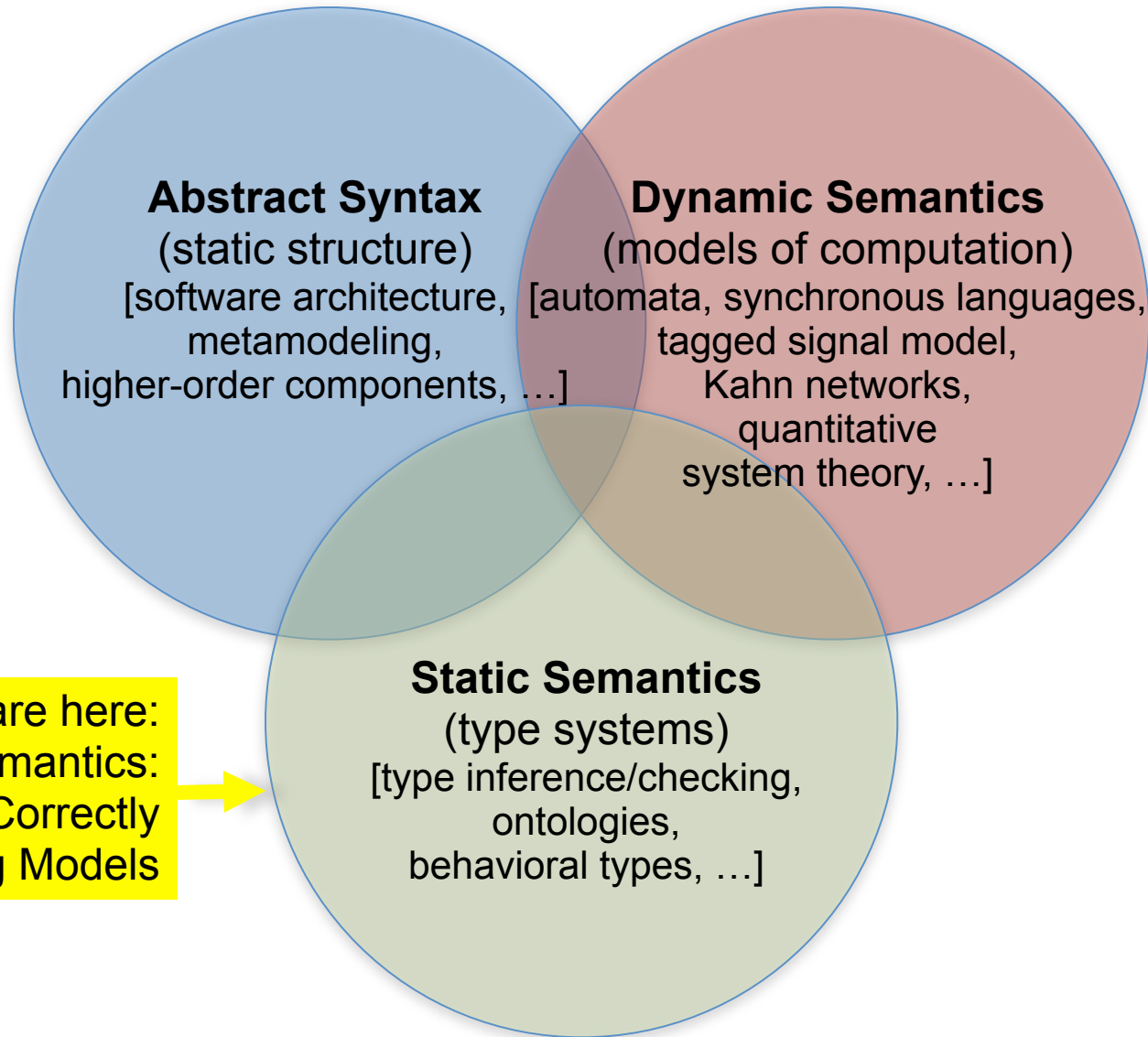


# A Practical Ontology Framework for Static Model Analysis

**Ben Lickly**  
**Charles Shelton**  
**Elizabeth Latronico**  
**Edward A. Lee**

**EMSOFT 2011**  
**October 9-14, 2011**  
**UC Berkeley & Bosch Research**

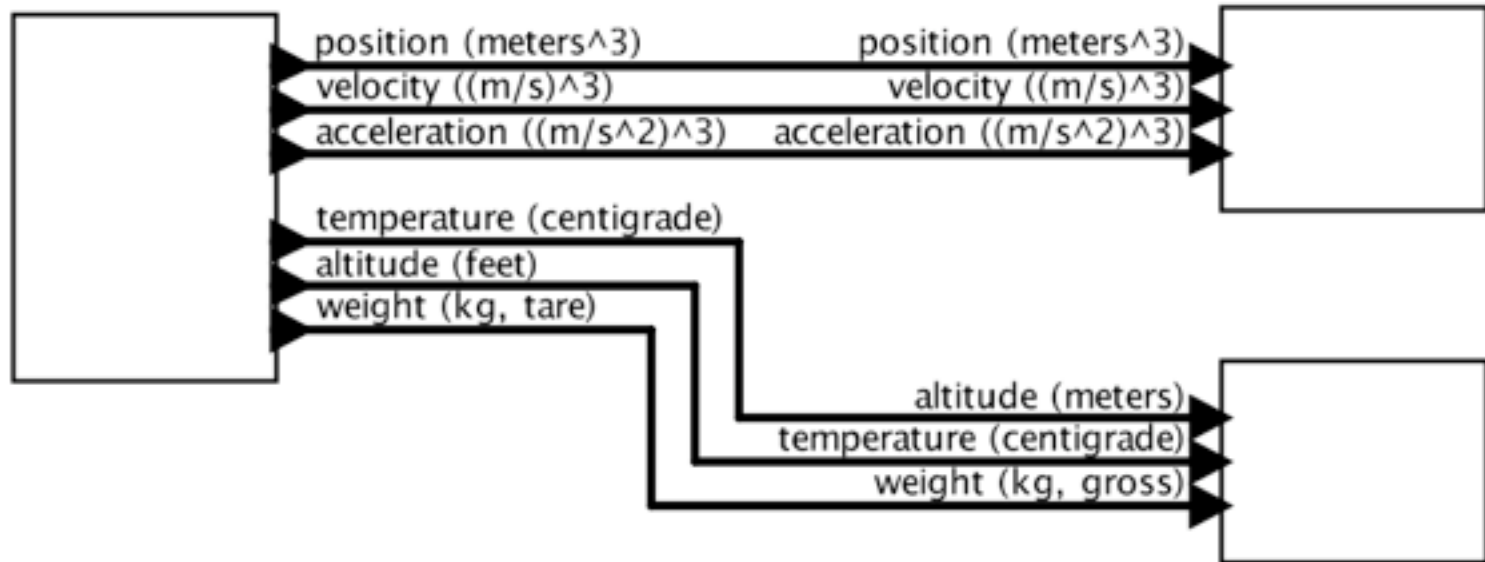
# A Taxonomy of Modeling Issues



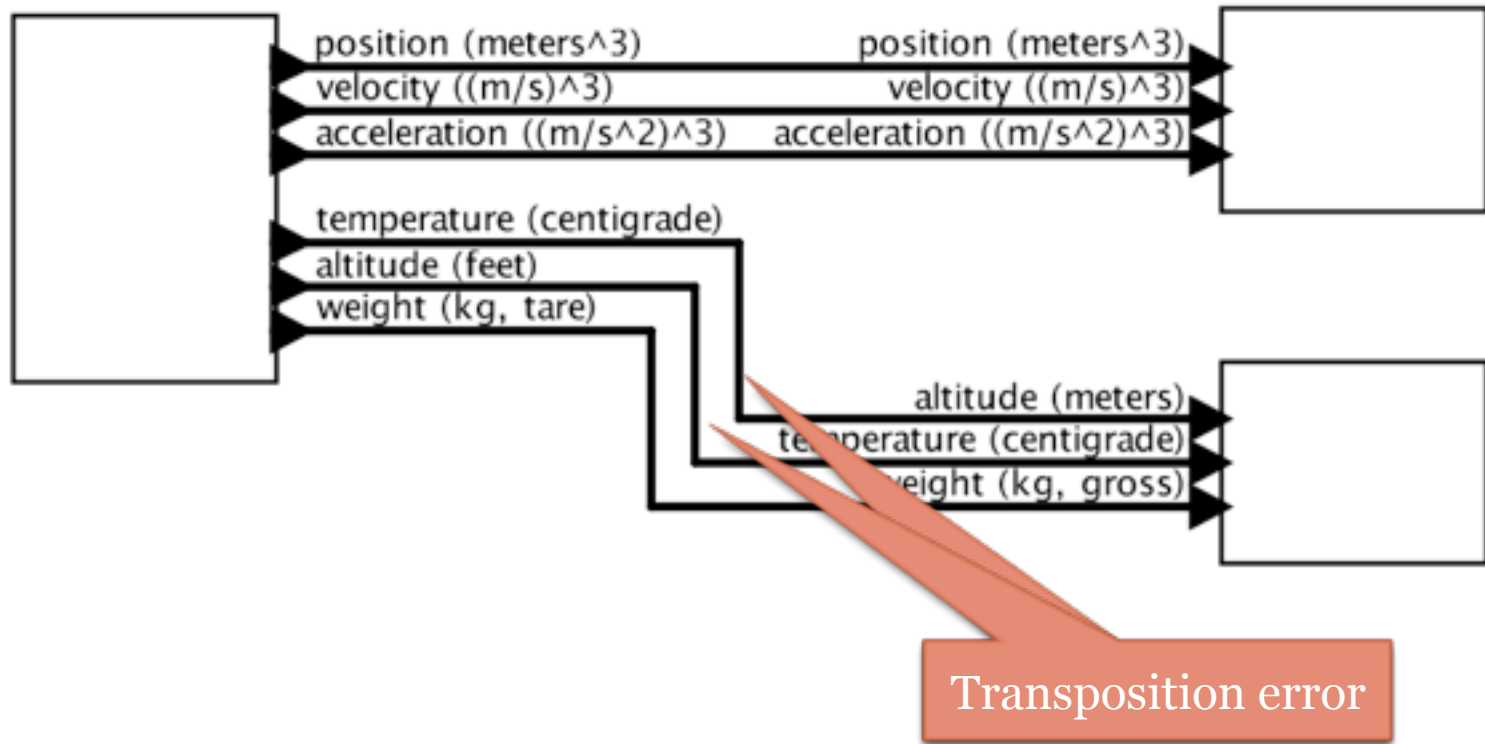
We are here:  
Static semantics:  
Correctly  
Composing Models



