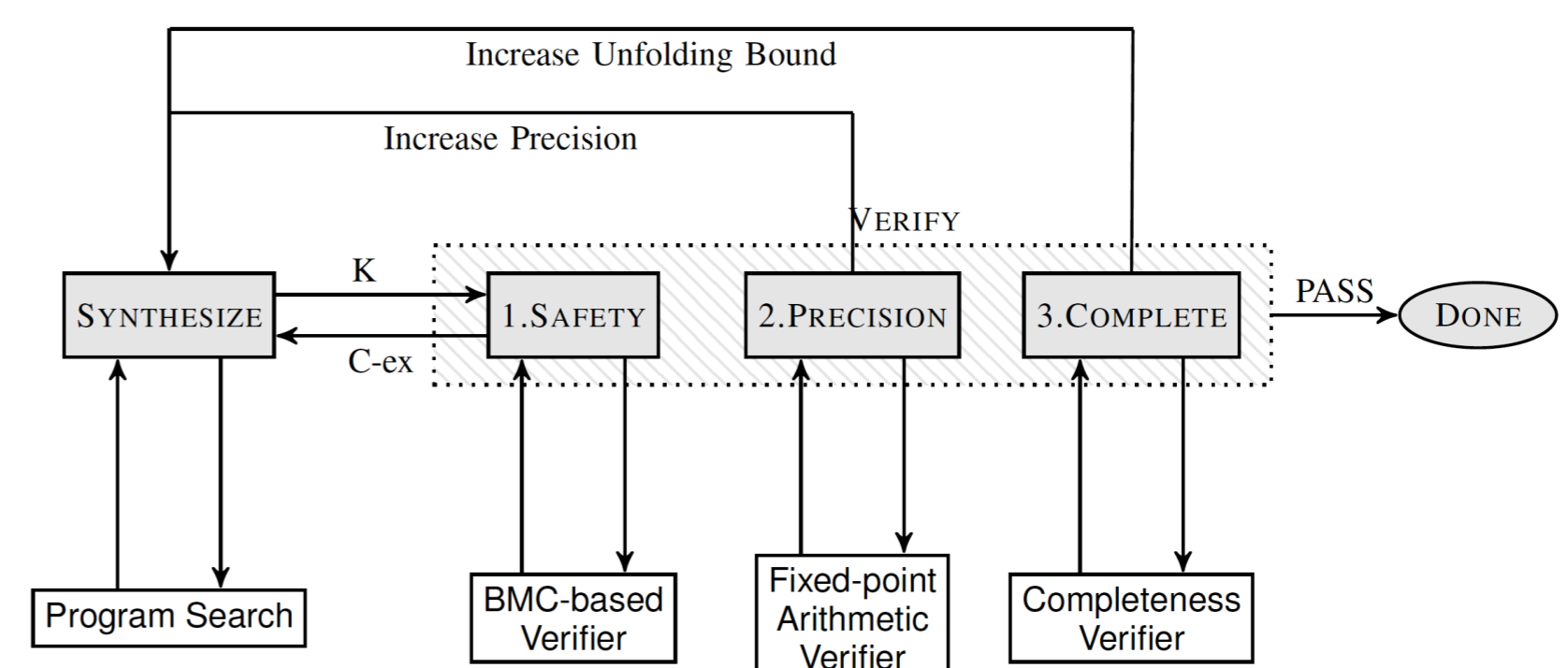
- state-space: matrices A, B, C and D
- transfer-function: coefficients b_0, b_1, \dots, b_m and a_0, a_1, \dots, a_n
- uncertainty over the numerator and denominator coefficients

