

TEXAS TECH UNIVERSITY Department of Mathematics & Statistics^{**}

Dayawansa Memorial (f. (*) - *) + t -Lecture Series

and Antone and Sponsored by Dick and Martha Brooks Endowed Professorship adar-lavel sh ID, when ID 24. 192.119.1. TD is IPof done

Lecture 1 FIL RE - Rotate

Control of Multi-Robot Systems: From Formations to Human-Swarm Interactions Time: 3:30-4:30 p.m., Tuesday, October 25, 2016 Location: CHEM 113 to the

Alternatively run:

Lecture 2

What is Fundamentally Computable by Networked, Dynamical Systems? Time: 3-4 p.m., Wednesday, October 26, 2016 Location: CHEM 107

Lecture 3

Control Classes on a Massive Scale: The Good, the Bad, the Ugly Time: 3:30-4:30 p.m., Thursday, October 27, 2016 Location: CHEM 113



 $(x + \varepsilon y) - L(x) + 2(f_2(x +$

F.(x(T)

OSter

5+57

Data

 $L(x) + \lambda (f_2(x) - \dot{x}))dt$

 $\frac{1}{\varepsilon} \left(\hat{J}(\tau + \varepsilon \theta) - \hat{J}(\tau) \right)$

-1(x)+2(f(x-

Speaker: Magnus Egerstedt Schlumberger Professor, School of **Electrical & Computer Engineering, Georgia Institute of Technology**

bijoy.ghosh@ttu.edu