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Formal Modeling and Verification of Process Models in Component-based Reactive Systems

Scientific Students' Association Report

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Kivonat

A biztonságkritikus rendszerek komplexitása folyamatosan növekedett az elmúlt években. A komplexitás csökkentése érdekében a modellalapú paradigma vált a meghatározó módszerre ilyen rendszerek tervezéshez. Modellalapú rendszertervezés során a komponensek viselkedését általában állapotalapú, vagy folyamatorientált modellek segítségével írjuk le. Az előbbi formalizmusa azt írja le, hogy a komponens milyen állapotokban lehet, míg az utóbbié azt, hogy milyen lépéseket hajthat végre, valamint milyen sorrendben. Gyakran ezen modellek valamilyen kombinálása a legjobb módja egy komplex komponens viselkedésének leírásához.

Formális szemantikával rendelkező modellezési nyelvek lehetővé teszik a leírt viselkedés (kimerítő) verifikációját. Formális verifikáció használatával már a fejlesztés korai fázisaiban felfedezhetőek a hibák: a módszer ellenőrzi, hogy a rendszer egy adott (hibás) állapota elérhető-e, és amennyiben elérhető, ad hozzá egy elérési útvonalat. A formális verifikációs eszközök emiatt gyakran csak alacsony szintű, állapotalapú modelleken működnek, melyek messze vannak az emberek által könnyen érthető nyelvektől. Ezért, hogy magas szintű viselkedési modelleket tudjunk verifikálni, implementálnunk kell egy olyan modell transzformációt, mely megtartja a folyamat- és állapotalapú modellek szemantikáját azok kombinációja után is.

Ebben a dolgozatban megvizsgálom a folyamatalapú modellek szemantikáját, valamint a kapcsolatukat egyéb hagyományos állapotalapú modellekkel. Emellett megoldásokat vetek fel a potenciális konfliktusokra a kombinált alacsonyszintű modellben. Munkám során a Gamma állapotgép kompozíciós keretrendszerre építék, mellyel komponensalapú reaktív rendszereket modellezhetünk és verifikálhatunk. Mivel a Gamma még nem támogatja az aktivitásokat, bevezetek egy új aktivitás nyelvet, melyhez a SysMLv2 szolgál inspirációként. Ezzel együtt implementálok hozzá a szükséges transzformációkat a Gamma alacsony szintű analízis formalizmusára. Végezetül pedig kiértékelem a koncepcionális és gyakorlati eredményeket esettanulmányokon és méréseken keresztül, valamint felvetek lehetséges fejlesztéseket és alkalmazásokat.

Abstract

The complexity of safety-critical systems has been increasing rapidly in recent years. To mitigate said complexity, the model-based paradigm has become the decisive way to design such systems. In model-based systems engineering, we usually define the behaviour of system components using state-based or process-oriented models. The former formalism describes what states the component can be in, while the latter describes what steps it can perform and in what order. Oftentimes, the best way to model the behaviour of a complex component is to combine these models in some way.

Modelling languages with formal semantics enable the (exhaustive) verification of the described behaviour. Formal verification may be used to detect errors early during development by checking if a given (erroneous) state of the system can be reached, and if so, providing a way to reach it. Formal verification tools often require low-level state-based mathematical models, which are far from human-understandable languages. Thus, to enable the verification of high-level behavioural models, a model transformation must be implemented that preserves the semantics of both process-oriented and state-based models, even when combined.

In this report, I analyse the semantics of process-oriented models, as well as its relation to traditional state-based models, and propose solutions for the possible conflicts in a combined low-level model. In my work, I build on the Gamma Statechart Composition Framework, which is a tool for modelling and verifying component-based reactive systems based on statecharts. Since Gamma does not support activities yet, I introduce a new activity language inspired by SysMLv2, and implement the necessary transformations to Gamma's low-level analysis formalism. Finally, I evaluate the conceptual and practical results through case studies and measurements then propose potential improvements and applications.

Chapter 1

Introduction

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Chapter 2

Background

In this chapter I present the foundations of this work. In Section 2.1, I introduce the concept of model-based systems engineering, which is a well known approach for complex system design. This section also goes into detail about SysML as well (Section 2.1.1), which is a widely used *systems modeling language*. Next, I talk about the concept of formal verification in Section 2.2, and introduce Petri nets (Section 2.2.2) and a mapping between activities and Petri nets (Section 2.2.3). Lastly, I introduce the Gamma Statechart Composition Framework, which is a tool for modeling and verifying composite systems using statechart behaviours (Section 2.3), and a low-level formalism called XSTS (Section 2.4), used as an intermediary language for model checking by Gamma.

2.1 Model-based Systems Engineering

The INCOSE SE Vision 2020 [1] defines Model-based systems engineering (MBSE) as:

the formalized application of modeling to support system requirements, design, analysis, verification and validation activities beginning in the conceptual design phase and continuing throughout development and later life cycle phases. MBSE is part of a long-term trend toward model-centric approaches adopted by other engineering disciplines, including mechanical, electrical and software. In particular, MBSE is expected to replace the document-centric approach that has been practiced by systems engineers in the past and to influence the future practice of systems engineering by being fully integrated into the definition of systems engineering processes.

Applying MBSE is expected to provide significant benefits over the document centric approach by enhancing productivity and quality, reducing risk, and providing improved communications among the system development team [2].

In MBSE, one of the most important concepts is the term „model” itself. Literature gives various definitions for models:

1. A physical, mathematical, or otherwise logical representation of a system, entity, phenomenon, or process.[5]
2. A representation of one or more concepts that may be realized in the physical world [7].

3. A simplified representation of a system at some particular point in time or space intended to promote understanding of the real system [4].
4. An abstraction of a system, aimed at understanding, communicating, explaining, or designing aspects of interest of that system [6].
5. A selective representation of some system whose form and content are chosen based on a specific set of concerns. The model is related to the system by an explicit or implicit mapping [10].

As one can see, choosing a definition is very much dependent upon how we wish to use our „model”; in this work I will use the 1st definition.

2.1.1 Systems Modeling Language

Systems Modeling Language (OMG SysML [9]) is a general-purpose modeling language that supports the specification, design, analysis, and verification of systems that may include hardware and equipment, software, data, personnel, procedures, and facilities. SysML is a graphical modeling language with a semantic foundation for representing requirements, behaviour, structure, and properties of the system and its components [7].

This work focuses only on the *behavioural* modeling tools SysML provides. In the following section, I present two of the most used concepts; State Machines and Activity Diagrams.

2.1.1.1 State Machine

Reactive systems are all around us in our daily lives; in smart phones, avionics systems or even our calculators. Frequently, reactive systems appear in areas, where safety-critical operation is crucial, as even the slightest misbehaviour can have catastrophic consequences. This makes the verification of these systems a must during their design process.

The defining characteristic of reactive systems is their event-driven nature, which means that they continuously receive external stimuli (*events*), based on which they change their internal *state* and possibly react with some output [13]. Reactive systems can be verified using model checking techniques (see Section 2.2). Statecharts [14] are a popular and intuitive language to capture the behaviour of reactive systems [16, 24], while also being formally defined.

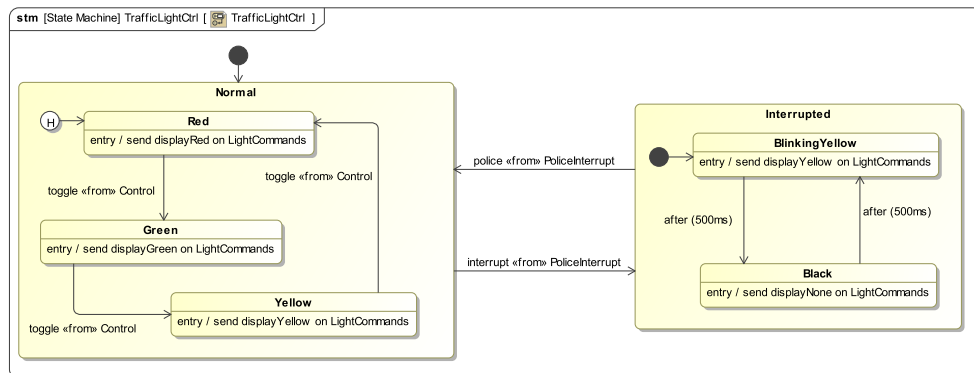


Figure 2.1: SysML State Machine describing the behaviour of a traffic light controller.

SysML state machines extend the concept of statecharts with hierarchical state-refinement, orthogonal regions, action-effect behaviour and state machine composition. These advanced abstraction constructs make state machines easy to use for engineers, but hinder their formal verification. This abstraction gap can be bridged using a transformation tool, such as Gamma, of which I will be talking in Section 2.3.

Figure 2.1 shows a state machine modeling the behaviour of a traffic light controller.

explain
con-
troller
be-
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in words

2.1.1.2 Activity Diagram

State machines cannot describe the complicated semantics of distributed systems with concurrent, parallel behaviour, where the *interesting* thing is what the system *does* step-by-step. SysML activity diagrams are a primary representation for modeling process based behaviour [9] for distributed, concurrent systems. Figure 2.2 shows the set of interesting modeling elements used in this work. In the following, I will introduce the different artifacts and show an example of a SysML activity diagram.

