



# About the Beamer class in presentation making

## A short story

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### **Definition 1 (Plant)**

*A plant automaton is a tuple  $\mathcal{P} = (Q, \Sigma_c, \delta, q)$  where  $Q$  is a finite set of states,  $\Sigma_c$  is a set of controller commands,  $\delta : Q \times \Sigma_c \mapsto 2^Q$  is the transition function and  $q_o \in Q$  is an initial state.*

### **Definition 2 (Controllers)**

*A controller (strategy) for a plant specified by  $\mathcal{P} = (Q, \Sigma_c, \delta, q)$  is a function  $C : Q^+ \mapsto \Sigma_c$ . A simple controller is a controller that can be written as a function  $C : Q^+ \mapsto \Sigma_c$ .*

### Definition 3 (Trajectories)

Let  $\mathcal{P}$  be a plant and let  $C : Q^+ \mapsto \Sigma_c$  be a controller. An infinite sequence of states  $\alpha : q[0], q[1], \dots$  such that  $q[0] = q_0$  is called a trajectory of  $\mathcal{P}$  if

$$q[i + 1] \in \bigcup_{\sigma \in \Sigma_c} \delta(q[i], \sigma)$$

### Definition 4 (Acceptance Condition)