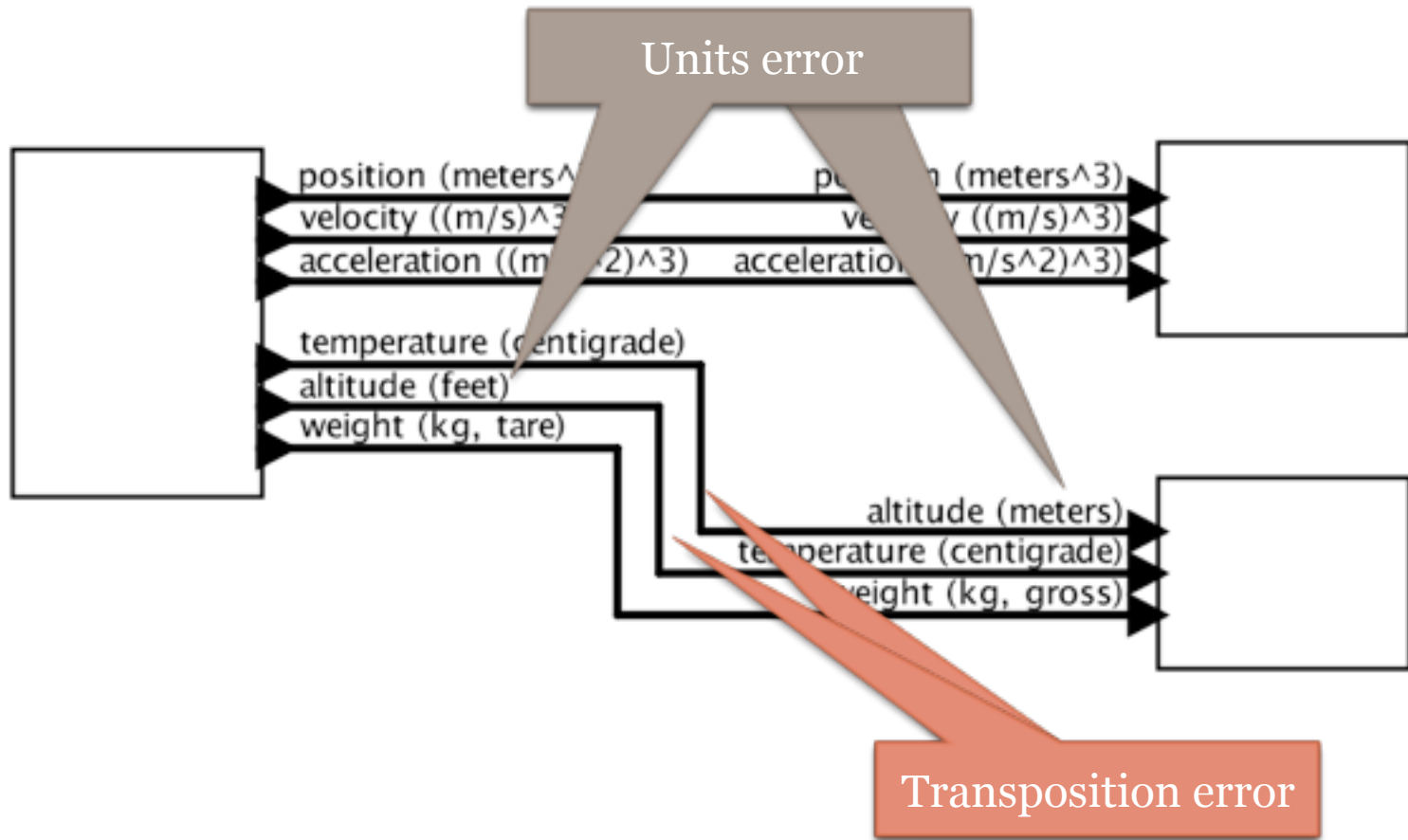
# Model Composition Errors



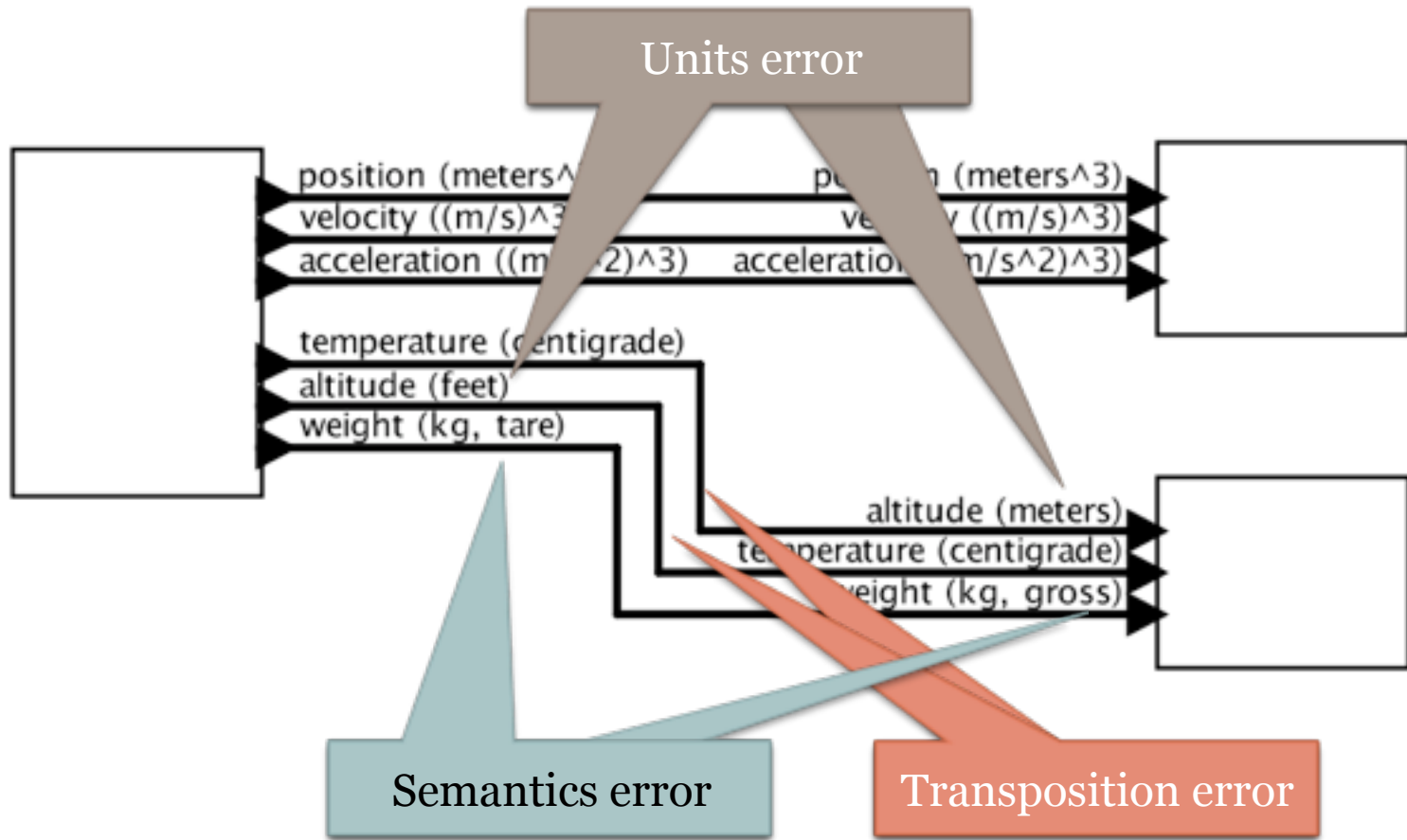
# Model Composition Errors



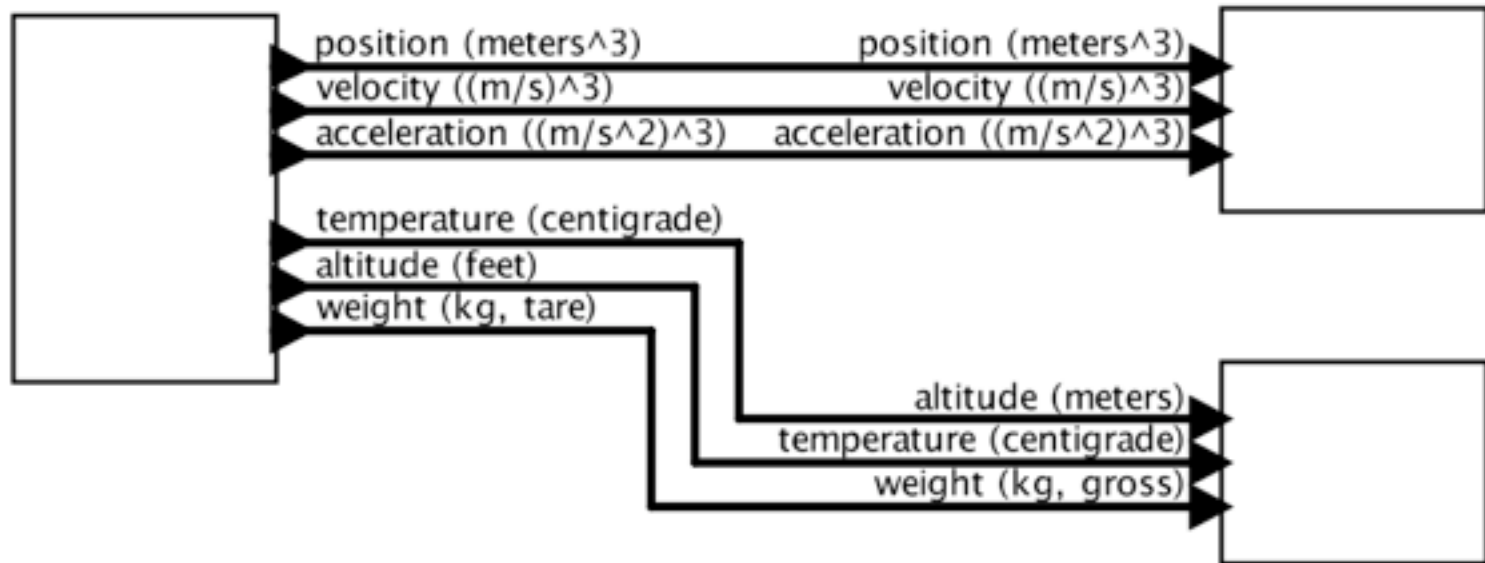
# Model Composition Errors



# Model Composition Errors



# Our Goals



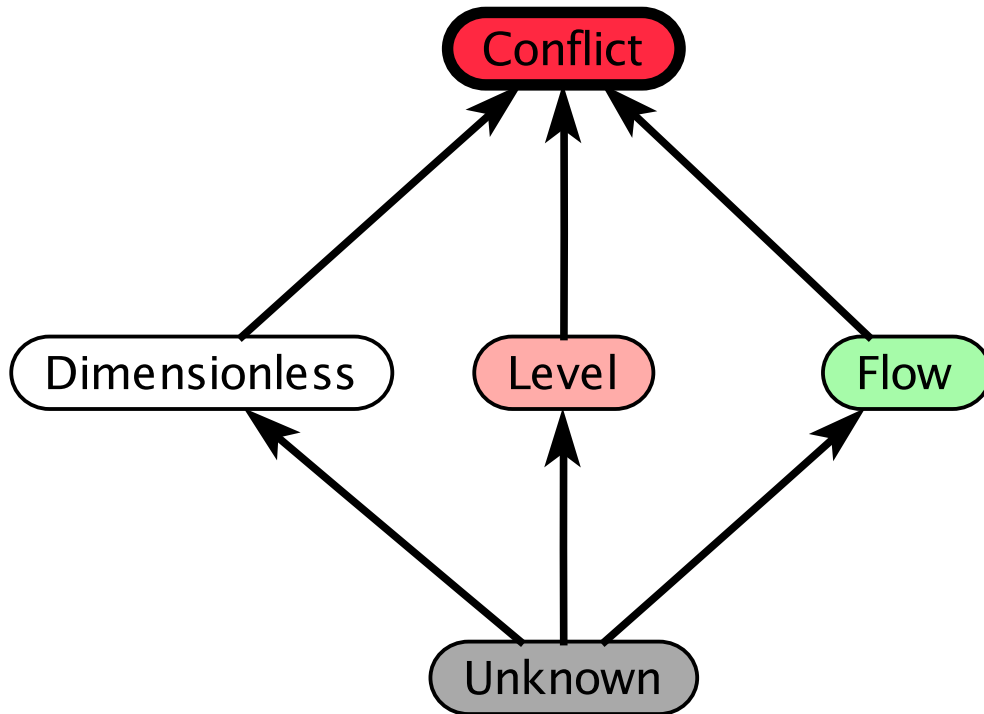
- Detect such interfacing errors
- Minimize the manual annotations required (use inference)
- Improve communication in engineering teams by augmenting interface definitions with semantic information

# Outline

1. Existing (Finite) Ontology Analysis
2. Value-parametrized Ontologies
3. Recursive Ontologies



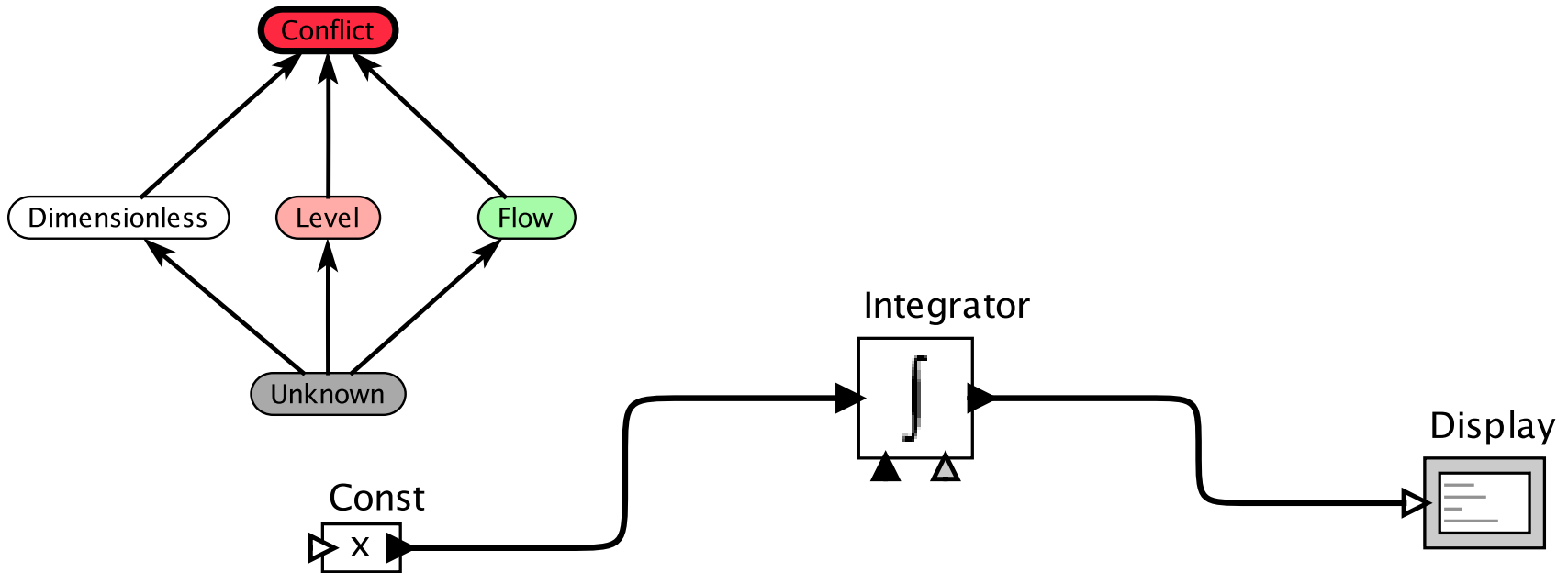
# Domain-Specific Ontologies



Here is a *lattice* representing a simple dimension ontology.

- Components in a model (e.g. parameters, ports, messages, fields in a packet, etc.) can have properties drawn from a lattice.
- Components in a model (e.g. actors) can impose constraints on property relationships.
- The type system infrastructure can infer concepts and detect errors.