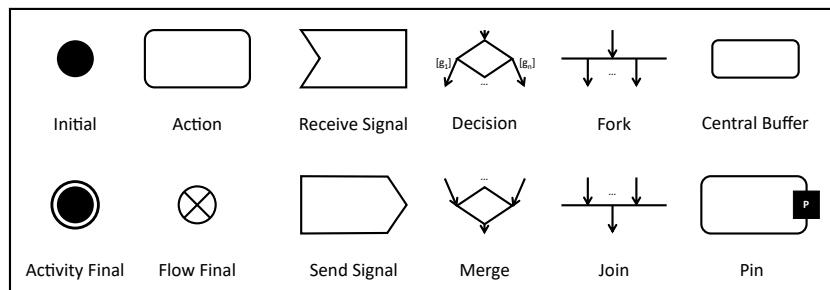


Figure 2.2: Artifacts of SysML activity diagrams.

SysML activity diagram is a graph based model, where the nodes are connected via flows. The dynamic behaviour of activity diagrams comes from *tokens* travelling from node to node; based on the given node's semantics, a connected flow removes tokens from the source node and puts them onto the target node. Flows can also have *guards*, which are expressions specifying when the given flow is *enabled* or not; only enabled nodes can transfer tokens.

Tokens are a way of creating limitations over which node can run, and which cannot; a given node is considered *running*, only when it contains a token. Tokens *flow* between nodes, carrying with them a given value - this value can be of type *void*, which makes it a *control* token.

The different nodes represent the different semantic „tools“ at our disposal; they can represent different actions, or introduce interesting token flow semantics. Simple **actions** represent a single step of behaviour that convert a set of inputs to a set of outputs. Both inputs and outputs are specified as pins, which get their data from connected flows - making that flow a *data flow*. The flow starts from the initial node, and ends with a *Flow Final* or *Activity Final* node. *Fork* nodes generate tokens on all of their output flows, and *Join* nodes forward the tokens, only when all input flows contain one - thus, the two nodes come in a *pair*. On the other hand, *Merge* nodes do not wait for all flows, they forward any token they receive instantly. Likewise, *Decision* nodes take one token from its input flows, and sends it out on its single enabled output flow.

The detailed specification for SysML Activity Diagrams can be found in the OMG specification [9].

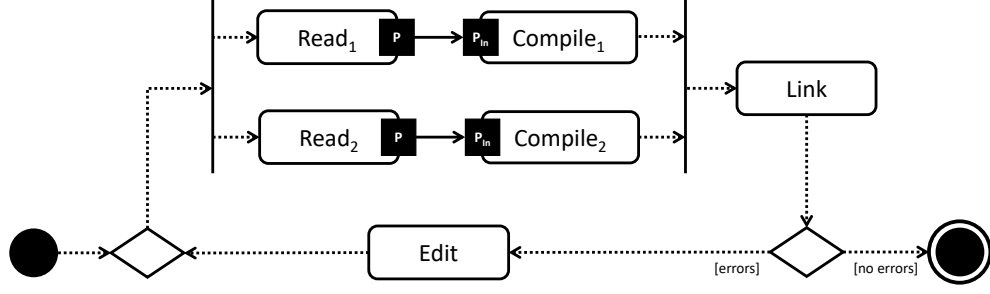


Figure 2.3: The activity of editing, compiling and linking two files.

Figure 2.3 shows an example activity diagram, modeling the process of editing, compiling and linking two files. First, the files have to be read, after which they are *transferred* to the compiler module. We want to compile the two different files in *parallel*, thus we split the control flow using a *fork* node. Once the files are compiled, we link both of them - since linking requires both files, it is preceded by a *join* node. Finally, if the resulting code contains errors, we *edit* the source files and start over - otherwise we are done.

2.2 Formal Verification

In order to raise the reliability of system analysis, a system analysis technique is required that can have the precision of paper-and-pencil based mathematical proofs, and thus does not rely upon computer-arithmetic, and utilizes the computers for bookkeeping, to be able to handle complex systems without having to worry about human-errors. Formal verification methods, which are primarily based on theoretical computer science fundamentals like logic calculi, automata theory and strongly type systems, fulfil these requirements. The main principle behind formal analysis of a system is to construct a computer based mathematical model of the given system and formally verify, within a computer, that this model meets rigorous specifications of intended behaviour. Due to the mathematical nature of the analysis, 100% accuracy can be guaranteed. [15]

2.2.1 Model Checking

Model checking is a formal verification method to verify properties of finite systems, i.e., to decide whether a given formal model M satisfies a given requirement γ or not. The name comes from formal logic, where a logical formula may have zero or more models, which define the interpretation of the symbols used in the formula and the base set such that the formula is true. In this sense, the question is whether the formal model is indeed a model of the formal requirement: $M \models \gamma$?

Model checker algorithms (see Figure 2.4), such as the ones used in UPPAAL¹ [3] or Theta² [25] can answer this question, and can even return a *proof* (i.e., a part of the model) that M indeed does satisfy said requirement³. If the formal requirement does not hold for the model-requirement pair, the model checker only returns a *no* state.

¹<https://uppaal.org/>

²<https://inf.mit.bme.hu/en/theta>

³These proofs usually come in the form of an execution trace

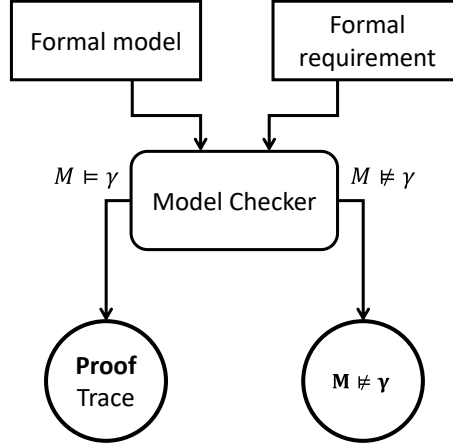


Figure 2.4: An illustration of model checking.

2.2.2 Petri Nets

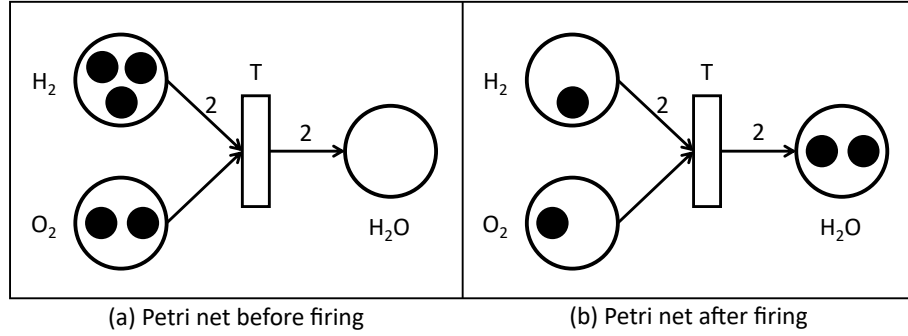


Figure 2.5: An example Petri net modeling the process of H_2O molecule creation.

Petri nets are a widely used formalism to model concurrent, asynchronous systems [22]. The formal definition of a Petri net (including inhibitor arcs) is as follows (see Figure 2.5 for an illustration of the notations).

Definition 1 (Petri net). A Petri net is a tuple $PN = (P, T, W, M_0)$

- P is the set of *places* (defining state variables);
- T is the set of *transitions* (defining behaviour), such that $P \cap T = \emptyset$;
- $W \subseteq W^+ \cup W^-$ is a set of two types of arcs, where $W^+ : T \times P \rightarrow \mathbb{N}$ and $W^- : P \times T \rightarrow \mathbb{N}$ are the set of input arcs and output arcs, respectively (\mathbb{N} is the set of all natural numbers);
- $M_0 : P \rightarrow \mathbb{N}$ is the *initial marking*, i.e., the number of *tokens* on each place. .

The state of a Petri net is defined by the current marking $M : P \rightarrow \mathbb{N}$. The behaviour of the systems is described as follows. A transition t is enabled if $\forall p \in P : M(p) \in W(p, t)$. Any enabled transition t may fire nondeterministically, creating the new marking M' of the Petri as follows: $\forall p \in P : M'(p) = M(p) - W^-(p, t) + W^+(t, p)$.

In words: W describes the *weight* of each flow from a transition to a place, or from a place to a transition. Firing a transition t in a marking M consumes $W^-(p_i, t)$ tokens from each

of its input places p_i , and produces $W(t, p_o)$ tokens in each of its output places p_o . One such transition t is *enabled* (it may *fire*) in M if there are enough tokens in its input places for the consumptions to be possible, i.e., if and only if $\forall p : M(p) \geq W(s, t)$.

2.2.3 Activities as Petri Nets

Formal verification requires models to be specified using *mathematical* precision, however SysML does not have precise semantics [21, 23, 18]. Huang et al. in [17] propose a way to *partially* map SysML activity diagrams to Petri nets. In the following, I will summarise their work.

2.2.3.1 Constrained Subset of SysML

Since SysML Activity Diagrams do not have precise execution semantics, the Petri net mapping can only be done for a limited subset of the modeling elements: *actions*, *initial nodes*, *final nodes*, *join nodes*, *fork nodes*, *merge nodes*, *decision nodes*, *pins* and *object/control flows*, which have precise execution semantics as defined in the Foundational Subset for Executable UML Models [11].

The paper also assumes the following constraints:

1. The value of tokens is not considered.
2. Control flows with multiple tokens at a time are not considered.
3. Optional object/control flows are not considered, i.e., multiplicity lower bounds are strictly positive.

