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Max-Planck Institute for Dynamics of Complex Technical Systems
Computational Methods in Systems and Control Theory Group

My Interests:

Applied Mathematics

Model Reduction

Complex Networks

System Theory

Control Engineering

Scientific Computing

My Research:

Nonlinear Model Order Reduction

Combined State and Parameter Reduction

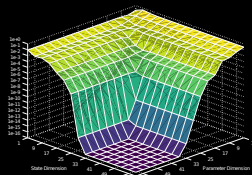
Model Reduction for Hyperbolic PDAEs

My Software:

emgr - EMpirical GRamian Framework

More info at: gramian.de

$$\dot{x}(t) = f(x(t), u(t), \theta)$$
$$y(t) = g(x(t), u(t), \theta)$$



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