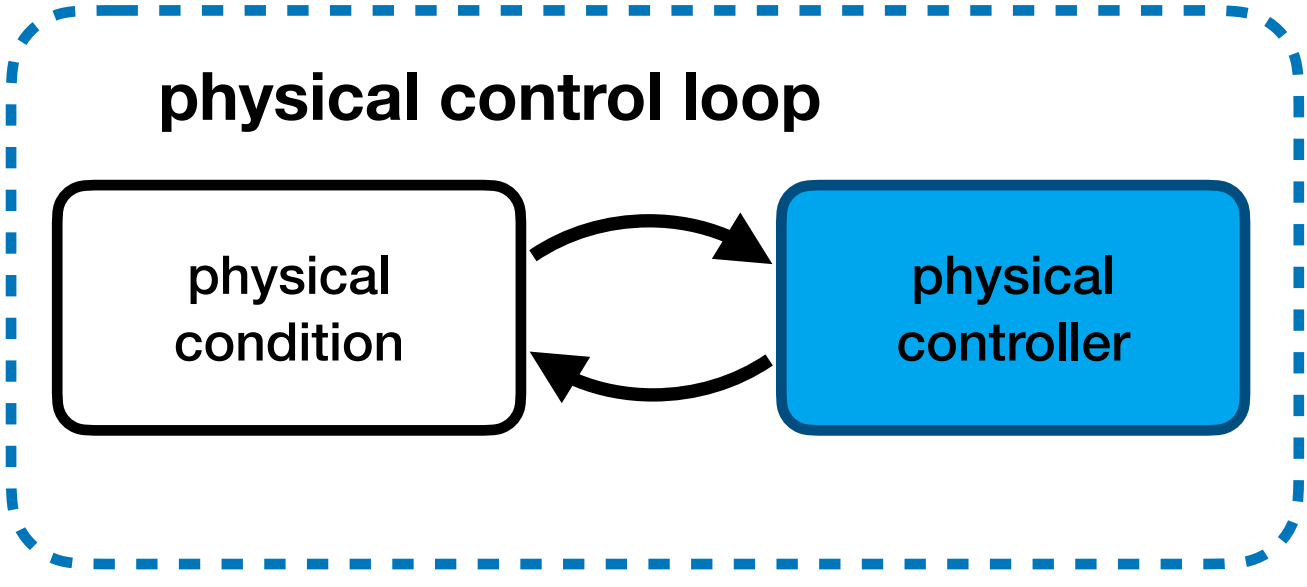
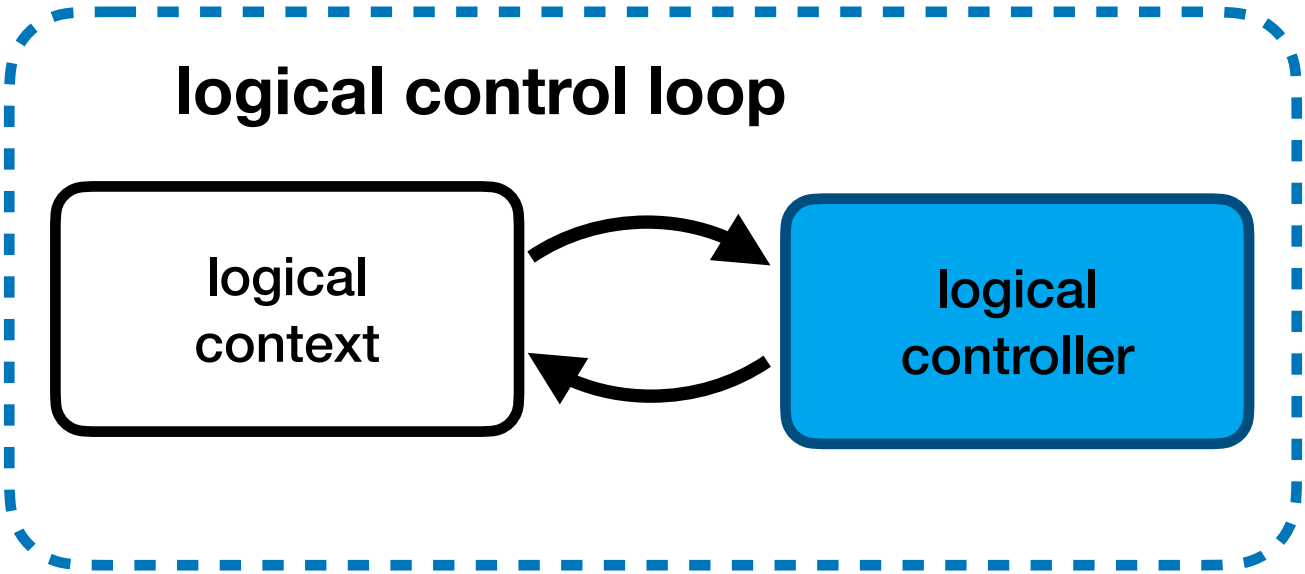
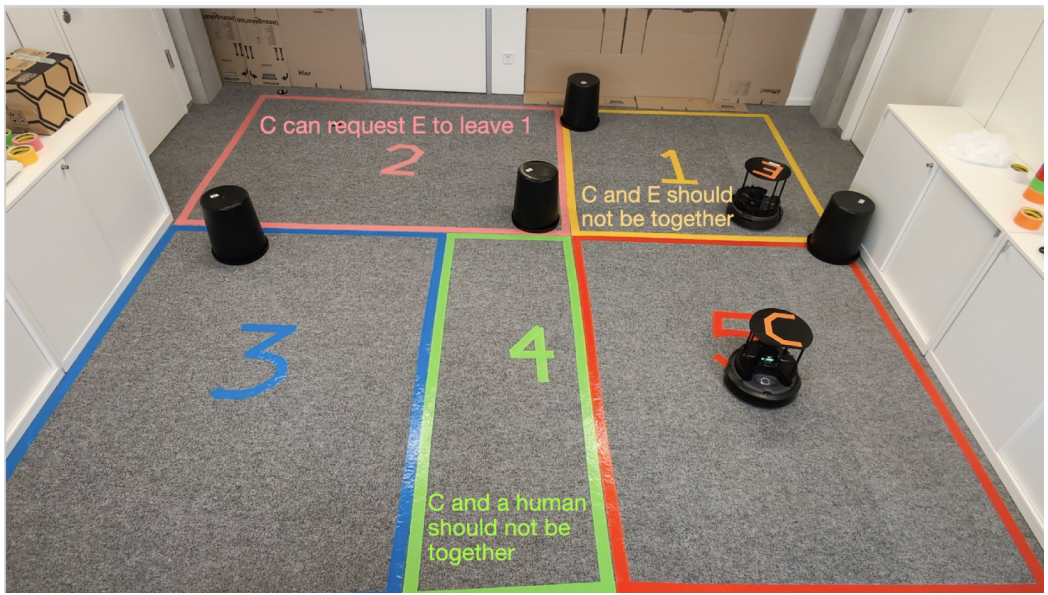
Control for Autonomy