These constraints allow the mapping between activities and Petri nets, however, the constructed Petri net will not be semantically equivalent - data cannot flow between nodes. This fact is the motivation behind formalising a more-complete mapping (see Chapter 3).

2.2.3.2 Mapping Rules

Activity elements can be grouped into two sets: *load-and-send* (LAS) and *immediate-repeat* (IR).

LAS nodes are fired when all their inputs have tokens. When an *LAS* node fires, the number of tokens associated with the input flows/pin is consumed and the number of tokens associated with an output flows/pin is added. In SysML activity diagrams, the execution semantics of all nodes, except *decision* and *merge* nodes are LAS, because these nodes are fired when all their input nodes have at least one token. As a result, these nodes can be mapped to *transitions* in the resulting Petri net.

In contrast, as soon as an *IR* node receives a token from any input, it immediately adds a token to its output nodes. For SysML activity diagrams, merge nodes, decision nodes IR nodes, because they are fired immediately when any token is received. As a result, these nodes can be mapped to *places* in the resulting Petri net.

Given the set of assumptions in Section 2.2.3.1, control flows and object flows in an activity diagram can be mapped to arcs in a Petri net.

Finally, after mapping the elements, the resulting Petri net may contain transition-transition and place-place arcs, which are not valid; as the final step, these arcs must be split in two by inserting a transition or a place in the middle, making the model conform to the formalism.

2.2.3.3 Example Mapping

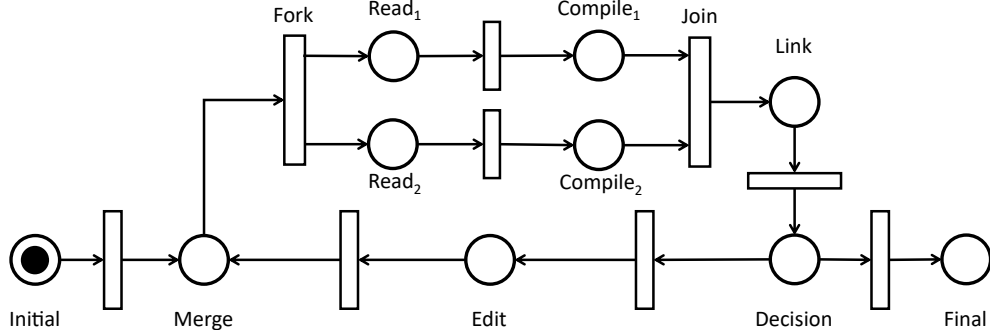


Figure 2.6: Example mapping from activity diagram to Petri net.

Figure 2.6 shows an example mapping from the activity Figure 2.3. The resulting elements are annotated with the names of their counter parts in the activity diagram.

For more information, please refer to [17].

2.3 The Gamma Statechart Composition Framework

The Gamma Statechart Composition Framework⁴ [8] is an integrated tool to support the design, verification and validation as well as code generation for component-based reactive systems. The behaviour of each component is captured by a statechart, while assembling the system from components is driven by a domain-specific composition language⁵. Gamma supports formal verification by mapping composite statecharts to a back-end model checker. Execution traces obtained as witnesses during verification are back-annotated as test cases to replay an error trace or to validate external code generators [19].

The workflow of Gamma builds on a model transformation chain depicted in Figure 2.7, which illustrates the input and output models of these model transformations as well as the languages in which they are defined, and the relations between them. The modeling languages are as follows.

- The **Gamma Statechart Language (GSL)** is a UML/SysML-based statechart language supporting different semantic variants of statecharts.
- The **Gamma Composition Language (GCL)** is a composition language for the formal hierarchical composition of state-based components according to multiple execution and interaction semantics.
- The **Gamma Genmodel Language (GGL)** is a configuration language for configuring model transformations.

⁴<https://inf.mit.bme.hu/en/gamma>

⁵The composition language be the *ibd* model in SysML


```

1 package TrafficLightCtrl
2 import "Interfaces"
3 statechart TrafficLightCtrl [
4     port Control : requires Control
5     port PoliceInterrupt : requires PoliceInterrupt
6     port LightCommands : provides LightCommands
7 ] {
8     timeout BlinkingYellowTimeout3
9     timeout BlackTimeout4
10    transition from Yellow to Red when Control.toggle
11    transition from Normal to Interrupted when PoliceInterrupt.police
12    // ...
13    transition from BlinkingYellow to Black when timeout BlinkingYellowTimeout3
14    transition from Black to BlinkingYellow when timeout BlackTimeout4
15    region main_region {
16        state Normal {
17            region normal {
18                shallow history Entry2
19                state Green {
20                    entry / raise LightCommands.displayGreen;
21                }
22                state Red {
23                    entry / raise LightCommands.displayRed;
24                }
25                state Yellow {
26                    entry / raise LightCommands.displayYellow;
27                }
28            }
29        }
30        state Interrupted {
31            region interrupted {
32                initial Entry1
33                state Black {
34                    entry / set BlackTimeout4 := 500 ms;
35                    raise LightCommands.displayNone;
36                }
37                state BlinkingYellow {
38                    entry / set BlinkingYellowTimeout3 := 500 ms;
39                    raise LightCommands.displayYellow;
40                }
41            }
42        }
43        initial Entry0
44    }
45 }

```

Listing 2.1: The traffic light controller state machine in the Gamma textual representation.

language, which is a low-level modeling formalism designed to bridge the abstraction gap between engineering models and formal methods.

2.4.1 Formal definition

Definition 2 (Extended symbolic transition system). An *Extended symbolic transition system* is a tuple $XSTS = (D, V, V_C, IV, Tr, In, En)$, where:

- $D = \{d_{v_1}, d_{v_2}, \dots, d_{v_n}\}$ is a set of value domains;
- $V = \{v_1, v_2, \dots, v_n\}$ is a set of variables with domains $d_{v_1}, d_{v_2}, \dots, d_{v_n}$;
- $V_C \subseteq V$ is a set of variables marked as *control variables*;
- $IV \in d_{v_1} \times d_{v_2} \times \dots \times d_{v_n}$ is the *initial value function* used to describe the initial state. The initial value function IV assigns an initial value $IV(v) \in d_v$ to variables $v \in V$ of their domain d_v ;
- $Tr \subseteq Ops$ is a set of operations, representing the *internal transition relation*; it describes the internal behaviour of the system;
- $In \subseteq Ops$ is a set of operations, representing the *initialisation transition relation*; it is used to describe more complex initialisation, and is executed once and only once, at the very beginning;
- $En \subseteq Ops$ is a set of operations, representing the *environmental transition relation*; it is used to model the system's interactions with its environment. ▪

In any state of the system, a single operation is selected from the sets introduced above (Tr , In and En). The set from where the operation can be selected depends on the current state: In the initial state - which is described by the initialization vector IV - only operations from the In set can be executed. Operations from the In set can only fire in the initial state and nowhere else. After that, En and Tr are selected in an alternating manner.

Operations $op \in Ops$ describe the transitions between states of the system, where Ops is the set of all possible transitions. All operations are atomic in the sense that they are either executed in their entirety or none at all. XSTS defines the following operations:

Basic operations Basic operations contain no inner (nested) operations.

- *Assignments* assign a given value v from domain d_n to variable V_n .
- *Havocs* behave likewise, except the value is not predetermined; giving a way to assign random value to a variable.
- Lastly, *assume* operations check a condition, and can only be executed if their condition evaluates to *true*.

Composite operations Composite operations contain other operations, and can be used to describe complex control structures.

- *Sequences* are essentially multiple operations executed one after the other.
- *Parallels* are like sequences, however they execute all operations at the same time.
- And lastly, *choices* model non-deterministic choices between multiple operations; one and only one branch of the choice operation is selected for execution.

Note that while these are composite operations, their execution is still atomic; i.e., a potential false evaluation of a containing assume operation prevents the execution of all operations in that particular branch. E.g., if a sequence's 2nd operation is an assume operation, which cannot execute, then the whole sequence operation will be prevented from execution.

2.4.2 Traffic Light Controller Example

Listing 2.2 is the textual representation of the traffic light controller statechart (Figure 2.1) transformed to XSTS⁶. For a more exact presentation please see Section A.1.

2.5 Related Work

Add
related
work

⁶The transformation was done using Gamma.

```

1  type ActivityNodeState : { __Idle__, __Running__, __Done__ }
2  // ...
3  type Operating_Controller : { __Inactive__, Priority, Init, PriorityPrepares, Secondary,
4    SecondaryPrepares }
5  var PoliceInterrupt_police_In_Controller : boolean = false
6  // ...
7  ctrl var main_region_Controller : Main_region_Controller = __Inactive__
8  ctrl var operating_Controller : Operating_Controller = __Inactive__
9  var SecondaryTimeout2_Controller : integer = 0
10
11 trans {
12   // ...
13   choice {
14     assume (main_region_Controller == Interrupted);
15     // ...
16     choice {
17       assume (operating_Controller == Priority);
18       SecondaryTimeout2_Controller := 0;
19       PriorityControl_toggle_Out_Controller := true;
20       SecondaryControl_toggle_Out_Controller := true;
21       // ...
22     }
23   } or {
24     // ...
25   }
26   PoliceInterrupt_police_In_Controller := false;
27 }
28
29 init {
30   SecondaryTimeout2_Controller := 2 * 1000;
31   main_region_Controller := __Inactive__;
32   // ...
33   PriorityPolice_police_Out_Controller := false;
34   choice {
35     assume (operating_Controller == __Inactive__);
36     operating_Controller := Init;
37   } or {
38     assume !(operating_Controller == __Inactive__);
39   }
40   // ...
41 }
42
43 env {
44   havoc PoliceInterrupt_police_In_Controller;
45   PriorityPolice_police_Out_Controller := false;
46   SecondaryControl_toggle_Out_Controller := false;
47   PriorityControl_toggle_Out_Controller := false;
48   SecondaryPolice_police_Out_Controller := false;
49 }

```

Listing 2.2: Gamma XSTS Language representing the traffic light controller statechart.

