

## Validation of Real Time Applications

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# Validation of Real Time Applications

Françoise Simonot - Lion

**Zhejiang University  
China**

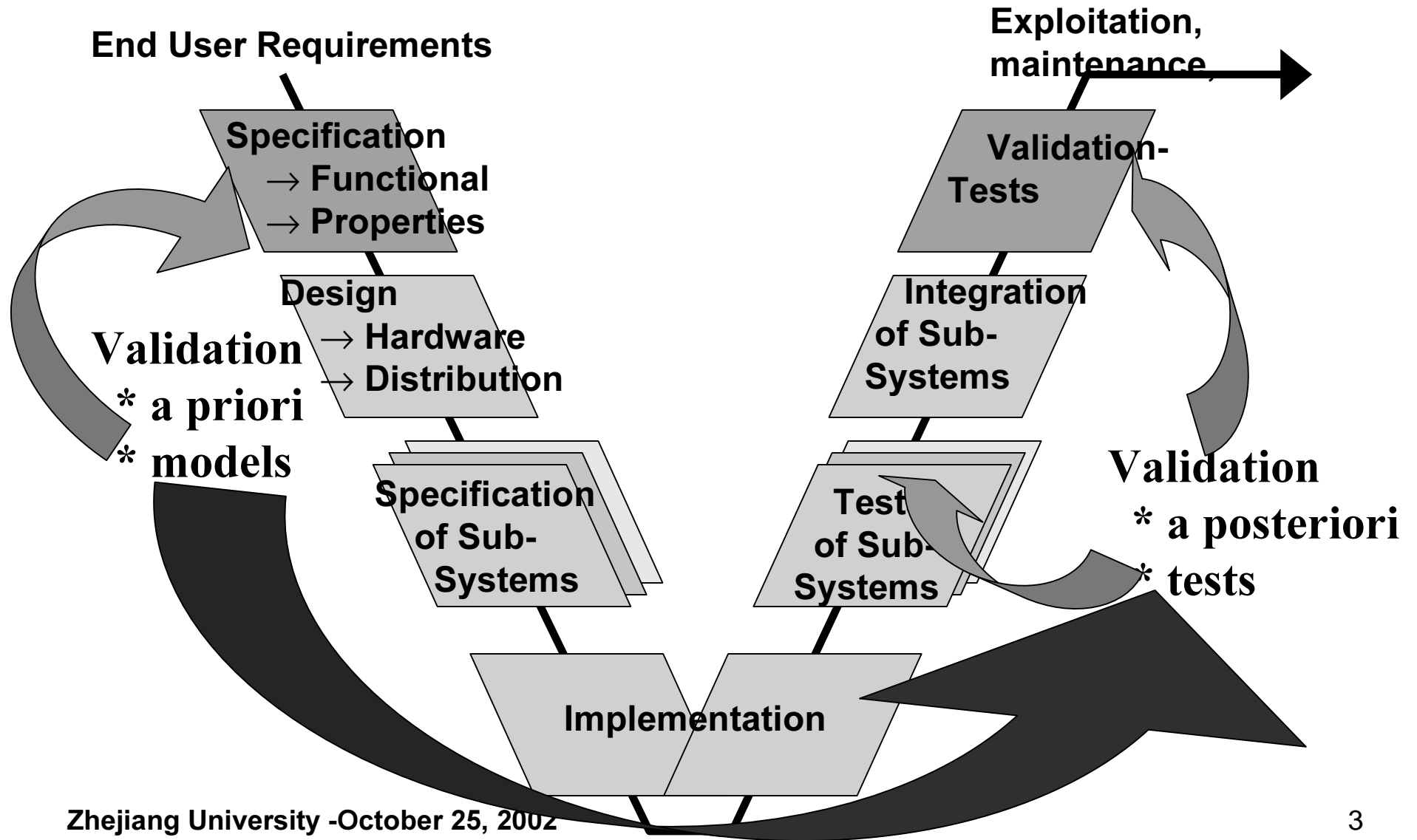
October 25, 2002



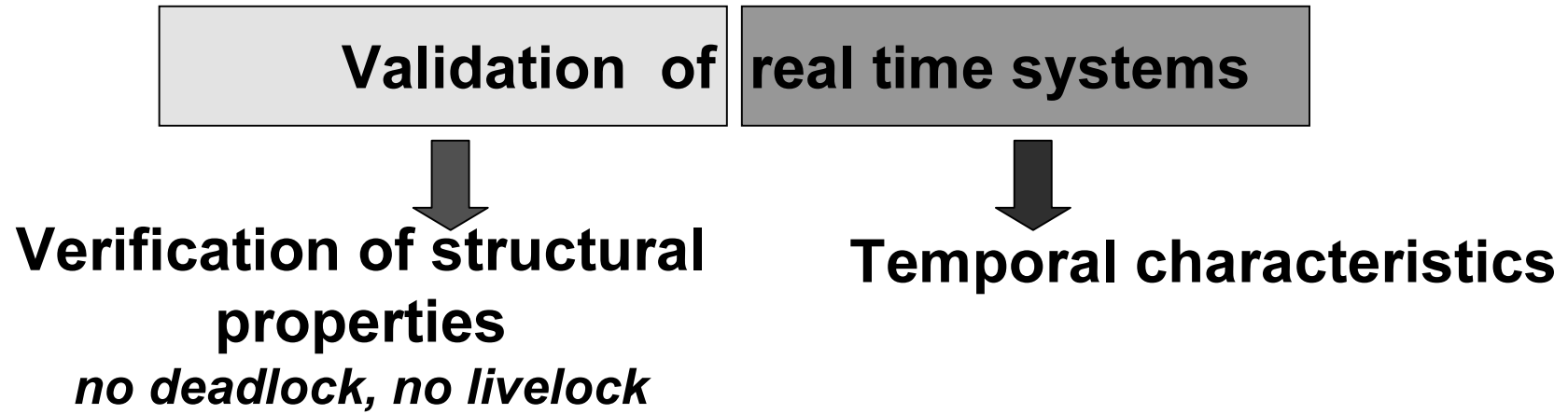
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- 1 ⇒ Validation : *When, What and How ?***
- 2 ⇒ Timed Input Output State Machine (TIOSM)  
*an adequate formalism***
- 3 ⇒ Validation a posteriori (Integration test)  
*how to be efficient***
- 4 ⇒ Validation a priori  
*how to master the complexity***
- 5 ⇒ Conclusions**

# Validation : when - what - how



# Validation : when - what - how



## Model

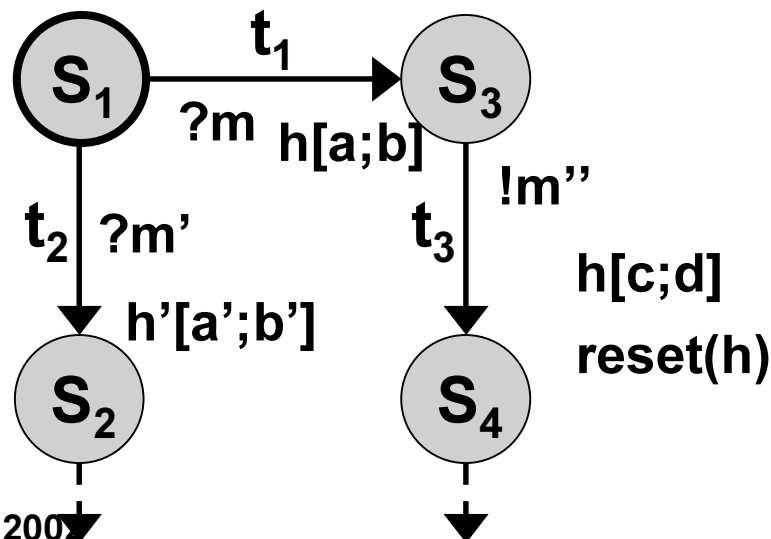
- state machines / temporal attributes
- deterministic approach

**“Timed automata”**

## 2 - Timed Input Output State Machine (TIOSM) *an adequate formalism*

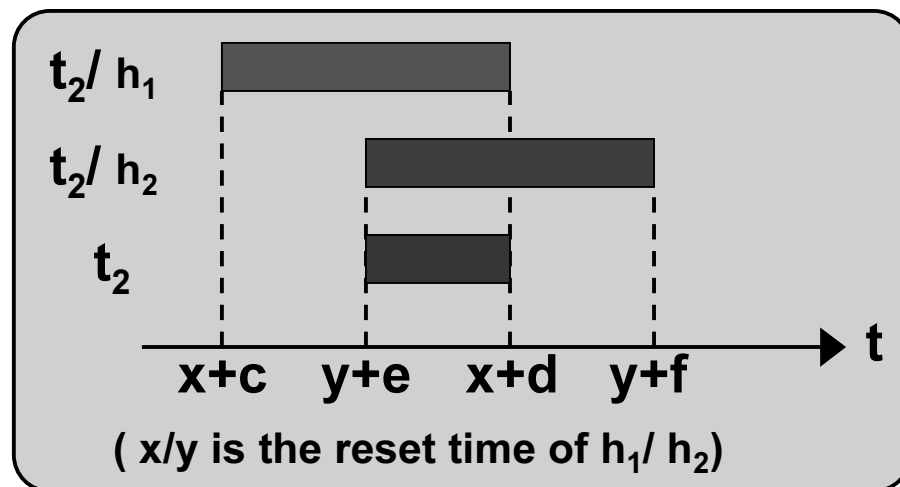
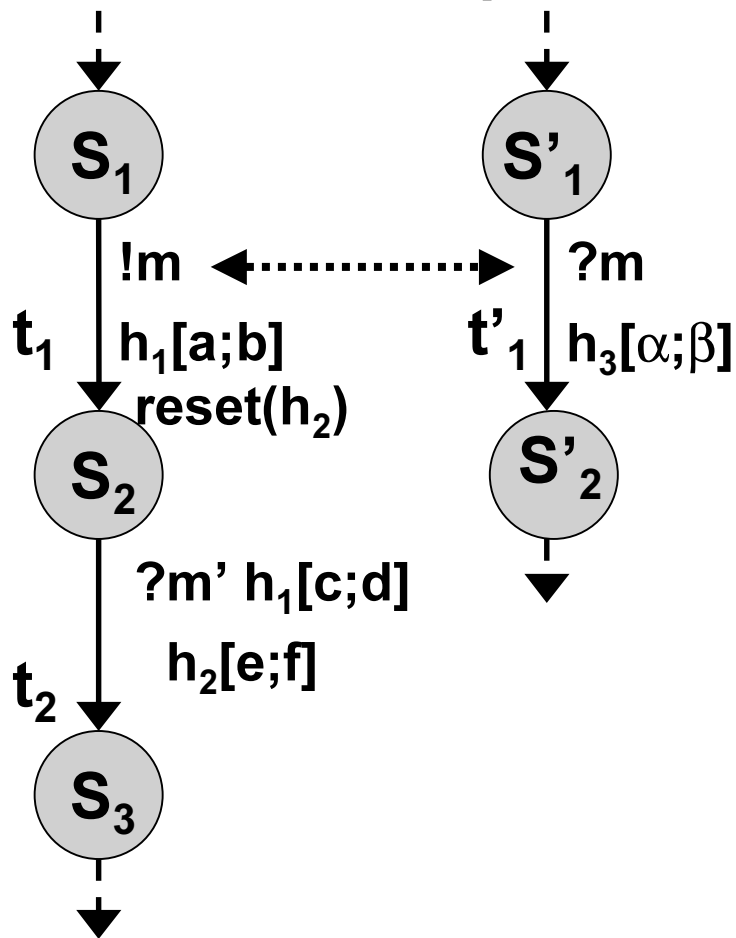
> TIOSM  $T=(S, L, C, s_0, \varepsilon)$

