

## 4. Verification of Real-Time systems in UPPAAL

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<https://lmf.di.uminho.pt/CyPhyComp2223/>

<https://haslab.github.io/MFP/PCF/2223/>



Universidade do Minho



- CSS: a simple language for concurrency
  - Syntax
  - Semantics
  - Equivalence
- Timed Automata
  - Syntax
  - Semantics (composition, Zeno)
  - Equivalence
  - UPPAAL tool
    - Specification
    - CTL and Verification
- A simple C-like language
  - Syntax
  - Semantics (operational)
- Hybrid-language: adding differential equations
  - Syntax
  - Semantics
  - Lince tool
    - Specification
    - Analysis
- Monads: semantics with computational effects

1. Modelling in UPPAAL
2. Behavioural Properties
3. Examples: proving mutual exclusion

# Modelling in Uppaal

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... an editor, simulator and model-checker for TA with extensions ...

## Editor.

- Templates and instantiations
- Global and local declarations
- System definition

## Simulator.

- Viewers: automata animator and message sequence chart
- Control (eg, trace management)
- Variable view: shows values of the integer variables and the clock constraints defining symbolic states

## Verifier.

- (see next session)

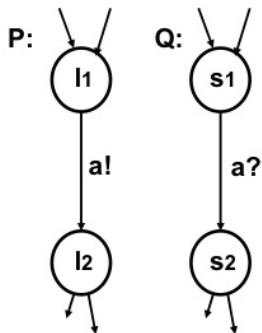
## Extensions (modelling view)

- templates with parameters and an instantiation mechanism
- data expressions over bounded integer variables (eg, `int[2..45] x`) allowed in guards, assignments and invariants
- rich set of operators over integer and booleans, including bitwise operations, arrays, initializers ... in general a whole subset of C is available
- non-standard types of synchronization
- non-standard types of locations

## Extension: broadcast synchronization

- A sender can synchronize with an arbitrary number of receivers
- Any receiver than can synchronize in the current state must do so
- Broadcast sending is never blocking (the send action can occur even with no receivers).

## Extension: urgent synchronization



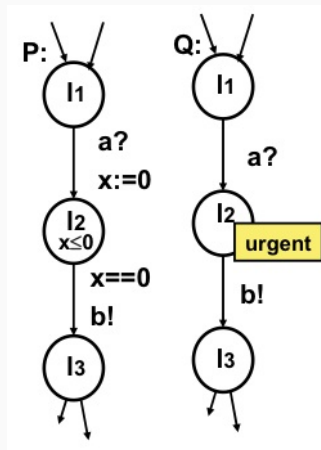
Channel  $a$  is declared **urgent chan  $a$**  if both edges are to be taken as soon as they are ready (**simultaneously** in locations  $\ell_1$  and  $s_1$ ).

Note the problem can **not** be solved with **invariants** because locations  $\ell_1$  and  $s_1$  can be reached at different moments

- No delay allowed if a synchronization transition on an urgent channel is enabled
- Edges using urgent channels for synchronization cannot have time constraints (ie, clock guards)

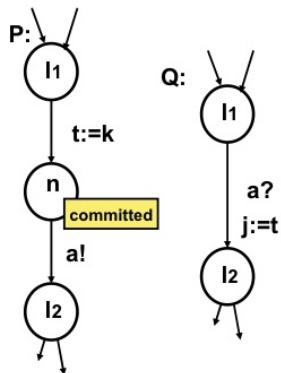


## Extension: urgent location



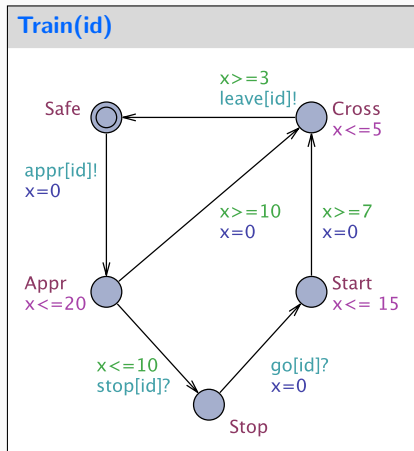
- Time does not progress but interleaving with normal location is allowed
- Both models are equivalent: **no delay at an urgent location**
- but the use of **urgent location** reduces the number of clocks in a model and simplifies analysis

