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Incremental Generation of Linear Invariants for Component-Based Systems

Saddek Bensalem, Marius Bozga  
UJF-Grenoble 1 / CNRS, VERIMAG UMR 5104  
Grenoble, France  
FirstName.LastName@imag.fr

Benoît Boyer, Axel Legay  
INRIA/IRISA  
Rennes, France  
FirstName.LastName@inria.fr

Abstract—Invariants generation has been intensively considered as an effective verification method for concurrent systems. However, none of the existing work on the topic strongly exploits the structure of the system and the algebra that defines the interactions between its components. This not only has an impact on the computation time, but also on the scalability of the method. In a series of recent work, we developed an efficient approach for generating invariants for systems described in the BIP component framework. BIP is an expressive modeling formalism including a rich algebra to describe component interactions. Our technique, which focuses on generating Boolean invariants corresponding to a subclass of the conjunctive normal form, was then extended to an incremental one capable of generating global invariants from smaller invariants obtained for sub-systems by exploiting the algebra that describes their interactions. This approach gives a panoply of techniques and libraries to rigorously design potentially complex systems. We also showed that Boolean invariants generated by our methodology correspond to trap of the Petri net induced by the BIP model. Unfortunately, this class of invariants may be too unprecise, and hence leads to discovery of false positive counter examples. The objective of this paper is to propose new techniques dedicated to the computation of linear interactions invariants, i.e., invariants that are described by linear constraints and that relate states of several components in the system. By definition, such new class is incomparable to the one of Boolean invariants, but we will show that it is generally more precise. In addition, we propose an incremental approach that allows to discover and reuse invariants that have already been computed on subparts of the model. Those new techniques have been implemented in DFIINDER, a tool for checking deadlock freedom on BIP systems using invariants, and evaluated on several case studies. The experiments show that our approach outperforms classical techniques on a wide range of models.

Keywords-component-based systems; model-checking; invariants generation; linear algebra.

I. INTRODUCTION

Component-based design confers numerous advantages, in particular, an increased productivity through reuse of existing components. Nonetheless, establishing the correctness of the designed systems remains an open issue. In contrast to other engineering disciplines, software and system engineering badly ensures predictability at design time. Consequently, a posteriori verification as well as empirical validation are essential for ensuring correctness. Monolithic verification [1], [2] of component-based systems is a challenging problem. It often requires computing for a composite component the product of its constituents by using both interleaving and synchronization. The complexity of the product system is often prohibitive due to state explosion. A solution to this problem is to generate an invariant that is an abstraction of the state-space of the system. We observed that most of the existing work on generating invariants for component-based systems are too general and do not strongly exploit the structure of the system and the algebra that defines the interactions between its components. In a series of recent work [3], [4], [5], we proposed novel approaches and the DFIINDER tool [6] for generating invariants for systems described in the BIP framework [7]. BIP is an expressive modeling formalism equipped with a rich algebra to describe component interactions. Our techniques start by building invariants for individual components, which can be done with any existing approach for invariants generation on sequential programs. The novel concept in DFIINDER is that the invariant for the overall system is then obtained by glueing this set of individual invariants with another one that is an abstraction of the algebra used to define the interactions between the components. By doing so, one avoids building huge part of the state-space before generating the invariant. One of the major advantages of our approach is that it allows for the development of incremental techniques such as [5] capable of reusing invariants that have already been computed on subparts of the model. The incremental approach is particularly useful when multiple instances of the same components (atomic or composite) are used in the system. In such cases, it allows to factorize some part of the analysis. Thus, local invariants established on some part of the system can be automatically lifted to all similar parts within the system. Until now, the DFIINDER approach has been limited to invariants that can be represented by conjunctive normal forms, called here Boolean Invariants. This representation, which corresponds to the traps of the Petri net induced by the BIP model [3], has been shown to be convenient in many contexts, going from simple to complex case studies.
However, there are situations where Boolean invariants may not be appropriate. Consider the state variable \( at_i \), which monitors that (local) control state \( l_i \) of some process is currently active. Whatever the transition relation of the system is, \textsc{dfinder} will only be able to generate invariants of the form e.g., \( at_{l_1} \lor at_{l_2} \lor at_{l_3} \). Such an invariant ensures that one of the control states \( l_1, l_2, l_3 \) is active, which is sometimes sufficient to infer the deadlock freeness. However, such invariants (which cannot count) are not precise enough to prove a mutual exclusion property. Here, what is needed is an invariant that guarantees that at most one process is in its critical section.

Hence, to reason on such more complex properties, we have to work with invariants capable of \emph{counting} how many processes are at a given states. A way to do this is to use linear invariants, i.e., invariants that can be represented by sets of linear equations. Such invariants have already been studied for a wide range of models for concurrent systems, and in particular for Petri Nets[9]. The objective of this paper is to propose new methods for linear invariants generation in \textsc{bip}. As a first contribution, we lay out a new framework to specify such invariants within the incremental structure proposed by the \textsc{bip} framework. We then focus on computing linear invariants. Our methods build on transitions of components that are abstracted by linear equations and then combined to form a system of equations. We show that each solution of such system is a linear invariant. Solving systems of linear equations can be done with classical techniques such as Gauss-Jordan elimination or \textsc{lu}-factorization. However, those general approaches do not exploit the structure of the system under consideration and may scale badly on large size systems. As a solution to this scalability problem, we propose an online algorithm that processes equations in the system in an iterative manner. The advantage of this algorithm, which is rather a trivial adaptation from [10], is that its structure eases the design of a new and efficient incremental approach for linear invariants. Concretely, the second main contribution of this paper is a new incremental approach to generate linear invariants by exploiting the incremental design process offered by the \textsc{bip} language. This new approach clearly exploits the framework from [5], but it requires a new decomposition methodology due to the nature of invariants we intend to generate.