Chapter 3

Gamma Activity Language

The high-level nature of SysML activities means they are easy to use for modeling complicated behaviours of distributed system, but their complexity encumbers formal verification. As discussed above in Section 2.2.3, we can define a semantic-preserving mapping between activities and Petri nets (which have a formal semantics), however, that mapping is not complete, as it disregards the data contained in tokens.

The Gamma Statechart Composition Framework (Section 2.3) implements a model transformation pipeline (see Figure 2.7) for the formal verification of collaborating statecharts, however, it does not include activity diagrams. For this reason, I propose the *Gamma Activity Language* (Chapter 3), and integrate it (Chapter 4) into the transformation pipeline.

3.1 Language Design

The purpose of the Gamma Activity Language is the following: it should support as many features from SysML activity diagrams as possible, while also being simple to implement and transform to low-level models. As you could see from the Section 2.2.3, SysML activity diagrams cannot be exactly transformed to a formal model; we have to constrain our language in order to offer formal semantics. However, as you will see, these constrains still allow us to write *almost* all activities.

Ezt a
részt át
kéne írni

3.1.1 Constraints

Compared to SysML activity diagrams, Activity Language has the following constrains:

- The model cannot contain *flow final* nodes.
- The model cannot contain *receive signal* nodes.
- The model cannot contain *interrupt* flows.
- Flows may contain only *one* token at a given time.
- Activities must be contained by *statecharts*, as they cannot describe a component's behaviour in itself.

3.1.2 Improvement over Petri Net Mapping

Compared to the Petri net mapping introduced in Section 2.2.3, the Activity Language supports guards, valued tokens, actions and composite activities.

3.2 Formal Definition

In order to offer mathematical precision, formal verification methods require formally defined models with clear semantics. In this section I present the formal definition of the novel GAL formalism.

Definition 3 (Gamma Activity Language). A Gamma Activity is a tuple of $GA = (N, P, F, G, D_{GA}, F_{Action})$, where:

- $N = N_{IR} \cup N_{LAS}$ is a set of *Nodes*, where N_{IR} contains the *immediate-repeat* nodes and N_{LAS} contains the *load-and-sand* nodes (see Section 2.2.3). $F_{Action} \in N_{LAS}$ is a special set of nodes, which are the *Action* nodes;
- $P \subseteq P_{In} \cup P_{Out}$ is a set of two types of pins, where $P_{In} : N_{Action} \rightarrow \{p_1, \dots, p_n\}$ and $P_{Out} : N_{Action} \rightarrow \{p_1, \dots, p_n\}$ are the set of *InputPins* and *OutputPins*, respectively, with domains $\{d_1, \dots, d_n\} \subseteq D_{GA}$;
- $F \subseteq F_C \cup F_D$, where $F_C = \{f_{C_1}, \dots, f_{C_n}\}$ and $F_D = \{f_{D_1}, \dots, f_{D_n}\}$ are the control and data flows, respectively. Let us denote the input/output flows of node n as $\delta(n)$ and $\Delta(n)$, and the source/target pins of flow f as $\phi(f)$ and $\Phi(f)$. For any given node n , $\delta(n) \neq \Delta(n)$ and for any given action node n_a $\Phi(f) \in P_{In}(n_a) \forall f \in F_D \cap \delta(n_a)$ and $\phi(f) \in P_{Out}(n_a) \forall f \in F_D \cap \Delta(n_a)$ shall always hold. This means, that a flow cannot be input and output to the same node at the same time, and for a given action node, all input/output flows shall be associated with an input/output token, respectively;
- $G : F \rightarrow \{True, False\}$ is a function determining whether a given flow is enabled;
- $D_{GA} = \{d_1, d_2, \dots, d_n\}$ is a set of value domains;
- $F_{Action} \subseteq d_1 \times d_2 \times \dots \times d_n$ is a function mapping an *action* nodes input pin values to it's output pin values. ▪

Informally, Gamma Activities are composed of *nodes* and flows in between them. A given *Action* node may have any number of *Pins* with domain $d \in D$, for which, there must be one and only one flow connected to the node. An action node also has a special F_{Action} , which returns the values of its output pins.

N_{IR} contains the nodes *decision/merge*, while N_{LAS} contains the nodes *fork/join*, *initial/final* and *action* nodes. For the most part, these elements have a similar behaviour as their SysML counter parts; however, there is a crucial difference regarding how a flow transmits a token. Figure 3.1 shows a simple data flow between two nodes, connected via their pins. When this flow is fired, the data inside the pins are transferred instantly, without any intermediate state in between.

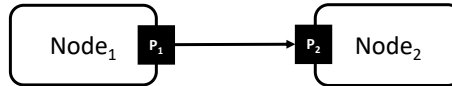


Figure 3.1: An example SysML data flow

Contrarily, in Gamma Activity Language, the equivalent data flow does indeed contain the given node, creating an intermediate state, where the token is in neither of the nodes. This would look like a *Central Buffer* in SysML (Figure 3.2). The reason for this is simplicity; by creating this intermediate state (and others), it is easier to state the set of transitions necessary to formally define the semantics of the language.

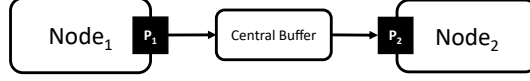


Figure 3.2: An example SysML data flow with central buffer

3.2.1 Behaviour Formalism

The behaviour of the Gamma Activity Language is defined using the XSTS (Section 2.4) formalism:

Definition 4 (Gamma Activity Behaviour). $XSTS_{GA} = (D, V, V_C, IV, Tr, In, En)$, where:

- $D = D_{GA} \cup d_{NodeState} \cup d_{FlowState}$, where D_{GA} is the domain in GA , $d_{NodeState} = \{Idle, Running, Done\}$ and $d_{FlowState} = \{Empty, Full\}$;
- $V = V_{NS} \cup V_{FS} \cup V_{NV} \cup V_{FV} \cup V_{PV}$, where $V_{NS} = \{v_1, v_2, \dots, v_n\}$ is the variable representing the *state* of the nodes with domain $d_{NodeState}$, $V_{FS} = \{v_1, v_2, \dots, v_n\}$ is the variable representing the *state* of the flows with domain $d_{FlowState}$ and V_{NV} , V_{FV} , V_{PV} are the variables representing the values contained inside *flows*, *nodes* and *pins* respectively;
- IV sets all variables to their default value;
- $V_C = V_{NS} \cup V_{FS}$ are the *control variables*¹;
- $Tr = T$, where T is the single transition defined down below;
- In sets all values of variables associated with *InitialNodes* to *Running*;
- $En = \emptyset$ is the empty environment transition, as simple activities do not have environments. ▪

We also define the following helper functions:

- $S_N : N \rightarrow V_{NS}$ is a function that returns the *state variable* of a node;
- $S_F : F \rightarrow V_{FS}$ is a function that returns the *state variable* of a flow;
- $V_{N_{in}} : N \times F \rightarrow V_{NV}$ is a function that returns the *input value variable* of a node regarding a specific connected flow;
- $V_N : N \rightarrow V_{NV}$ is a function that returns the *value variable* of a node;
- $V_F : F \rightarrow V_{FV}$ is a function that returns the *value variable* of a flow;
- $PV_N : N \times P \rightarrow V_{PV}$ is a function returning the *value variable* of a pin inside a node.

Informally, the state of Gamma Activities are determined by the nodes' *state* (*Idle*, *Running*, *Done*), the nodes' and their pins' values, the flows' *state* (*Empty*, *Full*) and their values. For example, given an action node n and one of it's pins p_1 , $PV_N(n, p)$ would give us the exact value that pin contains in this instance. This gives us the power - contrary

¹We don't have to set the value variables as control variables, because they only change when the given flow's or node's state variable changes.

to the Activity-PN mapping introduced in Section 2.2.3 - to formally define the values contained in tokens.

Let us define a shorthand function for finding a nodes input variable associated with a given flow:

$$V_{N_{In}}(n, f) = \begin{cases} PV_N(n, \Phi(f)) & \text{if } n \in N_{Action} \\ V_N(n), & \text{otherwise} \end{cases}$$

And a shorthand function for finding a nodes output variable associated with a given flow:

$$V_{N_{Out}}(n, f) = \begin{cases} PV_N(n, \phi(f)) & \text{if } n \in N_{Action} \\ V_N(n), & \text{otherwise} \end{cases}$$

These notation will help us easily transfer the data to and from the node value variables - by hiding the difference between the pin variables and the node variables.

In the following I define the operations used to construct the transitions in the transition set T .

