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Automated Testing of Models of Cyber-Physical Systems

by

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Abstract

Area of verification...

Keywords:

keyword1, keyword2, keyword3, keyword4, keyword5.

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Abbreviations

General[TODO delete if no other cathegory]

CPS	Cyber-Physical Systems
MBD	Model-based design
MTL	Metric Temporal Logic
GPS	Global Positioning System
\mathbb{Q}	Rational numbers set
\mathbb{F}_t	Floating point numbers set with a precision of t
\mathbb{R}	Real numbers set

Common Mathematical Functions and Operators

10_2	Numbers' radices are designated with a subscript
\mathbf{b}	Vector \mathbf{b}
b_i	the i^{th} element of vector \mathbf{b}
$\ \mathbf{b}\ $	Norm of vector \mathbf{b}
$\dim \mathbf{b}$	Dimension of vector \mathbf{b}
\mathbf{A}	Matrix \mathbf{A}
$a_{i,j}$	Element of matrix \mathbf{A} at the i^{th} row, and the j^{th} column
\mathbf{A}^{-1}	Inverse matrix to matrix \mathbf{A}
\mathbf{A}^T	Transposed matrix to matrix \mathbf{A}
$\ \mathbf{A}\ $	Norm of matrix \mathbf{A}
$\text{cond } \mathbf{A}$	Condition number of matrix \mathbf{A}
$\text{rank } \mathbf{A}$	Rank of matrix \mathbf{A} — how many independent rows/columns it has
$\max \{a, b\}$	Maximum of a and b , a when $a \geq b$, b when $a < b$
$\min \{a, b\}$	Minimum of a and b , a when $a \leq b$, b when $a > b$
$O(x)$	The big O notation
$\Theta(x)$	The big Θ notation

Mathematical Terminology

Q	Number of prime number modules
M	A product of individual modules $M = \prod_{i=1}^Q m_i$
...	...
...	...
...	...
...	...

Miscellaneous Abbreviations

FPU	Floating Point Unit
...	...
...	...
...	...
...	...

Chapter 1

Introduction

At the beginning of the 21.st century human race enters into a new era of industrial revolution generally called Industry 4.0[TODO citation]. So far humans used computers and automation to make industrial processes as efficient as possible. But now the technology allows us to create Cyber-Physical Systems (CPS) and integrate them into the industrial process. All the work thus can be passed to fully autonomous devices that man will only oversee, giving us more space for something humans do the best, intellectual creativity. But if we are to put all the work on CPS, we must make sure that such devices will be as safe and secure as possible.

1.1 Motivation

CPS are specific in their struture[5[Tariq,Florence]Design Specification of Cyber-Physical Systems]. They contain both a discrete unit and continuous unit. Most of such devices fit into cathegory of embedded systems, because they monitor variables of the physical world (temperature, pressure, chemical composition, speed, etc.) and also react based on the values of such variables. The manufacturing process of CPS is still very expensive. To address this issue, many companies all over the world use Model-based design (MBD) for prototyping and upgrading their products. MBD puts a lot of emphasis on the creation of digital model of CPS.

An important part of such process is model verification. Usually an engineer has a list of requirements that CPS must comply in order to be labeled as safe an secure. Manual process of verification of models of CPS is very time consuming and limited. That is why several verification tools have been developed to help companies by running automated tests simulations against a set of requirements. These tools use complex search algorithms to find a simulation trajectory that violates given requirement(s). It is not a trivial task, because of the conjunction of discrete and continuous worlds. For example continuous dynamic of rotating car wheel can be clearly described using set of differential equations, but when an Anti-lock braking system discrete controller locks the wheel, none of these equations holds.

1.2 Problem Statement

In addition to a vast complexity of behaviour of CPS, verification tools treat models of CPS only as black boxes, not considering its inner structure. This approach have its limitations. Testing a model without the knowledge of its inner structure will never be as effective as if we would test it with structure and contextual analysis. That is why we aim to propose new algorithms for automated testing of models of CPS with the consideration of their inner structure.

The first objective of our research is to gather useful models of CPS, preferably the ones used in the industry area. Then we focus on the verification process itself and the tools generally used in practise. We try to find use cases when the performance of conventional or academic tools is insufficient and enhance them by providing deep model analysis information.

1.3 Related Work/Previous Results

This research is based upon the work of the research group from Cyber-Physical Systems Laboratory at Arizona State University. [TODO publication citations] They created a verification tool named S-TaLiRo [TODO citation of S-TaLiRo paper] and also presented their own metric for effective searching for simulation trajectories when verifying a model against given specification [citation of robustness metric paper].