# Inferring Concepts



FuelDimensionSystemSolver

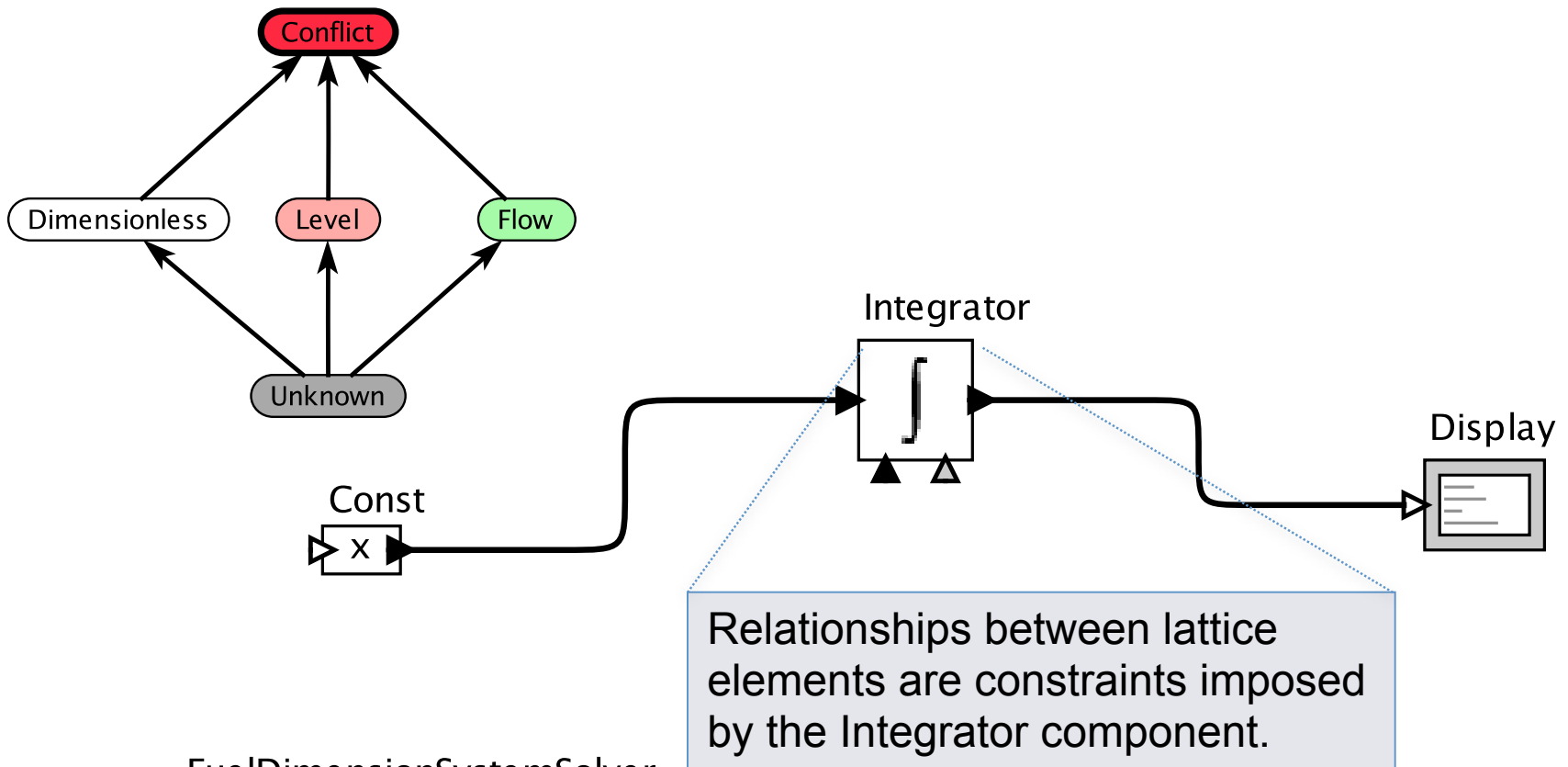
Double click to  
Apply Ontology

● x: 4.0

● fuelDimensionSystem::constraint3:  $x \geq \text{Flow}$

User-defined constraints added (in as few places as possible)

# Inferring Concepts



FuelDimensionSystemSolver

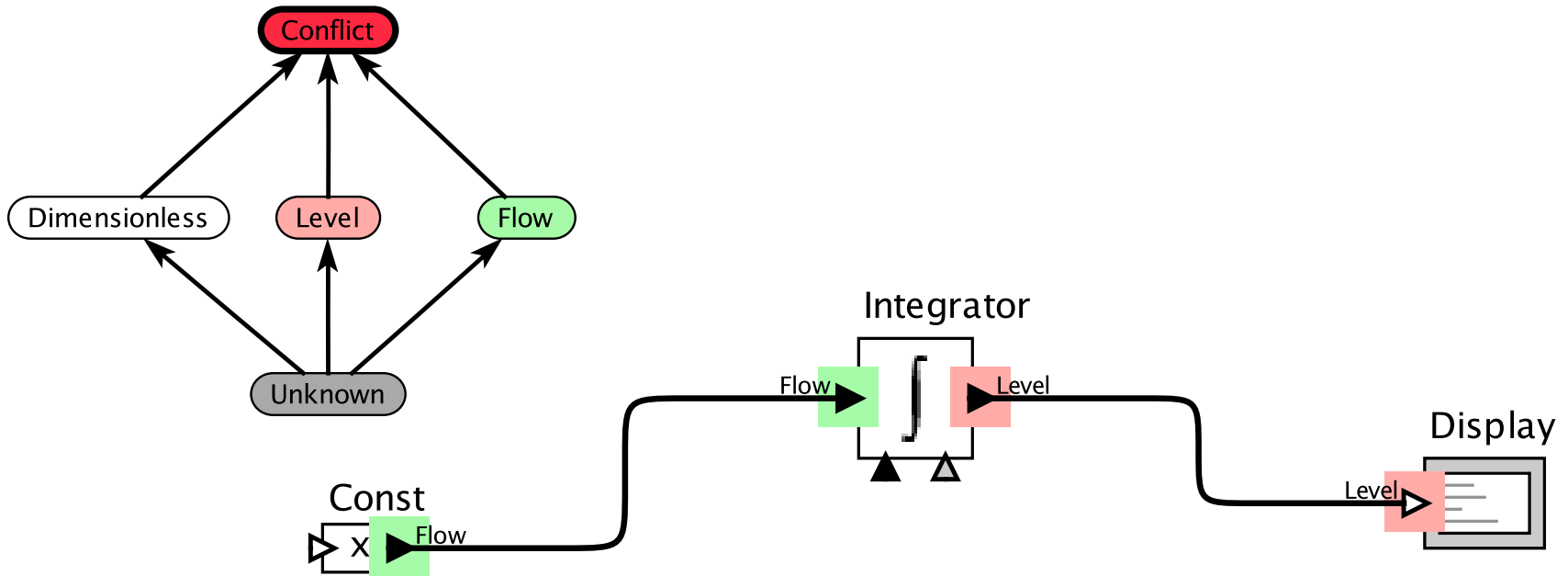
Double click to  
Apply Ontology

● x: 4.0

● fuelDimensionSystem::constraint3:  $x \geq \text{Flow}$

User-defined constraints added (in as few places as possible)