Finally, our last contribution is the implementation and experimental evaluation of these novel technique as an extension of the tool \textsc{dfinder}. This new version was then evaluated on several case studies. Contrary to the \textsc{dfinder} approach for Boolean invariants that relies on symbolic techniques, our new approach relies on sparse matrices that fully exploit the structure of our algorithms. The experiments show how our approaches outperform classical techniques on a wide range of models. Particularly, our method is as efficient as the one to compute Boolean invariants, and it allows for finer state-space approximations (hence removing more spurious counter-examples). We also make comparison with a classical mathematical approach.

\textbf{Related Work:} The literature on generation of Boolean invariants for \textsc{bip} and comparison with other works is wide and partly covered in [3], [5]. There exists an huge amount of literature on automatic generation of linear invariants for different categories of systems and/or programs. In fact, first results have been obtained in the context of hardware systems (see e.g. [11]). The main difference with our work is that we exploit a rich component-based design language that is clearly more expressive than classical Boolean circuits.

Work on discovery of linear relations between variables of a sequential program dates back to early days of program verification [12]. Linear invariants have received particular attention for generation methods derived from abstract interpretation [13]. In the former, linear constraints are definitely among the most useful, expressive abstract domain for program analysis.

The work on algebraic methods for the generation of so called linear state-invariants for Petri net models is perhaps the most closest to ours. An introductory survey can be found in [14] while several extensions for invariants generation under particular constraints are described in [15]. These methods have been implemented since a long time and tools like \textsc{charlie} [9] are widely known in the Petri net community. While being the most known, these techniques are however neither compositional nor incremental: the invariants generation problem is directly rephrased as linear algebra problem and solved using standard methods.

Another method for generating linear invariants for Petri nets has been explored in [16]. This method relies on Farkas lemma as an effective mean for quantifier elimination. Invariant computation is carried transition by transition, and therefore avoid a global computation phase. Nonetheless, this method is not incremental and can be applied only once the system has been entirely constructed. The main difference with other works is also the full exploitation of the very expressive input language of the \textsc{bip} toolset.

\textbf{Structure of the paper:} Section II recalls some basic definitions used throughout the rest of the paper. Section III introduces the component-based framework as well as the basic principles for compositional and incremental design. Section IV defines linear invariants and discuss their global generation. Section V presents a novel method for incremental generation. Finally, section VI review implementation and the experimental work done to validate the approach.

\section{Preliminaries}

We denote respectively by \( \mathbb{Z} \) and \( \mathbb{Q} \) the sets of integer and rational numbers. We consider \emph{homogeneous linear systems} \( S \) of the form \( S = \bigwedge_{i=1}^{m} \left( \sum_{j=1}^{n} a_{ij} x_j = 0 \right) \) where \( x_j \) are integer unknowns and \( a_{ij} \in \mathbb{Z} \) are integer coefficients, for all \( 1 \leq j \leq n \), \( 1 \leq i \leq m \). Such systems are compactly denoted as \( Ax = 0 \) where \( A = (a_{ij})_{1 \leq i \leq m, 1 \leq j \leq n} \in \mathbb{Z}^{m \times n} \).
is the matrix of coefficients, \( x = (x_j)_{1 \leq j \leq n} \) is the vector of unknowns and 0 is the null vector in \( \mathbb{Z}^m \). A vector of integers \( u \in \mathbb{Z}^n \) is a solution of the system if it satisfies \( Au = 0 \). We denote with \( Sol(S) \) the set of solutions of the system \( S \). Two systems \( S_1 \) and \( S_2 \) are called equivalent and denoted by \( S_1 \approx S_2 \) if they have the same set of solutions, that is, \( Sol(S_1) = Sol(S_2) \). For any system \( S \), the set of solutions contains at least the trivial solution which is the null vector \( 0_n \) in \( \mathbb{Z}^n \). Moreover, if the set \( Sol(S) \) contains non-trivial solutions, then it is infinite. In this latter case, we call \( solution \ basis \) any minimal (w.r.t. inclusion) set of solutions \( \{ u_k \}_{k \in K} \subseteq Sol(S) \) that allows to generate \( Sol(S) \) as linear combinations with rational coefficients, formally such that \( Sol(S) = \{ \sum_{k \in K} \lambda_k u_k \mid \lambda_k \in \mathbb{Q} \} \cap \mathbb{Z}^n \). We know from linear algebra that, for any system \( S \), a solution basis with at most \( n \) elements always exists. Such a basis can be effectively computed by using e.g., Gauss-Jordan elimination to transform the system (with an appropriate renaming of variables) into an equivalent solved (or left-bound) system \( S' \) of the form \( S' = \bigwedge_{i=1}^{m'} (a_{ii}' x_i = \sum_{j=m+1}^{n} a_{ij}' x_j) \) where \( m' \leq m \), \( a_{ii}' \neq 0 \) for all \( 1 \leq i \leq m' \). A basis is obtained immediately from the solved form by selecting the set of solutions \( \{ u_k \}_{m'+1 \leq k \leq n} \) such that \( u_{ki} \) is equal to \( (1) \ a_{ii}' \) for all \( 1 \leq i \leq m' \), \( (2) \lambda \), if \( i = k \) and \( (3) \ 0 \), for all \( m'+1 \leq i \neq k \leq n \) and where \( L = lcm\{a_{ii}' \mid 1 \leq i \leq m' \} \). For example, the system \( 2x_1 + 3x_3 - x_4 = 0 \land x_2 - 5x_3 + 2x_4 = 0 \land 4x_3 + x_2 + x_3 = 0 \) can be transformed into the left bound form \( 2x_1 = -3x_3 + x_4 \land x_2 = 5x_3 - 2x_4 \) which gives the basis \( \{ u_3, u_4 \} \) where \( u_3 = [-3, 10, 2, 0] \) and \( u_4 = [1, -4, 0, 2] \).

III. COMPONENT-BASED DESIGN

In this section, we introduce the underlying concepts for modeling and design of component-based systems.