## Extension: committed location



- delay is not allowed and the committed transition must be left in the next instant (or one of them if there are several), i.e., next transition must involve an outgoing edge of at least one of the committed locations
- Our aim is to pass the value  $k$  to variable  $j$  (via global variable  $t$ )
- Location  $n$  is committed to ensure that no other automata can assign  $j$  before the assignment  $j := t$

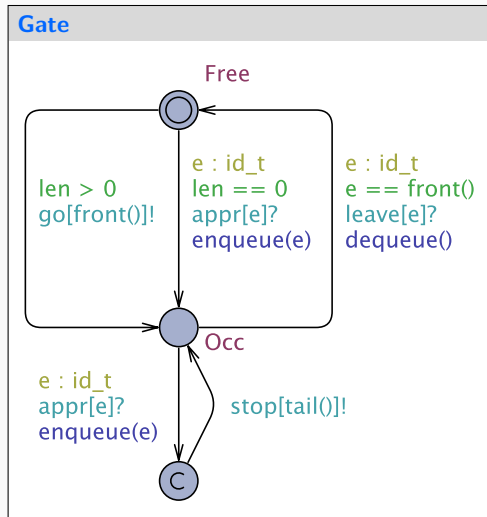
# The train-gate example



- Events model **approach/leave**, order to **stop/go**
- A train cannot be stopped or restart instantly
- After **approaching** it has 10m to receive a **stop**.
- After that it takes further 10m to reach the cross
- After **restarting** takes 7 to 15m to reach the cross and 3-5m to cross

# The train-gate example

- Note the use of parameters and the select clause on transitions
- Programming ...



# Behavioural Properties

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## The satisfaction problem

Given a **timed automata**,  $ta$ , and a **property**,  $\phi$ , show that

$$\mathcal{T}(ta) \models \phi$$

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Given a **timed automata**,  $ta$ , and a **property**,  $\phi$ , show that

$$\mathcal{T}(ta) \models \phi$$

- in which logic language shall  $\phi$  be specified?
- how is  $\models$  defined?

## Uppaal variant of CTL

- **state formulae**: describes individual states in  $\mathcal{T}(ta)$
- **path formulae**: describes properties of paths in  $\mathcal{T}(ta)$



## State formulae

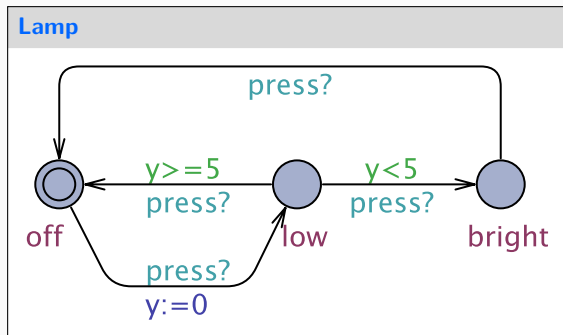
$$\Psi ::= ta.\ell \mid g_c \mid g_d \mid \text{deadlock} \mid \text{not } \Psi \mid \Psi \text{ or } \Psi \mid \Psi \text{ and } \Psi \mid \Psi \text{ imply } \Psi$$

Any expression which can be evaluated to a boolean value for a state (typically involving the **clock constraints** used for guards and invariants and similar constraints over integer variables):

$$x \geq 8, i == 8 \text{ and } x < 2, \dots$$

Additionally,

- **$ta.\ell$**  which tests **current location**:  $(\ell, \eta) \models ta.\ell$   
provided  $(\ell, \eta)$  is a state in  $\mathcal{T}(ta)$
- **deadlock**:  $(\ell, \eta) \models \forall_{d \in \mathcal{R}_0^+}. \text{there is no transition from } \langle \ell, \eta + d \rangle$



## Ex. 4.1: Write a state formula

1. The lamp is low
2. Not off and  $y > 25$
3. If it is low or bright, then  $y \leq 3600$

## Path formulae

$$\Pi ::= A\Box\Psi \mid A\Diamond\Psi \mid E\Box\Psi \mid E\Diamond\Psi \mid \Phi \rightsquigarrow \Psi$$

where

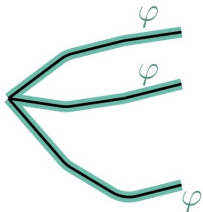
- $A, E$  quantify (universally and existentially, resp.) over **paths**
- $\Box, \Diamond$  quantify (universally and existentially, resp.) over **states in a path**

also notice that

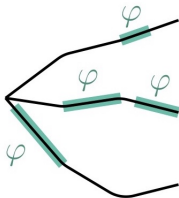
$$\Phi \rightsquigarrow \Psi \stackrel{\text{abv}}{=} A\Box(\Phi \Rightarrow A\Diamond\Psi)$$