- **S** set of states /  $\varepsilon$  set of transitions
- $s_0$  is the initial state
- **L** set of messages
- **C** set of clocks



# 2 - Timed Input Output State Machine (TIOSM) *an adequate formalism*

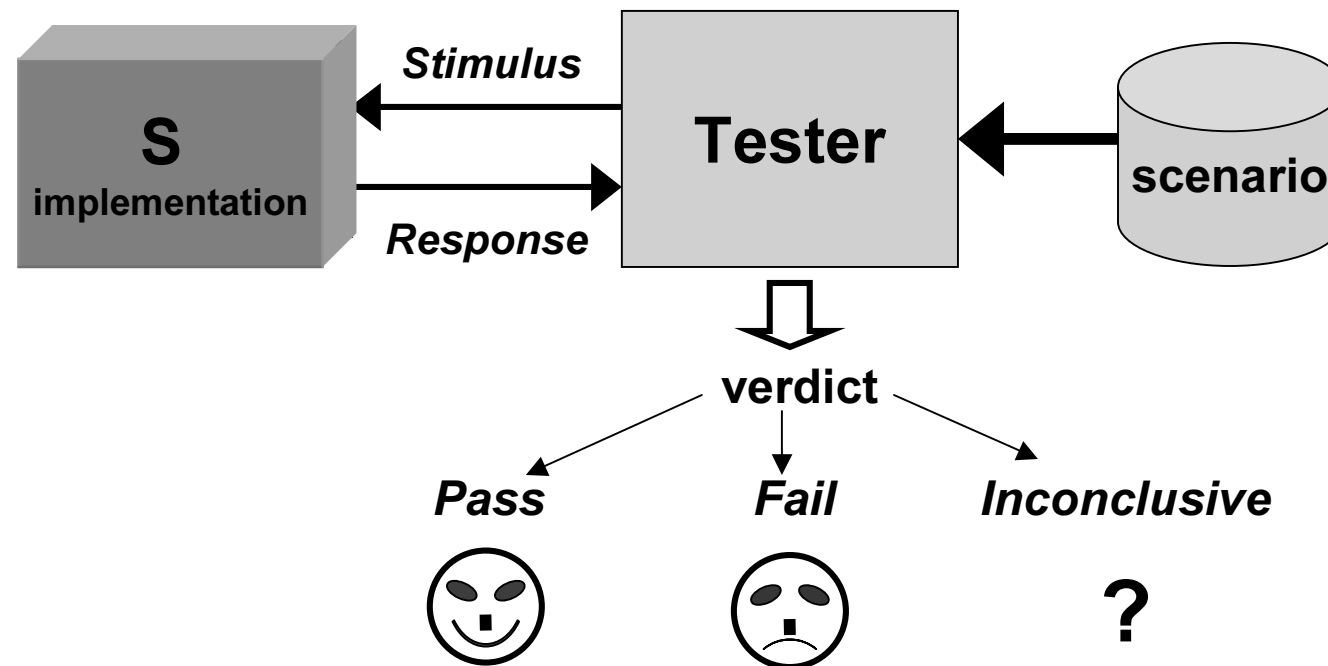
> Temporal behavior : an exemple



# 3 - Validation a posteriori (Integration test)

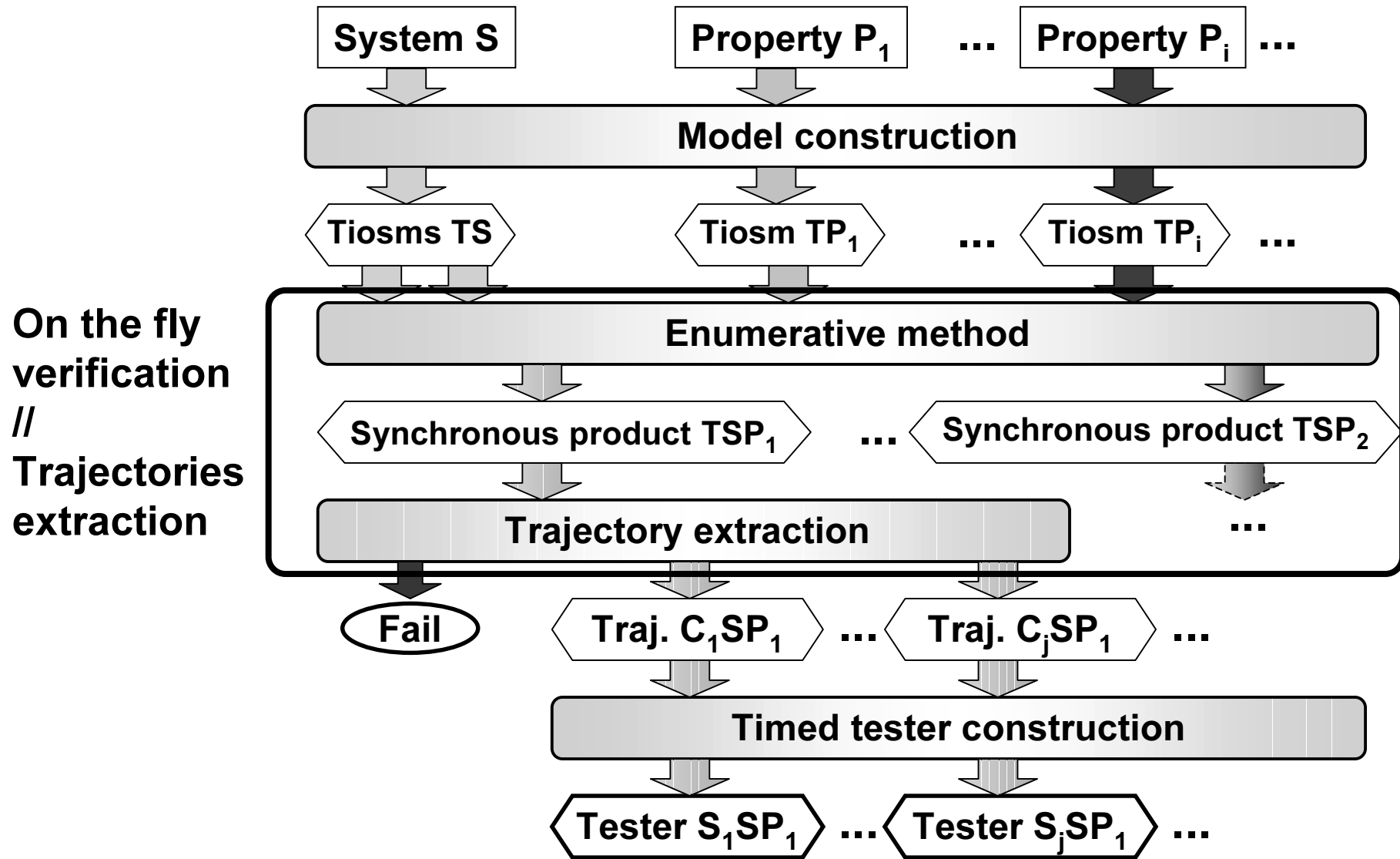
Implementation of S

Verification of Temporal Interoperability Properties  
Testing approach



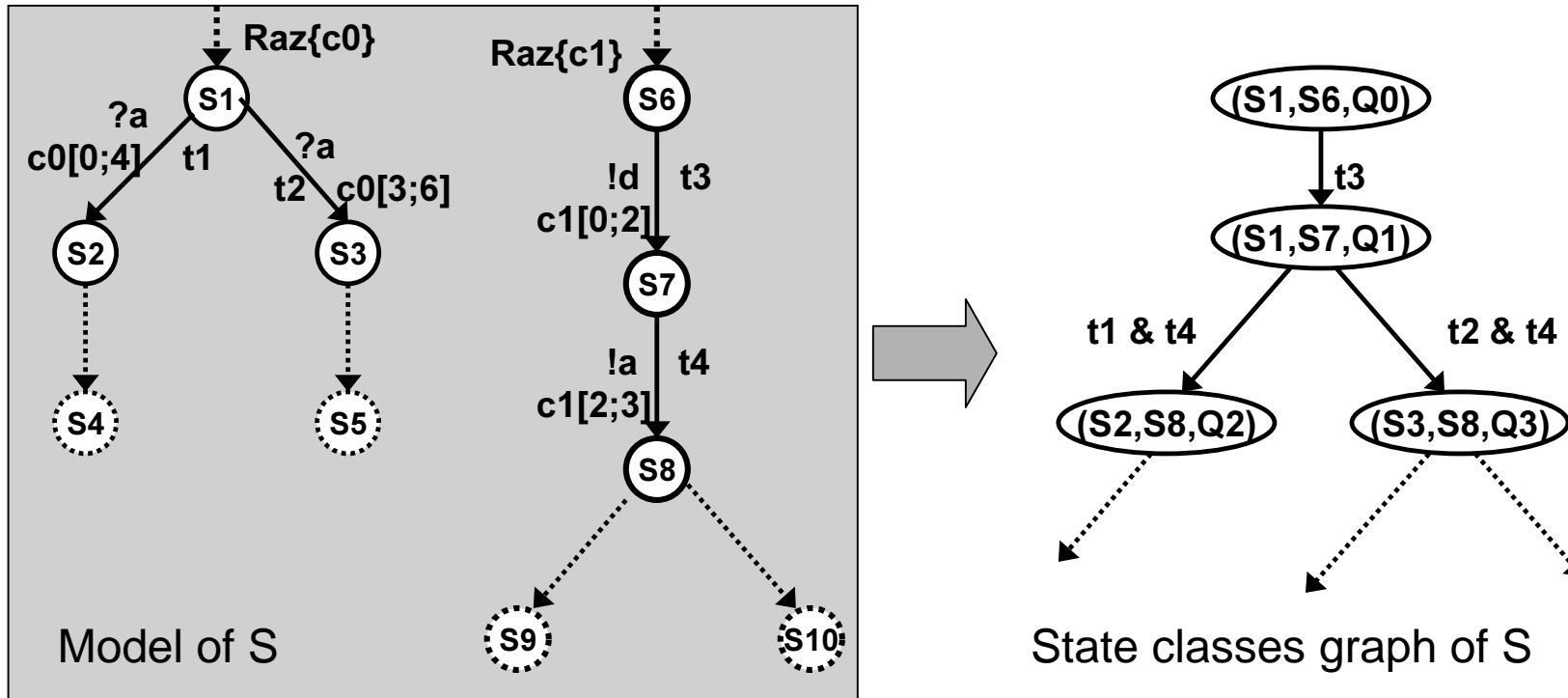


# 3 - Validation a posteriori (Integration test)



# 3 - Validation a posteriori (Integration test)

Construction of the state classes graph (cf. Berthomieu&Diaz) :