Our component-based framework is a fragment of the BIP framework [7]. The BIP - Behavior, Interaction, Priority - framework allows description of complex, heterogeneous systems in a hierarchical and compositional manner. BIP supports a modeling methodology based on the assumption that components are obtained as the superposition of three layers, that is:

- behavior, specified as a set of automata extended with C data and functions,
- interactions between the automata, modeled as sets of structured connectors,
- priorities used to schedule among possible interactions.

In this paper, we restrict ourselves to a strict fragment of BIP, that is, without data and without priorities. In fact, we have previously shown in [3] how data can be taken into account for computing invariants through abstraction. Regarding priorities, we do not consider them, however, let us remark that priorities preserve invariant properties and deadlock-freedom [17].

In the rest of the section, we recall the most relevant concepts useful in this context, that is, atomic components and their parallel composition through interactions. Then, we recapitulate a recent methodology proposed in [18] for incremental design of component-based systems with BIP.

A. Components and Interactions

In our setting, atomic components are labeled transition systems. Transitions’ labels are called ports and are used to interact with other components.

Definition 1 (Atomic Component): An atomic component is a transition system \( B = (L, P, T) \), where \( L = \{ l_1, l_2, \ldots, l_k \} \) is a set of locations, \( P \) is a set of ports, and \( T \subseteq L \times P \times L \) is a set of transitions.

Without loss of generality, we assume that, every port \( p \) labels exactly one transition \( \tau_p \in T \). Given \( \tau_p = (l, p, l') \in T \), \( l \) and \( l' \) are the source and destination locations for \( \tau \). These locations are equally denoted respectively as \( \tau \) and \( \tau' \).

**Example 1**: Figure 1 presents a simplified variant of the Reader-Writers problem with four atomic components \( P_1, P_2, P_3 \) and Lock. The ports of component \( P_1 \) are \( p_1, q_1, r_1 \). \( P_1 \) has three locations \( l_{11}, l_{12}, l_{13} \) and three transitions \( \tau_1 = (l_{11}, p_1, l_{12}) \), \( \tau_2 = (l_{12}, q_1, l_{13}) \) and \( \tau_3 = (l_{13}, r_1, l_{11}) \). Atomic components are running in parallel and communicate via interactions, i.e., by synchronization on ports. Formally, interactions and connectors are defined as follows.

Definition 2 (Interaction, Connector): Let \( \{ B_i = (L_i, P_i, T_i) \}_{i=1}^n \) be a set of atomic components with sets of locations and ports pairwise disjoint, that is, \( L_i \cap L_j = \emptyset \) and \( P_i \cap P_j = \emptyset \) for all \( i \neq j \). An interaction \( a \) is a set of ports, that is, a subset of \( \bigcup_{i=1}^n P_i \), such that \( \forall i = 1, \ldots, n. |a \cap P_i| \leq 1 \). A connector \( \gamma \) is a set of interactions \( \{a_1, \ldots, a_m\} \).

For the sake of simplicity, we write \( p_1 p_2 \ldots p_k \) to denote the interaction \( \{p_1, p_2, \ldots, p_k\} \). We also write \( a_1 \oplus \ldots \oplus a_m \) for the connector \( \{a_1, \ldots, a_m\} \).

**Example 2**: Graphically, interactions are represented by links between ports. The connector represented in Figure 1 consists of six binary and one ternary interactions,
respectively $p_1s \oplus p_2s \oplus p_3s \oplus q_1t \oplus q_2t \oplus q_3t \oplus r_1r_2r_3$.

We use parallel composition parameterized by a connector $\gamma$ to build composite components from atomic components. Any global step of the composite component corresponds to an interaction $a$ of $\gamma$. For any such interaction $a$, only those components that are involved in $a$ can make a step. This is ensured by following a transition labelled by the port used in $a$. If a component does not participate to the interaction, then it remains in the same location.

Definition 3 (Composite Component): Given a set of atomic components $\{B_i = (L_i, P_i, T_i)\}_{i=1}^{n}$ and a connector $\gamma$, we define the composite component $B = \gamma(B_1, \ldots, B_n)$ as the transition system $(\mathcal{L}, \gamma, \mathcal{T})$, where:

- $\mathcal{L} = L_1 \times L_2 \times \ldots \times L_n$ is the set of global states,
- $\gamma$ is the set of interactions, and
- $\mathcal{T} \subseteq \mathcal{L} \times \gamma \times \mathcal{L}$ contains all global transitions $\tau = ((l_i, \ldots, l_n), a, (l'_i, \ldots, l'_n))$ obtained by synchronization of sets of transitions $\{\tau_i = (l_i, p_i, l'_i) \in T_i\}_{i \in I}$ such that $\{p_i\}_{i \in I} = \gamma$ and $l'_j = l_j$ if $j \notin I$.

We denote by $\ell \xrightarrow{\gamma} \ell'$ transitions $(\ell, a, \ell') \in \mathcal{T}$. We say that a global state $\ell$ is reachable from an initial global state $\ell_0$ if there exist a sequence of interactions $a_1, \ldots, a_k$ and global states $\ell_1, \ldots, \ell_k$ such that $\ell_0 \xrightarrow{a_1} \ell_1 \xrightarrow{a_2} \ldots \xrightarrow{a_k} \ell_k = \ell$.

Moreover, we extend the notion of source and destination to interactions and denote $a = \{p_1^{\gamma} | p \in a\}$ and $a^\ast = \{t^{\gamma} | t \in a\}$.

Example 3: The example given in Figure 1 presents the composite component $\gamma(P_1, P_2, P_3)$ where $\gamma = p_1s \oplus p_2s \oplus p_3s \oplus q_1t \oplus q_2t \oplus q_3t \oplus r_1r_2r_3$.

Let us observe also that any composite component $B = \gamma(B_1, \ldots, B_n)$ can be equivalently seen as a 1-safe Petri net whose set of places is $L = \bigcup_{i=1}^{n} L_i$, that is, the set of locations of $B$, and whose transition relation is given by $\mathcal{T}$.