When working with specification and requirements we use Metric Temporal Logic (MTL) developed by Ron Koymans [citation]. This way of specifying demands on CPS is suitable because MTL allows us to formulate restrictions as: "There is a maximum number of time units so that each occurrence of an event E is responded to within this bound".

Our effort were presented on the student seminar PAD 2017 [citation] where we gathered a lot of valuable feedback. This helped us to concretise our goals and form reasonable milestones.

1.4 Structure of the Report

The report is organized into ... chapters as follows:

1. *Introduction*: Describes the motivation behind our efforts together with our goals. There is also a list of contributions of this report.
2. *Background and State-of-the-Art*: Introduces the reader to the necessary theoretical background and surveys the current state-of-the-art.
3. *Overview of Our Approach*: ...
4. *Preliminary Results*: ...

5. *Conclusions*: Summarizes the results of our research, suggests possible topics of your doctoral thesis and further research, and concludes the report.

Chapter 2

Background and State-of-the-Art

In the last decade we have seen a dramatic decrease in the cost of certain computation technologies and such phenomenon gave a birth of a new family of embedded control systems that are much better prepared for fluent, realistic interaction with the continuous physical world around them. For systems that combine physical world around us with the world of cybernetics, we use a term cyber-physical system. Although certain forms of CPS have been in industrial use since 1980s, only recently has the technology for processors, wireless communication, and sensors matured to allow the production of components with impressive capabilities at a low cost.[Rajeev Alur Principles of CPS]

Advance in the field of Cyber-physical systems will bring us closer to usage of high-speed, low-cost, and real-time embedded computers in technologies like electric networks that employ advanced monitoring [Smart Grids: A Cyber-Physical Systems Perspective, By Xinghuo Yu and Yusheng Xue], networked autonomous vehicles [E. A. Lee, "Cyber Physical Systems: Design Challenges," 978-0-7695-3132-8] or prosthesis like neural controlled artificial leg [On Design and Implementation of Neural-Machine Interface for Artificial Legs, Xiaorong Zhang, Yuhong Liu]. CPS are a research priority for both, government agencies (National Science foundation) and industry (automotive, avionics, medical devices).

2.1 Cyber-Physical Systems

The concept of a cyber-physical system is a generalization of embedded systems.[Rajeev Alur Principles of CPS] An embedded system consists of hardware and software integrated within a mechanical or and electrical system designed for a specific purpose. CPS consist of a computational unit, sensors, actuators and a physical world which it must observe and react on it. In a CPS the controller consists of discrete software concurrent components, operating in multiple modes of operation, interacting with the continuously evolving physical environment. Examples of on-board sensors include a global positioning system (GPS) receiver, a camera or an infrared thermal sensor.[Rajeev Alur Principles of CPS] CPS are reactive systems which interact with its environment in an ongoing manner. There is an

endless loop of data collection and input evaluation throughout the time.

TODO Chart of CPS

In comparison to the traditional software development architecture, the creation of CPS differs in the emphasis on the security, confidence, reliability and performance of the system. CPS are often used in areas with many safety requirements (medicine [cite S-TaLiRo insulin pump], automotive [cite EMB paper], civil engineering [cite some smarthome papers], avionics, etc.). Apart from embedded systems, CPS will not be operating in a controlled environments and must be robust to unexpected conditions and adaptable to subsystem failures. [E. A. Lee, Cyber Physical Systems: Design Challenges, 2008,978-0-7695-3132-8]. An example of such systems is an autopilot system used on Airbus aircraft. It is a device used to guide an aircraft without direct assistance from the pilot. Modern autopilots are capable of controlling every part of the flight from just after take-off to landing and are normally integrated with the flight management system.

2.1.1 Reactive Computation

CPS are intended to seamlessly interact with the physical world around in an infinite feedback loop. Such real-time computing can be very challenging, because it usually consist of processing huge amount of inputs and delivering immediate reactions. The traditional computing device process an input and produces an output. An example is a program that process an unsorted list of numbers and returns a sorted list (based on given criteria, e.g. in an ascending order).

A reactive system, in contrast, interacts with its environment in an ongoing manner via inputs and outputs. As a typical example of reactive computation consider a program for a cruise controller in a car. CPS are reative systems.[Rajeev Alur Principles of CPS]

The design of a complex cyber-physical system — especially one with heterogeneous subsystems distributed across networks — is a demanding task. Commonly employed design techniques are sophisticated and include mathematical modeling of physical systems, formal models of computation, simulation of heterogeneous systems, software synthesis, verification, validation, and testing.[J. C. Jensen, D. H. Chang and E. A. Lee, A model-based design methodology for cyber-physical systems,978-1-4244-9538-2].