# Inferring Concepts



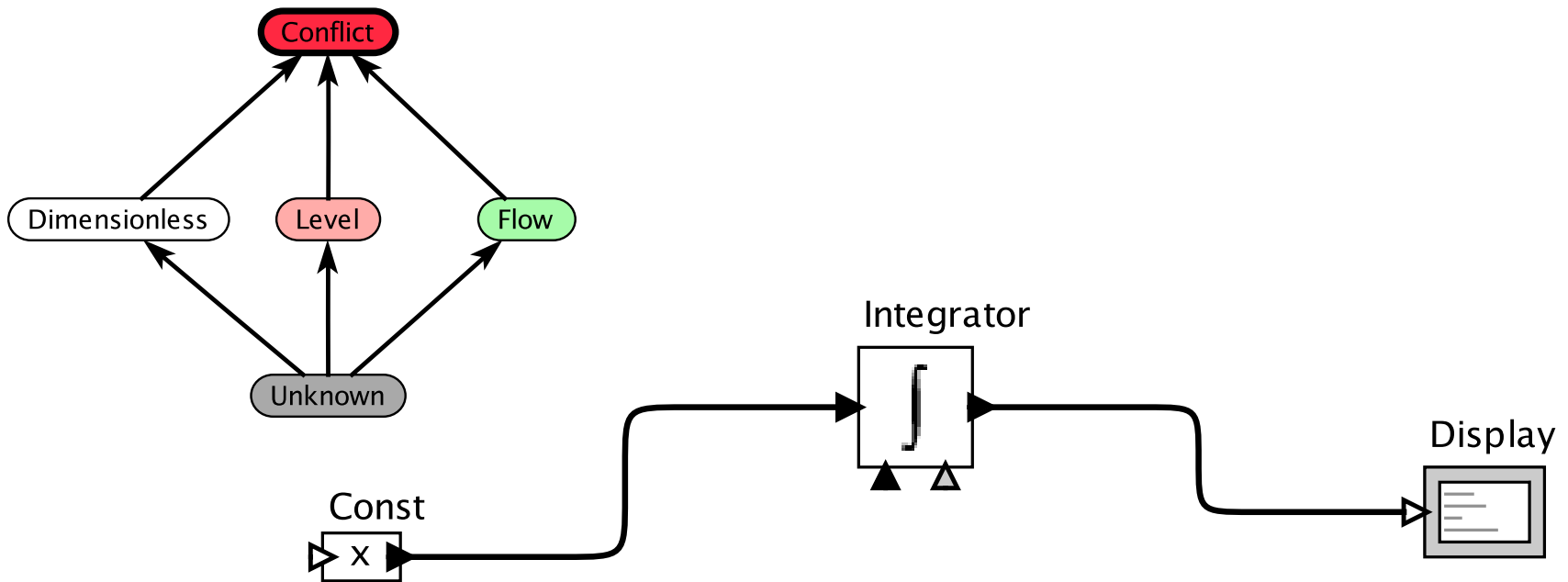
FuelDimensionSystemSolver

Double click to  
Apply Ontology

● x: 4.0

● fuelDimensionSystem::constraint3:  $x \geq \text{Flow}$

# Inferring Errors

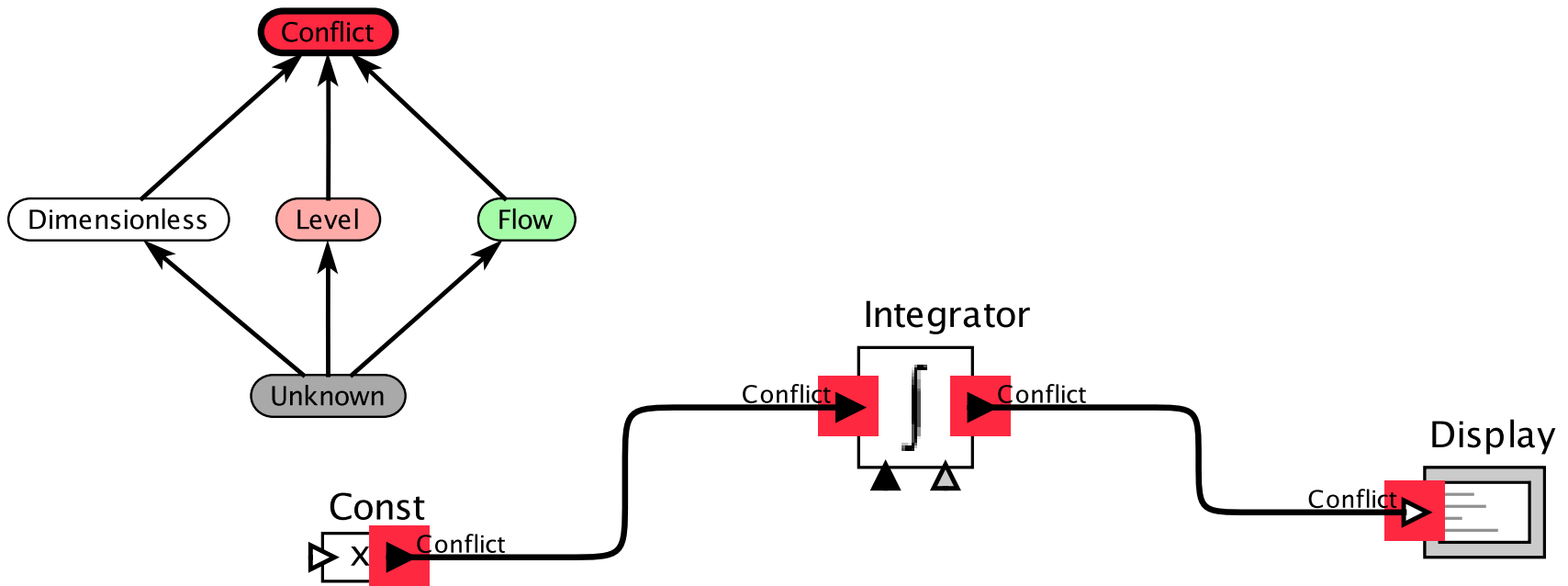


FuelDimensionSystemSolver

Double click to  
Apply Ontology

- x: 4.0
- fuelDimensionSystem::constraint3:  $x \geq \text{Level}$

# Inferring Errors



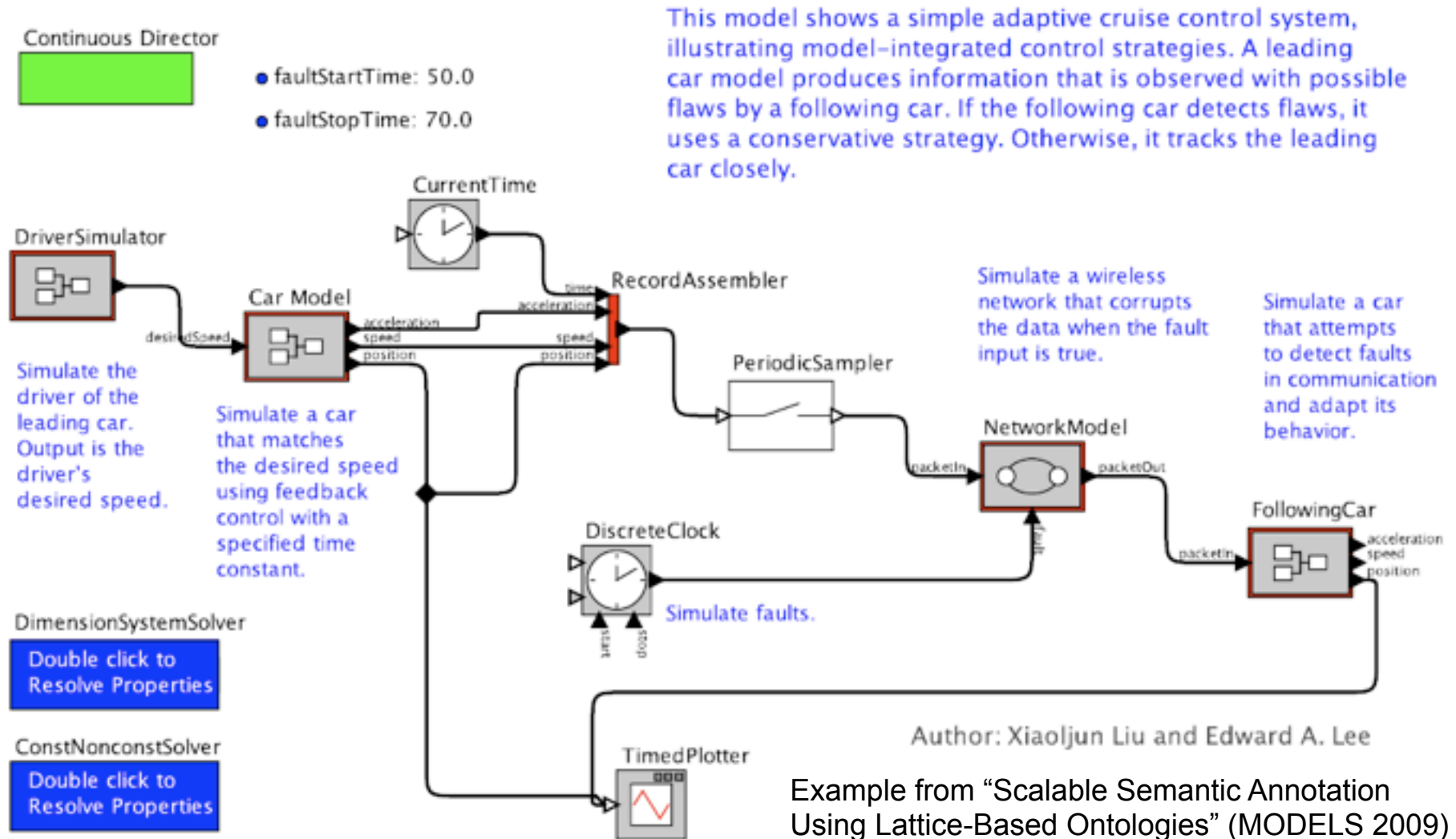
FuelDimensionSystemSolver

Double click to  
Apply Ontology

● x: 4.0

● fuelDimensionSystem::constraint3:  $x \geq \text{Level}$

# More Complex Model: Cooperative Cruise Control

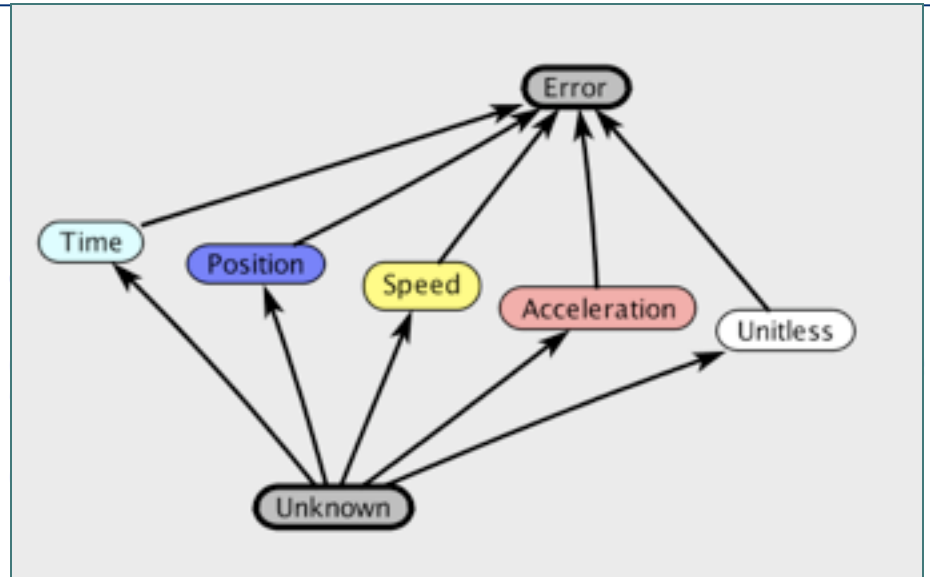


This model shows a simple adaptive cruise control system, illustrating model-integrated control strategies. A leading car model produces information that is observed with possible flaws by a following car. If the following car detects flaws, it uses a conservative strategy. Otherwise, it tracks the leading car closely.

Author: Xiaoljun Liu and Edward A. Lee

Example from "Scalable Semantic Annotation Using Lattice-Based Ontologies" (MODELS 2009)

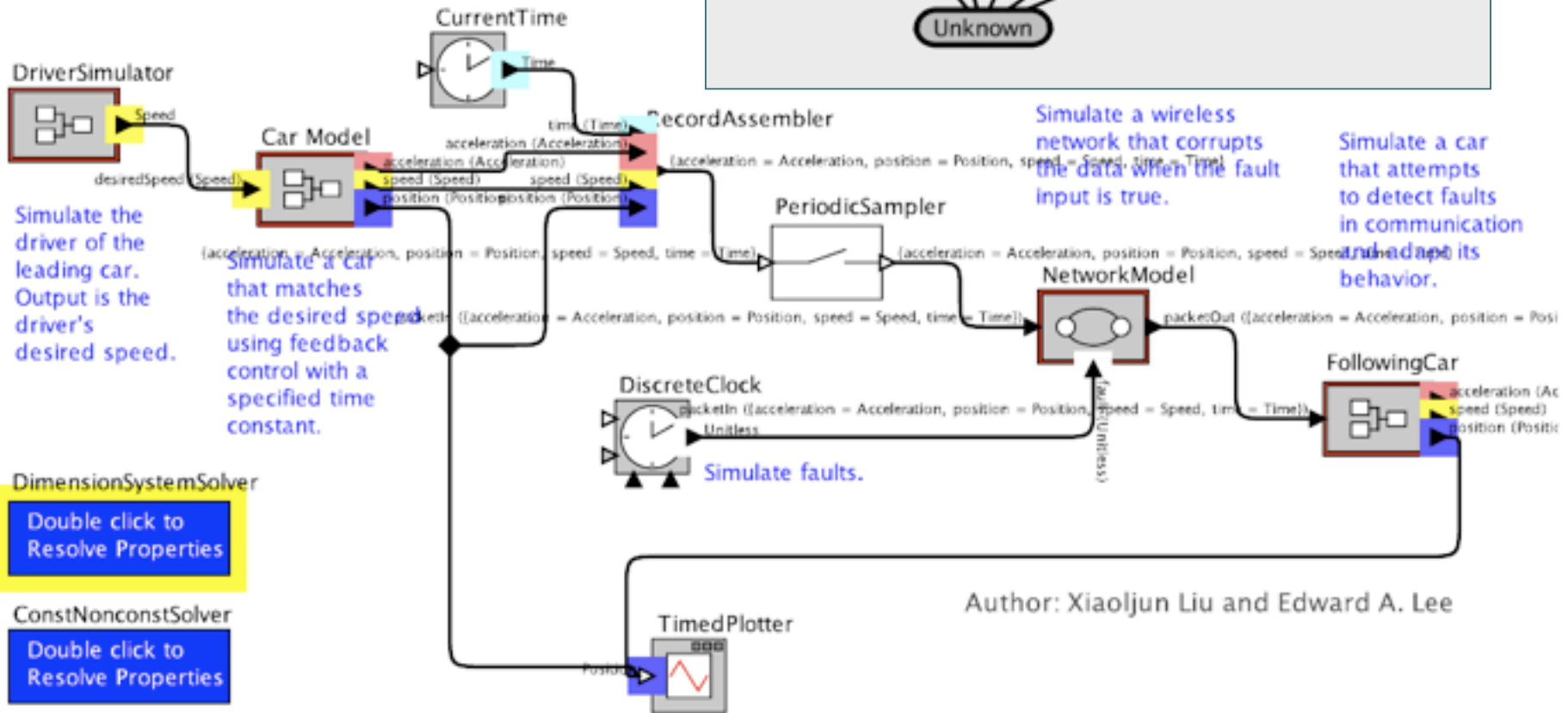
# More Complex Model: Cooperative Cruise Control



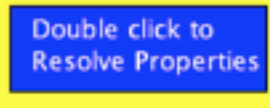
Continuous Director



- FaultStartTime: 50.0
- FaultStopTime: 70.0



DimensionSystemSolver



ConstNonconstSolver

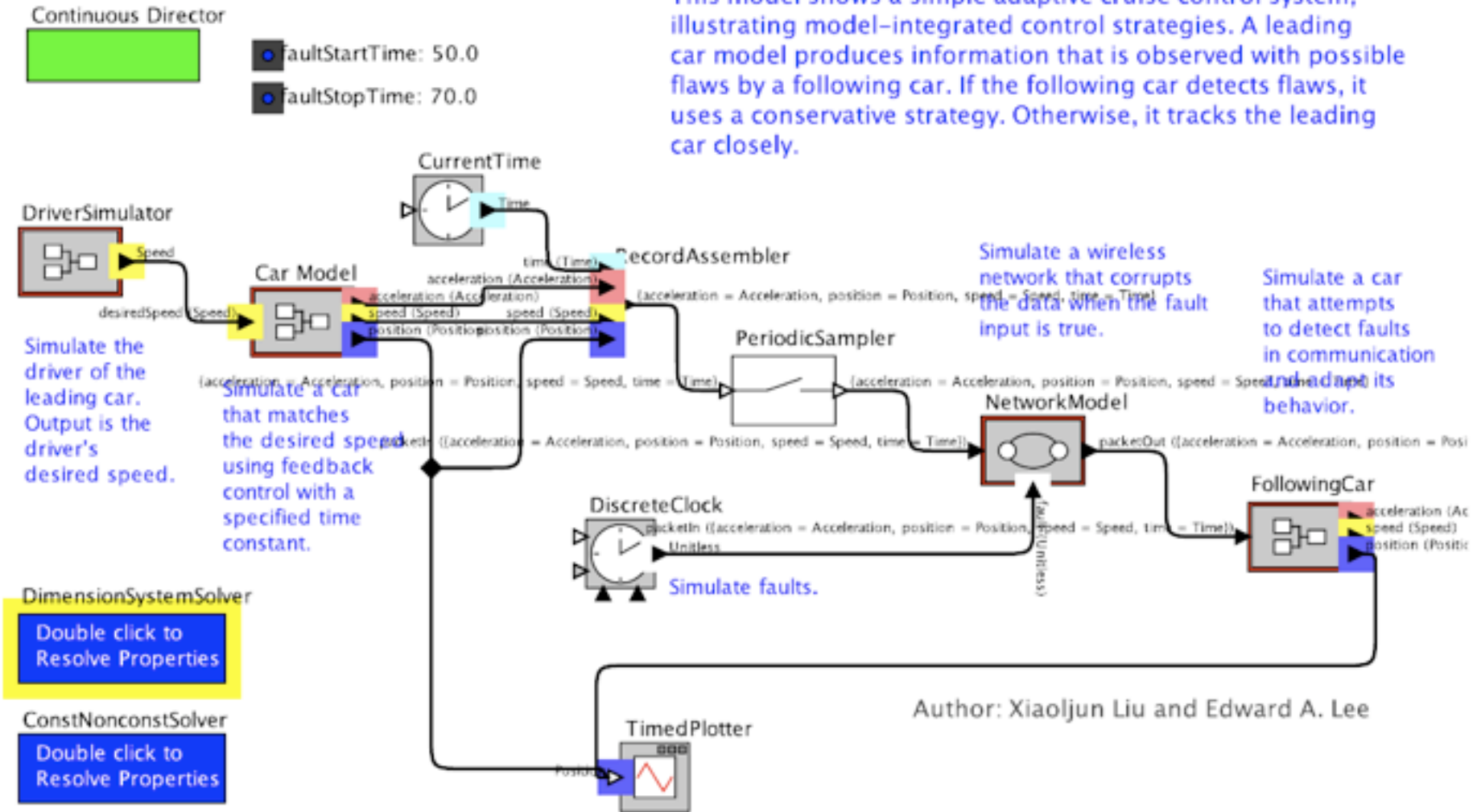


Author: Xiaojun Liu and Edward A. Lee



# More Complex Model: Cooperative Cruise Control

This model shows a simple adaptive cruise control system, illustrating model-integrated control strategies. A leading car model produces information that is observed with possible flaws by a following car. If the following car detects flaws, it uses a conservative strategy. Otherwise, it tracks the leading car closely.