B. Incremental Design

In component-based design, the construction of a composite system is both step-wise and hierarchical. Systems are usually obtained from atomic components by successive additions of new interactions also called increments. We have proposed in [18] a methodology to add new interactions to a composite component without breaking the existing synchronization. This way, properties enforced by synchronization at some step in the design flow are never lost in successive steps when increments are added.

In our theory, a connector describes a set of interactions and, by default, all those interactions where only one component can make progress. This assumption allows us to define new increments only in terms of existing interactions.

Definition 4 (Increments): Consider a connector $\gamma$ over atomic components $B_1, \ldots, B_n$ and let $\delta \subseteq 2^\gamma$ be a set of interactions. We say $\delta$ is an increment over $\gamma$ if for any interaction $a \in \delta$ there exists disjoint interactions $b_1, \ldots, b_n \in \gamma$ such that $\bigcup_{i=1}^{n} b_i = a$.

In a dual manner, when increments are used, one has also to make sure that existing interactions in $\gamma$ will not break the synchronizations that are enforced by the increment $\delta$.

Formally, we have the following definition.

Definition 5 (Layering): Given a connector $\gamma$ and an increment $\delta$ over $\gamma$, the set of interactions obtained by combining $\delta$ and $\gamma$, also called layering (or incremental modification of $\gamma$ by $\delta$), is given by the set $\delta \gamma = (\gamma \setminus \delta^f) \oplus \delta$ where $\delta^f = \{a \mid a \notin \delta \land \exists b \in \delta. a \subseteq b\}$ is the set of interactions forbidden by $\delta$.

Example 4: The connector $\gamma$ illustrated in Figure 1 can be obtained by successive layering from $\gamma_\perp = p_1 + q_1 + r_1 + p_2 + q_2 + r_2 + p_3 + q_3 + r_3 + s + t$.

That is, $\gamma = \delta_3 \delta_2 \delta_1 \perp$ where (i) increment $\delta_1 = \{p_1s, c_1t, s, t\}$ corresponds to synchronization of $P_1$ and Lock on $p_1s$ and $q_1t$ while leaving open $s$ and $t$ for further interactions (ii) increment $\delta_2 = \{r_1r_2r_3\}$ corresponds to synchronization of $P_2$ and $P_3$ and (iii) finally, increment $\delta_3 = \{p_2s, p_3s, q_2t, q_3t, r_1r_2r_3\}$ enforces the remaining interactions between respectively $P_2, P_3, Lock$ and $P_1, P_2, P_3$. This incremental construction is illustrated in Figure 2.

IV. LINEAR INVARIANTS

Let $B = \gamma(B_1, \ldots, B_n)$ be a composite component obtained by parallel composition using connector $\gamma$ of atomic components $\{B_i = (L_i, P_i, T_i)\}_{i=1}^{n}$. Let $(\mathcal{L}, \gamma, \mathcal{T})$ be the transition system associated to $B$, as defined by definition 3. Let $\ell_0$ be an initial global state of $B$, fixed.

We consider the set $At$ of location variables $\{at \mid l \in L = \bigcup_{i=1}^{n} L_i\}$. At any global state $\ell = (l_1, l_2, \ldots, l_n) \in \mathcal{L}$, each location variable of $At$ is assigned to a binary value through the valuation function $\sigma_{\ell} : At \rightarrow \{0, 1\}$. This function characterizes the global state $\ell$ by mapping to 1 (resp. 0) variables corresponding to locations (resp. not) in $\ell$. Formally $\sigma_{\ell}(at \mid l) = 1$ iff $l \in \{l_1, l_2, \ldots, l_n\}$ and $\sigma_{\ell}(at \mid l) = 0$ otherwise.
We consider linear equality constraints of the form \( \sum_{l \in L} u_l \cdot a_{lT} = u_0 \) built from location variables and with integer coefficients \( u_0, u_l \in \mathbb{Z} \) for all \( l \in L \). By abuse of notation, we interpret \((u_l)_{l \in L}\) and \((a_{lT})_{l \in L}\) as vectors and we denote more compactly the constraints above as \( u^T \cdot At = u_0 \).

Similarly, we define the particular vector \( At_0 \) as \( \sigma_{\ell_0}(At) \) which denotes the initial valuation of variables at \( \ell_0 \).

**Definition 6 (Linear Invariant):** A linear invariant is a linear equality constraint \( u^T \cdot At = u_0 \) which holds in all reachable global states of the composite component, that is, for all \( \ell \) reachable from \( \ell_0 \) it holds \( \sum_{l \in L} u_l \cdot \sigma_{\ell}(a_{lT}) = u_0 \).

Observe that linear invariants are different from the model of BIP Boolean invariants proposed in [3], that corresponds to conjunctive normal forms. BIP Boolean invariants are by definition incomparable with BIP linear invariants.

**Example 5:** In the example of Figure 1, the equality constraint \( a_{l12} \cdot l_{12} + a_{l22} \cdot l_{22} + a_{l32} \cdot l_{32} + a_{l41} \cdot l_{41} = 1 \) is a linear invariant for the composite component with initial global state \((l_{11}, l_{21}, l_{31}, l_{41})\). This linear invariant characterises a mutual exclusion property, that is, at most one process \( P_1, P_2, P_3 \) is in its critical location respectively \( l_{12}, l_{22}, l_{32} \) at any time.

If not empty, the set of linear invariants is infinite. For instance, it can be easily checked that if \( u^T \cdot At = u_0 \) is a linear invariant, so is \( (\lambda u^T) \cdot At = (\lambda u_0) \) for any integer coefficient \( \lambda \in \mathbb{Z} \). In order to provide a finite representation of such sets, we introduce the notion of basis of linear invariants, as follows.

