

# Piergiuseppe Mallozzi

Berkeley (CA), USA

+1 (442) 877-2865 | [piergiuseppe.mallozzi@gmail.com](mailto:piergiuseppe.mallozzi@gmail.com) | [pierg.github.io](https://github.com/pierg) | [pierg](#) | [piergiuseppe](#)

**Software Engineer | Formal Methods | AI/ML/DL | Cyber-Physical Systems**

## Current Position

### Postdoctoral Researcher in EECS

Berkeley, USA

UC BERKELEY

Sept. 2021 - present

- Utilizing artificial intelligence to develop correct-by-construction designs, with focus on air vehicles (UAVs) and robotic missions.
- Contributing to the development of PACTI, a specification-based system analysis and design tool that is being tested by multiple organizations, including NASA.
- Contributing as a key member of the research and development team for the DARPA project "Symbiotic Design for Cyber-Physical Systems".

## Education

### PhD in Electrical Engineering and Computer Science

Göteborg, Sweden

CHALMERS UNIVERSITY OF TECHNOLOGY

2016-2021

#### Thesis: "Designing Trustworthy Autonomous Systems".

- Designed and implemented a novel framework for robotic mission design that uses contracts to model requirements, ensuring consistency and completeness in system specifications. Developed new algorithms to maximize reuse of existing components and efficiently realize robotic missions, reducing design complexity.
- Applied formal methods, including model checking, run-time monitoring and reactive synthesis, to ensure trustworthiness of autonomous systems in different contexts, such as vehicle platooning, *reward hacking* prevention, *safe reinforcement learning* and requirement engineering.

### BSc, MSc in Computer Engineering Graduated with highest honors, full marks 110/110

Pisa, Italy

UNIVERSITY OF PISA

2009-2016

#### Thesis: "Design and development of a co-simulation library for the PVSio-web prototyping tool".

- Designed and developed a set of libraries for the *co-simulation* of Cyber-Physical Systems.
- Completed in collaboration with NASA Langley Research Center, Virginia, USA.
- Developed a library that forms a core part of the co-simulation engine. The library is responsible for coordinating and controlling different models, each developed in their own environment (e.g., Java, PVS, C, Matlab Simulink).

## Awards

### University of California, Berkeley

Berkeley, USA

FUNDED RESEARCH VISIT

2019

- Received Fellowship from Knut and Alice Wallenberg Foundation.
- Gained expertise in Deep Learning, Formal Methods and Contract-Based Design.

### IDEA League

Europe

FUNDED A DOCTORAL SCHOOL ACROSS TOP EUROPEAN UNIVERSITIES

2017 and 2018

- Developed a strong network with ETH Zurich, TUDelft, Politecnico di Milano

### WASEDA University

Tokyo, Japan

FUNDED RESEARCH VISIT

2018

- Collaborated with top Japanese research institutions as an awarded candidate among applicants from around the world.
- Received funding from JSPS (Japanese Society for Promoting Science) for the collaboration.

## Wallenberg AI, Autonomous Systems and Software Program

Sweden

FELLOWSHIP FROM THE LARGEST INDIVIDUAL RESEARCH PROGRAM IN SWEDEN

2016-2021

- Received full funding for doctoral program, international graduate school, and research visits through a prestigious fellowship program in Sweden.
- Awarded travel grants to present research at top academic and industry research centers worldwide, including Airbus (France), German Aerospace Center DLR (Germany), Stanford, UC Berkeley, Google, and Netflix (USA), and NTU, SUTD (Singapore).
- Engaged in high-level discussions with leading researchers in various fields, broadening my research expertise and network.

## NASA Langley Research Center

Virginia, USA

FUNDED INTERNSHIP

2015

- Led the design and development of a flight simulator to demonstrate the NextGen collision avoidance system (DAIDALUS) developed at NASA Langley.
- Utilized the PVS verification system to execute mathematical models developed by the NASA team in a simulator.

## Queen Mary University of London

London, UK

FUNDED TRAINEESHIP PROGRAM

2015

- Developed a communication middleware for co-simulation of device prototypes in the CHI+MED research team.
- Utilized the middleware to develop a demonstrative prototype of an Integrated Clinical Environment with interoperable medical devices.

## Institut supérieur d'électronique de Paris

Paris, France

FUNDED SCHOLARSHIP FOR STUDY ABROAD SEMESTER

2014

## Copenhagen University College of Engineering

Copenhagen, Denmark

SELECTED FOR INTERNATIONAL ENGINEERING PROJECT AND AWARDED SCHOLARSHIP

2012

## Universidad Carlos III de Madrid

Madrid, Spain

FUNDED SCHOLARSHIP FOR STUDY ABROAD SEMESTER

2011

## Some Open-Source Projects

---

### PACTI

Berkeley, USA

[HTTPS://GITHUB.COM/FORMALSYSTEMS/PACTI](https://github.com/FormalSystems/PACTI)

2021-2022

- Developed and maintained PACTI, an open-source tool for scalable system analysis and design using an Assume-Guarantee contracts framework with support for polyhedral constraints, and ongoing support for Linear Temporal Logic.

### Berkeley CPS Symbiotic Design

Berkeley, USA

[HTTPS://GITHUB.COM/BERKELEY-UAVS/BERKELEY-CPS-SYMBIOTIC-DESIGN](https://github.com/Berkeley-UAVS/Berkeley-CPS-Symbiotic-Design)

2021-2022

- Led the development of a comprehensive software pipeline for designing and evaluating unmanned aerial vehicles (UAVs) in the context of a DARPA challenge, contributing over 100,000 lines of code.
- Key features of the software pipeline include:
  - Context-sensitive grammar for generating abstract UAV topologies.
  - User-friendly JSON and GUI interfaces enabling designers to express preferences at multiple levels of abstraction.
  - Refinement from abstract topologies to graphs of UAV components and connectors, with optimization of component selection from a library of real UAV components.
  - Learning of common structures from existing UAV designs through graph isomorphism analysis.
  - Parameters and control optimization using Bayesian optimization techniques.

### CROME - Contract-Based Goal Graph Analysis Tool

Berkeley, USA

[HTTPS://GITHUB.COM/PIERG/CROME-CGG](https://github.com/PIERG/CROME-CGG)

2019-2021

- Contract-based goal graph analysis tool for modeling and deploying robotic missions in complex environments.
- Enabled designers to use Linear Temporal Logic (LTL) or Specification Patterns to model the environment and goals of robotic missions.
- Implemented efficient goal analysis via the construction of the CGG, a graph of contracts where each node is combined with algebraic operations.
- Enabled simulation of robotic missions through realization, execution, and orchestration of different controllers that guide the robot under varying environmental contexts.
- Implemented an LTL formulas manipulation library and parallel reactive synthesis controllers for more efficient realization of robotic missions.

# Teaching Activity

## Machine Learning and Software Engineering for AI Systems

Chalmers University of Technology

MAIN COURSE DEVELOPER AND LECTURER

fall19, summer20, fall20

- Created a course that provided a strong theoretical and mathematical foundation for Machine Learning and Deep Learning, while also offering practical applications and industry use cases.)
- Covered a wide range of topics including supervised learning (linear and polynomial regression, logistic regression, decision trees, gradient descent), unsupervised learning (clustering, K-means), reinforcement learning (MDP, value iteration, Q-learning), deep neural networks (convolutional neural networks, recurrent neural networks), and practical implementation using Python.

## Advanced Software Architecture

Chalmers University of Technology

TEACHING ASSISTANT AND LECTURER

spring16, spring17, spring18

- Covered various topics, including Architectural Styles, Patterns, and Tactics, as well as Domain-Specific Software Architectures.
- Explored the phenomenon of Software Architecture Decay and its implications on large-scale software systems.

## Model-Based Software Development

Chalmers University of Technology

TEACHING ASSISTANT AND LECTURER

fall16, fall17, fall18

- Covered topics including topics such as Domain Models, Use Case, Activity, Class, Component, Sequence, Deployment Diagrams, and State Machines, using modeling languages such as UML and SysML.
- Coordinated and supervised student groups working on a large-scale software development project for the course.

# Skills

**Languages** Italian (Native), English (Full Professional Proficiency), French (Good), Spanish (Intermediate)

**Programming** Python, HTML/CSS/Javascript, Flask/React/NextJS, JAVA, C/C++, MySQL, Matlab, LaTeX, Docker, Git

**Engineering** **Cyber-Physical Systems and Embedded Systems:** Electronics, Logic Circuits, Computer Architecture, Concurrent and Distributed Systems. **Formal Methods:** Linear Temporal Logic, Model Checking, Reactive Synthesis, Runtime Verification. **Machine Learning and Deep Learning:** Supervised Learning, Unsupervised Learning, Reinforcement Learning, Neural Networks, Convolutional Neural Networks, Transformers, Natural Language Processing. **Theory of Computation:** Automata and Languages, Computability, Complexity. **Algorithms and Data Structures:** Operations Research, Graph Theory, Optimization. **Software Engineering:** Object-Oriented Programming, Design Patterns, Software Architecture, Agile Development, Testing, Debugging. **Networking and Security:** Advanced Networking, Internet Protocols, Cryptography, Network Security, Blockchain Technology and Zero-Knowledge Proof.

# Publications

Pacti: Scaling Assume-Guarantee Reasoning for System Analysis and Design

Inigo Incer, Apurva Badithela, Josefine Graebener, **Piergiuseppe Mallozzi**, Ayush Pandey, Sheng-Jung Yu, Albert Benveniste, Benoit Caillaud, Richard Murray, Alberto Sangiovanni-Vincentelli, Sanjit Seshia

submitted at CAV23, 2023

Contract-Based Specification Refinement and Repair for Mission Planning

**Piergiuseppe Mallozzi**, Inigo Incer, Pierluigi Nuzzo, Alberto Sangiovanni-Vincentelli

International Conference of Formal Methods in Software Engineering (FORMALISE), 2023

A grammar for the representation of Unmanned Aerial Vehicles with 3D topologies

**Piergiuseppe Mallozzi**, Hussin Sibai, Inigo Pandey, Alberto Sangiovanni-Vincentelli, Sanjit Seshia

under review, 2023

A Framework for Specifying and Realizing Correct-by-Construction Contextual Robotic Missions Using Contracts

**Piergiuseppe Mallozzi**, Pierluigi Nuzzo, Nir Piterman, Patrizio Pelliccione, Gerardo Schneider

under review, 2022

Incremental Refinement of Goal Models with Contracts

**Piergiuseppe Mallozzi**, Pierluigi Nuzzo, Patrizio Pelliccione

Fundamentals of Software Engineering (FSEN), 2021

CROME: Contract-Based Robotic Mission Specification

**Piergiuseppe Mallozzi**, Pierluigi Nuzzo, Patrizio Pelliccione, Gerardo Schneider

International Conference on Formal Methods and Models for System Design (MEMOCODE), 2020

A Runtime Monitoring Framework to Enforce Invariants on Reinforcement Learning Agents Exploring Complex Environments

**Piergiuseppe Mallozzi**, Ezequiel Castellano, Patrizio Pelliccione, Gerardo Schneider, Kenji Tei

International Workshop on Robotics Software Engineering (RoSE), Co-located with ICSE, 2019

Autonomous Vehicles: State of the Art, Future Trends, and Challenges

**Piergiuseppe Mallozzi**, Patrizio Pelliccione, Alessia Knauss, Christian Berger, Nassar Mohammadiha

*Book Chapter in Automotive Systems and Software Engineering, 2019*

Engineering Trustworthy Self-Adaptive Autonomous Systems

**Piergiuseppe Mallozzi**

*Licentiate Thesis, 2018*

MoVEMo: a Structured Approach for Engineering Reward Functions

**Piergiuseppe Mallozzi**, Raúl Pardo, Vincent Duplessis, Patrizio Pelliccione, Gerardo Schneider

*IEEE International Conference on Robotic Computing (IRC), 2018*

Keeping Intelligence Under Control

**Piergiuseppe Mallozzi**, Patrizio Pelliccione, Claudio Menghi

*International Workshop on Software Engineering for Cognitive Services (SE4COG), Co-located with ICSE, 2018*