# More Complex Model: Cooperative Cruise Control

This model shows a simple adaptive cruise control system, illustrating model-integrated control strategies. A leading car model produces information that is observed with possible flaws by a following car. If the following car detects flaws it

Continuous Director



FaultStartTime: 50.0



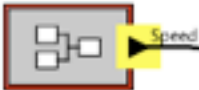
initialPosition: 10.0

timeConstant: 10.0

initialSpeed: 0.0

DimensionSystemSolver::constraint: timeConstant >= Time

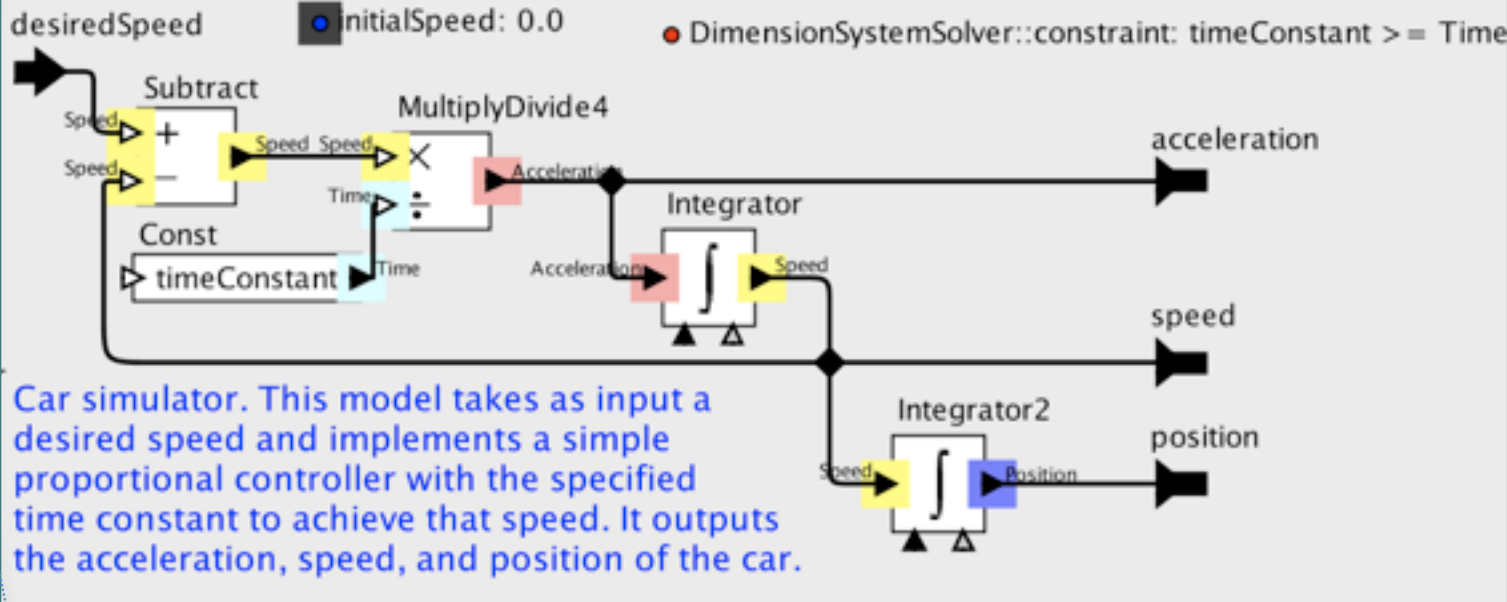
DriverSimulator



desiredSpeed

Simulate the driver of the leading car. Output is the driver's desired speed.

Car  
Simulate that makes the desired speed using feedback control with specified time constant



DimensionSystemSolver

Double click to Resolve Properties

ConstNonconstSolver

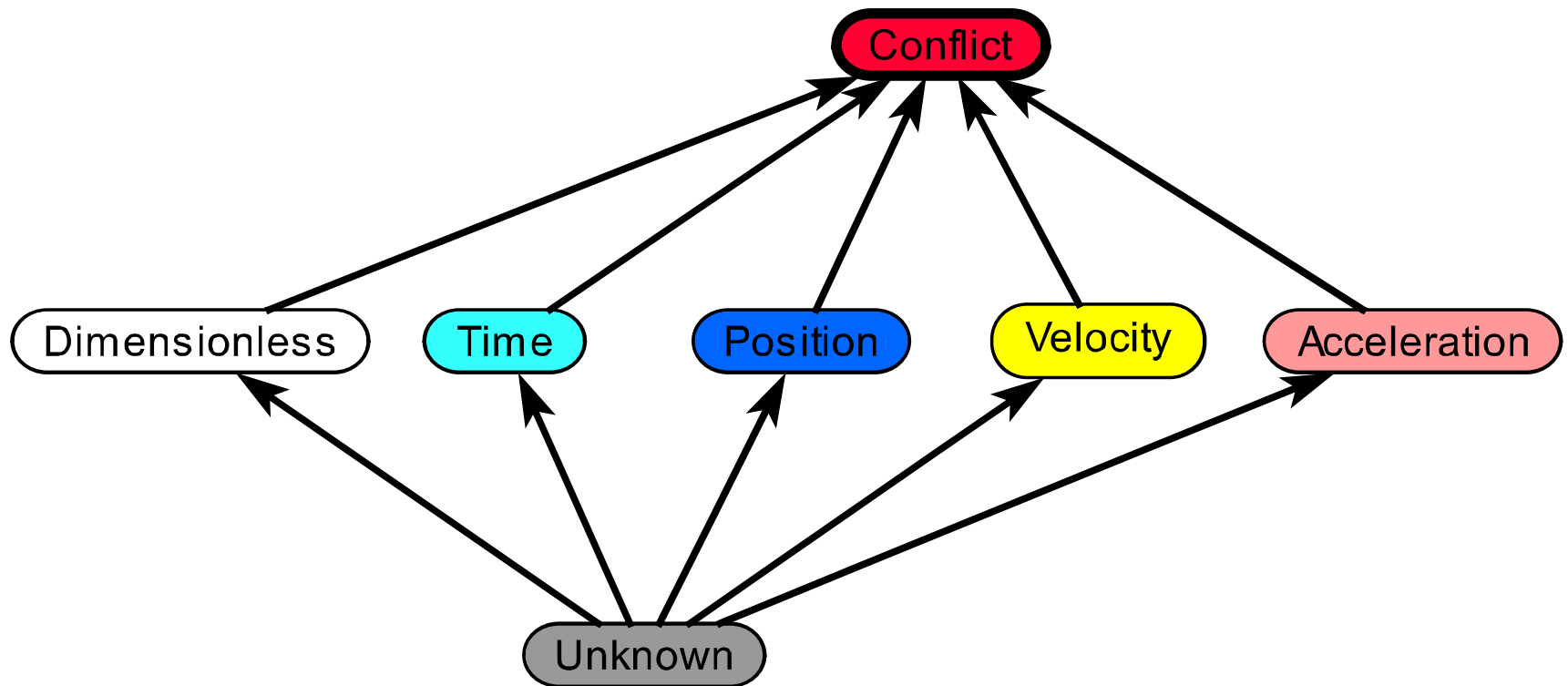
Double click to Resolve Properties

Author: Xiaoljun Liu and Edward A. Lee

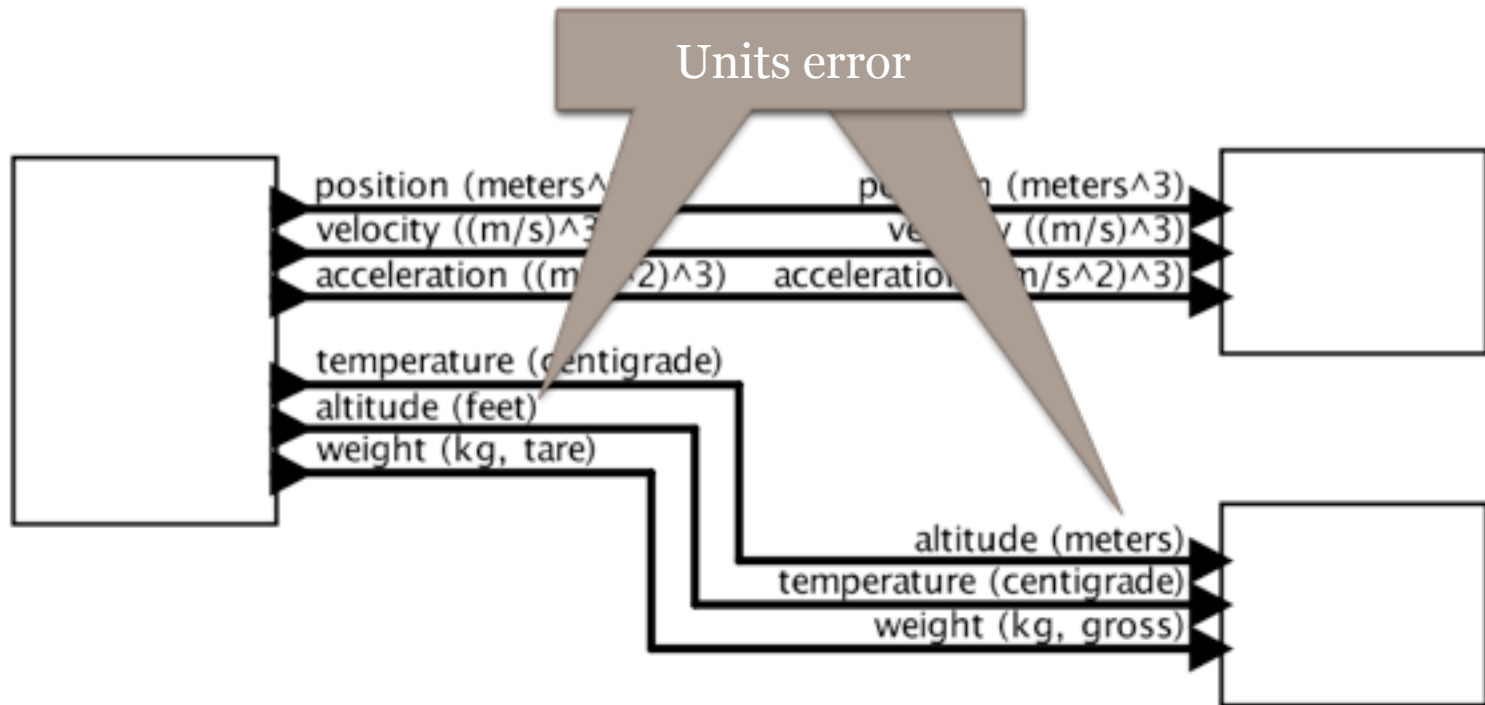
TimedPlotter



# Why is this insufficient?



# Units Errors



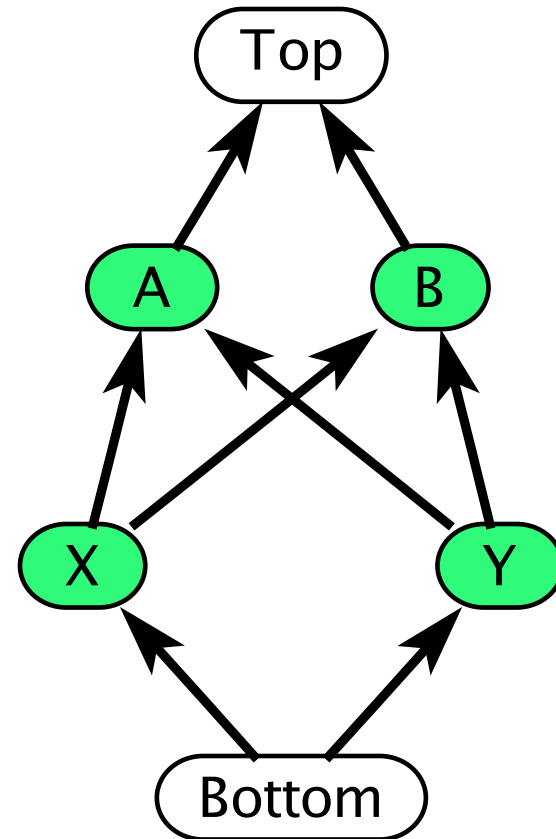
# Definitions

*Least Upper Bound/  
LUB(S):* The least  $x$ ,  
if it exists, such that

$$\forall s \in S, x \geq s.$$

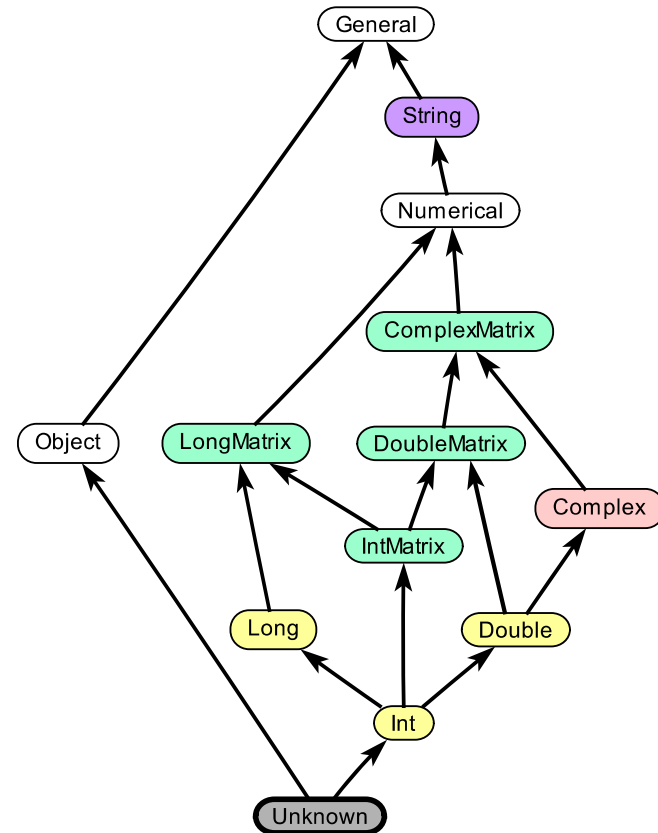
*Greatest Lower  
Bound/GLB(S):* The  
greatest  $x$ , if it exists,  
such that