**Definition 7 (Basis of Linear Invariants):** Let \( I \) be a set of linear invariants. A finite subset \( I_0 \subseteq I, I_0 = \{u^T \cdot At = u_0\}_{k \in K} \) is a basis for \( I \) if and only if for all invariant \( u^T \cdot At = u_0 \), \( I \) there exists rational coefficients \( \lambda_k \cdot k \in K \) such that \( u = \sum_{k \in K} \lambda_k u_k \) and \( u_0 = \sum_{k \in K} \lambda_k u_{0k} \).

**A. Automatic Generation of Linear Invariants**

Consider a composite component \( B = \gamma(B_1, \ldots, B_n) \) with associated transition system \( (L, \gamma, T) \) and initial state \( \ell_0 \).

In this section, we introduce the global method to compute linear invariants from solutions of the homogeneous system of flow equations which characterizes \( B \). While this first algorithm is a rather trivial extension from [10], we shall see in Section V that its structure ease the design of a new and efficient incremental approach for linear invariants.

We first introduce characteristic System, that is a system of linear equations representing the interactions within the BIP model. We then show that solutions of the characteristic systems are indeed linear invariants. This means that computing linear invariants reduces to solving a system of linear equations. Latter, we propose an efficient version of the Gauss-Jordan algorithm that exploits the structure of our specification language.

**Definition 8 (Characteristic System):** For a finite set of atomic components \( B_1, \ldots, B_n \) synchronized by a connector \( \gamma \), the characteristic system \( S_G(\gamma, B_1, \ldots, B_n) \) is defined as the conjunction

\[
S_G(\gamma, B_1, \ldots, B_n) \equiv \bigwedge_{a \in \gamma} \big( \sum_{l \in I \ast} x_l - \sum_{l \in a} x_l = 0 \big)
\]

The unknowns \( x_l \) correspond to locations \( l \in L = \bigcup_{i=1}^n L_i \). The characteristic system introduces exactly one flow equation for each interaction \( a \) of the system.

**Example 6:** The characteristic system for Example 1 following the enumeration of interactions \( p_1s, p_2s, p_3s, q_1t, q_2t, q_3t, r_1r_2r_3 \) is

\[
S_G \equiv \{ x_{l12} - x_{l11} + x_{l42} - x_{l41} = 0 \\
x_{l22} - x_{l21} + x_{l42} - x_{l41} = 0 \\
x_{l32} - x_{l31} + x_{l42} - x_{l41} = 0 \\
x_{l13} - x_{l12} + x_{l43} - x_{l42} = 0 \\
x_{l23} - x_{l22} - x_{l43} - x_{l42} = 0 \\
x_{l33} - x_{l32} - x_{l43} - x_{l42} = 0 \\
x_{l11} + x_{l21} + x_{l31} - x_{l23} - x_{l33} = 0 \}
\]

We are now ready to show that solutions of the characteristic system are indeed linear invariants for the corresponding model.

**Theorem 1:** Any solution \( u \) of \( S_G \) defines the linear invariant \( u^T \cdot At = u^T \cdot At_0 \) of the composite component \( B \).

**Proof:** Regarding the composite component \( B \) as its equivalent Petri-Net \( PN \), the characteristic system of \( S_G \) is equivalent to the equation \( C^T x = 0 \), where \( C \) is incidence matrix of \( PN \). Each solution denotes an invariant of \( PN \) (c.f. [14]) and thus, an invariant of \( B \).

**Theorem 2:** Any set of invariants \( \{u^T \cdot At = u^T \cdot At_0\}_{k \in K} \) constructed from a solution basis \( (u_k)_{k \in K} \) of \( S_G \) is a basis for the set of all linear invariants obtained from \( S_G \).

**Proof:** Using the solution basis \( (u_k)_{k \in K} \), all solutions \( u \) can be expressed as a linear combination such that we have the invariant \( \sum_{k \in K} \lambda_k u^T_k \cdot At = \sum_{k \in K} \lambda_k u^T_k \cdot At_0 \). This invariant is trivially implied by the set of \( \{u^T_k \cdot At = u^T_k \cdot At_0\}_{k \in K} \).

The common techniques to solve homogeneous systems \( Ax = 0 \) are the Gauss-Jordan elimination, Cholesky-, QR- or LU-factorization. These general well-known algorithms have low polynomial complexity and can be directly applied to solve the characteristic system \( S_G \). Nonetheless, naive implementations may badly scale to realistic systems, in particular, if they do not consider carefully the structure and the sparsity of the characteristic systems.

To ensure scalability, we developed an online resolution algorithm (Algorithm 1 below) that processes equations in the characteristic systems iteratively, one by one, while producing an equivalent left-bound system. It is essentially a variant of Gauss-Jordan that exploits the locality of unknowns as well as the particular form of equations. In
addition to efficiency that will be illustrated in Table II, one of the major advantages of the new algorithm is that its structure can be exploited to derive an incremental version. This shall be the subject of the next section.

In the algorithm, function Rewit(eq, LeftB) returns the equation eq in which all bounded unknowns $x_i$ are substituted according to their definition $def_i$ given by $(x_i = def_i)$ in LeftB. Function Propagate is the dual of Rewrite. Propagate(LeftB, $x = def$) returns the system LeftB where all occurrences of the free (unbounded) unknowns $x$ are substituted by $def$. When solve(eq) is called, $eq \equiv \sum k_jx_j = 0$ contains only free unknowns. One of them is selected and the equation is rewritten into a solved form $x = def$. The choice is led by preferring the $x_j$ with the smallest absolute value for $k_j$.

Our algorithm has been implemented in DFinder. Experimental results and comparison with similar tools/methodologies are reported in section VI.