Definition 5 (Flow Transition Operations). Let us denote the source/target node of flow f as $\theta(f)$ and $\Theta(f)$ respectively. Let us also construct the operation of $O_{FlowIn}(f)$ is the *sequential* operation of taking a token from a flow to a node, which is defined the following:

$$\begin{aligned} &assume(S_F(f) = Full) \\ &assume(S_N(\Theta(f)) = Idle) \\ &assign(S_F(f), Empty) \\ &assign(S_N(\Theta(f)), Running) \\ &assign(S_N(V_{N_{In}}(\Theta(f), f)), V_F(f)) \end{aligned}$$

Informally, this operation checks that the node is *Idle* and the flow is *Full*, in which case it transfers the token by changing their states. Let $O_{FlowOut}(f)$ be the *sequential* operation of taking a token from a node to a flow:

$$\begin{aligned} &assume(G(f) = true) \\ &assume(S_F(f) = Empty) \\ &assume(S_N(\theta(f)) = Done) \\ &assign(S_F(f), Full) \\ &assign(S_N(\theta(f)), Idle) \\ &assign(V_F(f), S_N(V_{N_{Out}}(\theta(f), f))) \end{aligned}$$

Informally, this operation checks that the node is *Done* and the flow is *Empty* and *enabled*, in which case it transfers the token by changing their states. ▪

Definition 6 (Node Token In/Out Operations). Given the different behaviours of *IR* and *LAS* nodes, we must construct different operations for their in and out transitions. $O_{IRNodeIn}(n)$ is the *choice* operation representing the „token intake” of an *IR* node:

$$O_{IRNodeIn}(n) = choice \left(\bigcup_{f \in \delta(n)} O_{FlowIn}(f) \right)$$

And $O_{IRNodeOut}(n)$ is the *choice* operation representing the „token output” of an *IR* node:

$$O_{IRNodeOut}(n) = choice \left(\bigcup_{f \in \Delta(n)} O_{FlowOut}(f) \right)$$

On a similar note, the *LAS* node „token intake” and „token output” operations are the following:

$$O_{LASNodeIn}(n) = parallel \left(\bigcup_{f \in \delta(n)} O_{FlowIn}(f) \right)$$

$$O_{LASNodeOut}(n) = parallel \left(\bigcup_{f \in \Delta(n)} O_{FlowOut}(f) \right)$$

For simplicities sake, I define the following operations to use one notation for all of the node operations:

$$O_{LASNodeIO}(n) = choice(O_{LASNodeIn}(n) \bigcup O_{LASNodeOut}(n))$$

$$O_{IRNodeIO}(n) = choice(O_{IRNodeIn}(n) \bigcup O_{IRNodeOut}(n))$$

$$O_{NodeIO}(n) = \begin{cases} O_{IRNodeIO}(n) & \text{if } n \in N_{IR} \\ O_{LASNodeIO}(n), & \text{otherwise} \end{cases} \quad .$$

In which case, $O_{NodeIO}(n)$ returns an operation transferring the tokens in and out of the specified node.

Informally, these operations realise the semantics of the *LAS* and *IR* nodes, by either putting the *flow in* and *flow out* operations inside a *parallel* or a *choice*, respectively².

Definition 7 (Node Transition Operations). Node transition operations take the given node from *Running* state to *Done* state, while also executing the underlying operation. Let us define the $O_{NodeTransition}(n)$ node transition *sequential* operation function as:

²Parallel operations execute *all* contained operations at the same time, while choices chose one at random.

$assume(S_N(n), Running)$
 $assign(S_N(n), Done)$

▪

Definition 8 (Composite Node Operation). Putting all of the work together, we can define a function returning an operation for each node, that implements the behaviour we desire:

$$O_{Node}(n) = choice(O_{NodeIO}(n) \cup O_{NodeTransition}(n))$$

▪

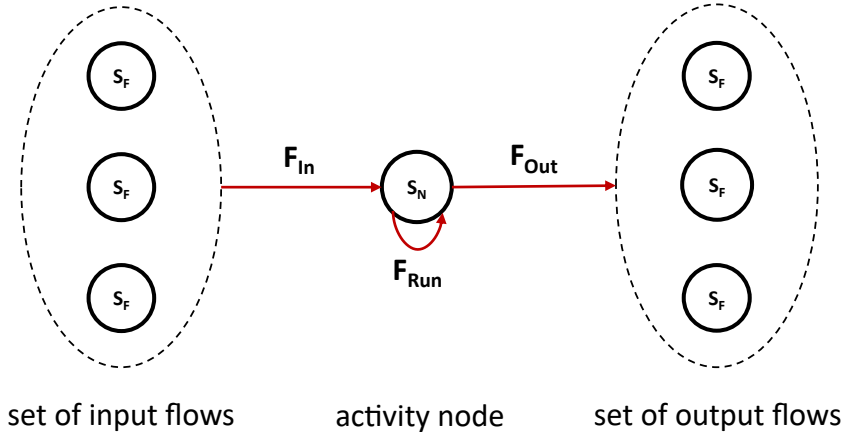


Figure 3.3: An illustration of activity node state and change functions

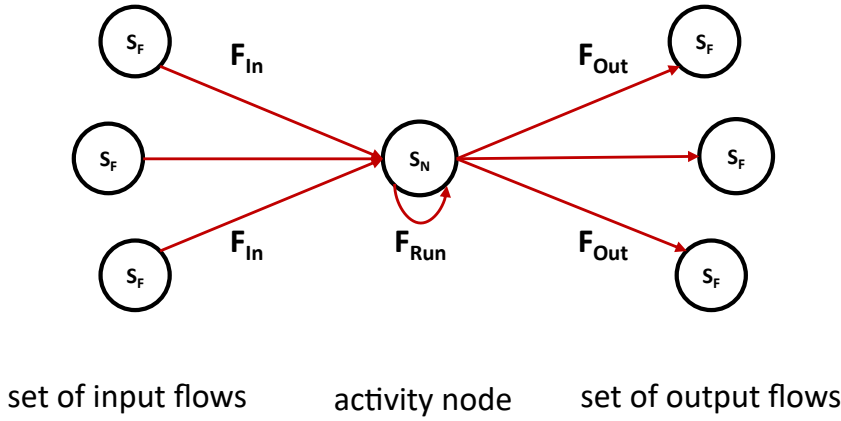


Figure 3.4: An illustration of activity node state and change functions

3.3 Language Grammar

Similarly to the Gamma Statechart Language, the Gamma Activity Language is intended to be a first-class citizen in the Gamma Framework, thus it must have a grammar to represent in a textual way. This implementation incorporates elements from the SysMLv2 [12] language design, while also fitting into the already existing language family of Gamma (Section 2.3).

3.3.1 Metamodel

Due to the complexity of the final meta-model of the language, I have split it into multiple parts for easier understanding.

3.3.1.1 Pins

There are two kinds of pins, *InputPins* and *OutputPins*. All pins have a *Type* associated with them from the Gamma grammar, which defines its domain. Figure 3.5 shows this section of the meta-model.

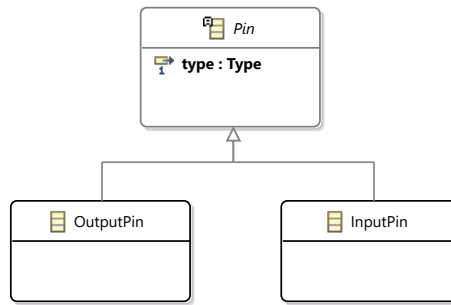


Figure 3.5: The Pins structure

3.3.1.2 Flows

There are two kinds of flows, *ControlFlows* and *DataFlows*. All flows have a guard of type *Expression*, which can be evaluated to a *boolean* value. If this guard evaluates to *True*, the flow is considered *enabled*. Figure 3.6 depicts the relation of flows in the meta-model.

Control Flow *ControlFlows* have a reference to their source and target nodes.

Data Flow *DataFlows* contain a *DataSourceReference* and a *DataTargetReference*. The reason for the reference, is because said reference can either be a *Pin*, or a *DataNode*. A data token may contain data (or value) of any kind, but that token can only travel to and from data *sources* and *targets*. This will be explained in more detail below.

3.3.1.3 Activity Nodes

In the following, I will talk about the different kinds of *ActivityNodes* and their special meanings. The meta-model described in this section can be seen in Figure 3.7.

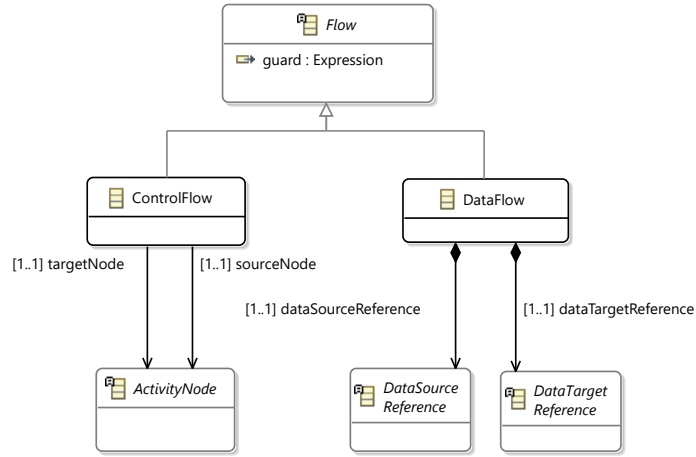


Figure 3.6: The Flows structure

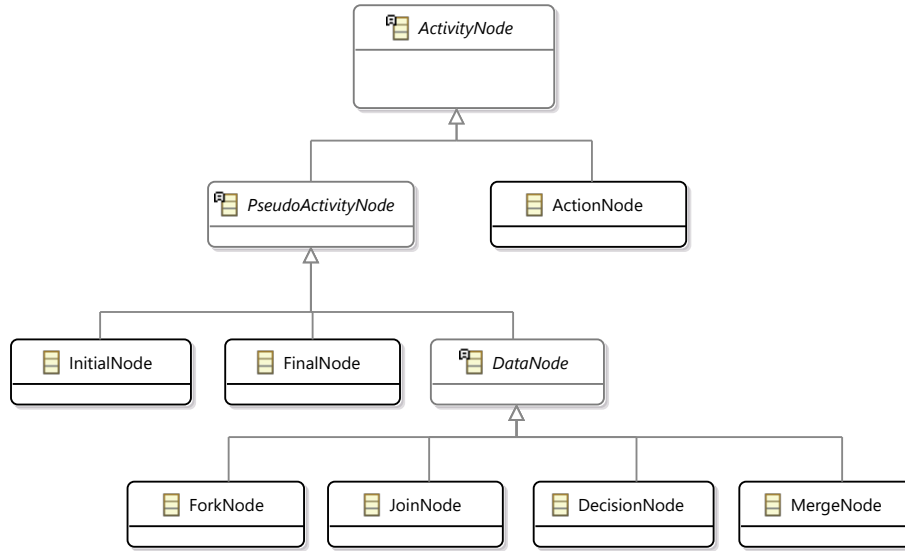


Figure 3.7: The Activity Node structure

Action Node *ActionNodes* represent a specific action the activity may execute. This action can be defined in multiple ways, see Section 3.3.1.5 for more detail.

Pseudo Activity Node *PseudoActivityNodes* are nodes, that do not represent a specific action, however are needed to convey specific meanings, e.g., the initial active node, or a decision between flows.

Initial Node *InitialNodes* represent the entry-point to the activity.

Final Node A special node representing the final node for the activity.

Data Node *DataNodes* encapsulate the meaning of *data* inside activities.

Fork Node *ForkNodes* are used to model parallelism, by creating one token on each of its output flows when executed. Fork nodes shall only have one input flow.

Join Node *JoinNodes* are the pair of fork nodes; the additional created tokens are swallowed by this node, by only sending out one token, regardless of the number of input flows.

Decision Node *DecisionNodes* create branches across multiple output flows. An input flow's token is removed, and sent out to a single output flow - depending on which of the output flows are *enabled* (see Section 3.3.1.2).

Merge Node *MergeNodes* forward all incoming tokens as soon as they arrive, one by one. They are used to *merge* different flow paths (created using *decisions*).

3.3.1.4 Root Structure

Every model has to have a root element structure; Activity Language is not any different. The meta-model described in this section can be seen in Figure 3.8.

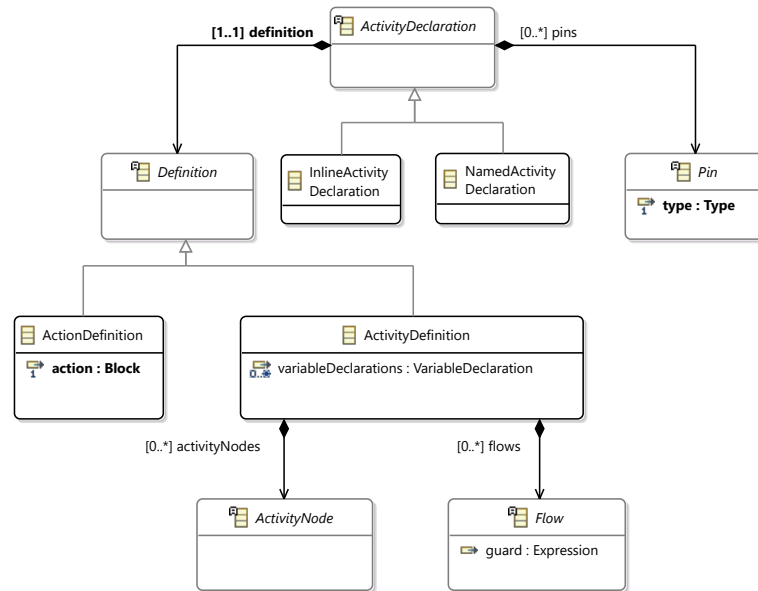


Figure 3.8: The root structure of the language

Activity Declaration All elements inside an activity are contained in a root *ActivityDeclaration* element. It contains *Pins* needed for value passing (see Section 3.3.1.1) and a *Definition*. A declaration can be *InlineActivityDeclaration*, which means they are declared in an other declaration, or *NamedActivityDeclaration*, which is a standalone activity declaration. The difference will be clarified in ??.

Definition The definition *defines* how the activity is described; using activity nodes, or by the Gamma Activity Language³. *ActionDefinition* contains a single *Block*⁴, which is

³Gamma Activity Language is a lightweight programming language-like construct for writing simple algorithms

⁴A *Block* contains multiple *Actions* which are executed one after the other

executed as-is when the activity is executed⁵. *ActivityDefinition* contains *ActivityNodes* (Section 3.3.1.3) and *Flows* (Section 3.3.1.2).

3.3.1.5 Composing Activities

When one defines an *ActionNode*, it may or may not add an *ActivityDeclarationReference*. If the node does not have any, it is considered a *simple* node, without any implementation. If it does contain an *ActivityDeclarationReference*, then when this node is executed, the underlying *ActivityDeclaration* is executed as well. This gives us the power to pre-declare specific activities, or inline declare them in the language; and use any definition defined above (Section 3.3.1.4). Figure 3.9 shows this part of the meta-model.

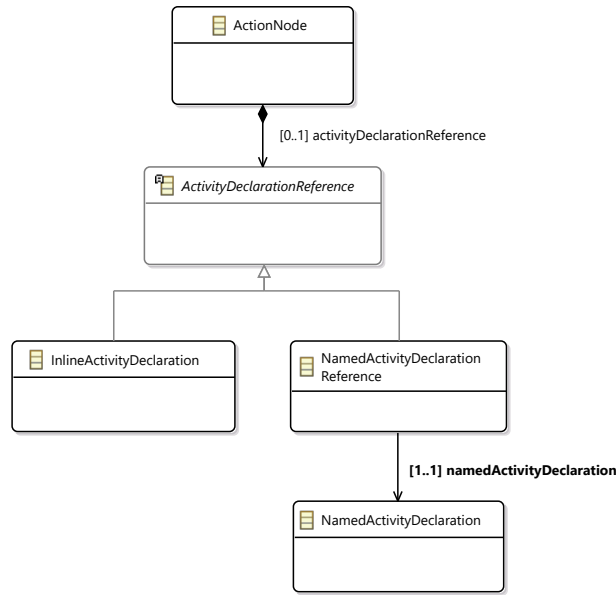


Figure 3.9: The action node containment hierarchy.

3.3.1.6 Data Source-Target Reference

In order to correctly set a data flow's data source and data target, we have to keep in mind where we are referencing the pins. A given *InputPin* can be considered a *DataTarget* from outside of the associated *Activity*, however, it is a *DataSource* from inside the *Defintion*. *DataNodes* can be considered both data sources and data targets. See Figure 3.10 for the meta-model.

Example of inside-input/outside-output pin Figure 3.11 shows an example of the aforementioned effect. From the perspective of the flow $P_1 \rightarrow P_2$ the pin P_1 is a *DataSource* and the pin P_2 is a *DataTarget*. However, from the perspective of the flow $P_2 \rightarrow P_3$, the pin P_2 is a *DataSource* - because the latter flow is inside the composite activity.

⁵This fact means, that if one used Action to define an activity, that activity is executed atomically; it will not be interlaced with other XSTS transitions. See Chapter 4.

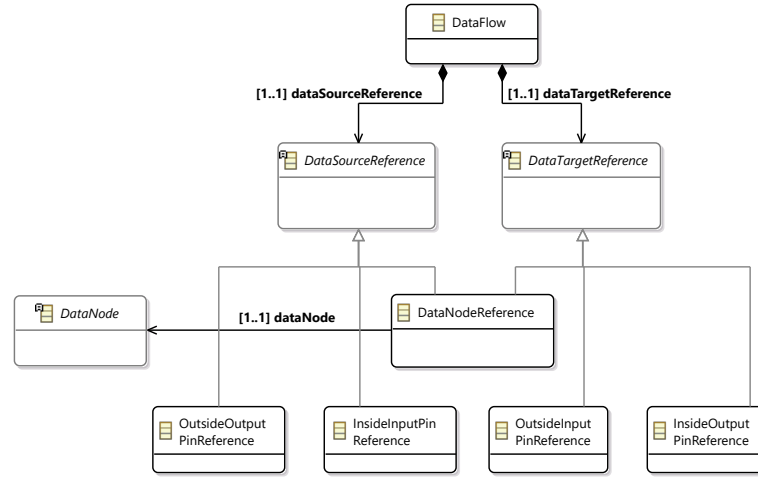


Figure 3.10: The Data Source-Target reference structure

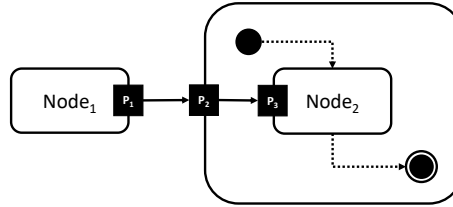


Figure 3.11: The Data node reference structure

3.3.1.7 Pin Reference

Pin references are used to define a rigid pin-reference structure in the model. *InputPinReferences* have a reference to a specific *InputPin*, *OutputPinReferences* have a reference to a specific *OutputPin*. *InsidePinReferences* and *OutsidePinReferences* are used to tell the direction the reference sees the given pin; inside reference sees it from the inside, outside reference sees it from the outside. The *OutsidePinReference* must also have a reference to the specific *ActionNode* the pin is associated with⁶. See Figure 3.12 for the meta-model.