$$\forall s \in S, x \leq s.$$



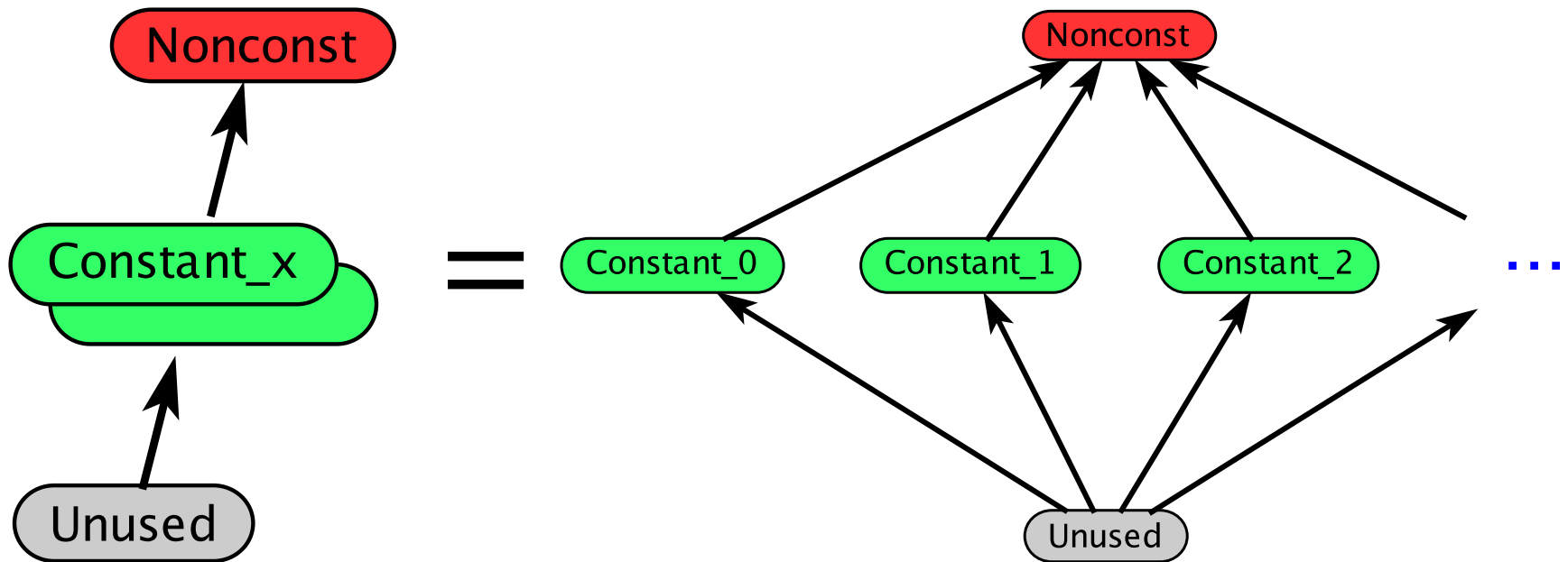
# Definitions

*Complete Lattice:*  
Partially ordered set  
in which all subsets  
have a *LUB* and  
*GLB*.

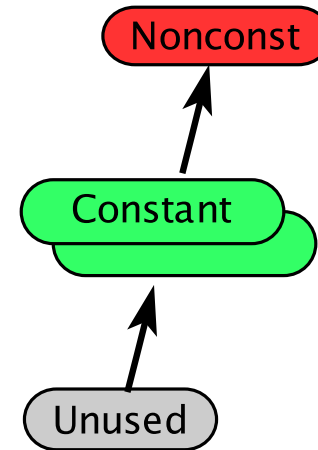
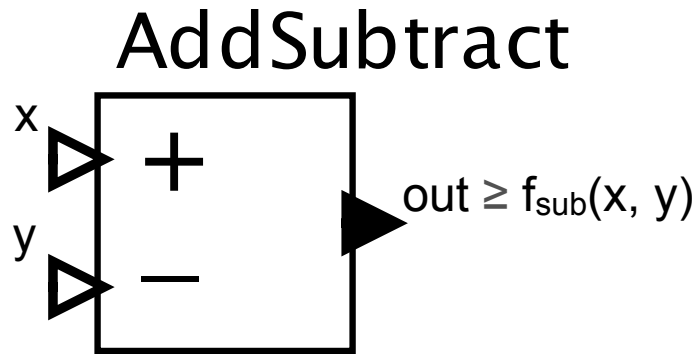


# Value-parametrized Concepts

Concepts with values can be useful.



# Value-dependent Constraints

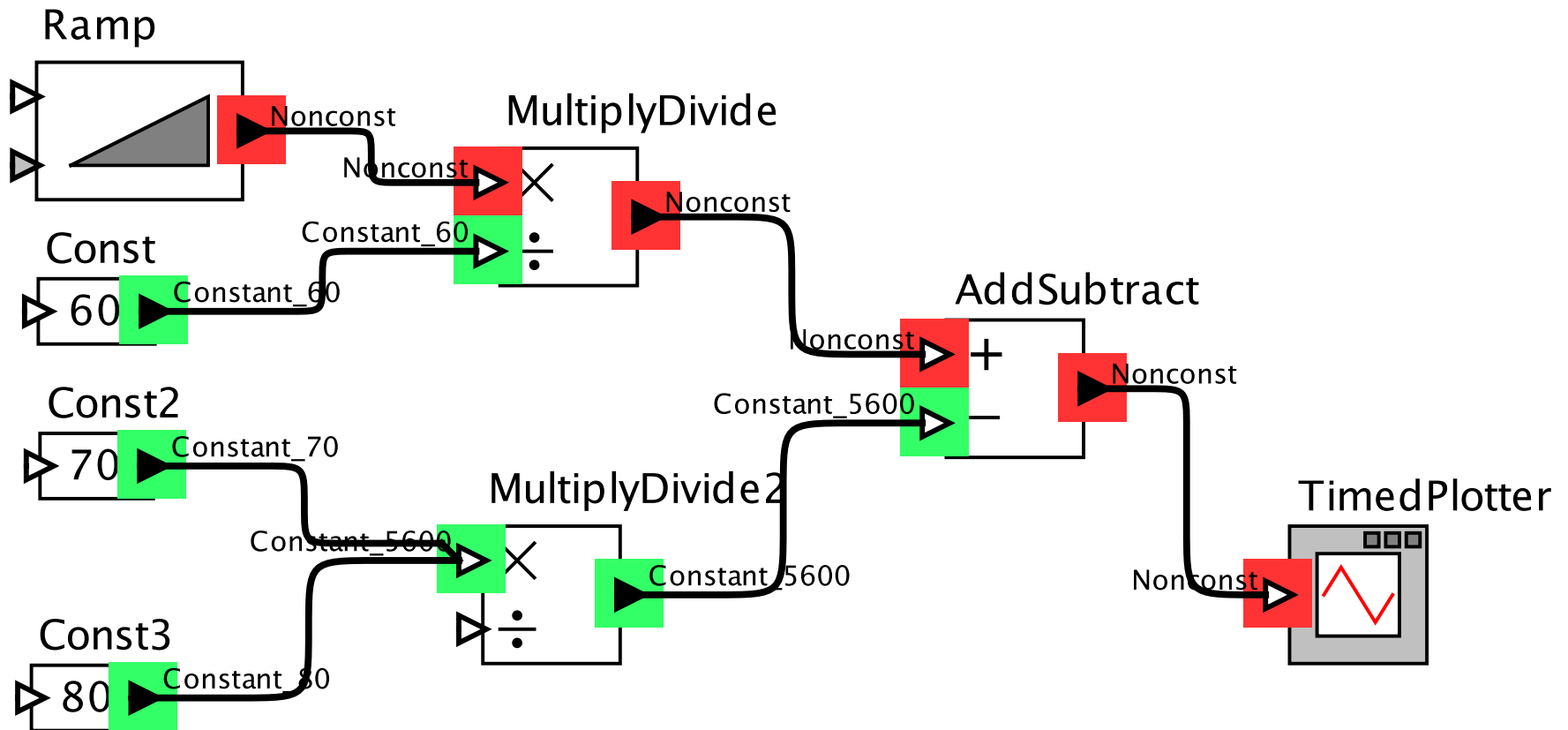


$f_{\text{sub}}(x, y) =$

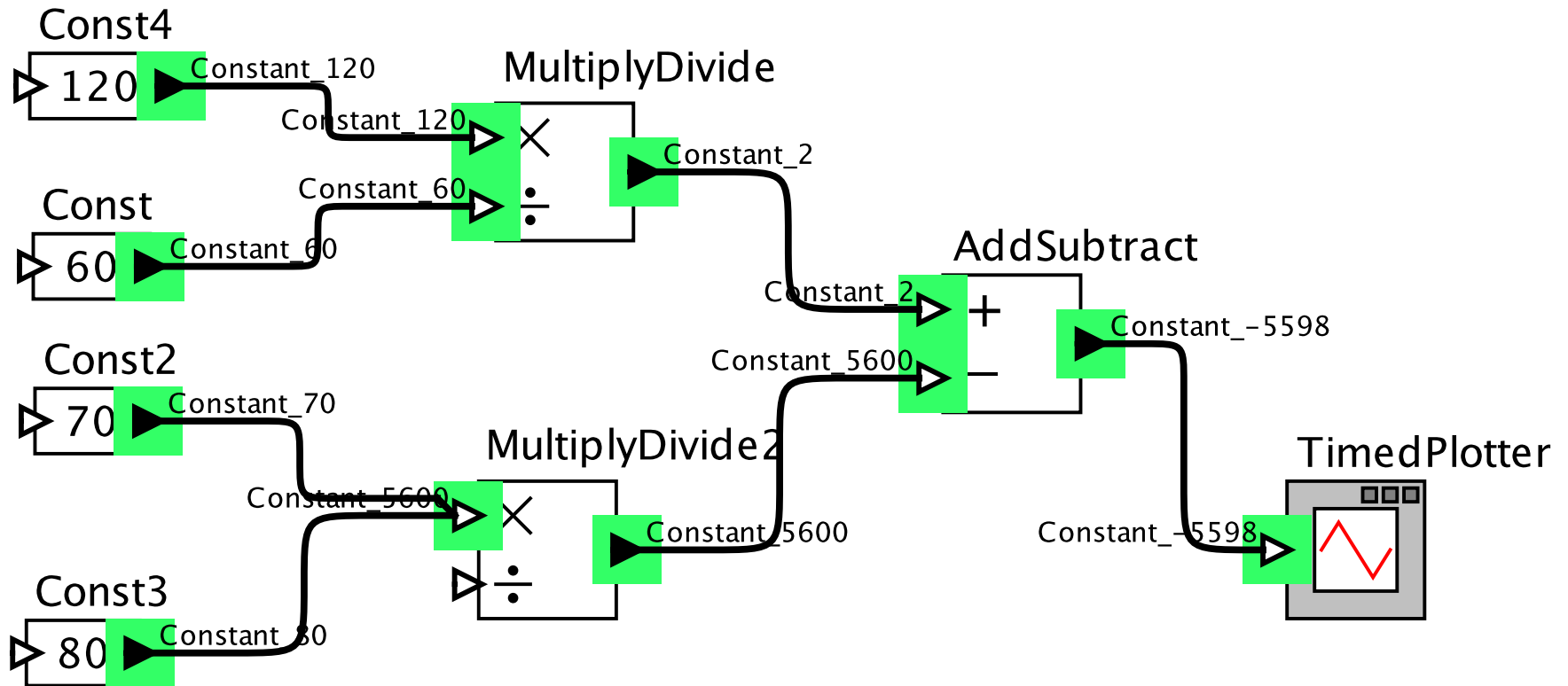
$$\left\{ \begin{array}{ll} \text{Unused} & \text{if } x = \text{Unused} \text{ or } y = \text{Unused} \\ \text{Constant}(c_x - c_y) & \text{if } x = \text{Constant}(c_x) \\ & \text{and } y = \text{Constant}(c_y) \\ \text{Nonconst} & \text{otherwise} \end{array} \right.$$