Algorithm 1 Online algorithm for direct resolution of $S_G$

1: $LeftB \leftarrow \emptyset \quad \triangleright \quad LeftB \equiv \bigwedge_{i \in J} (x_i = \sum_{j \in J} \lambda_{ij}x_j), \ I \cap J = 0$
2: while $\neg \text{finished}$ do
3: $eq \leftarrow \text{readEquation}()$
4: $eq \leftarrow \text{Rewrite}(eq, \text{LeftB}) \triangleright eq$ has the form $\sum_{j \in J} k_jx_j = 0$
5: if $\neg \text{trivial}(eq)$ then
6: $(x = def) \leftarrow \text{solve}(eq)$
7: $\text{LeftB} \leftarrow \text{Propagate}(\text{LeftB}, x = def)$
8: $\text{LeftB} \leftarrow \text{LeftB} \land (x = def)$
9: end if
10: end while
11: return $LeftB$

Example 7: Using Algorithm 1, the characteristic system $S_G$ given in Example 6 is transformed in left bound form shown below left. The solution basis extracted from the solved form generates $\mathcal{I}_0$ the basis of linear invariants.

$$S_G = \begin{cases} x_{l_{12}} = x_{l_{32}} + x_{l_{13}} - x_{l_{33}} \\ x_{l_{42}} = x_{l_{41}} - x_{l_{12}} + x_{l_{13}} \\ x_{l_{22}} = x_{l_{32}} + x_{l_{23}} - x_{l_{33}} \\ x_{l_{l_1}} = x_{l_{l_3}} \\ x_{l_{21}} = x_{l_{23}} \\ x_{l_{31}} = x_{l_{33}} \end{cases}$$

$$\mathcal{I}_0 = \begin{cases} al_{l_{12}} + at_{l_{12}} + al_{l_{11}} = 1 \\ al_{l_{23}} + at_{l_{23}} + al_{l_{21}} = 1 \\ al_{l_{33}} + at_{l_{33}} + al_{l_{31}} = 1 \\ al_{l_{41}} + at_{l_{41}} + al_{l_{42}} = 1 \\ al_{l_{l_2}} + at_{l_{l_2}} + al_{l_{l_1}} = 1 \end{cases}$$

V. INCREMENTAL APPROACH

We now present one of the major contributions of the paper, that is to exploit incremental design to ease the generation of linear invariants. In fact, the incremental approach allows to organize the computation of linear invariants by following the incremental design process. Actually, incremental design provides a natural and meaningful manner to split the global characteristic system and to optimize its resolution.

The incremental approach relies on construction and manipulation of incremental characteristic systems. For a composite component, this characteristic system characterizes both (1) the existing interactions defined inside and (2) the still open possibilities for further interaction (inside or with extra components).

Definition 9 (Incremental Characteristic System): For a finite set of atomic components $B_1, \ldots, B_n$ synchronized by a connector $\gamma$, the incremental characteristic system $S_I(\gamma, B_1, \ldots, B_n)$ is defined as the conjunction

$$S_I(\gamma, B_1, \ldots, B_n) \equiv \bigwedge_{i \in a} (\sum_{j \in a} x_l - \sum_{i \in a} x_l - y_a = 0)$$

The main difference with the global characteristic system is that, in addition to unknowns $x_l$ associated to locations $l \in L = \bigcup_{i=1}^n L_i$, the incremental system uses unknowns $y_a$ associated to interactions $a \in \gamma$. These unknowns are used to capture the (still) partial composition through $\gamma$. Every unknown $y_a$ can be interpreted as denoting the partial flow realized on interaction $a$ in the current composition by $\gamma$. Intuitively, any further extension of $\gamma$ through layering will simply add extra constraints on the $y_a$ unknowns, and preserve entirely the existing equations involving $x_l$ unknowns.

When the parallel composition is completed, that is, no more interactions are added, the global characteristic system can be obtained from the incremental system simply by substituting with the constant 0 all the unknowns that correspond to the interactions. We define this operation as freezing of interaction constraints.

Theorem 3 (Freezing): For every composite component $\gamma(B_1, \ldots, B_n)$, the characteristic system $S_G$ is obtained from the incremental characteristic system $S_I$ as follows:

$$S_G \approx (\exists y_a)_{a \in \gamma} (S_I \land \bigwedge_{a \in \gamma} y_a = 0)$$

Proof: The proof is trivial: the substitution of each unknown $y_a$ by 0 in $S_I$ gives syntactically the system $S_G$.

This equivalence allows to establish that linear invariants are preserved through freezing. If $u$ is a solution of the incremental characteristic system which assigns 0 to all $y_a$ unknowns then, its restriction $u_L$ to $x_l$ unknowns is a solution of global characteristic system. Such solutions $u$ of incremental systems are called hereafter invariant-generating. By using the observation above and theorem 1 it holds that $u|_L$ defines a linear invariant for the composite component $\gamma(B_1, \ldots, B_n)$ for any invariant-generating solution $u$ of $S_I(\gamma, B_1, \ldots, B_n)$.

The main advantage of incremental systems is that they are easily transformed through layering. That is, there exist a strong relationship between the incremental systems,
The above facts can be used together and prove the result.

**Theorem 4 (Layering):** Given composite component \( \gamma(B_1, \ldots, B_n) \) and \( \delta \) an increment of \( \gamma \), it holds that

\[
S_I(\delta \gamma, B_1, \ldots, B_n) \approx \\
(\exists y_b)_{b \in \gamma \cap \delta} \left( S_I(\gamma, B_1, \ldots, B_n) \wedge \bigwedge_{a \in \delta} \left( y_a - \sum_{l \in a^*} x_l - y_a = 0 \right) \right) \\
\left( \bigwedge_{b \in \gamma \cap \delta} \left( b_k \in \gamma, \bigwedge_{l \in b_k^*} x_l - y_a = 0 \right) \right)
\]

**Proof:** By definition of layering, \( \delta \gamma = (\gamma \ominus \delta^f) \oplus \delta \).

The incremental characteristic system \( S(\delta \gamma, B_1, \ldots, B_n) \) is therefore equal to \( S_I((\gamma \ominus \delta^f) \oplus \delta, B_1, \ldots, B_n) \) and can be rewritten as:

\[
\bigwedge_{a \in \gamma \cap \delta^f} \left( \bigwedge_{l \in a^*} \left( x_l - \sum_{l \in a^*} x_l - y_a = 0 \right) \right) \\
\bigwedge_{b \in \gamma \cap \delta^f} \left( b_k \in \gamma, \bigwedge_{l \in b_k^*} x_l - y_a = 0 \right)
\]

This implies that the incremental system can be split on disjoint union of components, as stated by the following proposition.