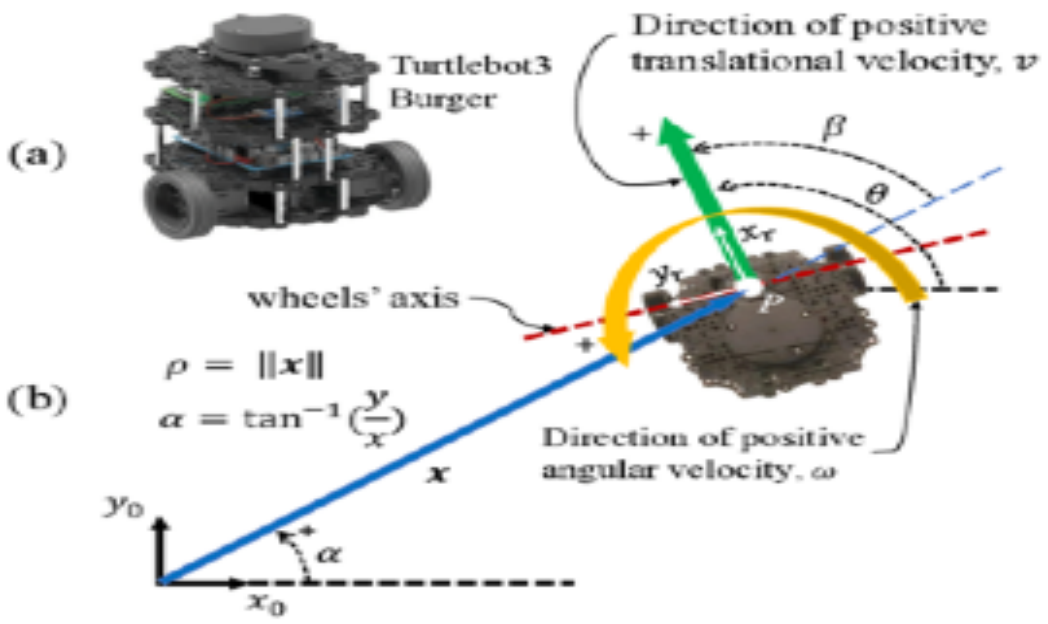


Lower Physical Layer

Higher Logical Layer




C can request E to leave 1
2
1
C and E should not be together
3
4
5
C and a human should not be together