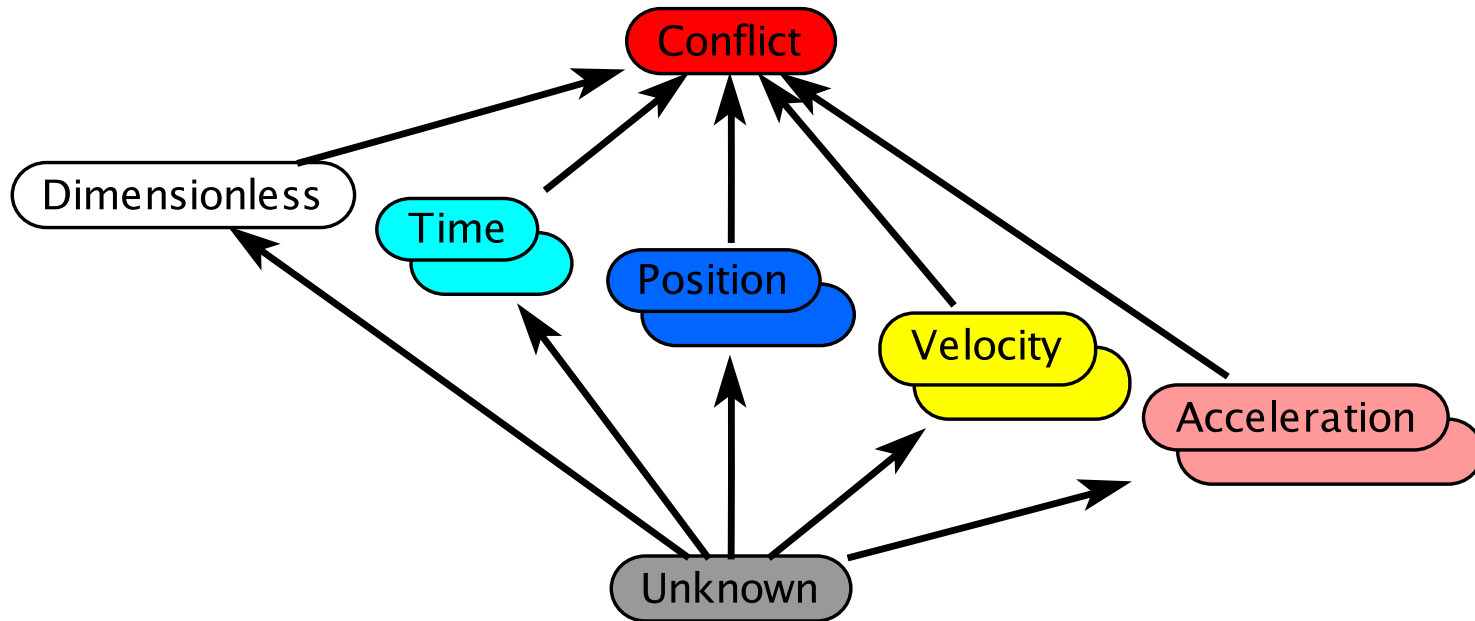
# Constant Propagation Analysis



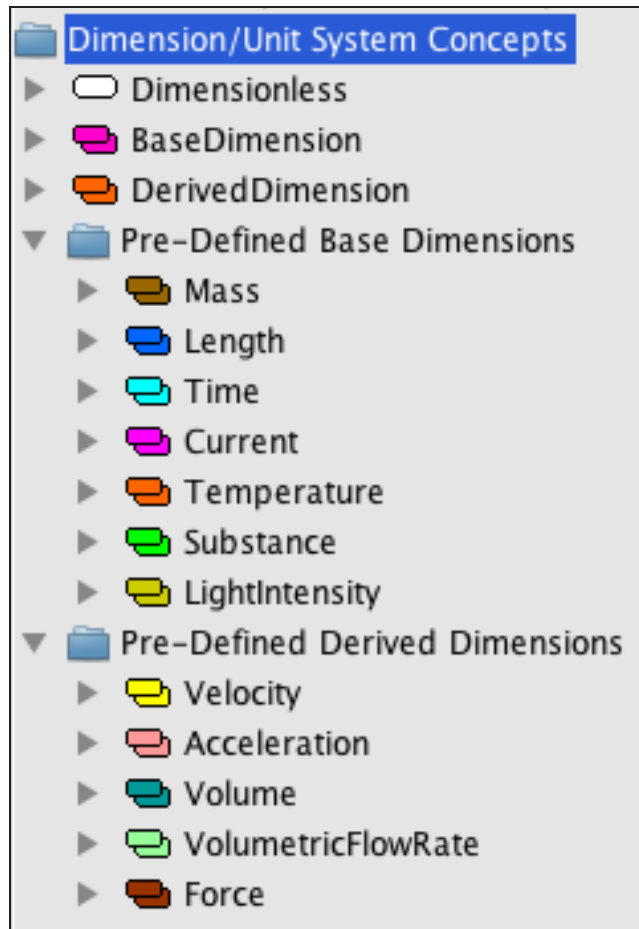
# Constant Propagation Analysis



# Full Unit Systems



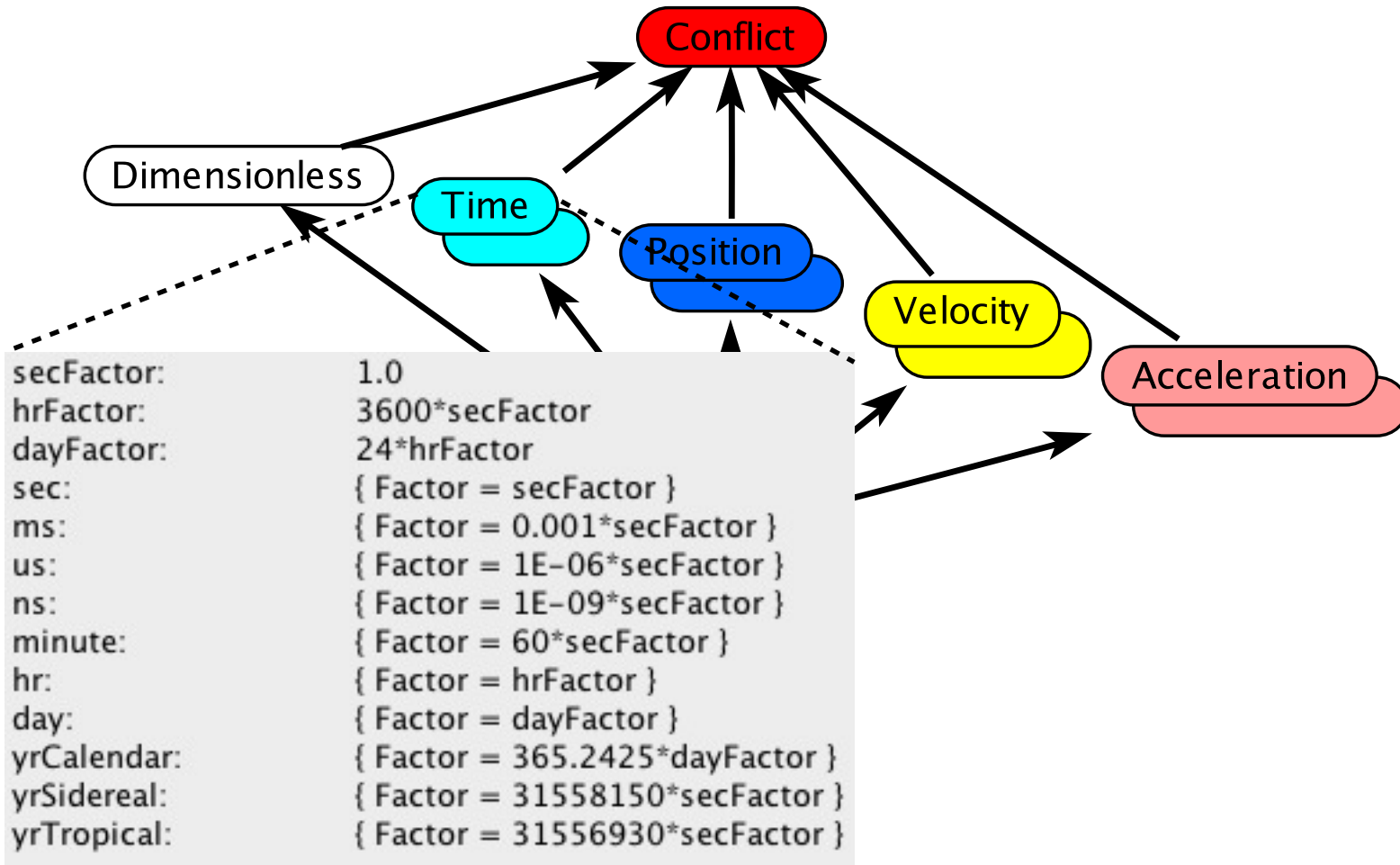
# Units Library



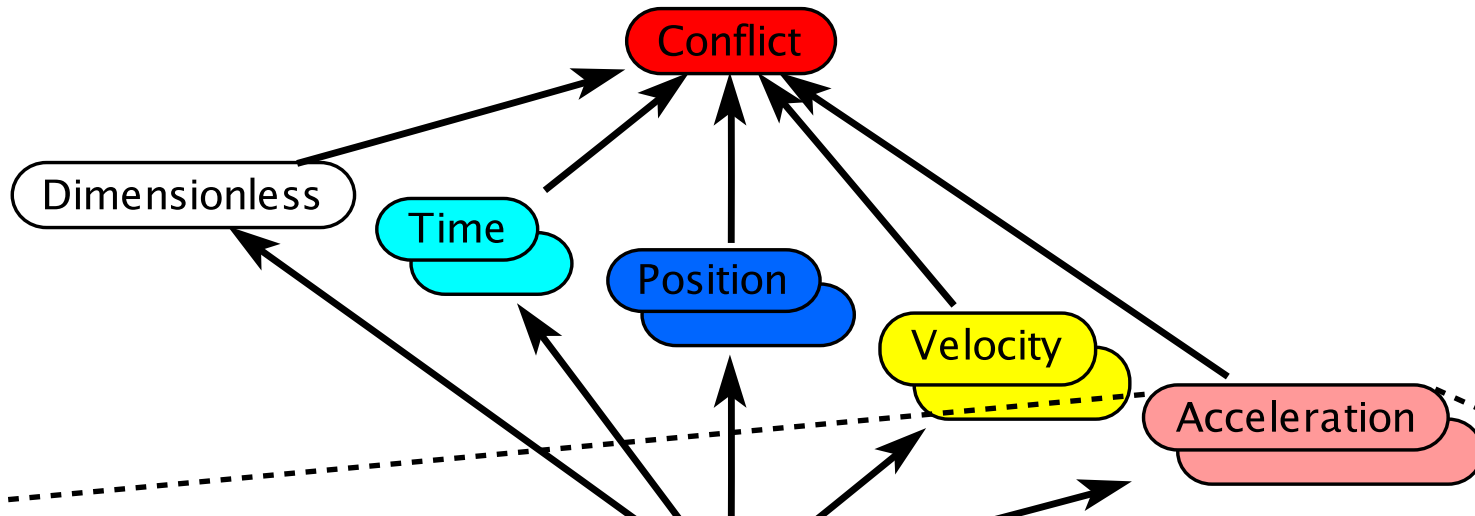
Divides units into *base dimensions* and *derived dimensions*.

Contains commonly used units of mass, time, length, force, etc.

# Base Concepts



# Derived Concepts

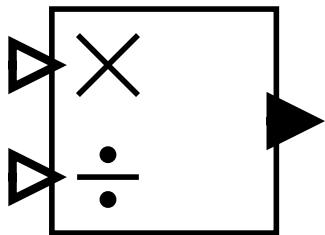


dimensionArray:	{ {Dimension = "LengthConcept", Exponent = 1}, {Dimension = "TimeConcept", Exponent = -2} }
LengthConcept:	Position
TimeConcept:	Time
m_per_sec2:	{ LengthConcept = {"m"}, TimeConcept = {"sec", "sec"} }
cm_per_sec2:	{ LengthConcept = {"cm"}, TimeConcept = {"sec", "sec"} }
ft_per_sec2:	{ LengthConcept = {"ft"}, TimeConcept = {"sec", "sec"} }
kph_per_sec:	{ LengthConcept = {"km"}, TimeConcept = {"hr", "sec"} }
mph_per_sec:	{ LengthConcept = {"mi"}, TimeConcept = {"hr", "sec"} }

# Automatically Inferred Constraints

Multiply/divide and related constraints need not be specified for these unit systems.