**Proposition 1 (Disjoint Union):** For any interaction \( \gamma \) and \( \delta \) in the second term. But now, regarding this second term, any interaction \( \gamma \ominus \delta^f \) can be safely extended over the set of interactions \( \delta \). Consequently, \( \gamma \ominus \delta^f \) gives solutions are preserved by disjoint union, and consequently, any invariant discovered locally for \( \gamma \ominus \delta^f \) is also an invariant for the composite \( \gamma \ominus \delta^f \).

Example 8: Following the incremental composition used for the example illustrated in Figure 2, the incremental characteristic systems constructed at different steps of the design are given in the Table I. For each increment (a subdivision of the table) we discover some linear invariants. The computation steps associated to the increments \( \delta_1 \) and \( \delta_2 \) gives an invariant \( at_{L_1} + at_{L_2} + at_{L_3} = 1 \) for each component \( P_i \) and the invariant \( at_{L_1} + at_{L_2} = 1 \) for the component Lock. The next step corresponds to the disjoint union: we merge the two characteristic systems, and we collect the invariants obtained form each one. For the last increment \( \delta_3 \), we obtain the invariant \( at_{L_2} + at_{L_3} + at_{L_4} = 1 \). This invariant ensures the mutual exclusion property in the system. When Lock is activated at \( at_{L_2} = 1 \) and hence \( at_{L_3} = 0 \), the invariant ensures that exactly one of the \( P_i \) reached its location at \( at_{L_2} \).
VI. IMPLEMENTATION, EXPERIMENTS AND RESULTS

We split the section in two parts. First we show the power of algorithm 1; second we demonstrate the efficiency of our incremental approach.

A. On Algorithm 1

As we have seen in previous sections, linear invariants generation relies on methods to compute the set of solutions of a given homogeneous system of linear equations.

The complexity of standard algorithms for solving such systems is \(O(mn^2)\), for systems of size \(m \times n\). Most of classical algorithms such as Gauss-Jordan elimination may reach this complexity. This is especially the case when considering dense systems. However, in the context of our work, we observed that characteristic systems are usually sparse. The reason is that interactions synchronize few components, and therefore the associated equations involve few locations. In many cases, the bigger the composition (which implies a large number of components and locations), the lower the fill factor of the characteristic system. Given a composition with \(|\gamma|\) interactions of atomic components totaling \(|L|\) locations, the matrix \(A\) for \(S_\mathcal{G}\) has size of \(|\gamma| \times |L|\). If \(\text{avg}(\gamma)\) denotes the average number of components used per interaction, the fill factor of \(A\) is \(2 \cdot \text{avg}(\gamma)/|L|\). Table II illustrates the fill factor for some common BIP examples. This particular structure is exploited by the global online Algorithm 1.

B. On Computing Linear Invariants

We have implemented the techniques proposed in this paper as an extension of dfinder, a tool capable of checking deadlocks of programmes written in the BIP language.

dFinder originally implements efficient symbolic techniques for computing Boolean invariants \(\psi\) of the interactions between components [6]. As shown in Figure 3 (that also illustrates the structure of the tool), \(\psi\) can then be combined with the invariant \(\phi_i\) of each constituent component to deduce a global invariant for the complete system (see [18] for a proof). At the same time, the tool also computes all the potential deadlock states denoted by \(DIS\). If the formula \(\land_i \phi_i \land \Psi \land DIS\) is unsatisfiable, then the system is deadlock free. In the other case, the solutions denote some suspicious counter examples that can be reused by the tool to refine automatically the analysis. For the purpose of this work, we have implemented new techniques based on linear invariants in order to compute \(\psi\). Those techniques rely on algebraic sparse matrices representations rather than BDD used in classical dfinder.

EXPERIMENTS. Table III represents a the results of a set of experiments. All the experiments have been conducted with incremental approach as we observed that it clearly outperforms the global one. All our experiments were done with a 2.4GHz Core 2 Duo CPU with 8GB of RAM (a laptop running Mac OS X 10.6). We generated linear invariants for various case studies, including the Gas Station [19], a

<table>
<thead>
<tr>
<th>BIP Model</th>
<th>Matrix A</th>
</tr>
</thead>
<tbody>
<tr>
<td>Name</td>
<td>(</td>
</tr>
<tr>
<td>Voting Serv</td>
<td>18</td>
</tr>
<tr>
<td>Philo(m)</td>
<td>5a</td>
</tr>
<tr>
<td>Smokes(n)</td>
<td>12n</td>
</tr>
<tr>
<td>ReadWrite(n)</td>
<td>33n</td>
</tr>
<tr>
<td>ATM(n)</td>
<td>39n</td>
</tr>
</tbody>
</table>

Table II

MATRIX SPARSITY FOR THE CHARACTERISTIC SYSTEMS \(S_\mathcal{G}\)