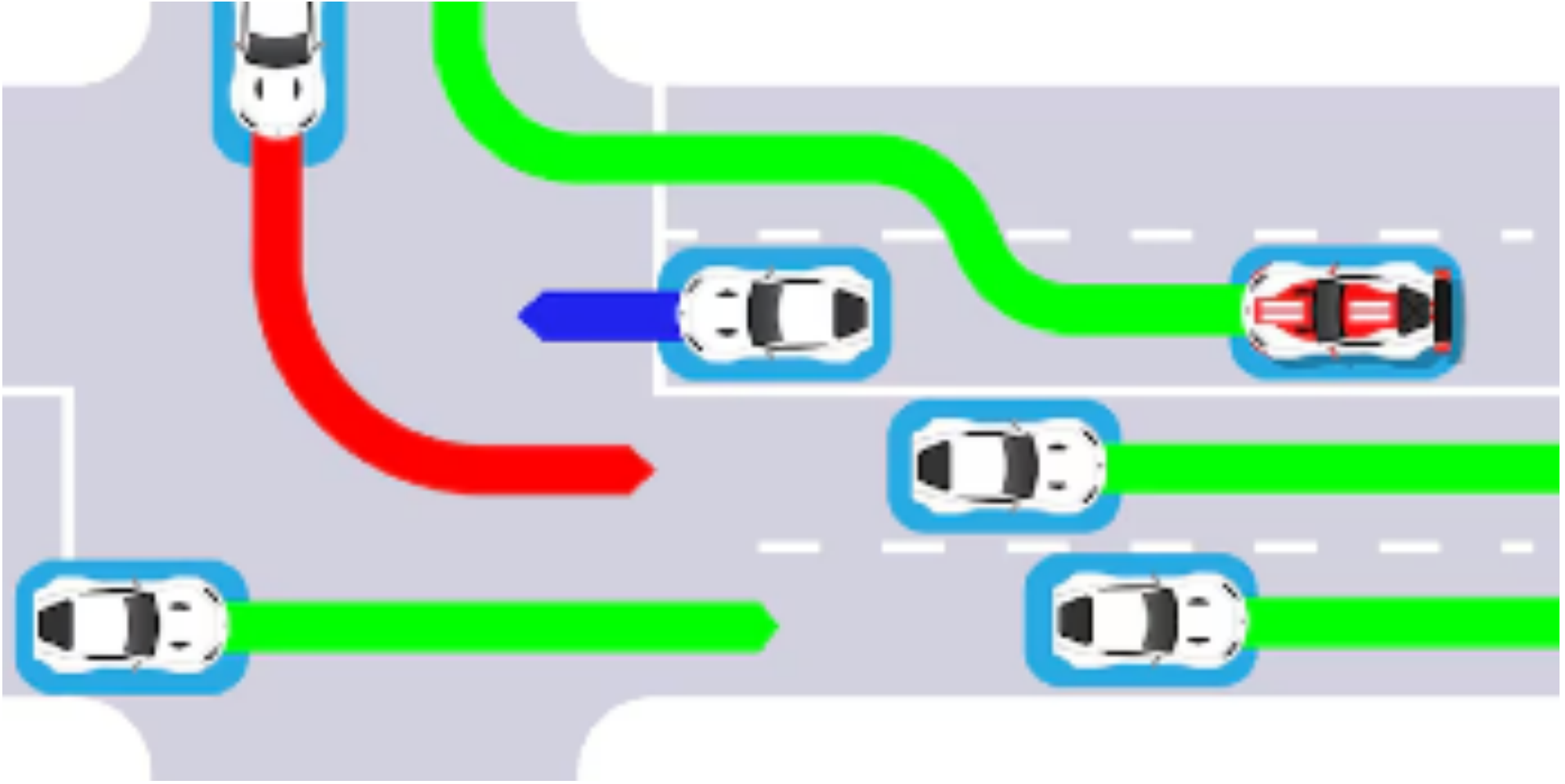

(a)
Turtlebot3
Burger
Direction of positive
translational velocity, v
+
β
θ
x_r
y_r
P
wheels' axis
+
(b)
$\rho = \|x\|$
$\alpha = \tan^{-1}(\frac{y}{x})$
x
Direction of positive
angular velocity, ω
y_0
α
x_0

Formal Methods