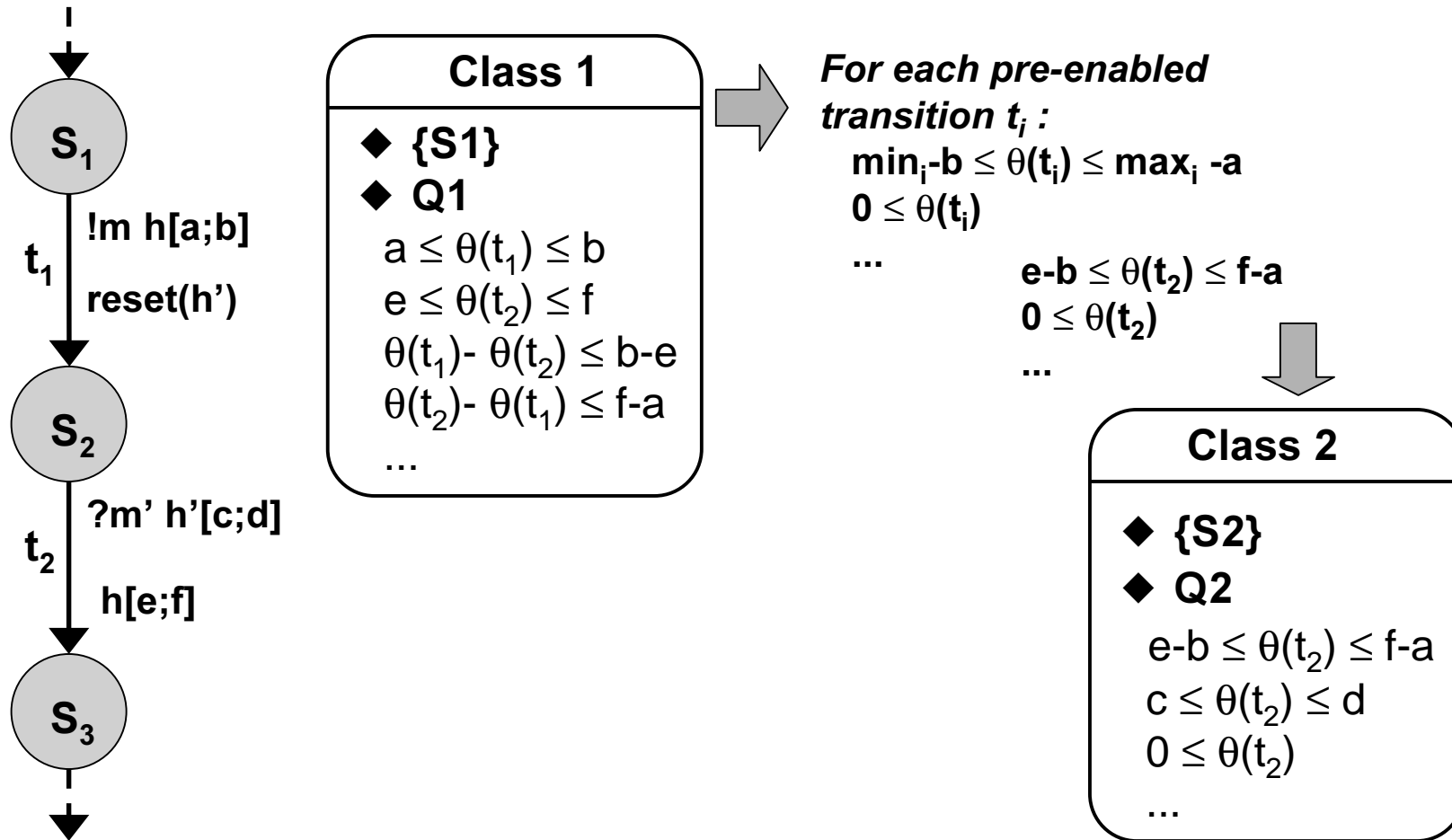


$S_i, S_j$  : current states of the TIOSM

$Q_k$  : inequations system

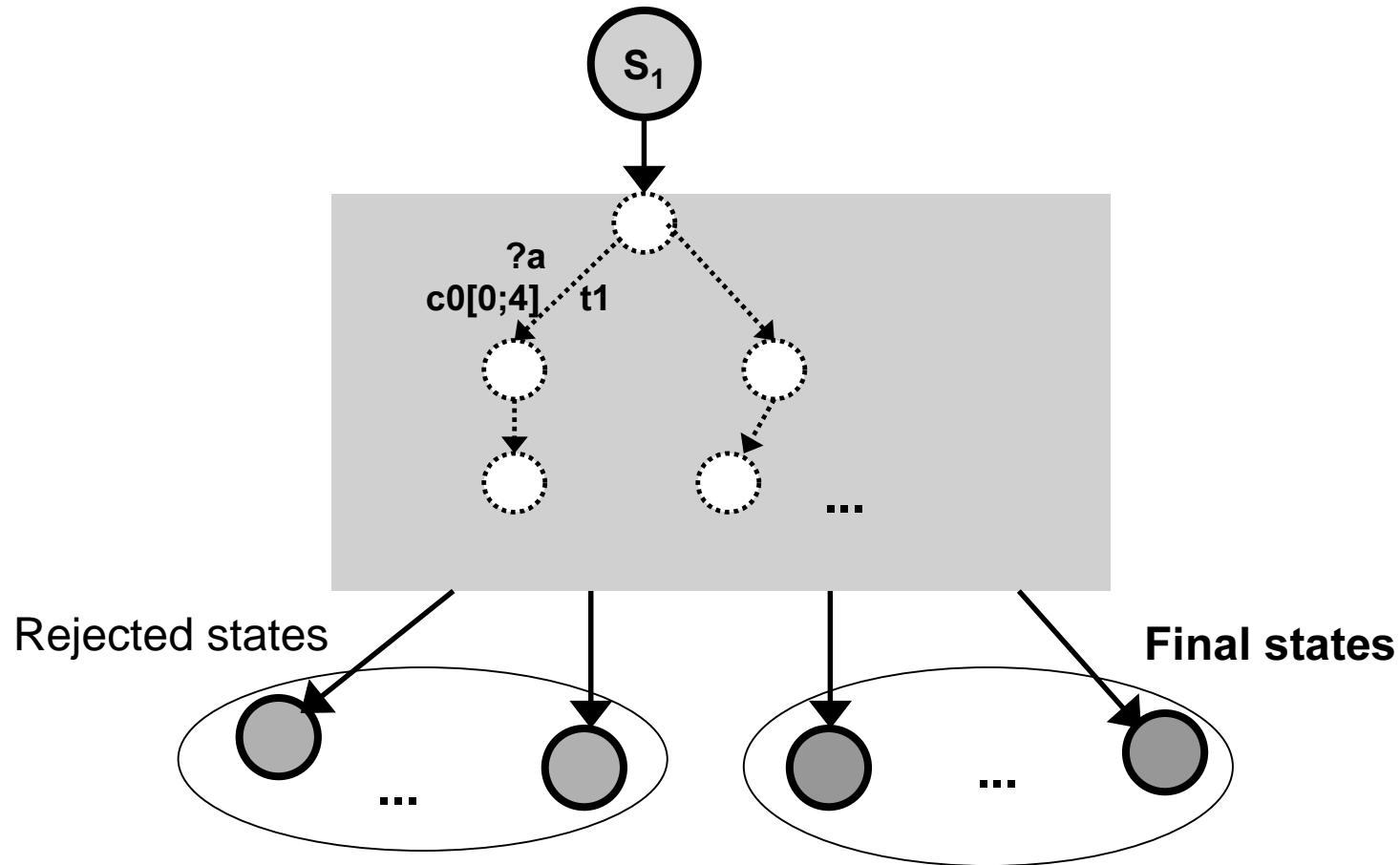
# 3 - Validation a posteriori (Integration test)

Construction of the inequations system / Pre-enabled transitions



# 3 - Validation a posteriori (Integration test)

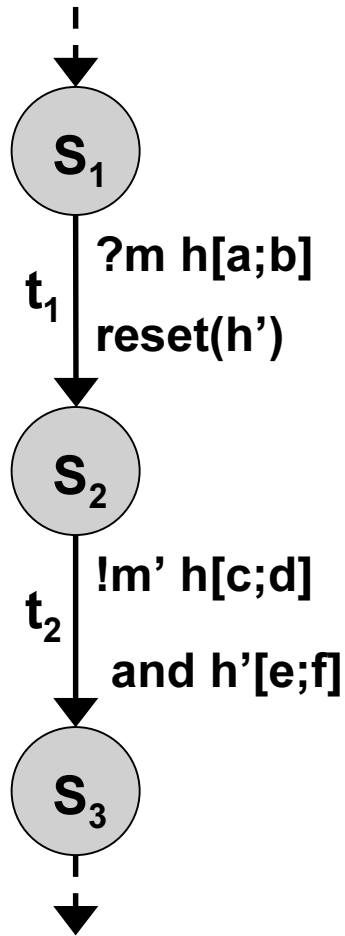
> Model of a Property  $T_p$  (TIOSM)