# Expressing properties: Uppaal

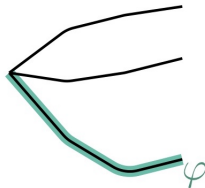
$A \Box \varphi$



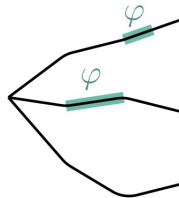
$A \Diamond \varphi$



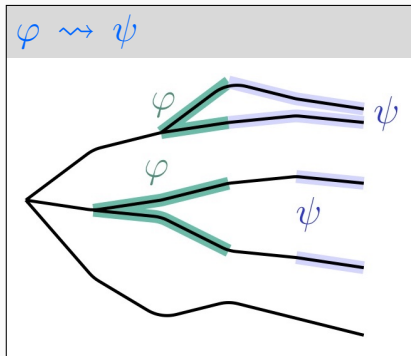
$E \Box \varphi$



$E \Diamond \varphi$



# Expressing properties: Uppaal



## Example

If a message is sent, it will eventually be received –  $\text{send}(m) \rightsquigarrow \text{received}(m)$

$E\Diamond\phi$

Is there a path starting at the initial state, such that a state formula  $\phi$  is eventually satisfied?

- Often used to perform sanity checks on a model:
  - is it possible for a sender to send a message?
  - can a message possibly be received?
  - ...
- Do not by themselves guarantee the correctness of the protocol (i.e. that any message is eventually delivered), but they validate the basic behavior of the model.

$A\Box\phi$  **and**  $E\Box\phi$

Something bad will never happen  
or something bad will possibly never happen

Examples

- In a nuclear power plant the temperature of the core is always (invariantly) under a certain threshold.
- In a game a safe state is one in which we can still win, ie, will possibly not loose.

In Uppaal these properties are formulated positively: something good is invariantly true.

$A \Diamond \phi$  and  $\phi \rightsquigarrow \psi$

Something good will *eventually happen*

or if *something* happens, then *something else* will eventually happen!

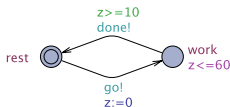
## Examples

- When pressing the on button, then eventually the television should turn on.
- In a communication protocol, any message that has been sent should eventually be received.

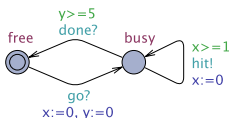


## Exercise: worker, hammer, nail - revisited

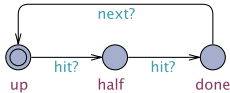
### Worker



### Hammer



### Nail

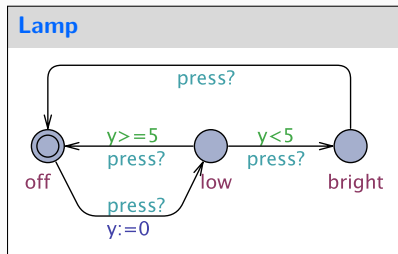


### Ex. 4.2: Write properties and explain them

1. Using  $E\Diamond$
2. Using  $E\Box$
3. Using  $A\Diamond$
4. Using  $A\Box$
5. Using  $\rightsquigarrow$

(Practice in UPPAAL)

## Exercise: write formulas



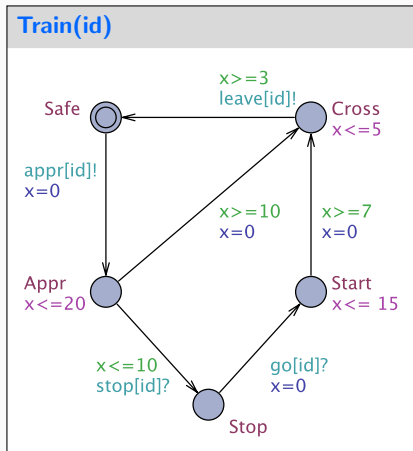
### Ex. 4.3: Write formulas, and say which ones are true

1. The lamp can become bright;
2. The lamp will eventually become bright;
3. The lamp can never be on for more than 3600s;
4. It is possible to never turn on the lamp;
5. Whenever the light is bright, the clock  $y$  is non-zero;
6. Whenever the light is bright, it will eventually become off.