techniques to to bridge high-level logical reasoning and low-level control for scalable, reliable autonomy.

Leverage

5



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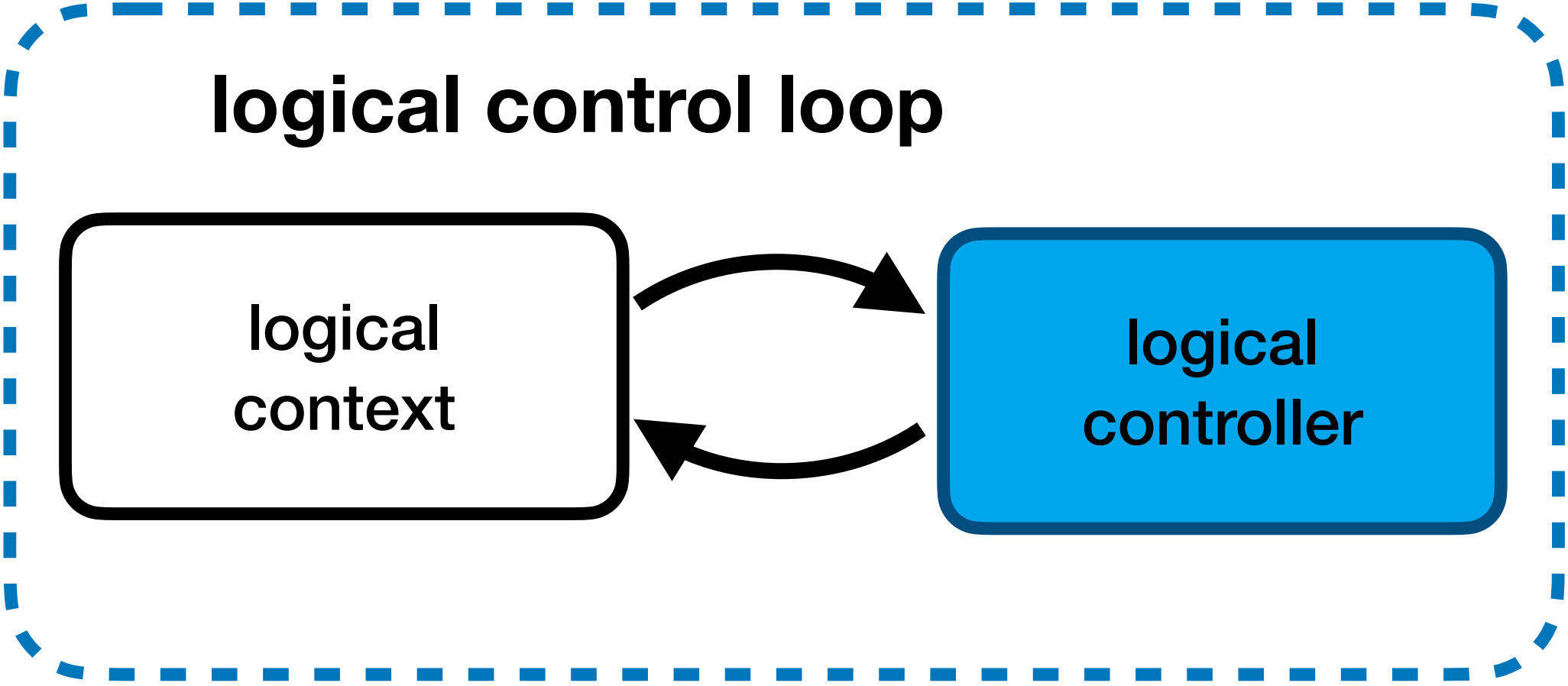
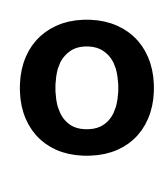
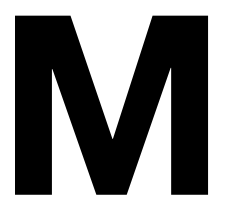
logical
disturbance

