

Timed traces accepted by a timed automaton

• state of $G = (x, \vec{v}) \in X \times \mathbb{R}_+^{|\mathcal{C}|}$

initial state = $(x_0, \vec{0})$

• Notation: $\vec{v} + t$, $t \in \mathbb{R}_+$, denotes clock vector after time t
 $\vec{v} \downarrow_{\hat{\mathcal{C}}}$, $\hat{\mathcal{C}} \subseteq \mathcal{C}$, denotes clock vector with clocks in $\hat{\mathcal{C}}$ reset to 0.

• state transition:

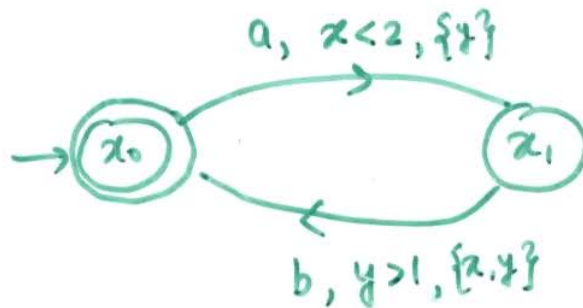
(x, \vec{v})

$\downarrow (\sigma, t)$

(x', \vec{v}')

$\Leftrightarrow \exists e = (x, \sigma, \phi, \hat{\mathcal{C}}, x') \in E$
 such that
 $\vec{v} + t$ satisfies ϕ (e enabled)
 and $(\vec{v} + t) \downarrow_{\hat{\mathcal{C}}} = \vec{v}'$

• Example:



$$(x_0, [0, 0]) \xrightarrow[t_0 < 2]{a, t_0} (x_1, [t_0, 0]) \xrightarrow[t_1 - t_0 > 1]{b, t_1} (x_0, [0, 0])$$

$$T_m(G) = \left\{ (a, t_0) (b, t_1) (a, t_2) (b, t_3) \dots \mid \begin{array}{l} t_{2i} - t_{2i-1} < 2, \text{ and} \\ t_{2i+1} - t_{2i} > 1 \end{array} \right\}$$