## Examples: proving mutual exclusion

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# The train gate example (1/2)

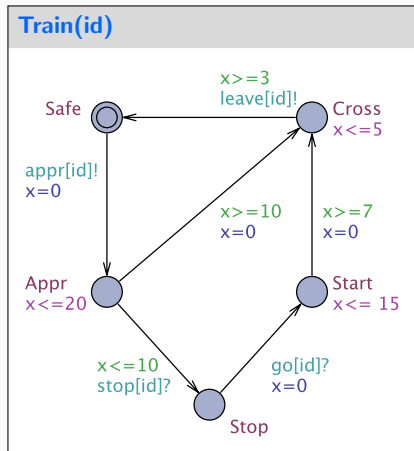


(Train 0 can reach the cross)

(Train 0 can be crossing bridge while Train 1 is waiting to cross)

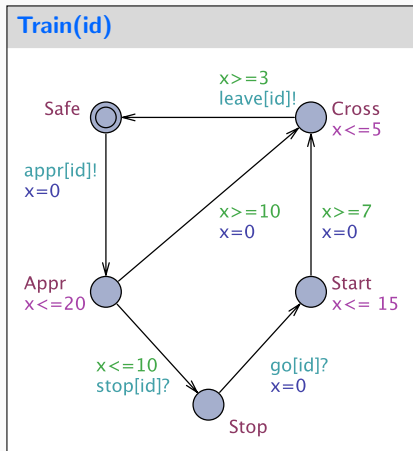
(Train 0 can cross bridge while the other trains are waiting to cross)

# The train gate example (1/2)



- $E \langle \rangle \text{Train}(0).\text{Cross}$   
(Train 0 can reach the cross)
- $E \langle \rangle \text{Train}(0).\text{Cross}$  and  $\text{Train}(1).\text{Stop}$   
(Train 0 can be crossing bridge while Train 1 is waiting to cross)
- $E \langle \rangle \text{Train}(0).\text{Cross}$  and  
     $(\text{forall } (i:\text{id}-t)$   
         $i \neq 0 \text{ imply } \text{Train}(i).\text{Stop})$   
(Train 0 can cross bridge while the other trains are waiting to cross)

## The train gate example (2/2)



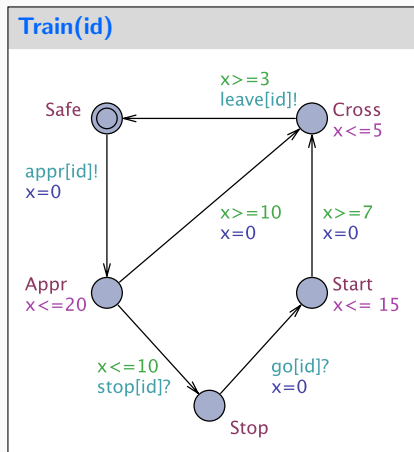
There can never be N elements in the queue

There is never more than one train crossing the bridge

Whenever a train approaches the bridge, it will eventually cross

The system is deadlock-free

## The train gate example (2/2)



- `A[] Gate.list[N] == 0`  
There can never be N elements in the queue
- `A[] forall (i:id-t) forall (j:id-t) Train(i).Cross && Train(j).Cross imply i == j`  
There is never more than one train crossing the bridge
- `Train(1).Appr --> Train(1).Cross`  
Whenever a train approaches the bridge, it will eventually cross
- `A[] not deadlock`  
The system is deadlock-free

## Properties

- **mutual exclusion**: no two processes are in their critical sections at the same time
- **deadlock freedom**: if some process is trying to access its critical section, then eventually some process (not necessarily the same) will be in its critical section; similarly for exiting the critical section



## The Problem

- Dijkstra's original asynchronous algorithm (1965) requires, for  $n$  processes to be controlled,  $\mathcal{O}(n)$  read-write registers and  $\mathcal{O}(n)$  operations.
- This result is a theoretical limit (proved by Lynch and Shavit in 1992) which compromises scalability.

## The Problem

- Dijkstra's original asynchronous algorithm (1965) requires, for  $n$  processes to be controlled,  $\mathcal{O}(n)$  read-write registers and  $\mathcal{O}(n)$  operations.
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but it can be overcome by introducing specific **timing constraints**

## Two timed algorithms:

- **Fisher's protocol** (included in the UPPAAL distribution)
- **Lamport's protocol**

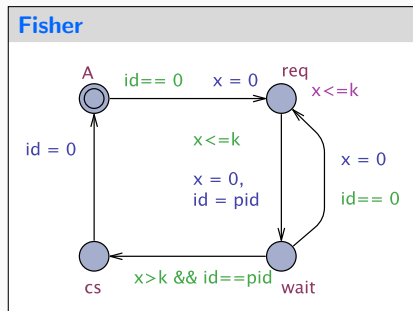
## The algorithm

```
repeat
  repeat
    await  $id = 0$ 
     $id := i$ 
    delay( $k$ )
  until  $id = i$ 
  (critical section)
   $id := 0$ 
forever
```

## Comments

- One shared read/write register (the variable  $id$ )
- Behaviour depends crucially on the value for  $k$  — the **time delay**
- Constant  $k$  should be **larger than the longest time that a process may take to perform a step while trying to get access to its critical section**
- This choice guarantees that whenever process  $i$  finds  $id = i$  on testing the loop guard it can enter safely its critical section: **all** other processes are out of the loop or with their index in  $id$  overwritten by  $i$ .

# Fisher's algorithm in Uppaal



- Each process uses a local clock  $x$  to guarantee that the upper bound between its successive steps, while trying to access the critical section, is  $k$  (cf. **invariant** in state *req*).
- **Invariant** in state *req* establishes  $k$  as such an upper bound
- **Guard** in transition from *wait* to *cs* ensures the correct delay before entering the critical section

# Fisher's algorithm in Uppaal

## Properties

```
% P(1) requests access => it will eventually wait
P(1).req -> P(1).wait
% the algorithm is deadlock-free
A[] not deadlock
% mutual exclusion invariant
A[] forall (i:int[1,6]) forall (j:int[1,6])
    P(i).cs && P(j).cs imply i == j
```

- The algorithm is **deadlock-free**
- It ensures mutual exclusion if the correct timing constraints.
- ... but it is critically sensible to small violations of such constraints: for example, replacing  $x > k$  by  $x \geq k$  in the transition leading to *cs* compromises both **mutual exclusion** and **liveness**.

## The algorithm

```
start :  $a := i$   
       if  $b \neq 0$  then goto start  
        $b := i$   
       if  $a \neq i$  then delay( $k$ )  
           else if  $b \neq i$  then goto start  
       (critical section)  
        $b := 0$ 
```

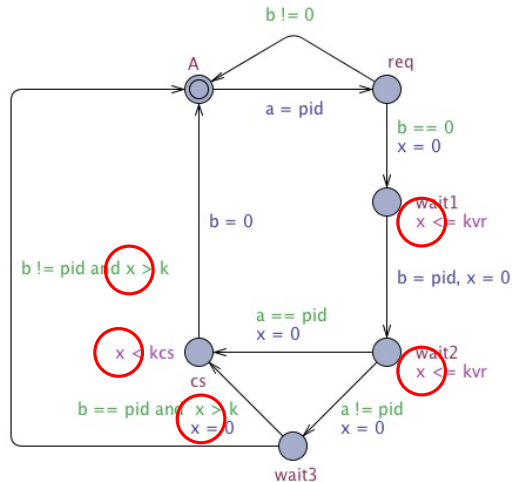
## Comments

- Two shared read/write registers (variables  $a$  and  $b$ )
- Avoids **forced waiting** when no other processes are requiring access to their critical sections



# Lamport's algorithm in Uppaal

## Lamport(pid)



# Lamport's algorithm

## Model time constants:

- $k$  — time delay
- $kvr$  — max bound for register access
- $kcs$  — max bound for permanence in critical section

Typically

$$k \geq kvr + kcs$$

## Experiments

	$k$	$kvr$	$kcs$	verified?
Mutual Exclusion	4	1	1	Yes
Mutual Exclusion	2	1	1	Yes
Mutual Exclusion	1	1	1	No
No deadlock	4	1	1	Yes
No deadlock	2	1	1	Yes
No deadlock	1	1	1	Yes