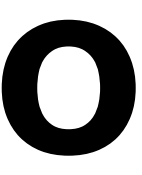
physical
disturbance

Higher Logical Layer









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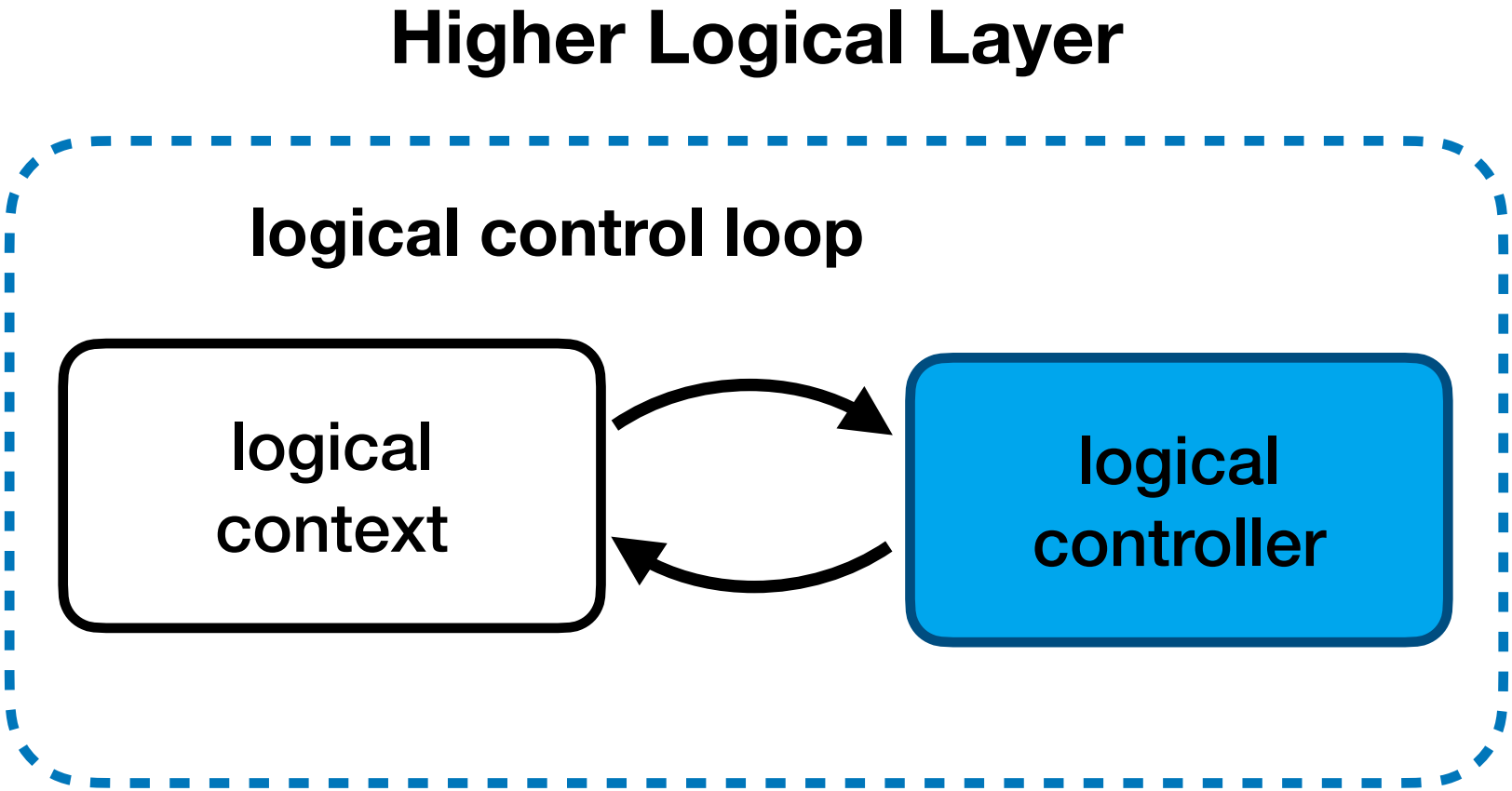
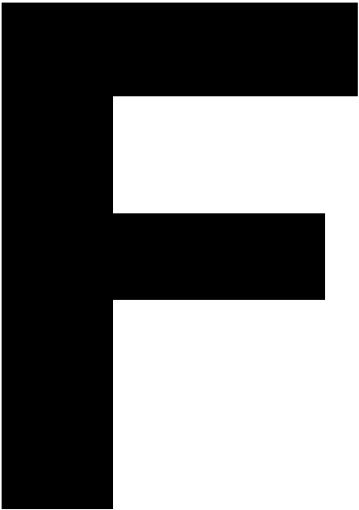
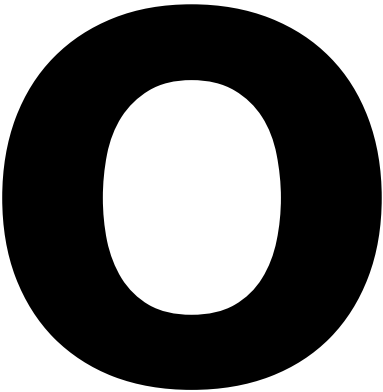
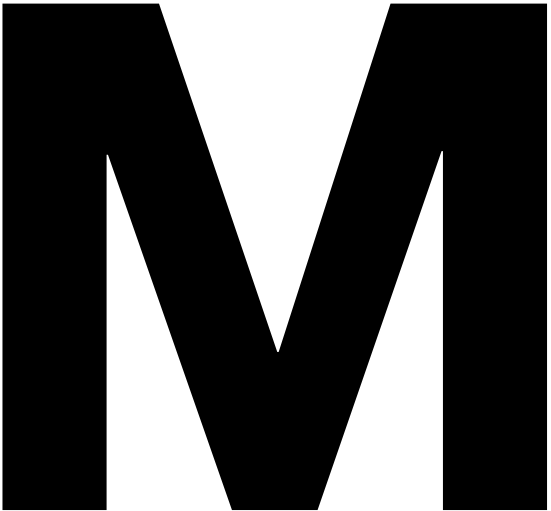
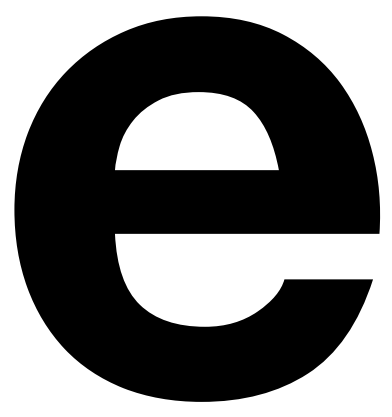
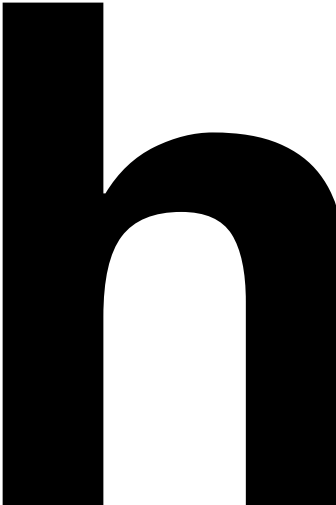

Higher Logical Layer
logical control loop
logical context
logical controller

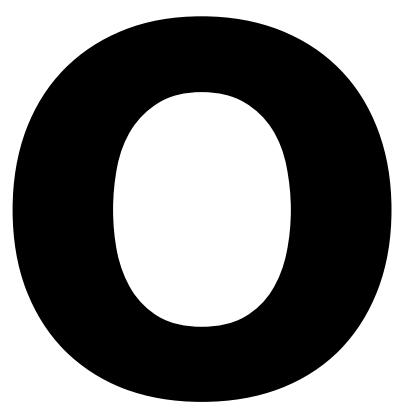


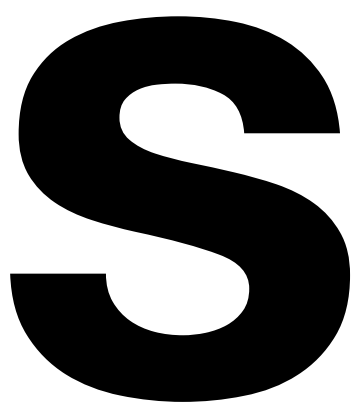












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