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- Needing of uncertainty;
- Different paths of the future;

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In Computation Tree Logic (CTL) the model of time is a tree-like structure. This way, we cannot use Linear Temporal Logic (LTL) to express the existence of a certain path of time in which some event occurs.

Syntax Definition

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The syntax of CTL consists on the syntax of temporal logic plus some path operators. The class of formulas can be defined in Backus-Naur form. If ϕ is a formula:

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$$\begin{split} \phi ::= \bot \mid \top \mid \rho \mid \neg \phi \mid \phi \land \phi \mid \phi \lor \phi \mid \phi \to \phi \mid \mathsf{AX}\phi \mid \mathsf{EX}\phi \mid \\ \mathsf{AF}\phi \mid \mathsf{EF}\phi \mid \mathsf{AG}\phi \mid \mathsf{EG}\phi \mid \mathsf{A}[\phi \mathsf{U}\phi] \mid \mathsf{E}[\phi \mathsf{U}\phi] \end{split}$$

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The syntax of CTL consists on the syntax of temporal logic plus some path operators. The class of formulas can be defined in Backus-Naur form. If ϕ is a formula:

$$\begin{split} \phi ::= \bot \mid \top \mid p \mid \neg \phi \mid \phi \land \phi \mid \phi \lor \phi \mid \phi \to \phi \mid \mathsf{AX}\phi \mid \mathsf{EX}\phi \mid \\ \mathsf{AF}\phi \mid \mathsf{EF}\phi \mid \mathsf{AG}\phi \mid \mathsf{EG}\phi \mid \mathsf{A}[\phi \mathsf{U}\phi] \mid \mathsf{E}[\phi \mathsf{U}\phi] \end{split}$$

With p as a literal (atomic formula), AX, EX, AF, EF, AG e EG unary operators.

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Some examples of what we can say The propositional operators: \neg, \lor, \land, \to have the same meaning of in the propositional logic.

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The propositional operators: \neg , \lor , \land , \rightarrow have the same meaning of in the propositional logic.

The temporal operators can be read (if φ is a formula) as follows:

■ $A\phi$: φ is true in all possible paths;

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- $\mathbf{E}\phi$: φ exists a path in which ϕ is true;

The path-specific operators can be read, considering φ and ψ formulas, as:

■ $\mathbf{X}\phi:\varphi$ is true until next state;

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- $\mathbf{X}\phi$: φ is true until next state;
- lacksquare F φ : There is some state in the future where φ is true;

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- $F\varphi$: There is some state in the future where φ is true;
- $G\varphi$: Globally (in all future states) φ is true;

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- $F\varphi$: There is some state in the future where φ is true;
- \blacksquare $G\varphi$: Globally (in all future states) φ is true;
- $\blacksquare \varphi U \psi$: φ is true at least until ψ becomes true;

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■ Notice that, in CTL, the combination of path specific operators and temporal operators are atomic, i.e., AF is a operator that can be read as "In all paths in the future there is some state where..."

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- Notice that, in CTL, the combination of path specific operators and temporal operators are atomic, i.e., AF is a operator that can be read as "In all paths in the future there is some state where..."
- Notice as well that the binary operators $A[\varphi U \psi]$ and $E[\varphi U\psi]$ can be represented as AU

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- Notice as well that the binary operators $\mathbb{A}[\varphi \mathbb{U}\psi]$ and $\mathbb{E}[\varphi \mathbb{U}\psi]$ can be represented as $\mathbb{A}\mathbb{U}$
- We assume that, similarly to the ¬ operator, the "new" unary operators (AX, EX, AF, EF, AG, and EG) have the first precedence. Next comes the ∧ and ∨ operators. And at last the →, AU and EU

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- Examples of well-formed formulas:
 - $AG(p \lor EFq)$

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Some examples of what we can say

- $AG(p \lor EFq)$
- $\blacksquare \ \mathtt{AX}(q \to \mathtt{E}[(p \lor q)\mathtt{U}r])$

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- $AG(p \lor EFq)$
- lacksquare AX $(q o E[(p \lor q)Ur])$
- EFEGp o AFr Note that this is binded as (EFEGp) o AFr, not as EFEG(p o AFr)