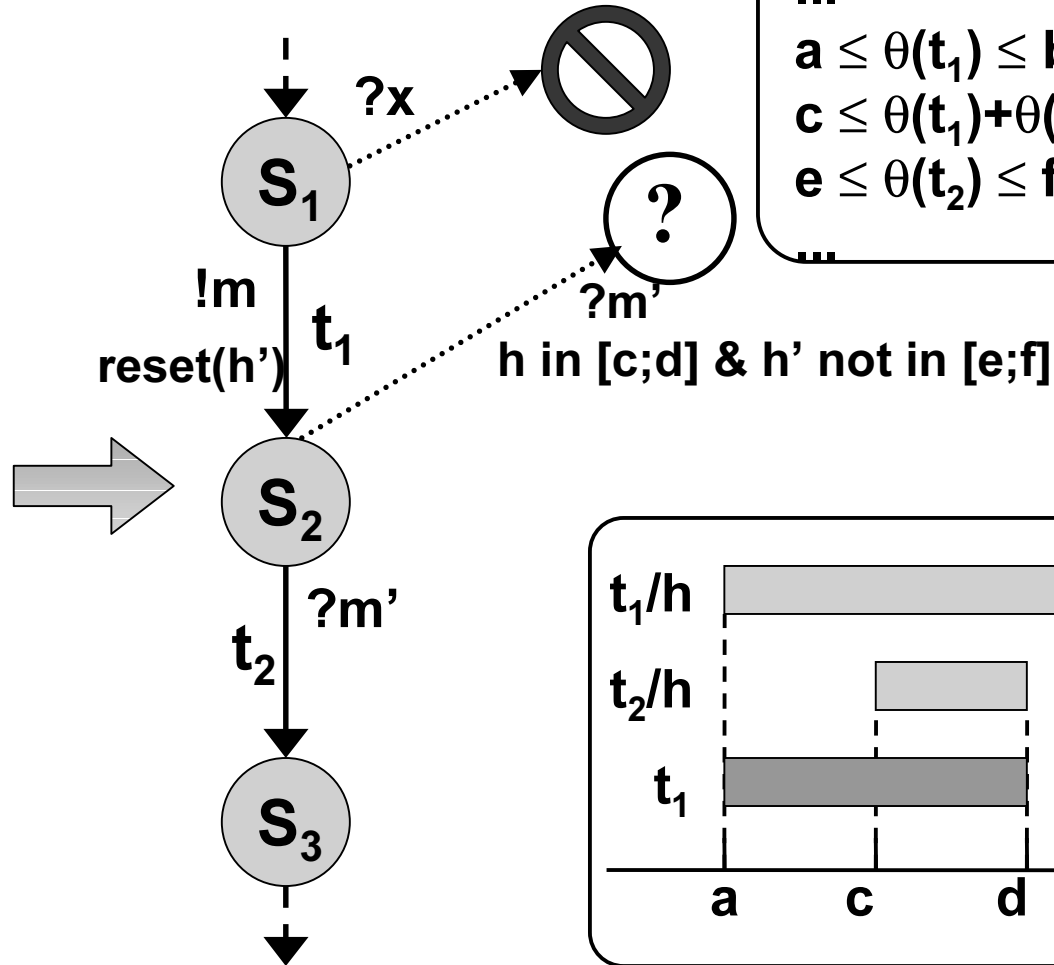


# 3 - Validation a posteriori (Integration test)

Trajectory  $T_C$



Tester  $T_T$



**Behaviour**

...

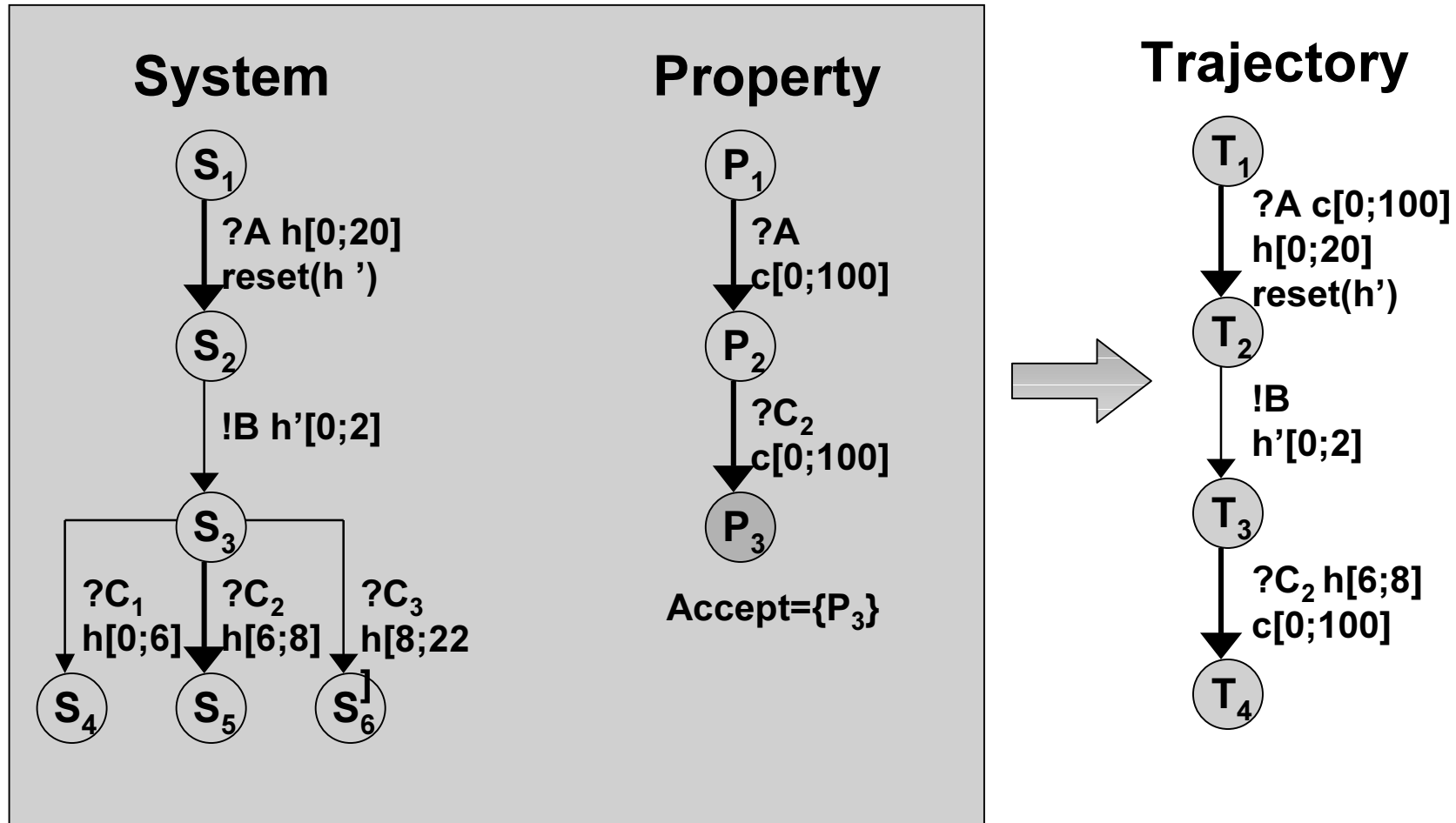
$a \leq \theta(t_1) \leq b$

$c \leq \theta(t_1) + \theta(t_2) \leq d$

$e \leq \theta(t_2) \leq f$

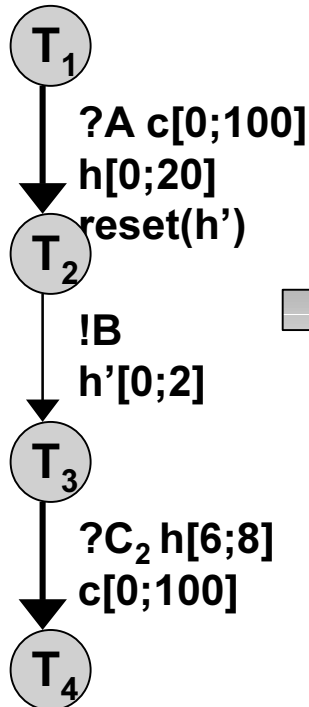
...

# 3 - Validation a posteriori (Integration test)

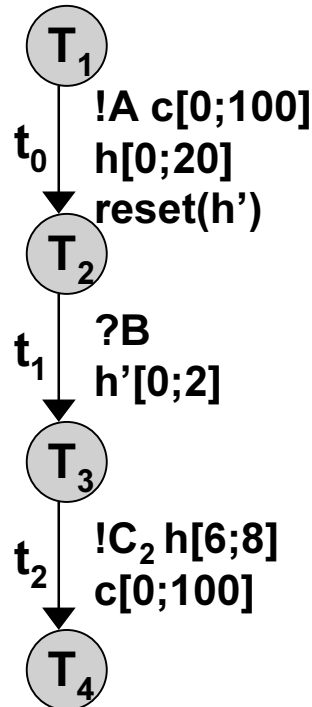


# 3 - Validation a posteriori (Integration test)

## Trajectory

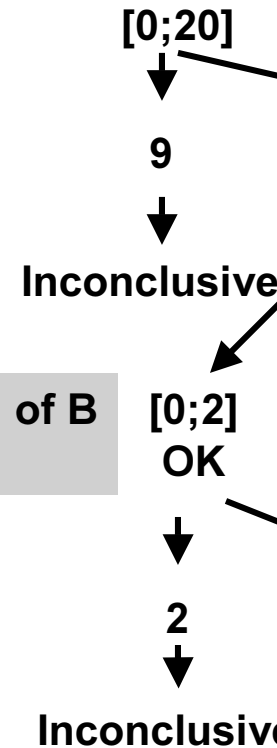


## Tester

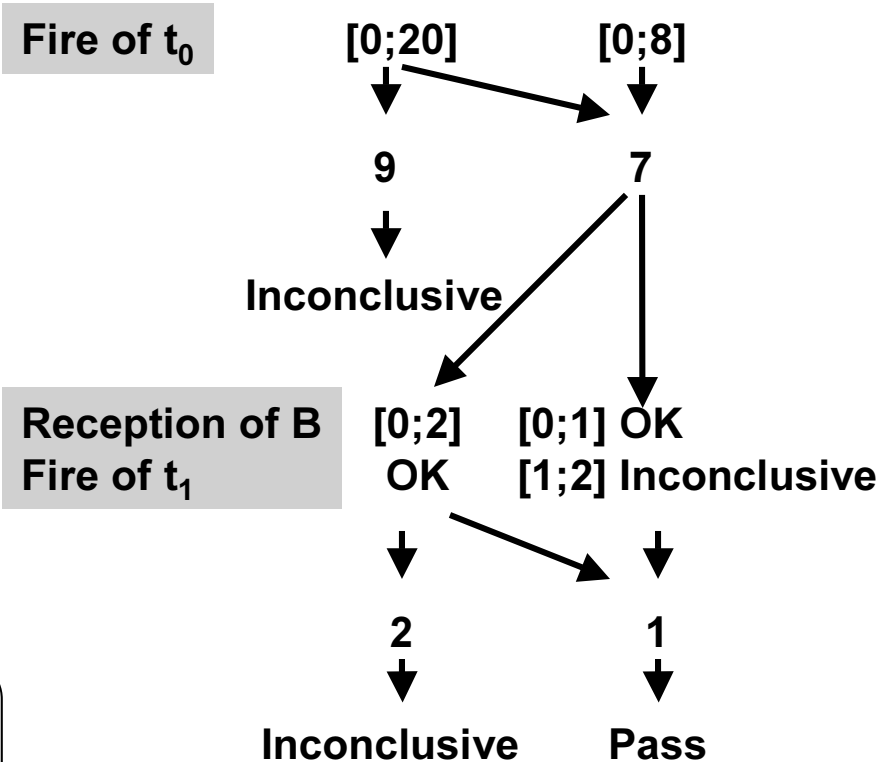


$$\begin{aligned}
 &0 \leq \theta(t_0) \leq 100 \ \& \ 0 \leq \theta(t_0) \leq 20 \ \& \\
 &0 \leq \theta(t_1) \leq 2 \ \& \\
 &0 \leq \theta(t_0) + \theta(t_1) + \theta(t_2) \leq 100 \ \& \\
 &6 \leq \theta(t_0) + \theta(t_1) + \theta(t_2) \leq 8
 \end{aligned}$$