3.3.2 Concrete Syntax

In order to make it easier to test and visualise activities, I created an Xtext domain-specific language. The SysMLv2 language served as the main inspiration for the language, however, much of the *syntactic sugars* have been omitted for simplicities' sake. As a result, many constructs are inherently repetitive to write. You can see an example in Listing 3.1. For the exact language definition, please see Section A.2

⁶Note, that the inside pin reference does not have a node reference, because it is implicitly the containing activity

```

1  activity CompilationProcess {
2      var errors : boolean := false
3
4      initial Initial
5      merge Merge
6      fork Fork
7
8      action Read1 : activity(
9          out p : integer
10     )
11     action Compile1 : activity(
12         in p : integer
13     )
14     action Read2 : activity(
15         out p : integer
16     )
17     action Compile2 : activity(
18         in p : integer
19     )
20
21     join Join
22     decision Decision
23     action Edit
24     final Final
25
26     control flow from Initial to Merge
27     // ...
28     data flow from Read1.p to Compile1.p
29     control flow from Fork to Read2
30     // ...
31     control flow from Decision to Edit [errors]
32     control flow from Edit to Merge [!errors]
33     control flow from Decision to Final
34 }

```

Listing 3.1: Gamma Activity Language representation of the compilation activity.

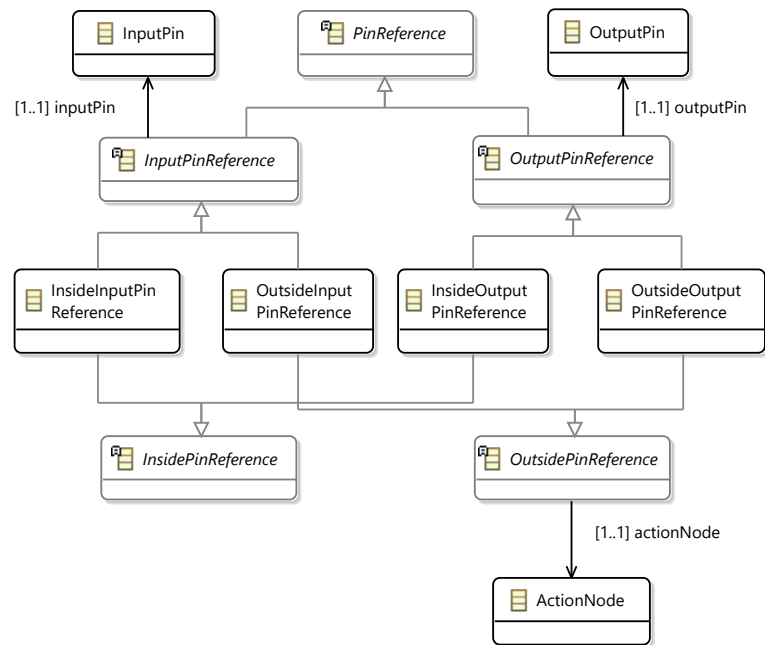


Figure 3.12: The Pin reference structure

Chapter 4

Integrating Activity Language Into Gamma

In the previous chapter, I have introduced the Gamma Activity Language - its formalism and textual representation. However, in order to use it for model verification, it has to be integrated into the Gamma transformation pipeline (see Figure 2.7). For this integration, I start by defining *how* it integrates with Gamma in Section 4.1, after which I show transformation algorithm in Section 4.2. Finally, I talk a bit about the implementation details in Section 4.3.

4.1 Activities Alongside Statecharts

In the real world, SysML models often contain state machines that call activity diagrams using a state's *do behaviour*, as often times this makes the design process easier. However, Gamma does not support statecharts containing *do activity* actions. Thus, first I extend the Gamma meta-model to support calling activities from states.

4.1.1 Gamma Extensions

First, I extended Gamma *States* to include *do* actions as well among *entry* and *exit* actions (see Figure 4.1b). In order to enable calling activities from statecharts, I added the *CallActivityAction*, which has a reference to an activity declaration (see Figure 4.1b). These changes can be seen visually in Figure 4.2. Added parts are outlined with green, while edited parts are outlined with orange.

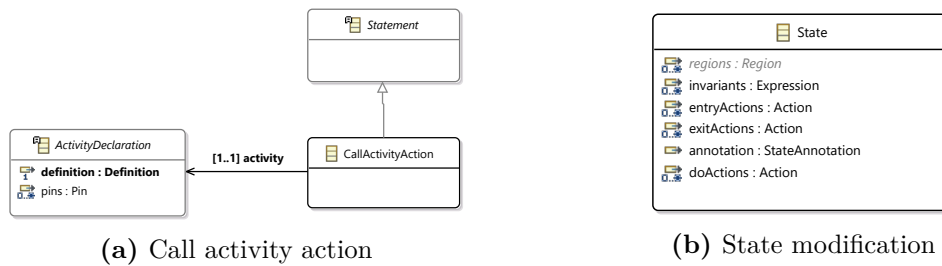


Figure 4.1: Extensions to the Gamma meta-model

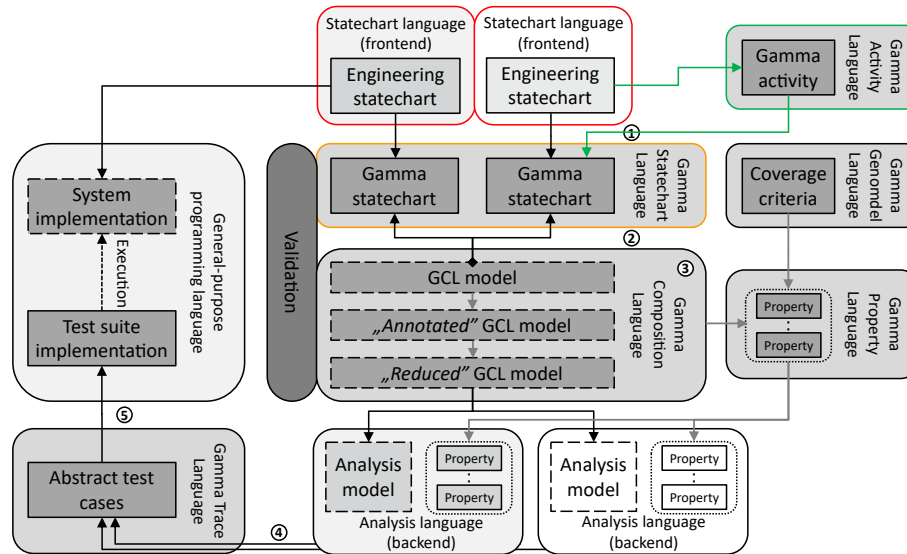


Figure 4.2: Overview of my modification to the Gamma framework.

4.1.2 Challenges of Calling Activities

how to integrate into gamma, action, do action, etc, transition gamma használja az xsts-t
-> xsts-re kell trafózni

ez a rész csak jegyzet

Initial/final node, action node, composite activity node, decision/merge node, fork/join node, pins, control/data flows.

Do behaviour:

call activity action on transitions is not supported, would have to be inlined and flattened, atomic functions, interlaced with line execution semantics (future work)

- call activity context függő - hosszú (nem atomikus) dolgot nem lehet akárhol meghívni (transition, sima action, stb) - validáció: inline környezetben tilos várakozás és ciklus (vagy csak x mélységig) - sok köztes nem stabil állapot - nagy változás a trafóban

ezért csak do activity van

fentebb leírtam, hogyan lehet leképezni proces modelleket, de így csak magukban futhatnak. Itt most leírom, hogy milyen nehézségeket okozhat, amikor egymás mellett futtatjuk őket:

do activity:

amikor a state aktív, futhat az aktivty, de ez pár problémával jön: párhuzamossági és szinkronizációs problémák

action:

egy activity értékét ki kell lapítani, hogy a tranzíció tüzelése után azonnal értelmezhető legyen (nem felezhethetjük el az adott tranzíciót, mert akkor érvénytelen állapotaink lesznek)

unlock:

még nagy kérdés, hogy milyen szinten bontuk fel a lépéseket, mennyire legyenek atomikusak, mik futhatnak egymás mellett, stb

alap elképzelésben akár egy activity akár egy állapotgép definiálhat egy komponens viselkedését, de jelenleg ezt is egyszerűsített módon implementáltuk; az activity az állapotgép része lehet

megoldás a kérdésekre:

megoldásként a legegyszerűbb módszert választottuk, mert első sorban az a kérdés, hogy ez a módszer egyáltalán alkalmazható-e; a másik mindenképpen bonyolítja az implementációt és a létrejövő modellt is

4.2 Activities as State-based Models

Because Gamma transforms its models to XSTS in order to run formal verification on them, to integrate activity language, it must also be transformed to XSTS. Luckily, the structure and behaviour of the activity formalism makes this transformation easy.