Example of Incremental System

\[
S_\mathcal{G}(\gamma, P_1, P_2, P_3, \text{Lock}) = \begin{cases} \gamma_{1}\gamma_{2}\gamma_{3} \end{cases}
\]

\[
S_1(\delta_1(\gamma_1^+ \oplus \gamma_2^+ \oplus \gamma_3^+), P_1, P_2, P_3, \text{Lock})
\]

\[
S_1(\delta_1(\gamma_1^+ \oplus \gamma_2^+ \oplus \gamma_3^+), P_1, \text{Lock})
\]

\[
S_1(\gamma_1^+ \oplus \gamma_2^+ \oplus \gamma_3^+), P_2, P_3)
\]

\[
S_1(\gamma_1^+ \oplus \gamma_2^+ \oplus \gamma_3^+), P_2, P_3)
\]

\[
x_{i12} - x_{i11} = y_{i1} + y_{i12} - x_{i11} = y_{i1} + y_{i12} = y_{i1}
\]
derived version of the Smoker [20], the Automatic Teller Machine (ATM) [21] and the classical Dining philosphers problem. Regarding the Gas Station example, we assume that every pump has 10 customers. Hence, if there are 50 pumps in a Gas Station, then we have 500 customers and the number of components including the operator is thus 551. In the ATM example, every ATM machine is associated to one user. Therefore, if we have 10 machines, then the number of components will be 22 (including the two components that describe the Bank). Each example is parameterized by \textit{scale}, which denotes its “size”; \textit{location} denotes the total number of control locations \(|L|\); \textit{interaction} is for the total number of interactions \(|\gamma|\). The computation time is given in minutes and the memory usage is given in kilo- or MegaBytes. The timeout, i.e., “-” is one hour. We implemented the methods described in Section IV-A within DFINDER. Alternatively we implemented \textsc{Gauss} a standard Gauss-Jordan elimination and we used \textsc{Charlie}, a general Petri-net analyzer \cite{9}. We observe that the approach based on Algorithm 1 is always faster, and the consumed memory by \textsc{DFINDER} is negligible compared to the other approaches. We also observe that \textsc{Charlie} fails to analyze the Petri-nets generated from the BIP models. It generates a particular set of invariants so-called semi-linear positive invariants that require an important complexity. They allow to check several kinds of properties (structural, coverability, reachability, ...), but for the reachability analysis they are however equivalent to the linear invariants.

\textbf{Preciseness.} We also observe that our technique generates invariants that are coarser than Booleans ones, which decreases the risk of introducing counter examples. Figures 4, 6, and 5 give the accuracy of the generated invariants (for both the Boolean and the linear one) for the Dining Philosophers, the Gas Station and the ATM, for each system with different sizes. On these figures, the value 60\% means that the reachable states of the system are 60\% of all the states characterized by the invariants. It dually means that these same invariants catch 40\% of unreachable states. Notice that an accuracy of 0\% (i.e. no reachable state contained) is never reached since the generated invariants are sound. But for some of the Boolean invariants, the approximation is so imprecise that the result is really close to 0\% in the figures.

The above examples have different types of interactions between the constituent components, and this has an impact on the preciseness. In the Dining Philosophers, one can see that all the interactions are there in order to introduce mutual exclusion mechanisms. As explained below, the linear invariants are really adequate to express such properties as they can be encoded by linear equations. For such an example, the result is of clear interest. Indeed, the generated linear invariants exactly denotes the set of reachable states. For the same reason, we also obtain an excellent precision (90\%) with the linear invariants for Readers/Writers example.

On the contrary, the approximation for the Gas Station example is coarser. Indeed, the relation between the consumers and the pumps is quite well-suited (e.g. resemble a mutual exclusion principle), but the overall behavior of the station is guaranteed by an operator that relies on global self-loops. Such interactions are more expressive than linear equation. This means that they can only be approximated by such equations. Additionally, each new pump added to the system is connected to the operator with interactions over the self-loops that deteriorate the precision of the approximation.

In Figure 5, the ATM example contains also some interactions defined over self-loops. But they are used to define timers in some of the components. As such, they do not define strong synchronizations between the components. This means that their impact is smaller than for the Gas Station. Consequently, this justifies that for each ATM added in the system, the 60\% of accuracy does not decrease so much.

<table>
<thead>
<tr>
<th>Example</th>
<th>1000 pumps</th>
<th>500 machines</th>
<th>2000 writers</th>
<th>1000 writers</th>
</tr>
</thead>
<tbody>
<tr>
<td>\textsc{Charlie}</td>
<td>0.0 %</td>
<td>0.0 %</td>
<td>0.0 %</td>
<td>0.0 %</td>
</tr>
<tr>
<td>\textsc{DFINDER}</td>
<td>100 %</td>
<td>80 %</td>
<td>40 %</td>
<td>60 %</td>
</tr>
</tbody>
</table>

\begin{table}[h]
\centering
\begin{tabular}{|c|c|c|c|c|c|}
\hline
\textbf{Component} & \textbf{scale} & \textbf{locations} & \textbf{interactions} & \textbf{reachability} & \textbf{coverability} & \textbf{invariants} \\
\hline
\textsc{ATM} & 1000 locations & 5000 & 6000 & 0.0 & 0.0 & 0.0 \\
\hline
\textsc{D-Finder} & 1000 locations & 5000 & 6000 & 0.0 & 0.0 & 0.0 \\
\hline
\hline
\textsc{Gas Station} & 1000 pumps & 500 machines & 2000 writers & 1000 writers & \\
\hline
\textsc{Charlie} & 0.0 \% & 0.0 \% & 0.0 \% & 0.0 \% & \\
\hline
\textsc{DFINDER} & 100 \% & 80 \% & 40 \% & 60 \% & \\
\hline
\end{tabular}
\caption{Execution time for some examples}
\end{table}
Globally, we clearly observe that the linear invariants drastically increase the accuracy of the verification compared to the Boolean invariants. But as explained in [6], Boolean invariants are sufficient to prove the deadlock freeness of a system. Moreover, if the linear invariants are more accurate than the Boolean invariants, the approximated states of the linear invariants are not always a subset of those of the Boolean invariants: the conjunction of the linear and Boolean invariants increase the precision of the analysis for the cases with self-loops like in the Gas Station example.

VII. CONCLUSION

We propose a technology to generate linear invariants for the BIP toolset. Contrary to our former contribution that relies on generating Boolean invariants, this new approach allows for the generation of linear invariants. Even though BIP Boolean invariants and BIP linear invariants are uncomparable, experimental results show the latter may be more precise. Future work includes proposing intensive techniques as well as extending the approach to the full class of liveness properties.

REFERENCES