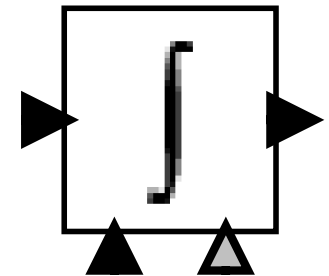
MultiplyDivide



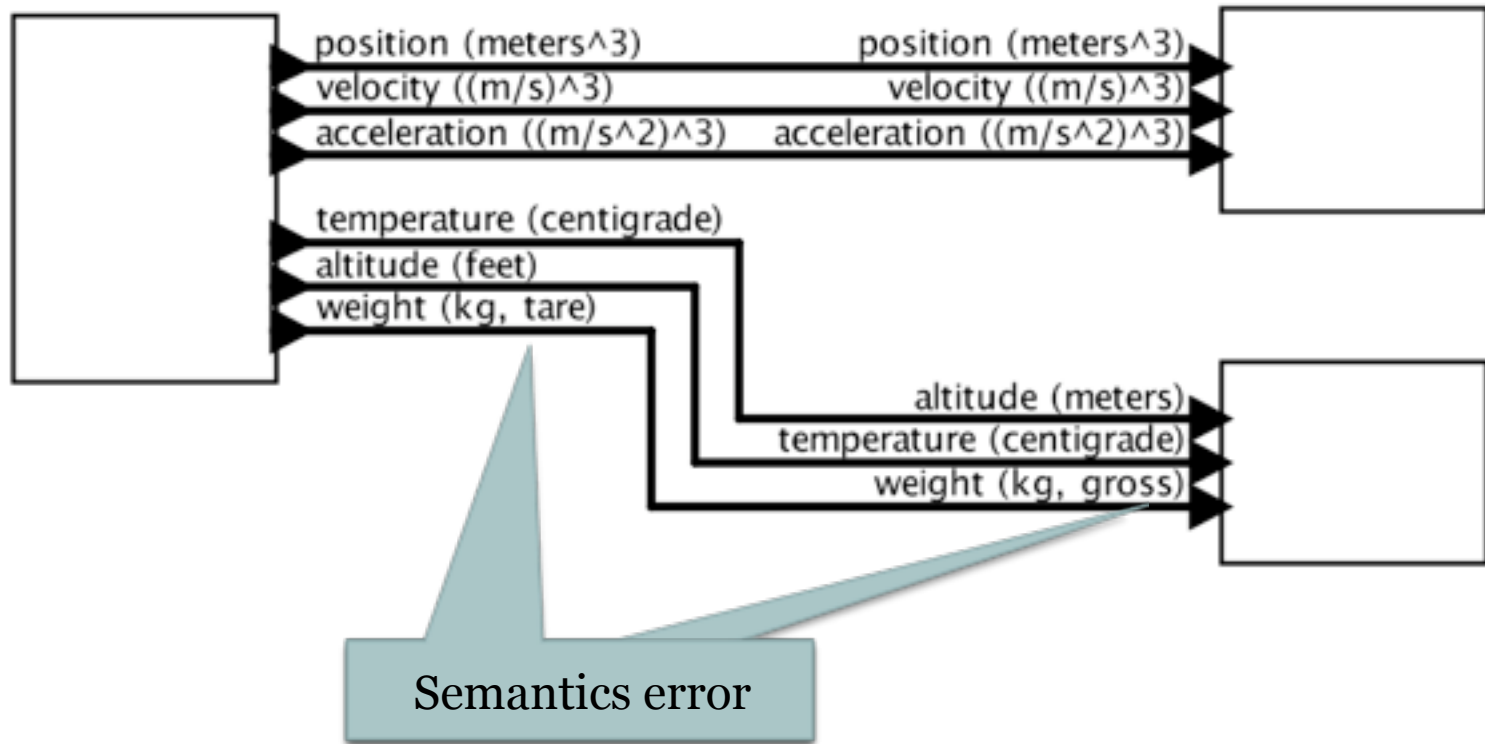
Estimate Current Position



Integrator

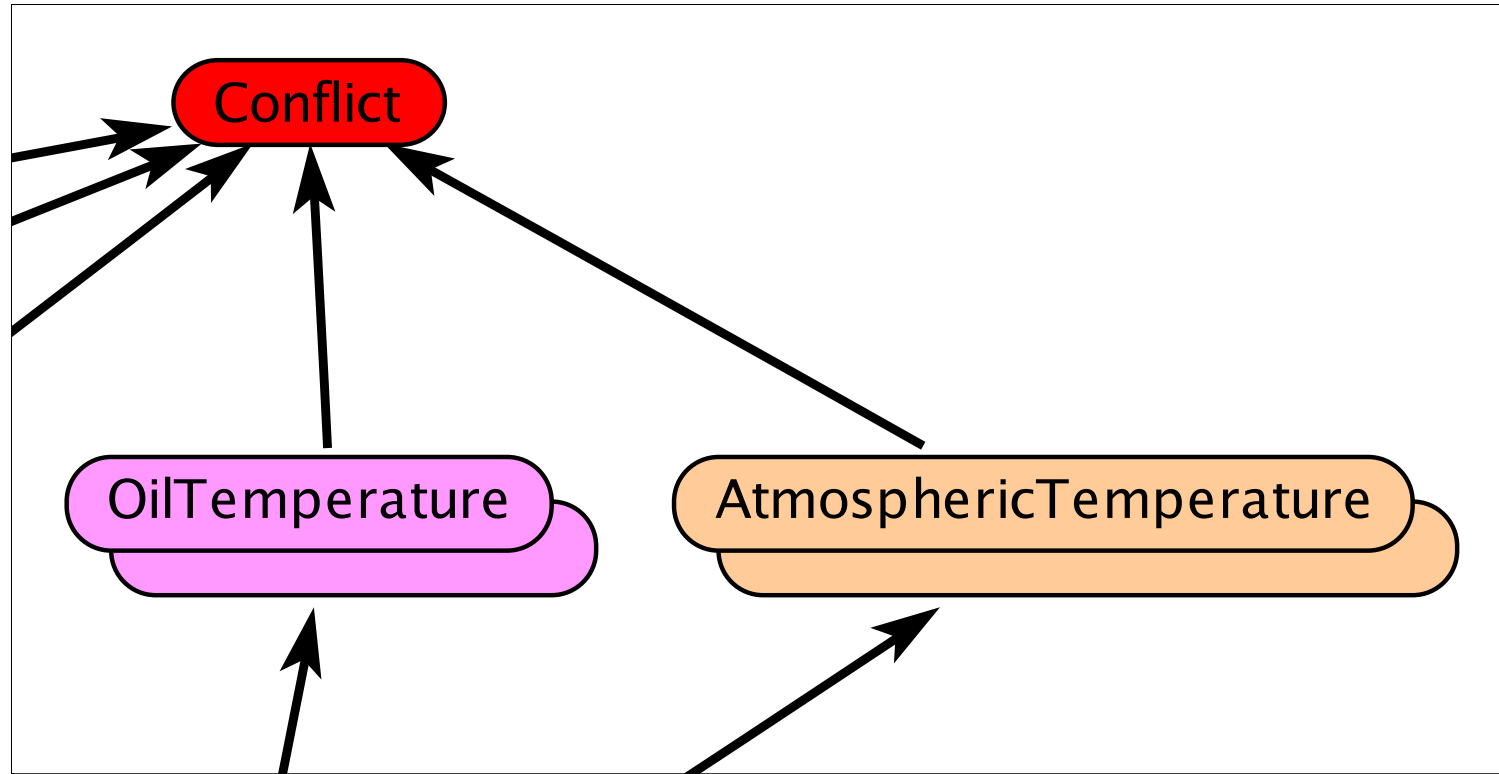


# Semantics Errors





# Domain-specific Units



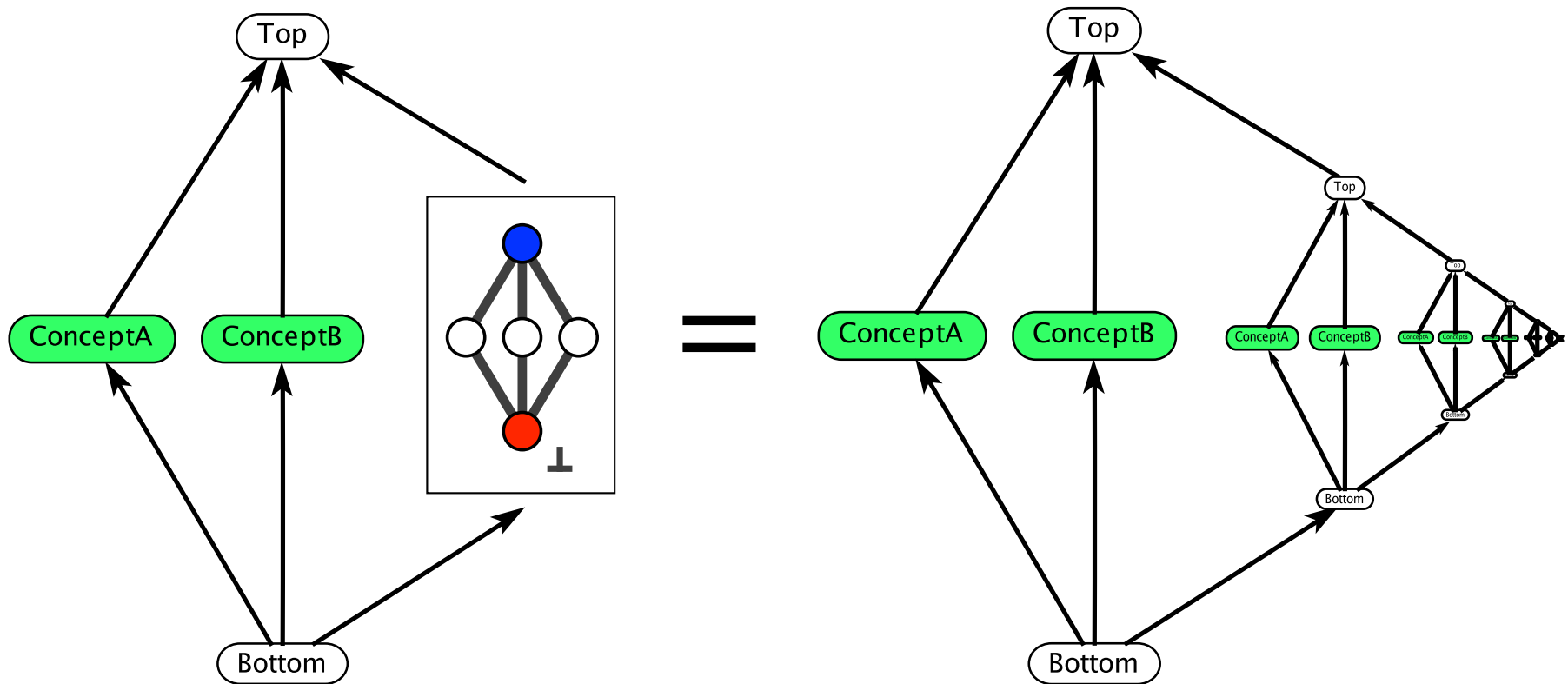
# Record Types

```
record = {  
    label1 : data1;  
    label2 : data2;  
    ...  
}
```

Representing the concept of a record can be difficult.

# Recursive Ontologies

Recursive lattices can express structured data types.



# Related Work

1. Constraint Satisfiability (Rehof and Mogensen)
  - Efficient inference algorithm
2. Abstract Interpretation (Cousot and Cousot)
  - Analysis of static semantics using complete lattices.
3. Existing systems for unit analysis, including those for Ada, SCADE, SystemC, and C++

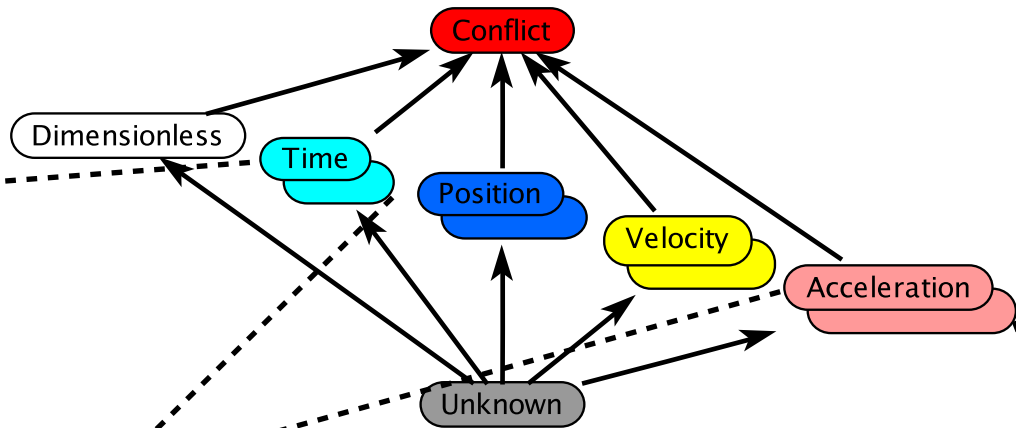
# Conclusion

Our analysis framework:

1. Efficiently infers unspecified concepts throughout large models.
2. Includes general mechanisms for infinite lattices
3. Specifically includes useful features for unit systems.

# Thanks!

# Questions?



```
secFactor: 1.0
hrFactor: 3600*secFactor
dayFactor: 24*hrFactor
sec: { Factor = secFactor }
ms: { Factor = 0.001*secFactor }
us: { Factor = 1E-06*secFactor }
ns: { Factor = 1E-09*secFactor }
minute: { Factor = 60*secFactor }
hr: { Factor = hrFactor }
day: { Factor = dayFactor }
yrCalendar: { Factor = 365.2425*dayFactor }
yrSidereal: { Factor = 31558150*secFactor }
yrTropical: { Factor = 31556930*secFactor }
```

```
dimensionArray: { {Dimension = "LengthConcept", Exponent = 1}, {Dimension = "TimeConcept", Exponent = -2} }
LengthConcept: Position
TimeConcept: Time
m_per_sec2: { LengthConcept = {"m"}, TimeConcept = {"sec", "sec"} }
cm_per_sec2: { LengthConcept = {"cm"}, TimeConcept = {"sec", "sec"} }
ft_per_sec2: { LengthConcept = {"ft"}, TimeConcept = {"sec", "sec"} }
kph_per_sec: { LengthConcept = {"km"}, TimeConcept = {"hr", "sec"} }
mph_per_sec: { LengthConcept = {"mi"}, TimeConcept = {"hr", "sec"} }
```