The state of the activities (Composite Node Operation 3.2.1) are defined by the nodes' *states* and *values*, it's pins' *values* and the flows' *states* and *values*. All of these can be represented using *variables* in the XSTS formalism. Because XSTS variables and types must have unique names, the name of the variables must be derived from their containers. In the following I will show the transformation algorithm using the XSTS's textual representation for easier understanding.

The transformations steps are:

Step One In order to create variables for the *state* of the nodes and flows, we must declare a *NodeState* and *FlowState* type.

```
1 type NodeState : { __Idle__, __Running__, __Done__ }
2 type FlowState : { __Empty__, __Full__ }
```

Step Two Now that we have the types needed, we can create the mappings of the nodes and flows. Flows are mapped to a variable of type *FlowState*. If it is a *DataFlow*, an additional *value* variable has to be added, which will have a type of the connected pin¹.

```
1 var activity_flow : FlowState = __Empty__
2 var activity_flow_value : integer = 0
```

Nodes are mapped to a variable of type *NodeState*. After which, according to its exact type, additional variables are added; if it is a *DataNode*, a single *value* variable will be added with the type of the connected *DataNode*. Otherwise, if it is an *ActionNode*, then all of its pins will be mapped to a variable - each with their own types.

```
1 var activity_node : NodeState = __Idle__
2 var activity_node_pin1 : integer = 0
3 var activity_node_pin2 : integer = 0
4 var activity_decision_node : NodeState = __Idle__
5 var activity_decision_value : boolean = false
```

Step Three Now that we have mapped the state of the activity, we must map the state-transition functions defined in *??*. All state transition functions defined have a

¹The connected pin can be determined by traversing the chain of flows in a direction, until we reach a pin

precondition, after which the state variables are *given* a new value. In the resulting XSTS, preconditions are mapped to *assume* operations, which is put into a sequential operation.

```
1  assume ((activity_flow == __Empty__) && (activity_node == __Done__));  
2  activity_flow := __Full__;  
3  activity_node := __Idle__;
```

```
1  assume ((activity_flow == __Empty__) && (activity_node == __Done__));  
2  activity_flow := __Full__;  
3  activity_node := __Idle__;
```

4.3 Implementation Regards

implementációs nehézségek, kérdések, stb (commitok, line change, projektek magas szinten)

Chapter 5

Evaluation

spacecraft model bevezetése, leírása statechart elemek referálása, activity-k megírása kézzel
(modell mehet apendix-be) mérések végzése és leírása

Chapter 6

Conclusion

ami nem ment evaluationbe - lassú - nem skálázódik - de egy első lépés, hogy unified verifikációt lehessen csinálni komplikált rendszereken

Future Work - sysml activity nagyobb mappelése - signalok bevezetése - activity külön komponensként - activity inline-olása transition action-re

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Ez nem kötelező, akár törölhető is. Ha a szerző szükségét érzi, itt lehet köszönetet nyilvánítani azoknak, akik hozzájárultak munkájukkal ahhoz, hogy a hallgató a szakdolgozatban vagy diplomamunkában leírt feladatokat sikeresen elvégezze. A konzulensnek való köszönetnyilvánítás sem kötelező, a konzulensnek hivatalosan is dolga, hogy a hallgatót konzultálja.

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Todo list

Add introduction	1
explain controller behaviour in words	4
more description	9
Add related work	12
Ezt a részt át kéne írni	14
nyugi, ez a rész nem lesz benne a véglegesben	

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Appendix

A.1 XSTS Language

In this appendix I introduce the exact language constructs for the XSTS language

A.1.1 Types

XSTS contains two default variable types, logical variables (*boolean*) and mathematical integers (*integer*). XSTS also allows the user to define *custom types*, similarly to enum types in common programming languages.

A custom type can be declared the following way:

```
1  type <name> : { <literal_1>, . . . , <literal_n> }  
2  
3  type Color : { RED, GREEN, BLUE }
```

A.1.2 Variables

Variables can be declared the following way, where **<value>** denotes the value that will be assigned to the variable in the initialization vector:

```
1  var <name> : <type> = <value>
```

The variable can only take a value of the specified type.

If the user wishes to declare a variable without an initial value, this is possible as well:

```
1  var <name> : <type>
```

A variable can be tagged as a control variable with the keyword **ctrl**:

```
1  ctrl var <name> : <type>
```

In which case the variable v will also be added to V_C (the set of control variables).

Examples:

```
1  var a : integer  
2  ctrl var b : boolean = false  
3  var c : Color = RED
```

A.1.2.1 Operations

The behaviour of XSTS can be described using basic and composite operations. Basic operations include assignments, assumptions and havocs. In the following, you can see an

example for each, where `<expr>` is an expression returning a value, and `<varname>` is the name of a variable.

```
1  assume <expr>
2
3  <varname> := <expr>
4
5  havoc <varname>
```

Composite operations are either non-deterministic choices, sequences or parallels. Non-deterministic choices have the following syntax, where `<operation>` are arbitrary basic or composite operations:

```
1  choice {
2      <operation>
3  } or {
4      <operation>
5  }
```

Sequences have the following syntax:

```
1  <operation>
2  <operation>
3  <operation>
```

And parallels have the following syntax:

```
1  parallel {
2      <operation>
3      <operation>
4  }
```

A.1.2.2 Transitions

Each transition is a single operation (basic or composite). We distinguish between three sets of transitions, *Tran*, *Init* and *Env*. Transitions are described with the following syntax, where `<transition-set>` is either `tran`, `env` or `init`:

```
1  <transition-set> {
2      <operation>
3  } or {
4      <operation>
5  } or
6  //...
7  or {
8      <operation>
9  }
```

A.2 Gamma Activity Language

A.2.1 Language elements

The following section gives high level introduction into the syntax of the Gamma Activity DSL.

A.2.1.1 Pins

Pins can be declared the following way, where `<direction>` can be either `in` or `out`, and `type` a valid Gamma Expression type.

```
1 <direction> <name> : <type>
```

For example:

```
1 in examplePin : integer
```

where the direction is `in`, the name is `examplePin` and the type is `integer`.

Nodes

Nodes can be declared by stating the `type` of the node and then it's name. The type determines the underlying meta element.

The available node types:

```
1 initial InitialNode
2 decision DecisionNode
3 merge MergeNode
4 fork ForkNode
5 join JoinNode
6 final FinalNode
7 action ActionNode
```

A.2.1.2 Flows

The behaviour of the Activity can be described by stating `data` or `control` flows between two nodes. Flows may have `guards` on them, which limits when the flow can fire. Activities may only be from the current activity definition's children. Pins can be accessed using the `.` accessor operator, the activity on the left hand side, and the pin's name on the right. The enclosing activity's name is `self`.

Flows can be declared the following way, where `<kind>` is the kind of flow, `<source>` and `<target>` is the source/target node or pin, and `<guard>` is a Gamma Expression returning boolean:

```
1 <kind> flow from <source> to <target> [<guard>]
2
3 control flow from activity1 to activity2
4 control flow from activity1 to activity2 [x == 10]
5 data flow from activity1.pin1 to activity2.pin2
6 data flow from self.pin to activity3.pin2
```

A.2.1.3 Declarations

Activity declarations state the *name* of the activity, as well as its *pins* A.2.1.1.


```

1 activity Example (
2     //..pins..
3 ) {
4     //..body..
5 }

```

You can also declare activities inline by using the `:` operator:

```

1 activity Example {
2     action InlineActivityExample : activity
3 }

```

A.2.1.4 Definitions

Activities also have definitions, which give them bodies. The body language can be either `activity` or `action` depending on the language metadata set. Using the `action` language let's you use any Gamma Action expression, including timeout resetting, raising events through component ports, or simple arithmetic operations.

An example activity defined by an action body:

```

1 activity Example (
2     in x : integer,
3     out y : integer
4 ) [language=action] {
5     self.y := self.x * 2;
6 }

```

Inline activities may also have pins and be defined using action language:

```

1 activity Example {
2     action InlineActivityExample : activity (
3         in input : integer,
4         out output : integer
5     ) [language=action] {
6         self.output := self.input;
7     }
8 }

```

A composite activity can be easily created using inline activity definition:

```

1 activity Example {
2     initial Init1
3     final Final1
4
5     action InlineActivityExample : activity {
6         initial Init2
7         final Final2
8
9         control flow from Init2 to Final2
10    }
11
12    control flow from Init1 to InlineActivityExample
13    control flow from InlineActivityExample to Final1
14 }

```

A.2.1.5 Example

A simple example activity can be seen in Listing A.2.1. This example shows two read actions, that return a random value, which are added together and logged to the console. The addition is defined using a *NamedActivitDeclaraiionReference*.

```

1  activity Adder(
2      in x : integer,
3      in y : integer,
4      out o : integer
5  ) [language=action] {
6      self.o := self.x + self.y;
7  }
8
9  activity Example {
10     initial Initial
11
12     action ReadSelf1 : activity (
13         out x : integer
14     )
15     action ReadSelf2 : activity (
16         out x : integer
17     )
18     action Add : Adder
19     action Log : activity (
20         in x : integer
21     )
22
23     final Final
24
25     control flow from Initial to ReadSelf1
26     control flow from Initial to ReadSelf2
27     control flow from Initial to Add
28     data flow from ReadSelf1.x to Add.x
29     data flow from ReadSelf2.x to Add.y
30     data flow from Add.o to Log.x
31     control flow from Log to Final
32 }

```

Listing A.2.1: Basic adder example.

A.3 Spacecraft Model