## Normal Tester



## Adaptative Tester





# 3 - Validation a posteriori (Integration test)

- **Conclusions**
  - **Formal generation of timed test sequences**
  - **Reduction of *inconclusive* cases during the test process**

# 4 - Validation a priori

## *how to master the complexity*

**Validation a priori**

**model analysis**

**model simulation**

**+ exhaustivity**  
**- number of states**

**+ easy to use**  
**- non exhaustivity**  
**scenario dependent**

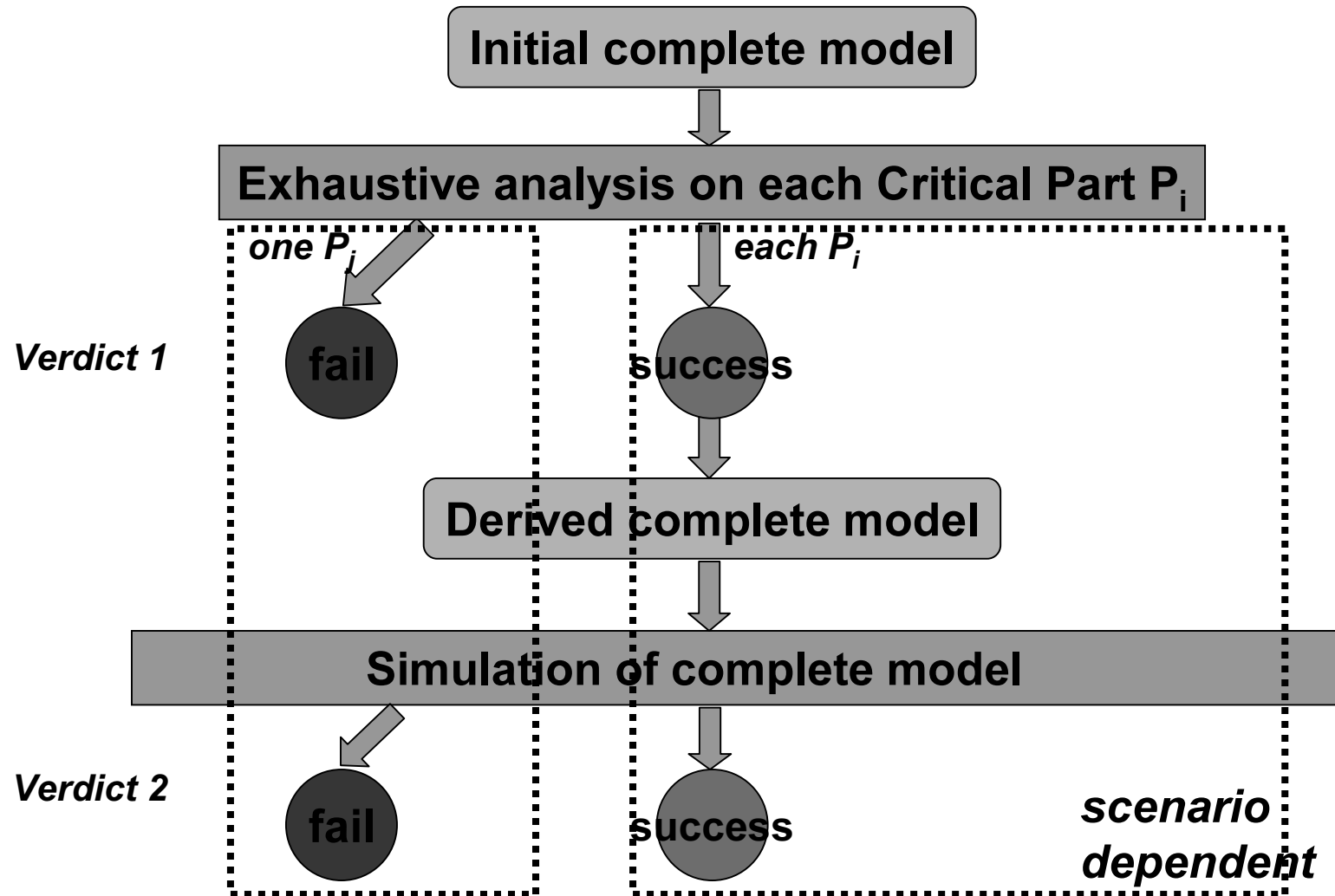
**An hybrid validation method**

**{ exhaustive analysis on critical parts }**

**+**

**{ simulation on the complete system }**

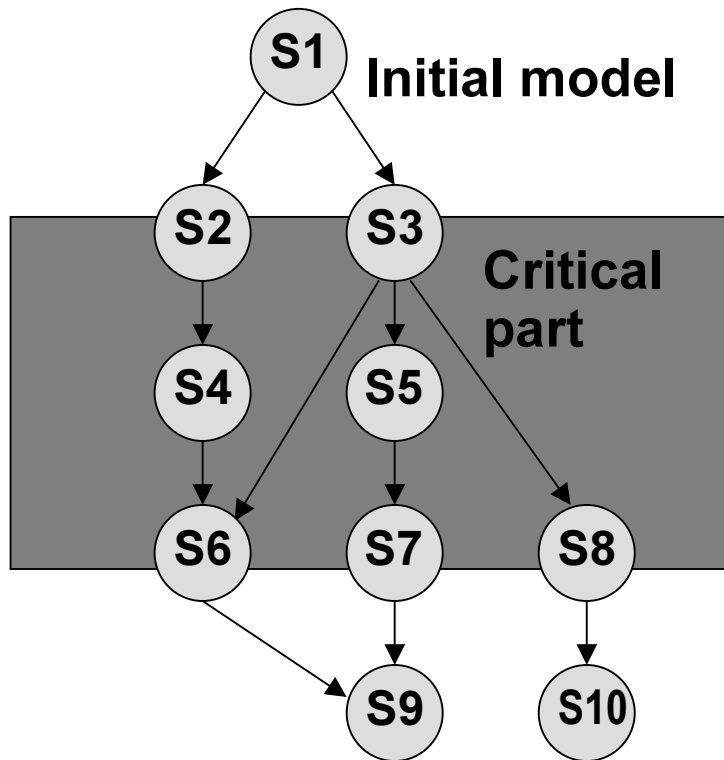
# 4 - Validation a priori - Hybrid Method



# 4 - Validation a priori - Hybrid Method

## Critical parts - partial models definition

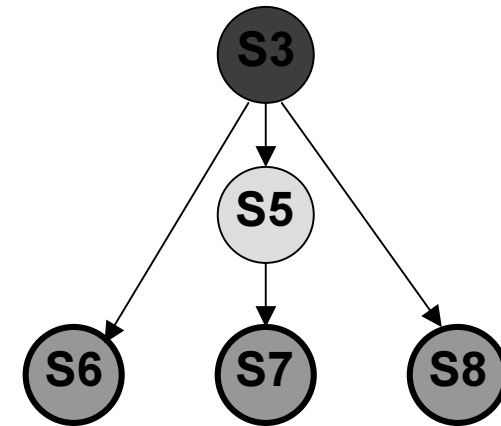
- 1 and only 1 input state
- at least one output states
- 2 partial models cannot be overlapped