Step 3

Define the numerical representation

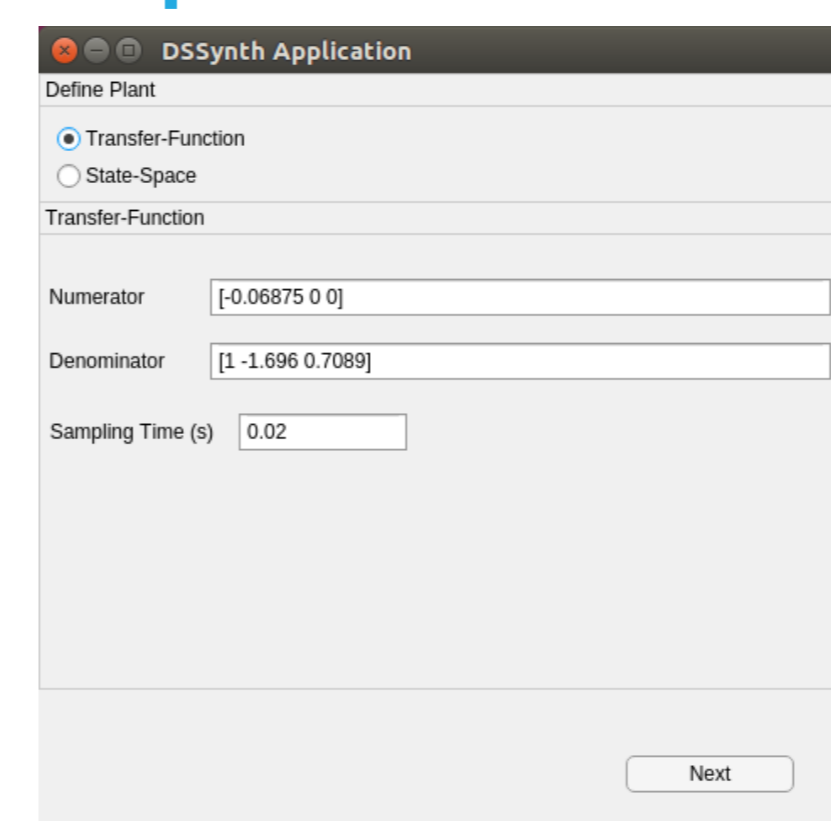
- I is the integer part
- F is the fractional part
- dynamical range