Combining Machine-learning with Invariants Assurance Techniques for Autonomous Systems

**Piergiuseppe Mallozzi**

*Doctoral Symposium at International Conference on Software Engineering (ICSE), 2017*

Automotive Architecture Framework: The Experience of Volvo Cars

Patrizio Pelliccione, Eric Knauss, Rogardt Heldal, S Magnus Ågren, **Piergiuseppe Mallozzi**, Anders Alminger, Daniel Borgentun

*Journal of Systems Architecture, 2017*

Formal Verification of the on-the-fly Vehicle Platooning Protocol

**Piergiuseppe Mallozzi**, Massimo Sciancalepore, Patrizio Pelliccione

*International Workshop on Software Engineering for Resilient Systems (SERENE), 2016*

A Proposal for an Automotive Architecture Framework for Volvo Cars

Patrizio Pelliccione, Eric Knauss, Rogardt Heldal, Magnus Ågren, **Piergiuseppe Mallozzi**, Anders Alminger, Daniel Borgentun

*Workshop on Automotive Systems/Software Architectures (WASA), 2016*

PVSio-web: Mathematically Based Tool Support for the Design of Interactive and Interoperable Medical Systems

Paul Curzon, Paolo Masci, Patrick Oladimeji, **Piergiuseppe Mallozzi**

*EAI Endorsed Transactions on Collaborative Computing, ACM, 2015*

Design and Development of a Co-simulation Library for the PVSio-web Prototyping Tool

**Piergiuseppe Mallozzi**

*Master Thesis, 2015*

Using PVSio-web and SAPERE for Rapid Prototyping of User Interfaces in Integrated Clinical Environments

Paolo Masci, **Piergiuseppe Mallozzi**, Francesco Luca De Angelis, G Di Marzo Serugendo, Paul Curzon

*Verisure2015, Workshop on Verification and Assurance, Co-located with CAV, 2015*

## Invited Talks

---

2022	<b>DARPA PI Meeting</b> , Contract-Based Symbiotic Design for Cyber-Physical Systems	<i>Seattle, USA</i>
2019	<b>Nanyang Technological University (NTU)</b> , Hierarchical Refinement of Goal Models using Contracts	<i>Singapore</i>
2019	<b>Singapore University of Technology and Design (SUTD)</b> , Goal Models and Contract-Based Design	<i>Singapore</i>
2018	<b>Japanese Society for Promoting Science (JSPS)</b> , STINT Sweden Representative Talk	<i>Tokyo, Japan</i>
2018	<b>Okinawa Institute of Science and Technology (OIST)</b> , Safe Reinforcement Learning	<i>Okinawa, Japan</i>
2018	<b>Osaka University</b> , Run-time Monitoring and Reinforcement Learning	<i>Osaka, Japan</i>
2018	<b>Kyoto University</b> , Run-time Monitoring and Reinforcement Learning	<i>Kyoto, Japan</i>
2018	<b>Advanced Telecommunications Research Institute (ATR)</b> , Safe Reinforcement Learning	<i>Kyoto, Japan</i>
2017	<b>Cruise</b> , Autonomous Driving and Reinforcement Learning	<i>San Francisco, USA</i>
2017	<b>Ericsson</b> , Thrustworthy Autonomous Systems	<i>Santa Clara, USA</i>
2017	<b>International Conference of Software Engineering (ICSE)</b> , Self-Adaptive Systems	<i>Buenos Aires, ARG</i>
2015	<b>NASA Langley Research Center</b> , Flight Simulator Demonstration and Formal Verification	<i>Langley, USA</i>

## References

---

**Alberto Sangiovanni-Vincentelli** Supervisor at UC-Berkeley

[alberto@berkeley.edu](mailto:alberto@berkeley.edu)

**Pierluigi Nuzzo** Assistant Professor at USC-Viterbi

[nuzzo@usc.edu](mailto:nuzzo@usc.edu)

*Additional references available upon request.*