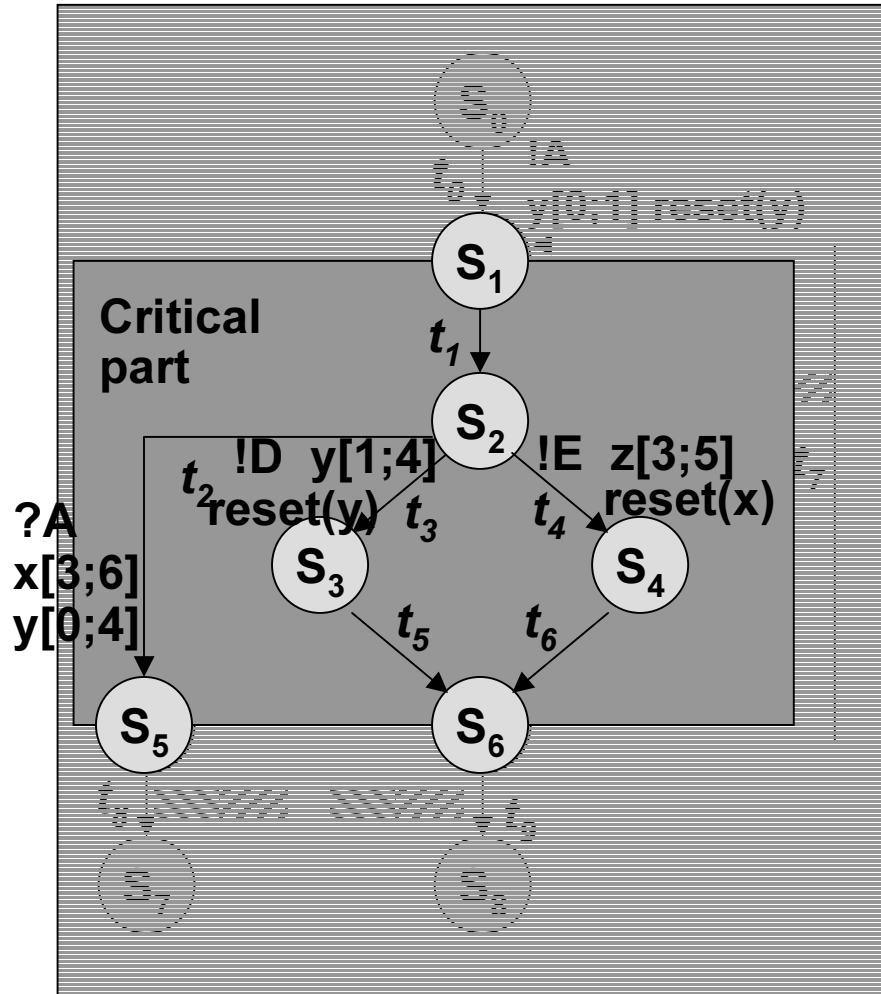
Partial model  
 $PM_1$



Partial model  
 $PM_2$

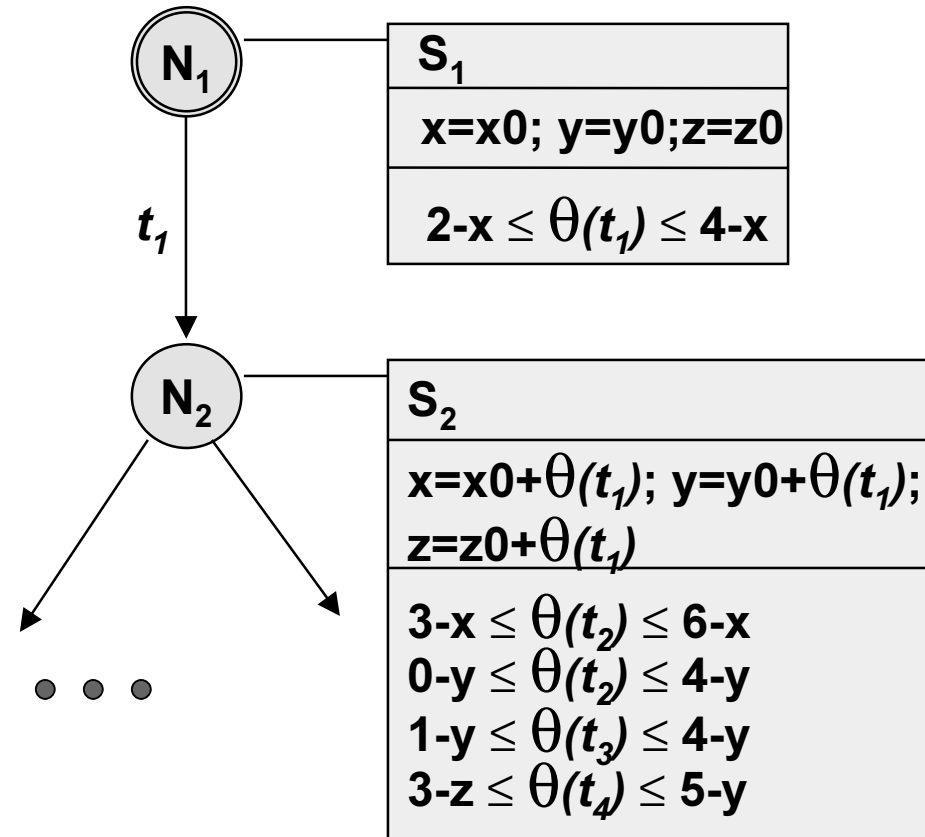


# 4 - Validation a priori - Hybrid Method



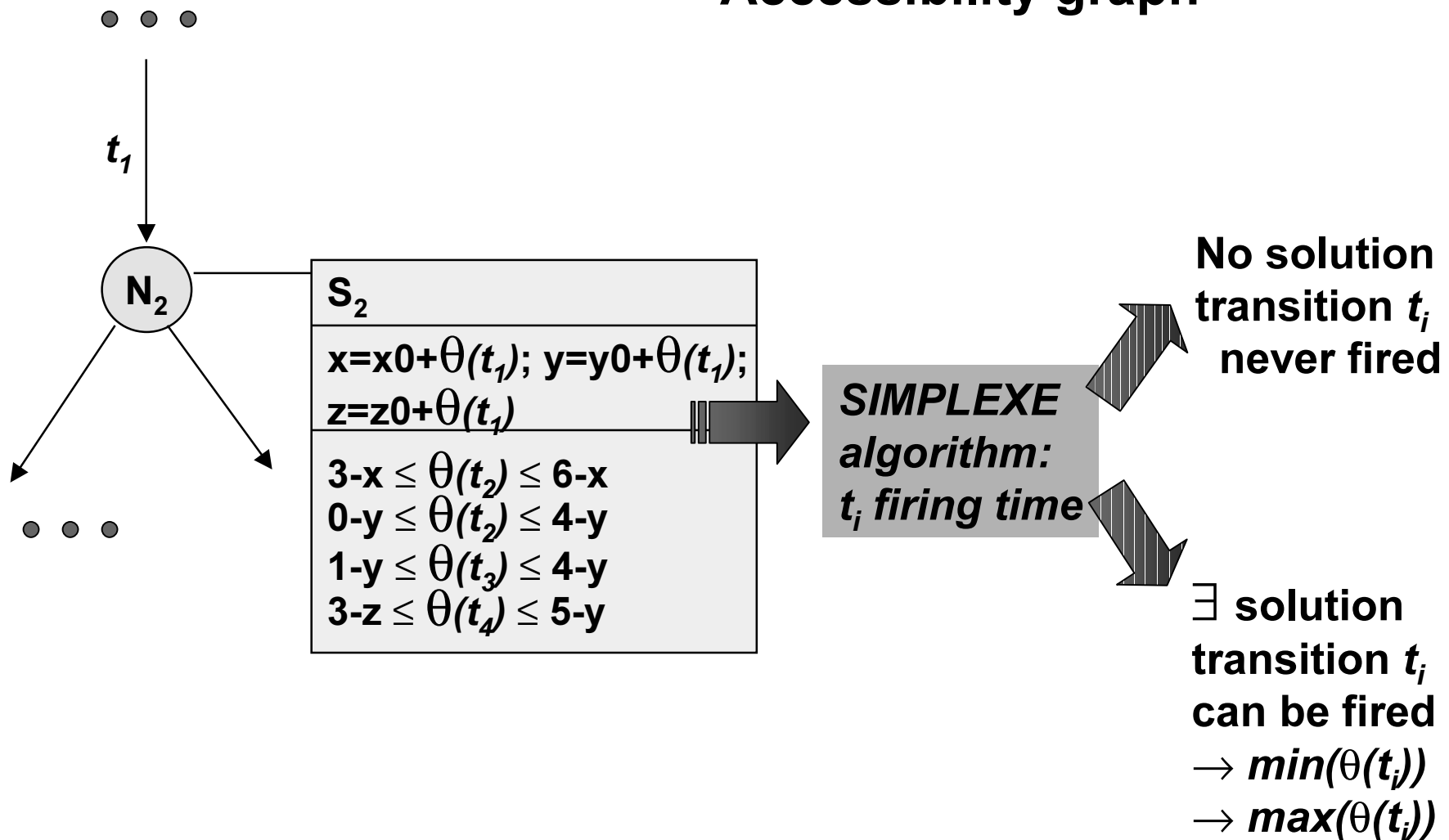
## Accessibility graph

Set of clocks :  $C = \{x,y,z\}$



# 4 - Validation a priori - Hybrid Method

## Accessibility graph

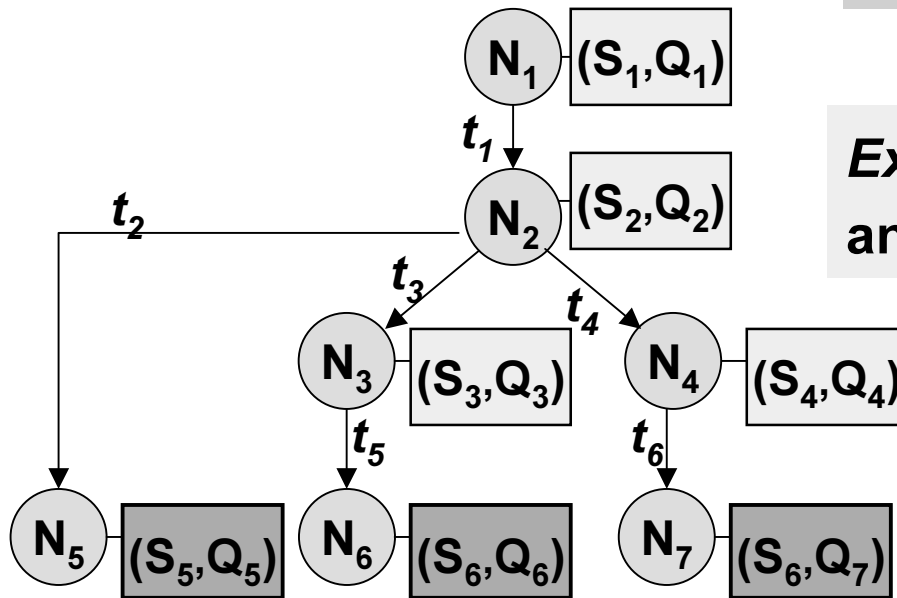


# 4 - Validation a priori - Hybrid Method

## Accessibility graph

*Exit states of partial model* : {S5, S6}

*Exit Nodes* : node characterized with an exit state



Every exit node can be reached

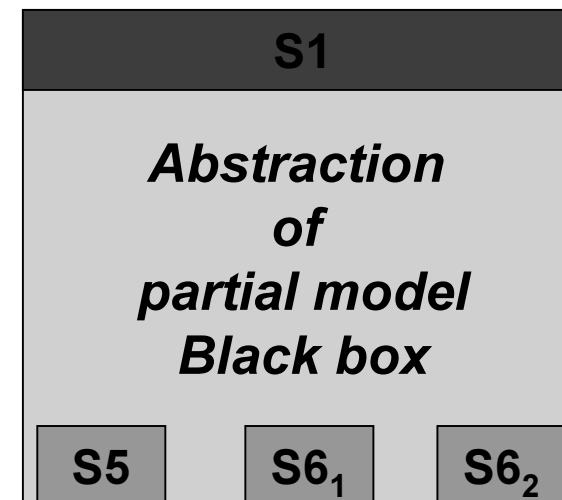
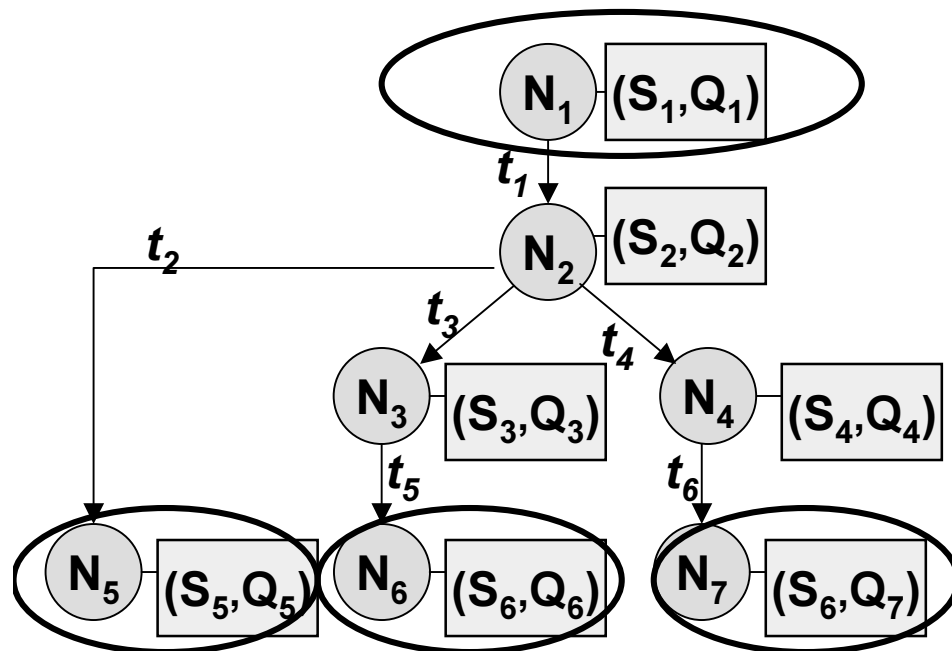
➔ **Success**