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 - A \neg G \neg p

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 - $A[pUs \land qUs]$

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Different from usual logics, CTL formulas are interpreted by a transition system. Given an set of atoms:

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Some examples of what we can say Different from usual logics, CTL formulas are interpreted by a transition system. Given an set of atoms:

Definition (1)

A **transition system** \mathcal{M} is a triple $\mathcal{M} = (S, \rightarrow, L)$ in which S is a set of states, \rightarrow is a binary relation over S ($\rightarrow \subseteq S \times S$) and $L: S \rightarrow \mathcal{P}(Atoms)$ is a labelling function.

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Definition (2)

A **model** is a duple \mathcal{M}, s in which \mathcal{M} is a transition system and s is a state.

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Definition (2)

A **model** is a duple \mathcal{M}, s in which \mathcal{M} is a transition system and s is a state.

Notation: we will use $\mathcal{M}, s \vDash \varphi$ to say that the model \mathcal{M}, s satisfies the formula φ

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Some examples of what we can

Take an arbitrary model \mathcal{M} . Let s, s_1, s_2, s_3 be states in S. Let $\varphi, \varphi_1, \varphi_2$ be well-formed formulas of CTL. And let p be an atom. The satisfaction of CTL formulas can be defined as follows:

 $lackbox{\blacksquare} \mathcal{M}, s \vDash \top \text{ and } \mathcal{M}, s \not\vDash \bot \text{ for all } s \in S$

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- lacksquare $\mathcal{M}, s Dash op$ and $\mathcal{M}, s
 ot ecta$ for all $s \in S$
- \mathcal{M} , $s \models p$ iff $p \in L(S)$

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- $\blacksquare \mathcal{M}, s \vDash p \text{ iff } p \in L(S)$
- $\blacksquare \mathcal{M}, s \vDash \neg \varphi \text{ iff } \mathcal{M}, s \nvDash \varphi$
- \mathcal{M} , $s \vDash \varphi_1 \land \varphi_2$ iff \mathcal{M} , $s \vDash \varphi_1$ AND \mathcal{M} , $s \vDash \varphi_2$

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Some examples of what we can

- $\mathcal{M}, s \vDash \top$ and $\mathcal{M}, s \not\vDash \bot$ for all $s \in S$
- \mathcal{M} , $s \models p$ iff $p \in L(S)$
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- \mathcal{M} , $s \vDash \varphi_1 \lor \varphi_2$ iff \mathcal{M} , $s \vDash \varphi_1$ OR \mathcal{M} , $s \vDash \varphi_2$

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- $\blacksquare \mathcal{M}, s \vDash \varphi_1 \rightarrow \varphi_2 \text{ iff } \mathcal{M}, s \not\vDash \varphi_1 \text{ OR } \mathcal{M}, s \vDash \varphi_2$

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■ $\mathcal{M}, s \models \mathtt{AX}\varphi$ iff for all s_1 that $s \to s_1$ and $\mathcal{M}, s_1 \models \varphi$. Thus, AX says: "in every next state..."

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- $\mathcal{M}, s \vDash \mathsf{EX}\varphi$ iff exists s_1 that $s \to s_1$ and $\mathcal{M}, s_1 \vDash \varphi$. Thus, EX says: "in some next state..."

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- $M, s, \models AG\varphi$ iff for all paths $s_1 \rightarrow s_2 \rightarrow s_3 \rightarrow ...$ in which $s = s_1$, for all s_i , $M, s_i \models \varphi$. Thus, AG says: "In all possible paths from now on in all next states..."

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- $M, s, \models AG\varphi$ iff exists some path $s_1 \rightarrow s_2 \rightarrow s_3 \rightarrow ...$ in which $s = s_1$, for all s_i , $M, s_i \models \varphi$ Thus, EG says: "Exists a path from now on in all next states..."

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Some examples of what we can

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Satisfaction

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Some examples of what we can say

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Examples

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Some examples of

examples of what we can say ■ "It's possible to get to a state where something has started but it's not ready": $EF(started \land \neg ready)$