Embedded system is usually constructed from the physical plant and the controller module. The controller contains specific algorithm, designed for capabilities and resources of given embedded system. In industry production area a Model-driven development paradigm has been deployed and successfully tested for development of embedded systems. Unfortunately when we move from simple programs to more complex software systems and particularly to cyber-physical systems, former design techniques and tools are no longer applicable.

During the process of creation and implementation of an autopilot system, we expect a high level of assurance in the correct behavior of the system. If it would be the other way around, any error can lead to unacceptable consequences such as losses of lifes. Systems where safety requirements have higher priority than other design objectives such as performance and developement cost are called safety-critical. CPS generally fit into this

category. That is why assurance of a system's correctness during design is of utmost importance and sometimes even mandatory because of government regulations.

Former approach of system development is divided into several phases: design, implementation, testing and validation. More suitable and practical approach is to write mathematically precise requirements of the desired system, design models of system components and using analysis tools check if the system meets the requirements. Usage of formal models and verification is fitting for the area of safety-critical applications.

And that is why a different paradigm for developing CPS was created. It is called Model-Based Design and it is increasingly adopted by industry.[J. C. Jensen, D. H. Chang and E. A. Lee, A model-based design methodology for cyber-physical systems,978-1-4244-9538-2]

2.2 Model-Based Design

The goal of modeling in system design is to provide mathematical abstractions to manage the complexity of design. In the context of reactive systems, the basic unit of modeling is a component that interacts with its environment via inputs and outputs.[Rajeev Alur Principles of CPS]

In their work Jensen et al. 2011 [J. C. Jensen, D. H. Chang and E. A. Lee, A model-based design methodology for cyber-physical systems,978-1-4244-9538-2] propose a 10-step methodology for developing cyber-physical systems:

1. State the problem
2. Model physical processes
3. Characterize the problem
4. Derive a control algorithm
5. Select models of computation
6. Specify hardware
7. Simulate
8. Construct
9. Synthesize software
10. Verify, validate and test

This approach helps designers break enormous task of creation of CPS into manageable iterations, which can be repeated if needed. Main goal is to identify any bugs or errors as soon as possible and preferably before the construction phase.

2.3 Safety requirements

TODO collect all the examples of the requirements plus from the course at Matfyz the requirements collection and specification and all engineering process around the ccreation of a new model of a system.

2.4 Metric Temporal Logic

2.5 Verification process

about the simulation, tools, robustness metric...

2.6 Previous Results and Related Work

Chapter 3

Overview of Our Approach

The sample Fig. 3.1 shows ...

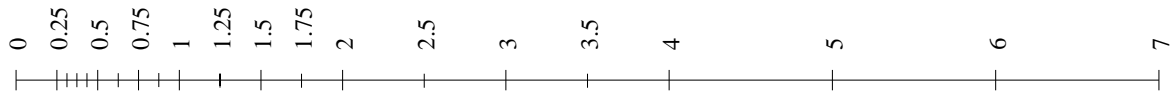


Figure 3.1: Distribution of the floating point numbers. This figure shows a distribution of a sample floating point number set with a precision $t = 3$, and $e_{min} = -1$ and $e_{max} = 3$.

There are two basic floating point data types , as defined by the IEEE 754-2008 [1] standard, are shown in Tab. 3.1.

	Sign [b]	Exponent [b]	Mantissa [b]	Prec. [dig]	Total [b]
binary32	1	8	24	8	32
binary64	1	11	53	16	64

Table 3.1: Basic floating point data types.

Chapter 4

Preliminary Results

4.1 Preliminary Result 1

4.2 Preliminary Result 2

4.3 Preliminary Result 3

4.4 Discussion

4.5 Summary

Chapter 5

Conclusions

5.1 Proposed Doctoral Thesis

Title of the thesis:

TITLE

The author of the report suggests to present the following:

5.1.1 Topic 1

5.1.2 Topic 2

5.1.3 Topic 3

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- [1] IEEE Computer Society Standards Committee. *IEEE Standard for Floating-Point Arithmetic*. ANSI/IEEE STD 754-2008. The Institute of Electrical and Electronics Engineers, Inc., 2008.

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- [A.1] R. Gortz, F. Tölökő. *On the Carpathian Castle*. Transylvanian Journal of ..., Werst, Romania, 2010.

The paper has been cited in:

- Š. Nováků. *Carpathian Castle Revealed*, International Symposium on Carpathian Legends, 1:319–323, 2010.
- [A.2] R. Gortz *Another publication*. 36th International Conference on ..., pp. 19-24, Štrbské pleso, Slovak Republic, 2010.

Appendix A

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A.1 ...

Section not in the Table of Contents