One exit node cannot be reached

➔ **Fail**

# 4 - Validation a priori - Hybrid Method

Partial model	Accessibility graph	Abstraction of partial model
Initial state : $S_1$	Initial node : $N_1 = (S_1, Q_1)$	Initial state : $S_1$
Exit state : $S_i$	Node : $N_k = (S_i, Q_i)$	Exit state : $S_{i,l}$



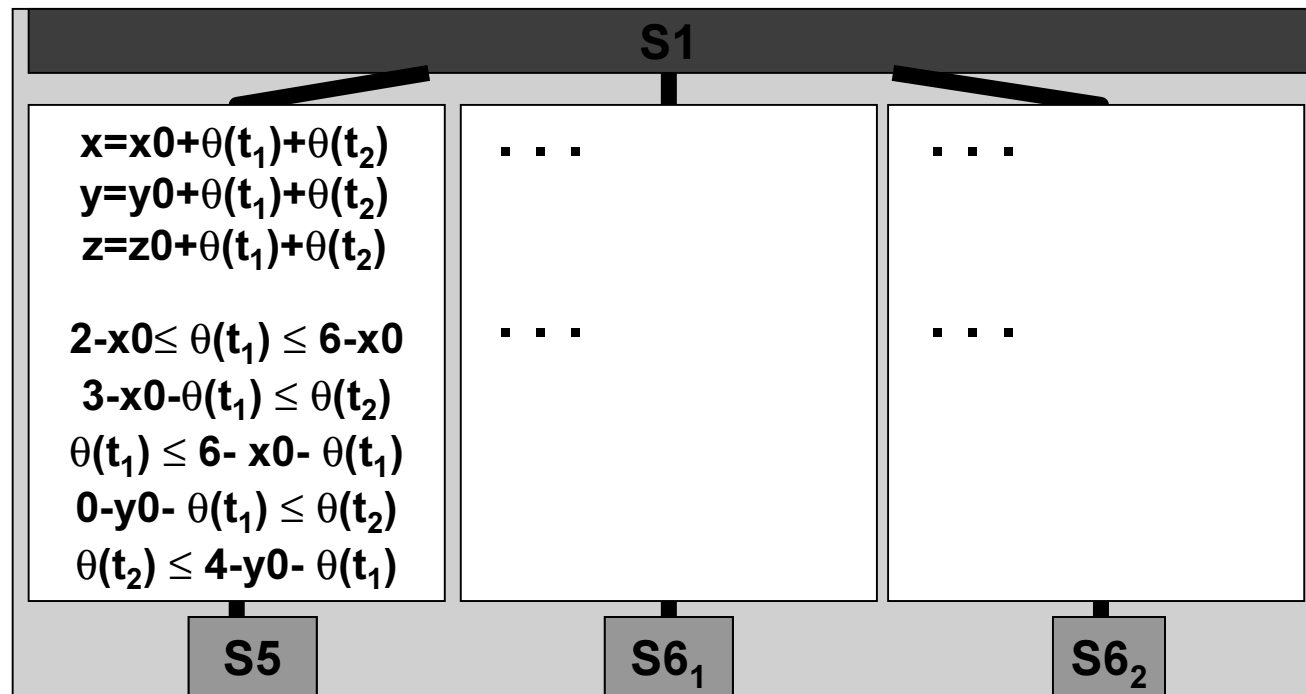


# 4 - Validation a priori - Hybrid Method

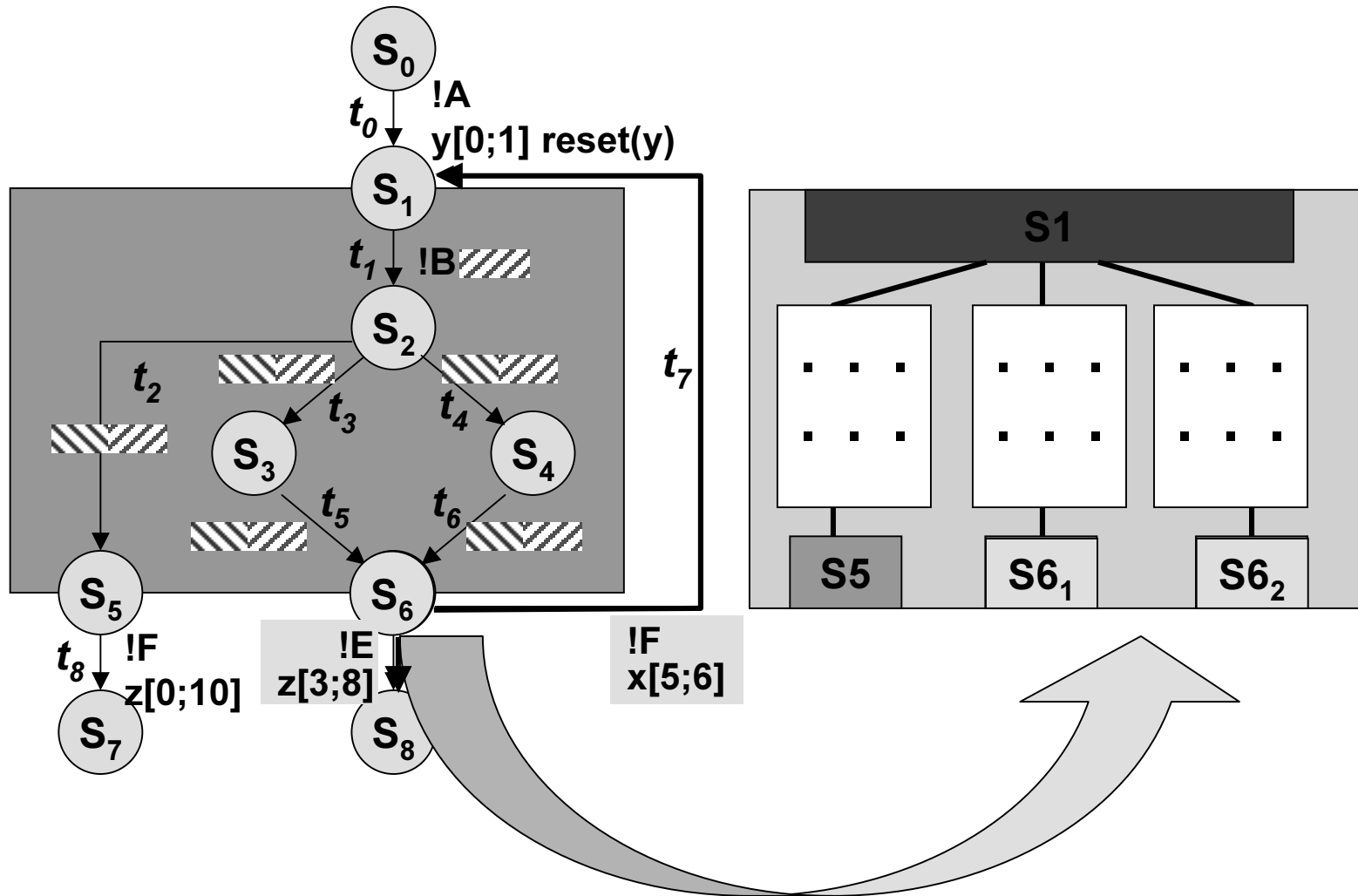
For each exit state  $S$

Value of each clock when reaching this state

Constraints on clocks along the path from init state to  $S$

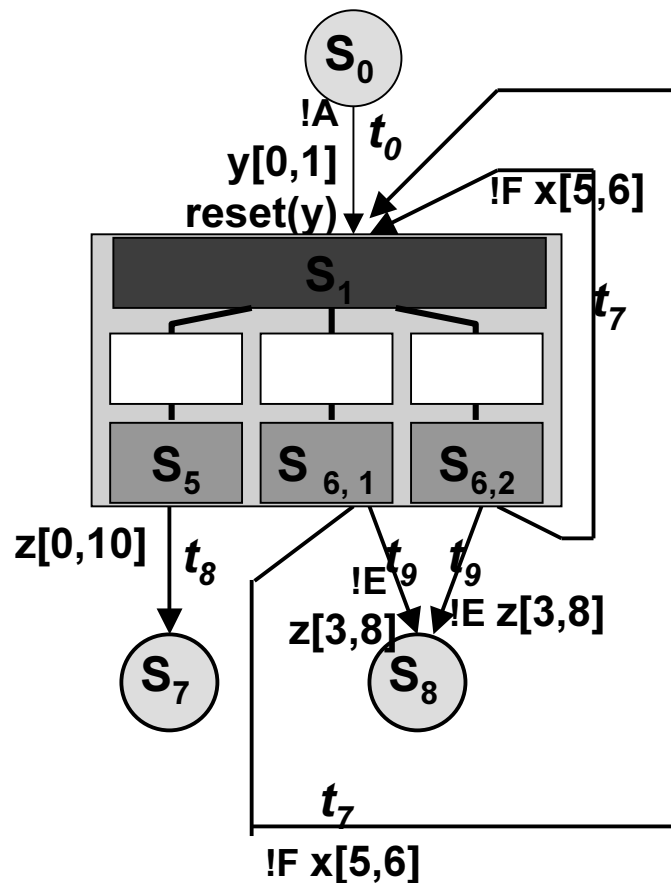


# 4 - Validation a priori - Hybrid Method

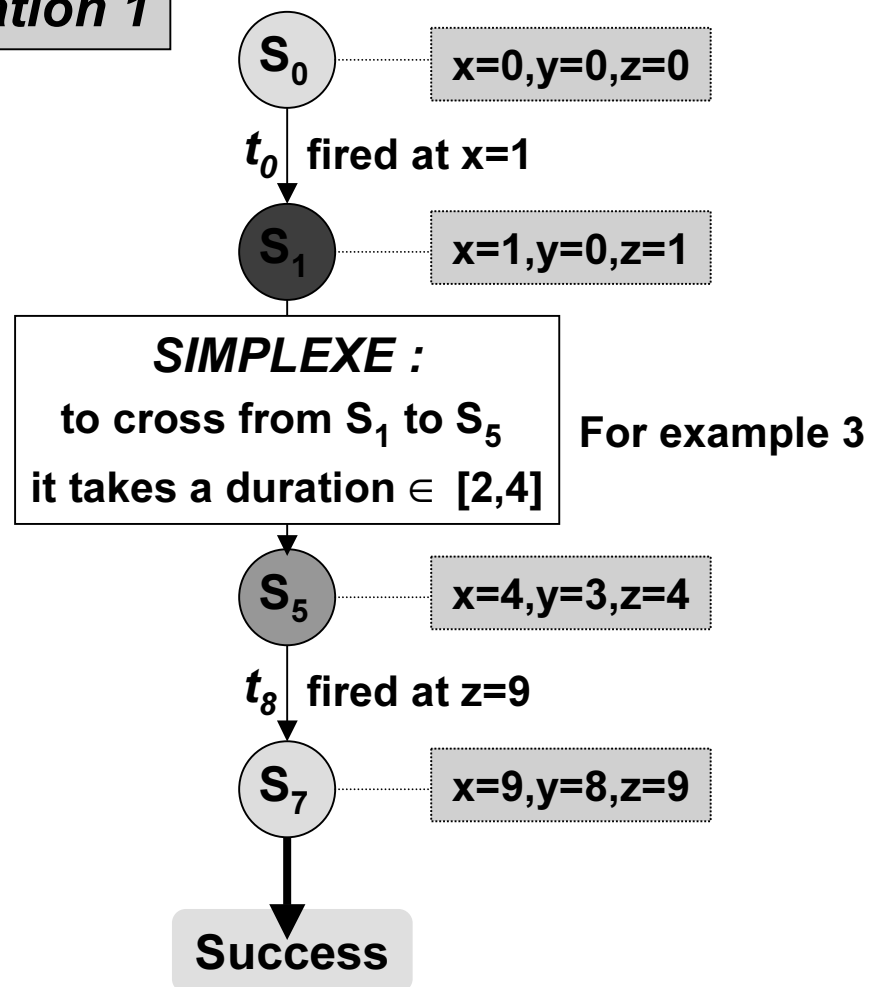


# 4 - Validation a priori - Hybrid Method

## Derived model

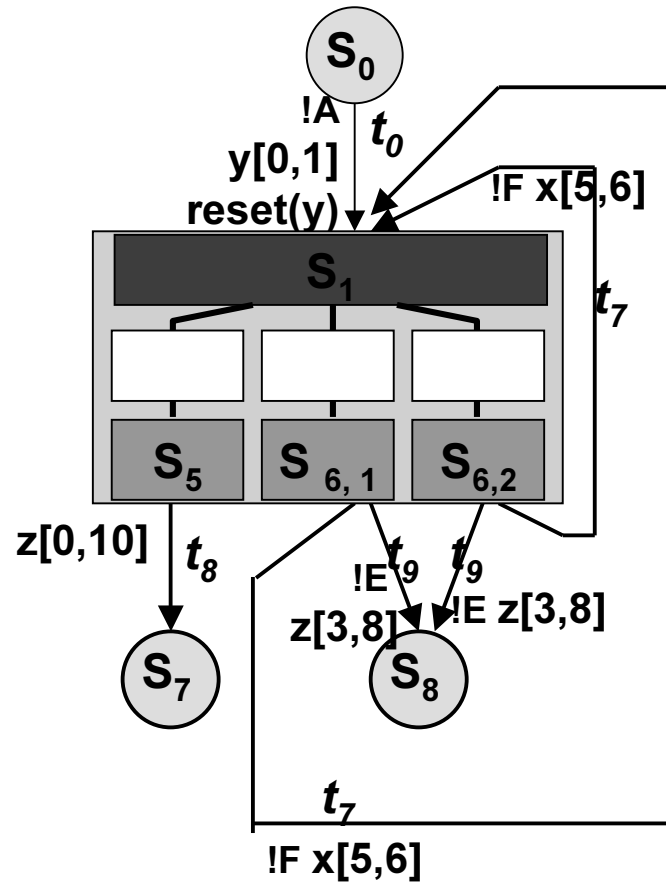


## Simulation 1

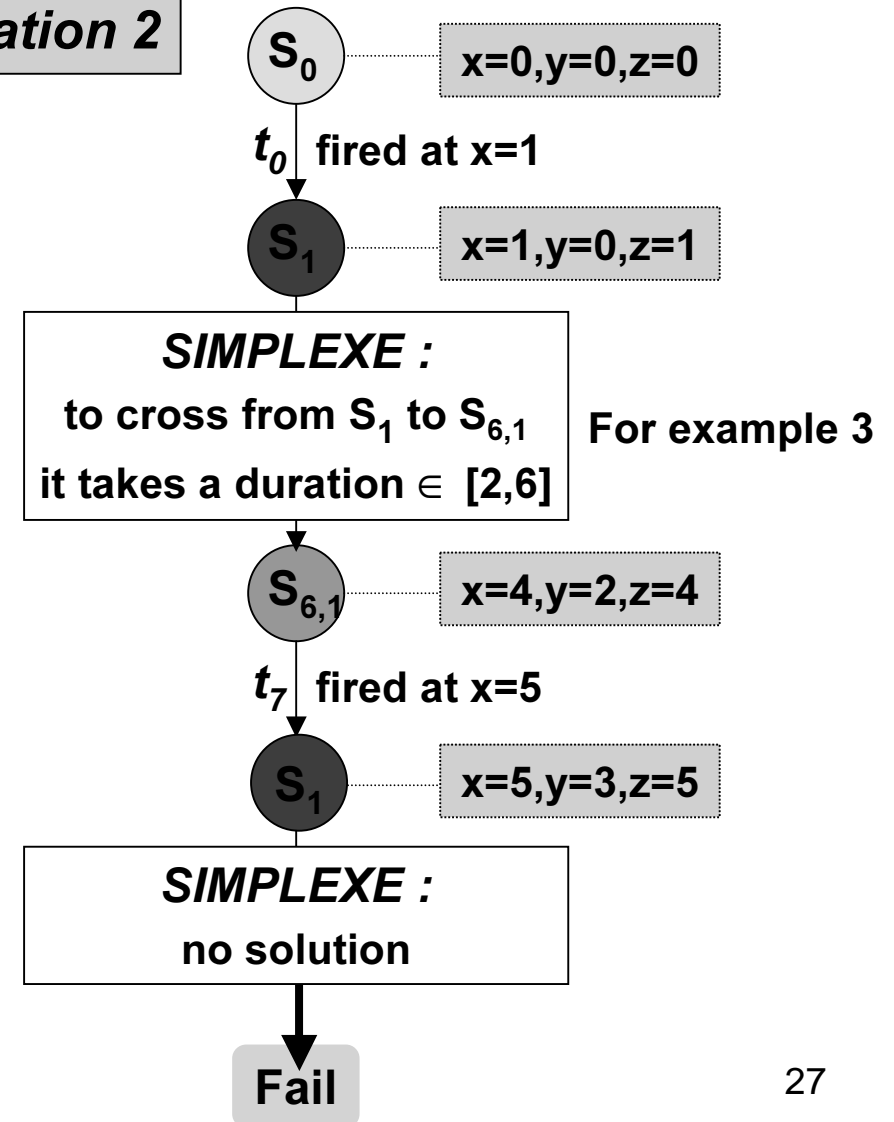


# 4 - Validation a priori - Hybrid Method

## Derived model



## Simulation 2

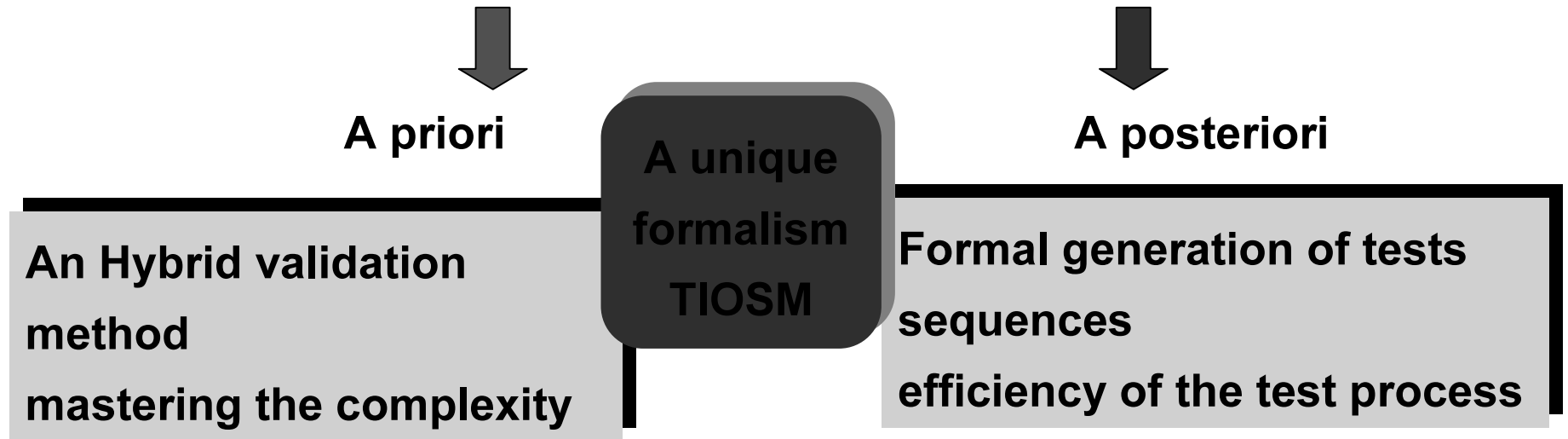


# 4 - Validation a priori - Hybrid Method

- **Conclusions**

- **A validation method decreasing the complexity**
- **Simulation and Exhaustive analysis**

# 5 - Validation of Real Time Systems



## Future trends

- ◆ *Composition / communication between critical parts*
- ◆ *COTS (Components off-the-shelf)*
- ◆ *Industrial Tester - CANoe (TTCN)*