III CEGIS for Control Systems

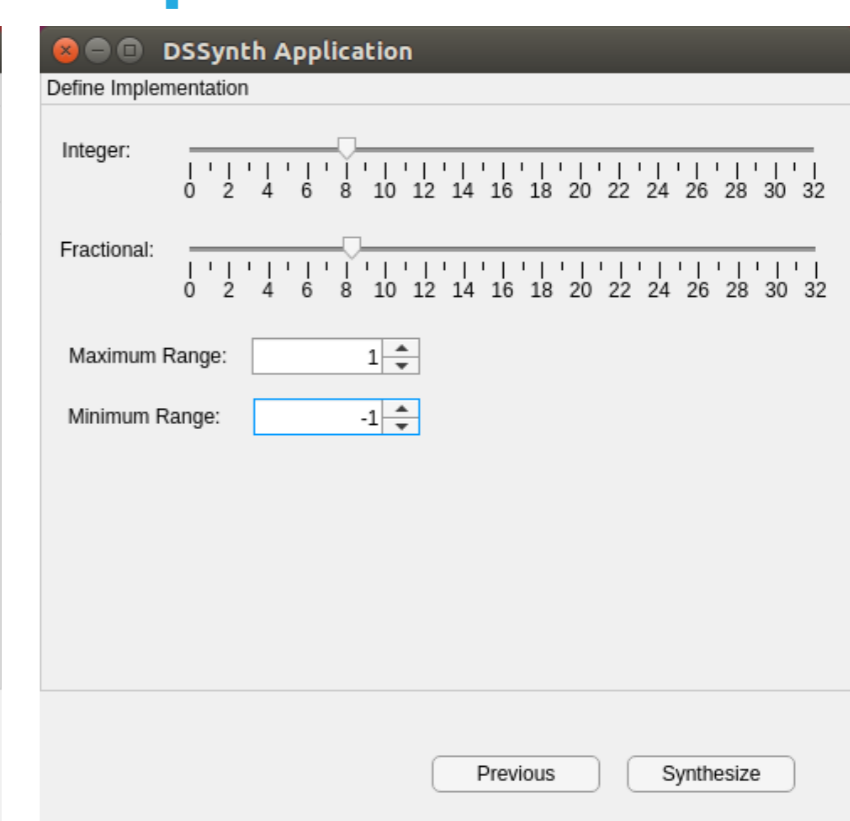


IV DSSynth Toolbox

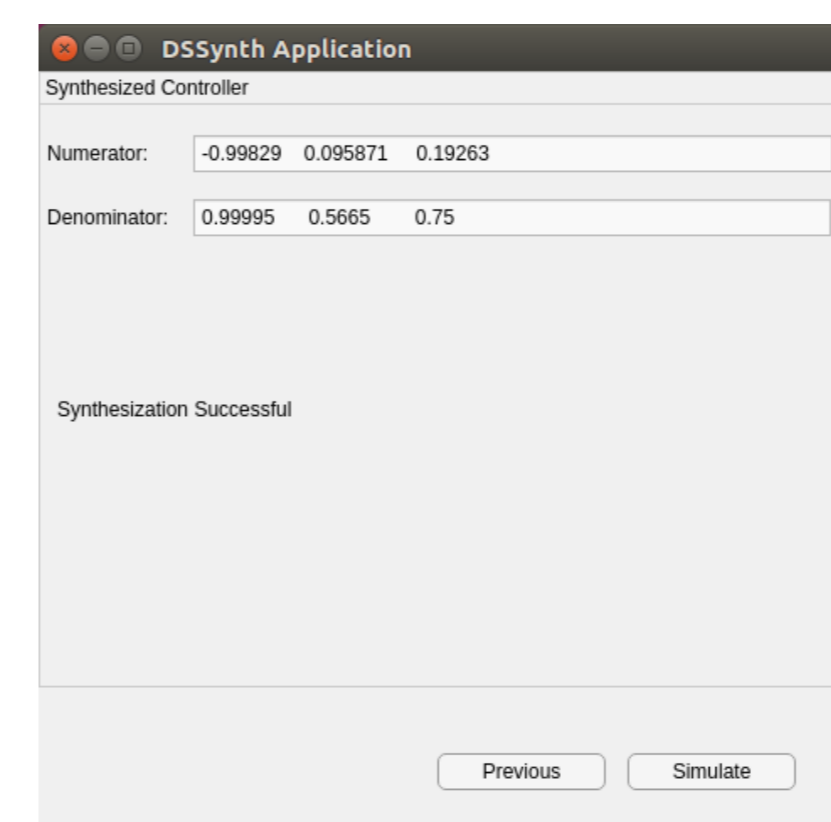
Steps 1 and 2



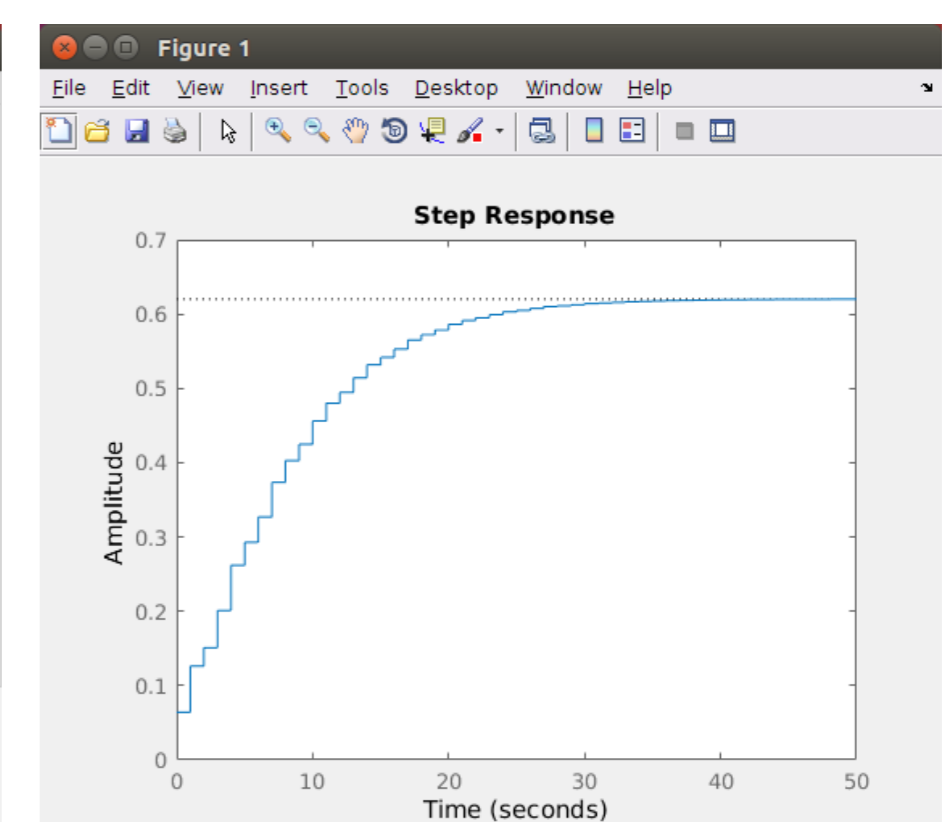
Step 3



Steps A, B and C



Simulation in MATLAB



V Contributions

- support for transfer-function and state-space representations in closed-loop form;
- synthesize different numerical representations and realization forms of the controller using CEGIS;
- provide a MATLAB toolbox to synthesize digital controllers while taking into account FWL effects.

As future work:

- DSSynth Toolbox will perform synthesis considering performance requirements;
- we will also pursue the application of CEGIS to further software engineering problems.

Sponsors:

