Modelling Software-based Systems
The Modelling Language Event-B

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General Summary

❶ Documentation

❷ Introduction by Problems
    Safety Properties of C Programs
    Importance of Domain
    Tracking bugs in C codes

❸ Modelling Language

❹ A Simple Example : Management of Students and Teachers

❺ Modelling state-based systems

❻ The Event B modelling language

❼ Examples of Event B models

❽ Summary on Events

Current Summary

Tools

- Event B : http ://www.event-b.org/
- Atelier B : http ://www.atelierb.eu/
- RODIN Platform : http ://www.event-b.org/platform.html
- EB2ALL Toolset : http ://eb2all.loria.fr
- RIMEL project : http ://rimel.loria.fr
- The Modelling Language Event-B and related topics as lectures notes, tutorials, models. https ://mery54.github.io/teaching/mosos/
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RTE

```c
#include <stdio.h>
#include <stdlib.h>
#include <time.h>

int main() {
    int x, y;
    // Seed the random number generator with the current time
    srand(time(NULL));
    // Generate a random number between 1 and 100
    x = rand() % 100 + 1;
    // Perform some calculations
    y = x / (100 - x);
    printf("Result: %d\n", y);
    return 0;
}
```

RTE with frama-c

```c
int main(void)
{
  int __retres;
  int x;
  int y;
  time_t tmp;
  int tmp_0;
  tmp = time((time_t *)0);
  srand((unsigned int)tmp);
  { /* sequence */
    tmp_0 = rand();
    /*@ assert rte: signed_overflow: (int)(tmp_0 % 100) + 1 <= 214
    x = tmp_0 % 100 + 1;
  }
  /*@ assert rte: signed_overflow: 100 - x <= 2147483647; */
  /*@ assert rte: division_by_zero: (int)(100 - x) /= 0; */
  /*@ assert rte: signed_overflow: x / (int)(100 - x) <= 214748364
  y = x / (100 - x);
  printf("Result:-%d\n",y); /* printf_va_1 */
  __retres = 0;
  return __retres;
}
```

RTE with frama-c

```c
// Heisenbug
#include <stdio.h>
#include <stdlib.h>
#include <time.h>


int main() {
  int x, y, i=0;

    for (i = 0; i <= 100000; i++) {
    // Seed the random number generator with the current time
    srand(time(NULL));

    // Generate a random number between 1 and 100
    x = rand() % 100 + 1;
        printf("Result: x= %d\n",x);
    // Perform some calculations
    y = x / (100 - x);

    printf("Result: i=%d  %d\n",i, y);
    }

    return 0;
```

RTE with frama-c but a modification

```c
// Heisenbug
#include <stdio.h>
#include <stdlib.h>
#include <time.h>


int main() {
    int x, y, i=0;

        for (i = 0; i <= 100; i++) {
        // Seed the random number generator with the current time
        srand(time(NULL)+i);

        // Generate a random number between 1 and 100
        x = rand() % 100 + 1;
            printf("Result: x= %d\n",x);
        // Perform some calculations
        y = x / (100 - x);

        printf("Result: i=%d %d\n",i, y);
        }

        return 0;
```

Our aim is to analyze what is implicit and what is explicit in formal modelling...

- **Semantics in modelling** :
  - ▶ Semantics expressed by a *theory* (e.g. Event-B) used to formalize hardware and/or software systems
  - ▶ Same theory is used for wide variety of heterogeneous systems

- **Semantics in domain** :
  - ▶ Environment within which system evolve : application domain/context
  - ▶ Information provided by domain is often associated while in operation
  - ▶ Either assumed and omitted while formalising systems or hardcoded in formal models
  - ▶ Same context is used for wide variety of heterogeneous systems

A case study for studying these properties

Nose Gear Velocity

- Estimated ground velocity of the aircraft should be available only if it is within 3 `km/hr` of the true velocity at some moment within past 3 seconds

- NG velocity system :
  - ▶ **Hardware** :
    - *Electro-mechanical sensor* : detects rotations
    - *Two 16-bit counters* : Rotation counter, Milliseconds counter
    - *Interrupt service routine* : updates rotation counter and stores current time.
  - ▶ **Software** :
    - *Real-time operating system* : invokes update function every 500 ms
    - *16-bit global variable* : for recording rotation counter update time
    - *An update function* : estimates ground velocity of the aircraft.
- Input data available to the system :
  - ▶ *time* : in milliseconds
  - ▶ *distance* : in inches
  - ▶ *rotation angle* : in degrees
- Specified system performs velocity estimations in *imperial* unit system
- Note : expressed functional requirement is in *SI* unit system (km/hr).

What are the main properties to consider for formalization ?

- **Two different types of data** :
  - ▶ counters with modulo semantics
  - ▶ non-negative values for time, distance, and velocity
- **Two dimensions** : *distance* and *time*
- **Many units** : distance (`inches`, `kilometers`, `miles`), time (`milliseconds`, `hours`), velocity (`kph`, `mph`)
- And interaction among components

How should we model ?

- Designer needs to consider units and conversions between them to manipulate the model
- **One approach** : Model units as *sets*, and conversions as constructed types – *projections*.
- Example :
  1. $estimateVelocity \in \texttt{MILES} \times \texttt{HOURS} \to \texttt{MPH}$
  2. $mphTokph \in \texttt{MPH} \rightarrowtail \texttt{KPH}$

time →

0 degrees → "click"   120 degrees   240 degrees   0 degrees → "click"

H/W interrupt

NGClickTime = 4123 millisecs
NGRotations = 8954

H/W interrupt

NGClickTime = 4367 millis
NGRotations = 8955

WHEEL_DIAMETER = 22 inches   12 inches/foot
PI = 3.14   5280 feet/mile

estimatedGroundVelocity = distance travel/elapsed time
= ((3.14 * 22)/(12*5280))/((4367-4123)/(1000*3600
= 16 mph

Listing 1 – Bug bug0

```c
#include <stdio.h>
#include <stdlib.h>
#include <time.h>

int main() {
    int x, y;
    // Seed the random number generator with the current time
    srand(time(NULL));
    // Generate a random number between 1 and 100
    x = rand() % 100 + 1;
    // Perform some calculations
    y = x / (100 - x);
    printf("Result: %d\n", y);
    return 0;
}
```

bug00.c

Listing 2 – Bug bug00

```c
// Heisenbug
#include <stdio.h>
#include <stdlib.h>
#include <time.h>


int main() {
  int x, y, i=0;

    for (i = 0; i <= 100000; i++) {
    // Seed the random number generator with the current time
    srand(time(NULL));

    // Generate a random number between 1 and 100
    x = rand() % 100 + 1;
        printf("Result: x= %d\n",x);
    // Perform some calculations
    y = x / (100 - x);

    printf("Result: i=%d  %d\n",i, y);
    }

    return 0;
}
```

bug000.c

Listing 3 – Bug bug000

```c
// Heisenbug
#include <stdio.h>
#include <stdlib.h>
#include <time.h>


int main() {
  int x, y, i=0;

    for (i = 0; i <= 100; i++) {
    // Seed the random number generator with the current time
    srand(time(NULL)+i);

    // Generate a random number between 1 and 100
    x = rand() % 100 + 1;
        printf("Result:x=%d\n",x);
    // Perform some calculations
    y = x / (100 − x);

    printf("Result:i=%d%d\n",i, y);
    }

    return 0;
}
```

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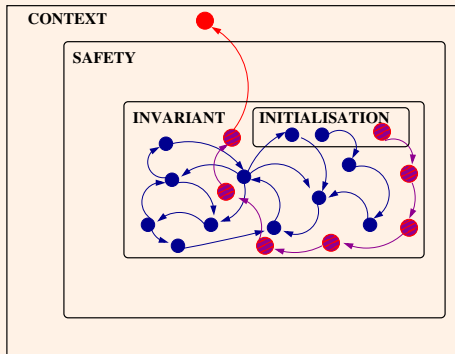
7 Examples of Event B models

8 Summary on Events

Observing the safe system

- The context defines the possible values
- Safety requirement means that *something bad will never happen*.
- Invariant defines the set of effective possible values
- Transitions modify state variables and maintains the invariant.

- Transitions modify state variables and may not maintain the invariant.
- . . . and may not guarantee safety properties.

Tools

- Event B : http ://www.event-b.org/
- Atelier B : http ://www.atelierb.eu/
- RODIN Platform : http://www.event-b.org/platform.html

The Event B Method

- The Event B Method is invented by J.-R. Abrial from 1988 : abstract system, events, refinement, invariant.
- Atelier B and RODIN are supporting the Event B method
- An event is observed and triggered, when a guard is true
- Proof obligations are generated using the weakest-precondition semantics.
- A Event B model intends to model a reactive system.

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A Simple Example

Managing teachers, students, lectures and class rooms

- Modelling the access control of students for lectures given by teachers

- When a student is attending a lecture, he/she can not attend another lecture

- When a teacher is lecturing, he/she is not lecturing another session.

- A student can not be lecturing without a teacher and when he is not attending a lecture, he is outside the classroom.

- When a teacher is ending a lecture, every student which is attending, is leaving the class room.

- When a student is not attending a lecture, he is free.

- Sets : students, teachers
- **Property 1 :** When a student is attending a lecture, he/she can not attend another lecture
- **Property 2 :** When a teacher is lecturing, he/she is not lecturing another session.
- **Property 3 :** A student can not be lecturing without a teacher and when he is not attending a lecture, he is outside the classroom.
- **Property 4 :** When a teacher is ending a lecture, every student which is attending, is leaving the class room.
- **Property 5 :** When a student is not attending a lecture, he is free.

- **The system model should be able to record the lecturing teachers and the attending students.**
- **The system model should be enough expressive to state when a given student is attending a lecture given by whom.**
- **Variable attending records students which atteding some lecture with a given teacher.**
- **Variable islecturing records teachers who are lecturing.**
- **Variable pause records sudents are not attending a lecture but are somewhere not in a lecture.**

Expression of the invariant

$$
\begin{aligned}
&inv1 : attending \in STUDENTS \nrightarrow TEACHERS \\
&inv2 : islecturing \subseteq TEACHERS \\
&inv3 : \forall e \cdot e \in STUDENTS \land e \in dom(attending) \\
&\qquad\qquad \Rightarrow \quad attending(e) \in islecturing \\
&inv4 : pause \subseteq STUDENTS \\
&inv5 : pause \cap dom(attending) = \varnothing \\
&inv6 : pause \cup dom(attending) = STUDENTS
\end{aligned}
$$

Checking proof obligations !

UseCases

- **EVENT** INITIALISATION : initializing state variables
- **EVENT** startingattending : a group of students is moving from *pause* to *lecture*
- **EVENT** teachergivinglecture : a teacher is starting a new lecture
- **EVENT** teacherendinglecture : a teacher is halting the lecture
- **EVENT** studentleavinglecture : a group of students is moving from *lecture* to *pause*

EVENT INITIALISATION
  BEGIN
    $act1:\ attending := \varnothing$
    $act2:\ islecturing := \varnothing$
    $act3:\ pause := STUDENTS$
  END

Fourth step : Updating state variables

EVENT startingattending
   ANY
      e e is a student
      p p is a teacher
   WHERE
      $grd1 : e \in STUDENTS$
      $grd3 : p \in TEACHERS$
      $grd4 : p \in islecturing$
      $grd2 : e \notin dom(attending)$
   THEN
      $act1 : attending(e) := p$
      $act2 : pause := pause \setminus \{e\}$
   END

Fourth step : Updating state variables

EVENT teachergivinglecture
   ANY
     p
   WHERE
     $grd2 : p \in TEACHERS$
     $grd1 : p \notin islecturing$
   THEN
     $act1\ islecturing := islecturing \cup \{p\}$
END

Fourth step : Updating state variables

EVENT teacherendinglecture
  ANY
    p
  WHERE
    $grd1 : p \in TEACHERS$
    $grd2 : p \in islecturing$
  THEN
    $act1 : islecturing := islecturing \setminus \{p\}$

$act3 : attending := attending \setminus \{f \mapsto q \mid \left(\begin{array}{l} f \in STUDENTS \\ \wedge q \in TEACHERS \\ \wedge f \mapsto q \in attending \\ \wedge q = p \end{array} \right) \}$

$act2 : pause := pause \cup \{f \mid f \in STUDENTS \wedge f \in attending^{-1}[\{p\}]\}$
  END

Fourth step : Updating state variables

```
EVENT studentleavinglecture
  ANY
    ge
  WHERE
    grd1 : ge ⊆ dom(attending)
    grd2 : ge ≠ ∅
  THEN
    act1 : attending := ge ⩤ attending
    act2 : pause := pause ∪ ge
  END
```

- **set theory : sets, relations, functions . . .**
- **transition systems**
- **predicate calculus**
- **decision procedures**
- **interactive theorem prover**

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- A **system** is **observed**
- Observation of things which are
  - ▶ either changing over the **time** (*variable*)
  - ▶ or stuttering over the **time** (*constant*)
- A system is characterized by a **state**
- A state is made up of contextual **constant informations** over the problem theory and of **modifiable flexible informations** over the system.

A **flexible variable** x is observed at different instants :

$$x_0 \; \overset{\tau}{\to} \; x_1 \; \overset{\tau}{\to} \; x_2 \; \overset{\tau}{\to} \; x_3 \; \overset{\tau}{\to} \ldots \overset{\tau}{\to} \; x_i \; \overset{\tau}{\to} \; x_{i+1} \; \overset{\tau}{\to} \ldots$$

τ hides effectives changes of state or actions or events

$$x_0 \; \overset{\alpha_1}{\to} \; x_1 \; \overset{\alpha_2}{\to} \; x_2 \; \overset{\alpha_3}{\to} \; x_3 \; \overset{\alpha_4}{\to} \ldots \overset{\alpha_i}{\to} \; x_i \; \overset{\alpha_{i+1}}{\to} \; x_{i+1} \; \overset{\alpha_{i+2}}{\to} \ldots$$

Occurences of e τ can be added between two instants ie stuttering steps :

$$x_0 \; \overset{\alpha_1}{\to} \; x_1 \; \overset{\alpha_2}{\to} \; x_2 \; \overset{\tau}{\to} \; x_2 \; \overset{\alpha_3}{\to} \; x_3 \; \overset{\alpha_4}{\to} \ldots \overset{\alpha_i}{\to} \; x_i \; \overset{\tau}{\to} \; x_i \; \overset{\alpha_{i+1}}{\to} \; x_{i+1} \; \overset{\alpha_{i+2}}{\to} \ldots$$

A **flexible variable** x is observed at different instants :

$$x_0 \xrightarrow{\tau} x_1 \xrightarrow{\tau} x_2 \xrightarrow{\tau} x_3 \xrightarrow{\tau} \ldots \xrightarrow{\tau} x_i \xrightarrow{\tau} x_{i+1} \xrightarrow{\tau} \ldots$$

τ hides effectives changes of state or actions or events

$$x_0 \xrightarrow{\alpha_1} x_1 \xrightarrow{\alpha_2} x_2 \xrightarrow{\alpha_3} x_3 \xrightarrow{\alpha_4} \ldots \xrightarrow{\alpha_i} x_i \xrightarrow{\alpha_{i+1}} x_{i+1} \xrightarrow{\alpha_{i+2}} \ldots$$

Occurences of e τ can be added between two instants ie stuttering steps :

$$x_0 \xrightarrow{\alpha_1} x_1 \xrightarrow{\alpha_2} x_2 \xrightarrow{\tau} x_2 \xrightarrow{\alpha_3} x_3 \xrightarrow{\alpha_4} \ldots \xrightarrow{\alpha_i} x_i \xrightarrow{\tau} x_i \xrightarrow{\alpha_{i+1}} x_{i+1} \xrightarrow{\alpha_{i+2}} \ldots$$

A **flexible variable** x is observed at different instants :

$x_0 \overset{\tau}{\to} x_1 \overset{\tau}{\to} x_2 \overset{\tau}{\to} x_3 \overset{\tau}{\to} \ldots \overset{\tau}{\to} x_i \overset{\tau}{\to} x_{i+1} \overset{\tau}{\to} \ldots$

τ hides effectives changes of state or actions or events

$x_0 \overset{\alpha_1}{\to} x_1 \overset{\alpha_2}{\to} x_2 \overset{\alpha_3}{\to} x_3 \overset{\alpha_4}{\to} \ldots \overset{\alpha_i}{\to} x_i \overset{\alpha_{i+1}}{\to} x_{i+1} \overset{\alpha_{i+2}}{\to} \ldots$

Occurences of e τ can be added between two instants ie stuttering steps :

$x_0 \overset{\alpha_1}{\to} x_1 \overset{\alpha_2}{\to} x_2 \overset{\tau}{\to} x_2 \overset{\alpha_3}{\to} x_3 \overset{\alpha_4}{\to} \ldots \overset{\alpha_i}{\to} x_i \overset{\tau}{\to} x_i \overset{\alpha_{i+1}}{\to} x_{i+1} \overset{\alpha_{i+2}}{\to} \ldots$

A **flexible variable** x is observed at different instants :

$$x_0 \ \overset{\tau}{\rightarrow} \ x_1 \ \overset{\tau}{\rightarrow} \ x_2 \ \overset{\tau}{\rightarrow} \ x_3 \ \overset{\tau}{\rightarrow} \ldots \overset{\tau}{\rightarrow} \ x_i \ \overset{\tau}{\rightarrow} \ x_{i+1} \ \overset{\tau}{\rightarrow} \ldots$$

τ hides effectives changes of state or actions or events

$$x_0 \ \overset{\alpha_1}{\rightarrow} \ x_1 \ \overset{\alpha_2}{\rightarrow} \ x_2 \ \overset{\alpha_3}{\rightarrow} \ x_3 \ \overset{\alpha_4}{\rightarrow} \ldots \overset{\alpha_i}{\rightarrow} \ x_i \ \overset{\alpha_{i+1}}{\rightarrow} \ x_{i+1} \ \overset{\alpha_{i+2}}{\rightarrow} \ldots$$

Occurences of e τ can be added between two instants ie **stuttering steps** :

$$x_0 \ \overset{\alpha_1}{\rightarrow} \ x_1 \ \overset{\alpha_2}{\rightarrow} \ x_2 \ \overset{\tau}{\rightarrow} \ x_2 \ \overset{\alpha_3}{\rightarrow} \ x_3 \ \overset{\alpha_4}{\rightarrow} \ldots \overset{\alpha_i}{\rightarrow} \ x_i \ \overset{\tau}{\rightarrow} \ x_i \ \overset{\alpha_{i+1}}{\rightarrow} \ x_{i+1} \ \overset{\alpha_{i+2}}{\rightarrow} \ldots$$

Changing state of system

A **flexible variable** x is observed at different instants :

$$x_0 \stackrel{\tau}{\rightarrow} x_1 \stackrel{\tau}{\rightarrow} x_2 \stackrel{\tau}{\rightarrow} x_3 \stackrel{\tau}{\rightarrow} \ldots \stackrel{\tau}{\rightarrow} x_i \stackrel{\tau}{\rightarrow} x_{i+1} \stackrel{\tau}{\rightarrow} \ldots$$

τ hides effectives changes of state or actions or events

$$x_0 \stackrel{\alpha_1}{\rightarrow} x_1 \stackrel{\alpha_2}{\rightarrow} x_2 \stackrel{\alpha_3}{\rightarrow} x_3 \stackrel{\alpha_4}{\rightarrow} \ldots \stackrel{\alpha_i}{\rightarrow} x_i \stackrel{\alpha_{i+1}}{\rightarrow} x_{i+1} \stackrel{\alpha_{i+2}}{\rightarrow} \ldots$$

Occurences of e τ can be added between two instants ie **stuttering steps** :

$$x_0 \stackrel{\alpha_1}{\rightarrow} x_1 \stackrel{\alpha_2}{\rightarrow} x_2 \stackrel{\tau}{\rightarrow} x_2 \stackrel{\alpha_3}{\rightarrow} x_3 \stackrel{\alpha_4}{\rightarrow} \ldots \stackrel{\alpha_i}{\rightarrow} x_i \stackrel{\tau}{\rightarrow} x_i \stackrel{\alpha_{i+1}}{\rightarrow} x_{i+1} \stackrel{\alpha_{i+2}}{\rightarrow} \ldots$$

A **safety** property S over x states that something will not happen : $S(x)$ means that S holds for x

An **invariant** property I over x states a strong safety property

$$x_0 \xrightarrow{\alpha_1} x_1 \xrightarrow{\alpha_2} x_2 \xrightarrow{\tau} x_2 \xrightarrow{\alpha_3} x_3 \xrightarrow{\alpha_4} \ldots \xrightarrow{\alpha_i} x_i \xrightarrow{\tau} x_i \xrightarrow{\alpha_{i+1}} x_{i+1} \xrightarrow{\alpha_{i+2}} \ldots$$

$$(S(x_0) \xrightarrow{\alpha_1} S(x_1) \xrightarrow{\alpha_2} S(x_2) \xrightarrow{\tau} S(x_2) \xrightarrow{\alpha_3} S(x_3) \xrightarrow{\alpha_4} \ldots \xrightarrow{\alpha_i} S(x_i) \xrightarrow{\tau}$$

$$S(x_i) \xrightarrow{\alpha_{i+1}} S(x_{i+1}) \xrightarrow{\alpha_{i+2}} \ldots$$

or equivalently $\forall i \in \mathbb{N} : S(x_i)$

- You can check for every i in $\mathbb{N}$ that $S(x_i)$ is true but it can be long if states are different
- You can compute an abstraction of the set of states
- You can try to prove and for instance the induction principle may be usefull
- So be carefull and improve your modelling before to run the checker
- Use the induction

- A state property namely $P(x)$ is a first order predicate with free variables x, where x is a flexible variable.
- A flexible variable x has a current value x, a next value x', an initial value x_0 and possibly a final value x_f.
- A predicate $P(x)$ is considered as a set of values v such that $P(v)$ holds : set-theoretical interpretation

State Properties

Safety Property

A safety property states that nothing bad can happen.

Example

Safety Properties

- Partial correctness a component is correct wit respect to a precondition and a postcondition.
- No Run Time Error any software action or event does not produce a run-time error as overflow, division by zero . . .
- Mutual exclusion a set of processes share common ressources, a printer is shared by users, . . .
- Deadlock freedom the system is never blocked, there is always at least one next state, . . .

- An action α over states is a relation between values of state variables **before** and values of variables **after**
$$\alpha(x, x') \text{ or } x \xrightarrow{\alpha} x'$$

- Flexible variable x has two values x and x'.

- Priming flexible variables is borrowed from TLA

- **Hypothesis 1** : **Values of x belongs to a set of values called** Values **and defines the context of the system.**

- **Hypothesis 2** : **Relations over x and x' belong to a set of relations** $\{r_0, \ldots, r_n\}$

Operational model of a system

- A system $\mathcal{S}$ is observed with respect to flexible variables x.
- Flexible variables x of $\mathcal{S}$ are modified according to a finite set of relations over the set of values $\text{VALUES} : \{r_0, \ldots, r_n\}$
- $\text{INIT}(x)$ denotes the set of possible intial values for x.

$$\mathcal{OMS} = (x, \textbf{Values}, \textbf{Init}(x), \{r_0, \ldots, r_n\})$$

Safety and invariance of system

- **Hypothesis 3** : $\mathcal{OMS} = (x, \text{VALUES}, \text{INIT}(x), \{r_0, \ldots, r_n\})$
- **Hypothesis 4** : $x \longrightarrow x' \triangleq (x\ r_0\ x') \vee \ldots \vee (x\ r_n\ x')$
- $\text{I}(\text{X})$ is inductively invariant for a system called $\mathcal{S}$, if
$$\begin{cases} \forall x \in \text{VALUES} : \text{INIT}(x) \Rightarrow \text{I}(x) \\ \forall x, x' \in \text{VALUES} : \text{I}(x) \wedge x \longrightarrow x' \Rightarrow \text{I}(x') \end{cases}$$
  I(x) is called an invariant in B
- $\text{Q}(\text{X})$ is a safety property for a system called $\mathcal{S}$, if
$\forall x, y \in \text{VALUES} : \text{INIT}(x) \wedge x \overset{\star}{\longrightarrow} y \Rightarrow \text{Q}(y)$
  Q(x) is called a theorem in B

```
MODEL
   m
. . .
. . .
. . .
VARIABLES
   x
INVARIANT
   I(x)
THEOREMS
   Q(x)
INITIALISATION
   Init(x)
EVENTS
   {r_0, . . . , r_n}
END
```

- A model has a name m
- Flexibles variables x are declared
- $I(x)$ provides informations over x
- $Q(x)$ provides informations over x

Checking safety properties of the model

- $\forall x_0, x \in \text{VALUES} : \text{INIT}(x_0) \land x_0 \xrightarrow{\star} x \Rightarrow Q(x)$
- **Solution 1** Writing a procedure checking
  $\text{INIT}(x_0) \land x_0 \xrightarrow{\star} x \Rightarrow Q(x)$ for each pair $x_0, x \in \text{VALUES}$, when VALUES is finite and small.
- **Solution 2** Writing a procedure checking
  $\text{INIT}(x_0) \land x_0 \xrightarrow{\star} x \Rightarrow Q(x)$ for each pair $x_0, x \in \text{VALUES}$, by constructing an abstraction of VALUES.
- **Solution 3** Writing a proof for
  $\forall x_0, x \in \text{VALUES} : \text{INIT}(x_0) \land x_0 \xrightarrow{\star} x \Rightarrow Q(x)$.

(I) $\forall x_0, x \in \textbf{Values} : \textsf{Init}(x_0) \wedge x_0 \overset{\star}{\longrightarrow} x \Rightarrow \textbf{Q}(x)$

if, and only if,

(II) there exists a state property $\textrm{I}(x)$ such that :

$\forall x_0, x, x' \in \textbf{Values} : \begin{cases} (1) & \textsf{Init}(x_0) \Rightarrow \textsf{I}(x_0) \\ (2) & \textsf{I}(x) \Rightarrow \textbf{Q}(x) \\ (3) & \textsf{I}(x) \wedge x \longrightarrow x' \Rightarrow \textsf{I}(x') \end{cases}$

if, and only if,

(III) there exists a state property $\textrm{I}(x)$ such that :

$\forall x_0, x, x' \in \textbf{Values} : \begin{cases} (1) & \textsf{Init}(x_0) \Rightarrow \textsf{I}(x_0) \\ (2) & \textsf{I}(x) \Rightarrow \textbf{Q}(x) \\ (3) & \forall i \in \{0, \ldots, n\} : \textsf{I}(x) \wedge x \; r_i \; x' \Rightarrow \textsf{I}(x') \end{cases}$

Modelling systems : second attempt

```
MODEL
   m
. . .
. . .
. . .
VARIABLES
   x
INVARIANT
   I(x)
THEOREMS
   Q(x)
INITIALISATION
   Init(x)
EVENTS
   {r_0, . . . , r_n}
END
```

- $\forall x_0 \in \text{VALUES} : \text{INIT}(x_0) \Rightarrow \text{I}(x_0)$
- $\forall x, x' \in \text{VALUES} : \forall i \in \{0, \dots, n\} :$
$$\text{I}(x) \wedge x \ r_i \ x' \Rightarrow \text{I}(x')$$
- $\forall x \in \text{VALUES} : \text{I}(x) \Rightarrow \text{Q}(x)$

```
MODEL
   m
?
?
?
VARIABLES
   x
INVARIANT
   I(x)
THEOREMS
   Q(x)
INITIALISATION
   Init(x)
EVENTS
   {r_0, ..., r_n}
END
```

- What are the environment of the proof for properties ?
- What are theories ?
- How are defining the static objects ?

Modelling systems : last attempt !

```
MODEL
  m
Γ(m)
VARIABLES
  x
INVARIANT
  I(x)
THEOREMS
  Q(x)
INITIALISATION
  Init(x)
EVENTS
  {r_0, ..., r_n}
END
```

- $\Gamma(m)$ defines the static environment for the proofs related to m.

- $\Gamma(m) \vdash \forall x \in \text{VALUES} : \text{INIT}(x) \Rightarrow \text{I}(x)$

- $\forall i \in \{0, \ldots, n\}$:
  $\Gamma(m) \vdash \forall x, x' \in \text{VALUES} : \text{I}(x) \wedge x\ r_i\ x' \Rightarrow \text{I}(x')$

- $\Gamma(m) \vdash \forall x \in \text{VALUES} : \text{I}(x) \Rightarrow \text{Q}(x)$

An **event system model** is made of

      State **constants** and state **variables** constrained by a state **invariant**

      A finite set of **events**

Proofs ensures the consistency between the invariant and the events

An event system model can be **refined**

Proofs must ensure the correctness of refinement

Modelling systems : Hello world !

MODEL *FACTORIAL_EVENTS*
Static Part *context*

> **CONSTANTS**
> $factorial, m$
> **AXIOMS**
> $m \in \mathbb{N} \wedge factorial \in \mathbb{N} \leftrightarrow \mathbb{N} \wedge 0 \mapsto 1 \in factorial \wedge$
> $\forall(n, fn).(n \mapsto fn \in factorial \Rightarrow n + 1 \mapsto (n + 1) * fn \in factorial) \wedge$
> $\forall f \cdot \left(\begin{array}{l} f \in \mathbb{N} \leftrightarrow \mathbb{N} \wedge \\ 0 \mapsto 1 \in f \wedge \\ \forall(n, fn).(n \mapsto fn \in f \Rightarrow n + 1 \mapsto (n + 1) \times fn \in f) \\ \Longrightarrow \\ factorial \subseteq f \end{array} \right)$

Dynamic Part *machine*
VARIABLES
  $result, ok$
INVARIANT
  $result \in \mathbb{N}$
  $ok \in \mathbb{B}$
  $ok = TRUE \Rightarrow result = factorial(n)$
THEOREMS
  $factorial \in \mathbb{N} \longrightarrow \mathbb{N}$;
  $factorial(0) = 1$;
  $\forall n.(n \in \mathbb{N} \Rightarrow factorial(n + 1) = (n + 1) \times factorial(n))$
INITIALISATION
  $result :\in \mathbb{N}$
  $ok := FALSE$
EVENTS
  $computation =$ **ANY** $ok = FALSE$ **THEN** $result, ok := factorial(m), TRUE$ **END**
END

Modelling systems relations as events

MODEL
  m
Static Part *context*

> **SETS**
> s
> **CONSTANTS**
> c
> **AXIOMS**
> $P(s,c)$
> **THEOREMS**
> $Q(s,c)$

Dynamic Part *machine*
VARIABLES
  x
INVARIANT
  $I(s,c,x)$
THEOREMS
  $S(s,c,x)$
INITIALISATION
  $Init(s,c,x)$
EVENTS
  $\{r_1, \ldots, r_n\}$
END

- $\Gamma(m)$ defines the static environment for the proofs related to m from s, c and $P(s,c)$ and $\Gamma(m)$ is defined from the static part.

- $\Gamma(m) \vdash Q(s,c)$

- $\Gamma(m) \vdash \forall x, x' \in \text{VALUES} : \text{INIT}(s,c,x) \Rightarrow \text{I}(s,c,x)$

- $\forall i \in \{1, \ldots, n\} :$
  $\Gamma(m) \vdash \forall x, x' \in \text{VALUES} :$
  $\text{I}(s,c,x) \wedge x \ r_i \ x' \Rightarrow \text{I}(s,c,x')$

- $\Gamma(m) \vdash \forall x, x' \in \text{VALUES} : \text{I}(s,c,x) \Rightarrow \text{S}(s,c,x)$

Modelling systems relations as events

```
CONTEXT
   context_name
SETS
   s
CONSTANTS
   c
AXIOMS
   P(s, c)
THEOREMS
   Q(s, c)
```

```
MACHINE
   m
SEES
   context_name
VARIABLES
   x
INVARIANT
   I(s, c, x)
THEOREMS
   S(s, c, x)
INITIALISATION
   Init(s, c, x)
EVENTS
   {e_1, ..., e_n}
END
```

- $\Gamma(m)$ defines the static environment for the proofs related to m from s, c and $P(s, c)$ and $\Gamma(m)$ is defined from the static part.

- $\Gamma(m) \vdash Q(s, c)$

- $\Gamma(m) \vdash \forall x, x' \in \text{VALUES} : \text{INIT}(s, c, x) \Rightarrow \text{I}(s, c, x)$

- $\forall i \in \{0, \ldots, n\} : r_i(x, x') \triangleq BA(e_i)(s, c, x, x')$

- $\forall i \in \{0, \ldots, n\} :$
  $\Gamma(m) \vdash \forall x, x' \in \text{VALUES} :$
  $\text{I}(x) \wedge BA(e_i)(s, c, x, x') \Rightarrow \text{I}(s, c, x')$

- $\Gamma(m) \vdash \forall x, x' \in \text{VALUES} : \text{I}(x) \Rightarrow \text{S}(s, c, x)$

step 1 : Understanding the **problem** to solve

step 2 : **Organizing** requirements and extracting properties

step 3 : Writing a first very **abstract** system model

step 4 : Consulting the requirements and **adding** a new detail in the current model by **refinement**

step 5 : Either the model is enough detailed and the process stops, or the model is not yet enough concrete and the step 4 is repeated.

Current Summary

Expressing models in the event B notation

- Models are defined in two ways :
  - ▶ an abstract machine
  - ▶ a refinement of an existing model
- Models use **constants** which are defined in structures called **contexts**
- B structures are related by the three possible relations :
  - ▶ the **sees** relationship for expressing the use of constants, sets satisfying axioms and theorems.
  - ▶ the **extends** relationship for expressing the extension of contexts by adding new constants and new sets
  - ▶ the **refines** relationship stating that a B model is refined by another one.

Machines and contexts

Machines
- **REFINES**
- **SEES** a context
- **VARIABLES** of the model
- **INVARIANTS** satisfied by the variables
- **THEOREMS** satisfied by the variables
- **EVENTS** modifying the variables
- **VARIANT**

Contexts
- **EXTENDS** another context
- **SETS** declares new sets
- **CONSTANTS** define a list of constants
- **AXIOMS** define the properties of constants and sets
- **THEOREMS** list the theorems which should be derived from axioms

Machines en Event B

```
MACHINE
  m
REFINES
  am
SEES
  c
VARIABLES
  u
INVARIANTS
  I(u)
THEOREMS
  Q(u)
VARIANT
  < variant >
EVENTS
  < event >
END
```

- $\Gamma(m)$: environment for the machine m defined by the context c

- $\Gamma(m) \vdash \forall u \in \text{VALUES} : \text{INIT}(u) \Rightarrow \text{I}(u)$

- For each event e in E :
  $\Gamma(m) \vdash \forall u, u' \in \text{VALUES} : \text{I}(u) \wedge BA(e)(u, u') \Rightarrow \text{I}(u')$

- $\Gamma(m) \vdash \forall u \in \text{VALUES} : \text{I}(u) \Rightarrow \text{Q}(u)$

```
CONTEXTS
  c
EXTENDS
  ac
SETS
  s
CONSTANTS
  c
AXIOMS
  ax1 : . . .
THEOREMS
  th1 : . . .
END
```

- ac : c is extending ac and add new features
- s : sets are defined either by intension or by extension
- c : constants are defined and
- axioms characterize constants and sets
- theorems are derived from axioms in the current context

Events

Event : E	Before-After Predicate
BEGIN $x :| P(x, x')$ **END**	$P(x, x')$
WHEN $G(x)$ **THEN** $x :| P(x, x')$ **END**	$G(x) \quad \wedge \quad P(x, x')$
ANY t **WHERE** $G(t, x)$ **THEN** $x :| P(x, x', t)$ **END**	$\exists t \cdot (G(t, x) \quad \wedge \quad P(x, x', t))$

Guards of event

Event : E	Guard : grd(E)
BEGIN S **END**	$TRUE$
WHEN $G(x)$ **THEN** T **END**	$G(x)$
ANY t **WHERE** $G(t,x)$ **THEN** T **END**	$\exists t \cdot G(t,x)$

Proof obligations for a B model

	Proof obligation
(INV1)	$\Gamma(s,c) \ \vdash \ Init(x) \ \Rightarrow \ I(x)$
(INV2)	$\Gamma(s,c) \ \vdash \ I(x) \ \wedge \ BA(e)(x,x') \ \Rightarrow \ I(x')$
(DEAD)	$\Gamma(s,c) \ \vdash \ I(x) \ \Rightarrow \ (\mathsf{grd}(e_1) \ \vee \ \ldots \ \mathsf{grd}(e_n))$
(SAFE)	$\Gamma(s,c) \ \vdash \ I(x) \ \Rightarrow \ A(x)$
(FIS)	$\Gamma(s,c) \ \vdash \ I(x) \ \wedge \ \mathsf{grd}\,(E) \ \Rightarrow \ \exists x' \cdot P(x,x')$

Current Summary

The factorial model

```
CONTEXT
    fonctions
CONSTANTS
    factorial, n
AXIOMS
    ax1 : n ∈ ℕ
    ax2 : factorial ∈ ℕ ↔ ℕ
    ax3 : 0 ↦ 1 ∈ factorial
    ax4 : ∀(i, fn).(i ↦ fn ∈ factorial ⟹ i + 1 ↦ (i + 1) * fi ∈ factorial) ∧
```

$$\forall f \cdot \left(\begin{array}{l} f \in \mathbb{N} \leftrightarrow \mathbb{N} \land \\ 0 \mapsto 1 \in f \land \\ \forall(n, fn).(n \mapsto fn \in f \Rightarrow n + 1 \mapsto (n + 1) \times fn \in f) \\ \Longrightarrow \\ factorial \subseteq f \end{array} \right)$$

```
END
```

The factorial model

```
MACHINE
    specification
SEES fonctions
VARIABLES
    resultat
INVARIANT
    resultat ∈ ℕ
THEOREMS
    th1 : factorial ∈ ℕ ⟶ ℕ ;
    th2 : factorial(0) = 1 ;
    th3 : ∀n.(n ∈ ℕ ⇒ factorial(n + 1) = (n + 1) × factorial(n))
INITIALISATION
    resultat :∈ ℕ
EVENTS
    computing1 = BEGIN resultat := factorial(n) END
END
```

Communications between agents

```
MACHINE agents
SEES data
VARIABLES
    sent
    got
    lost
INVARIANTS
    inv1 : sent ⊆ AGENTS × AGENTS
    inv2 : got ⊆ AGENTS × AGENTS
    inv4 : (got ∪ lost) ⊆ sent
    inv6 : lost ⊆ AGENTS × AGENTS
    inv7 : got ∩ lost = ∅
```

```
INITIALISATION
BEGIN
    act1 : sent := ∅
    act2 : got := ∅
    act4 : lost := ∅
END
```

Communications between agents

EVENT sending a message
ANY
  a, b
WHERE
  $grd11 : a \in AGENTS$
  $grd12 : b \in AGENTS$
  $grd1 : a \mapsto b \notin sent$
THEN
  $act11 : sent := sent \cup \{a \mapsto b\}$
END

EVENT getting a message
ANY
  a, b
WHERE
  $grd11 : a \in AGENTS$
  $grd12 : b \in AGENTS$
  $grd13 : a \mapsto b \in sent \setminus (got \cup lost)$
THEN
  $act11 : got := got \cup \{a \mapsto b\}$
END

Communications between agents

EVENT loosing a messge
ANY
  a
  b
WHERE $grd1 : a \in AGENTS$
  $grd2 : b \in AGENTS$
  $grd3 : a \mapsto b \in sent \setminus (got \cup lost)$
THEN
  $act1 : lost := lost \cup \{a \mapsto b\}$
END

CONTEXTS
  $data$
SETS
  $MESSAGES$
  $AGENTS$
  $DATA$
CONSTANTS
  n
  $infile$
AXIOMS
  $axm1 : n \in \mathbb{N}$
  $axm2 : n \neq 0$
  $axm3 : infile \in 1 .. n \rightarrow DATA$
END

Current Summary

1 Documentation

2 Introduction by Problems

3 Modelling Language

4 A Simple Example : Management of Students and Teachers

5 Modelling state-based systems

6 The Event B modelling language

7 Examples of Event B models

8 Summary on Events

General form of an event

```
EVENT e
  ANY   t
  WHERE
    G(c, s, t, x)
  THEN
    x : |(P(c, s, t, x, x'))
  END
```

- c et s are constantes and visible sets by e
- x is a state variable or a list of variabless
- $G(c, s, t, x)$ is the condition for observing e.
- $P(c, s, t, x, x')$ is the assertion for the relation over x and x'.
- $BA(e)(c, s, x, x')$ is the *before-after* relationship for e and is defined by $\exists t. G(c, s, t, x) \ \wedge \ P(c, s, t, x, x')$.

General form of proof obligations for an event e

Proofs obligations are simplified when they are generated by the module called POG and goals in sequents as $\Gamma \vdash G$:

❶ $\Gamma \vdash G_1 \wedge G_2$ is decomposed into the two sequents $(1)\Gamma \vdash G_1$ $(2)\Gamma \vdash G_2$

❷ $\Gamma \vdash G_1 \Rightarrow G_2$ is transformed into the sequent $\Gamma, G_1 \vdash G_2$

Proof obligations in Rodin

- *INIT/I/INV* : $C(s,c), INIT(c,s,x) \vdash I(c,s,x)$
- *e/I/INV* : $C(s,c), I(c,s,x), G(c,s,t,x), P(c,s,t,x,x') \vdash I(c,s,x')$
- *e/act/FIS* : $C(s,c), I(c,s,x), G(c,s,t,x) \vdash \exists x'.P(c,s,t,x,x')$

- Chapter Event B
- The Event B Modelling Notation Version 1.4
- The Event-B Mathematical Language 2006
- User Manual of the RODIN PLatform