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Kyoto University
Deriving Parameter Conditions for Periodic Timed Automata Satisfying Real-Time Temporal Logic Formulas

1 Introduction

Model checking[1] have been recognized as one of very useful and effective methods for designing reliable hardware/software systems. Especially, in recent years, real-time systems must be developed for the areas that high reliability is required, such as aircraft/train/car controlling, nuclear reactors, medical devices and other real-time systems which may be produced a lot and hard to modify in later (e.g. hardware chips or embedded systems). Model checking techniques for real-time systems may be very useful for developing such a reliable real-time system to ensure that the system's design written in a some formal model satisfies the required properties such as safety, liveness, or fairness.

The classical model checking method is not parametric, that is, to check whether a behavioral specification written in some state model, satisfies some requirement specification (property) written in temporal logic, all the parameters in the specification must be fixed to some concrete values. [2] proposed a semi-decision procedure to derive a symbolic representation of states of a (parametric) hybrid automaton (an extension of a timed automaton) which satisfy a given temporal property written in a (parametric) real-time temporal logic formula. They adopt first-order theory with addition on real-numbers[3] as symbolic representation of state-sets. Although the satisfiability of the first-order theory with addition on real-numbers is decidable, fixpoint calculation is very costly and generally undecidable. On the other hand, [4] proposed an algorithm to obtain the condition of parameters in order that the given non-parametric state model on dense time domain satisfies the given parametric temporal logic formula. However, they only allow to write parameters to temporal logic formulas, not in a timed automaton. In a realistic system design process, we usually want to choose parameter values of models (implementations) rather than in temporal logic (specifications).

Thus, we propose a decision algorithm to derive a set of parameters of a subclass of a timed automaton model which may contain parameters (parametric timed automata[5]) and satisfies a formula of a real-time extension of CTL[1]. In our method, parameters are allowed in both a model and a temporal logic formula. We adopt formulas of first-order theory with addition on real-numbers[3] as symbolic representation of sets of parameter values. It is known to be decidable to check satisfiability and mechanical quantifier-elimination is also possible. In order to reduce the size of the intermediate symbolic representation, we take an on-the-fly approach, that is, we decompose the given problem on-the-fly to several subproblems, and recursively solve the subproblems to construct the entire condition for parameters. In this approach, we need not encode symbolically the entire state space (it tends to be very long), and only the necessary part of the tree is traversed. Specifically, we compute the weakest condition $WPC(s, f)$ of parameters in order that the state $s$ of the given model satisfy the given temporal property $f$. First, we define $WPC(s, f)$ as a recursive function such as

$$WPC(s, f) \triangleq F(WPC(s_1, f_1), \ldots, WPC(s_k, f_k)),$$

where $F()$ is a functional on first-order formulas, each $s_i$ is some next state of $s$, and each $f_i$ is some derived formula of $f$. Basically, we can compute the weakest condition $WPC(s, f)$ if the application of the recursive definition of $WPC(s, f)$ is ensured to terminate. However, that is not the case in general. If the model contains some loops, such a recursive application does not terminate. To cope with the problem, we find some subclass of the timed automaton such that we need not to explore the infinite computation tree. When the model is a periodic timed automaton, that is, after some fixed time period it returns to its initial state and continues its behavior, we have only to check some finite part of the infinite computation tree and output the result. In our method, $WPC(s, f)$ is ensured to be obtained after a fixed steps of recursive computations, thus we can avoid costly fixpoint calculations of first order theory on real-numbers.

2 Periodic Timed Automata

In this section, we formally define our model, periodic timed automata. To begin with, we define a (non-periodic) parametric timed automaton model. Our definition of timed automata is essentially the same but slightly different from the traditional definition in [6], since we generally allow timing constraints to be first-order formulas with addition on real-numbers.

Let $Act$ denote a set of actions, $Var$ denote a set of variables, and $Pred(Var)$ denote a set of formulas of
first order theory with addition on real-numbers over \( \text{Var} \). We also denote a set of real-numbers by \( \mathbb{R} \) and a set of nonnegative real-numbers by \( \mathbb{R}^{*} \).

**Definition 2.1** A parametric timed automaton is a tuple \((S, C, \text{PVar}, E, \text{Inv}(), \text{s}_\text{ini})\), where \( S \) is a finite set of control states, \( C \subseteq \text{Var} \) is a finite set of clocks, \( \text{PVar} \subseteq \text{Var} \) is a finite set of parameters, \( E \subseteq S \times \text{Act} \times \text{Pred}(\text{Var}) \times 2^C \times S \) is a transition relation, \( \text{Inv}() : S \mapsto \text{Pred}(\text{Var}) \) is an invariant condition for each state, \( \text{s}_\text{ini} \) is the initial state. We write \( s_i \xrightarrow{a_{Pr}} s_j \) if \((s_i, a, P, r, s_j) \in E\). □

Informally, a transition \( s_i \xrightarrow{a_{Pr}} s_j \) means that the action \( a \) can be executed from \( s_i \) when the values of both clocks and parameters satisfy the formula \( P \) (called a guard condition), and after executed, the state moves into \( s_j \) and the clock in the set \( r \) are reset to 0. In any state \( s \), values of all clocks always increase continuously at the same speed, representing the time passage. Note that the values of clocks (and parameters if any) can never violate the invariant condition \( \text{Inv}(s) \). Intuitively, \( \text{Inv}(s) \) represents the range of values (e.g. minimum and maximum values) allowed for clocks (and parameters). Thus, time passage at state \( s \) will stop when the value of some clock will exceed the maximum value specified by \( \text{Inv}(s) \). When time passage stops, some executable action is forced to execute, representing urgency of the action. Also, if \( \text{Inv}(s') \) will be violated, any transition into the state \( s' \) is not allowed to execute.

**Example 2.1** Fig. 1 is a simple example of a parametric timed automaton. In Fig. 1, a set of parameters is \( \{x, y, z\} \), a set of clocks is \( \{c, c'\} \), the initial state is \( s \), and the transition \( s \xrightarrow{a_{Pr}} s_1 \) means that in state \( s \), for a given value of the parameter \( x \), some time may be elapsed (i.e. the clock \( c \) increases) while \( c \) satisfies the invariant \( [c \leq x] \). When \( c \leq x \), the action \( a \) can be executed, no clocks are reset to 0, and the state changes to \( s_1 \) (the invariant of \( s_1 \) is [true]). Similarly, the transition \( s \xrightarrow{b_{Pr}} s_2 \) means that some time may be elapsed while \( c \) satisfies the invariant \( [c \leq x] \), and when \( c > x \), the action \( b \) can be executed, the clock \( c' \) is reset to 0, and the state changes to \( s_2 \). In the transition \( s \xrightarrow{d_{Pr}} s_3 \), a guard condition for both clocks \( c \) and \( c' \) are specified using parameters \( y \) and \( z \).

![Fig. 1: Example of Parametric Timed Automata](image)

Let \( CS \equiv ((s, \rho) | s \in S, \rho \in \text{Val} \) be a set of concrete states. The semantic transition system consists of delay-transitions and action-transitions. A delay transition represents a time passage and an action transition represents an execution of an action. Formally, the semantic transition system is defined as follows.

**Definition 2.2** A semantic transition system for a parametric timed automaton \((S, C, \text{PVar}, E, \text{Inv}(), \text{s}_\text{ini})\) is a labelled transition system on concrete states \( CS \), where the transition relation is defined by the following rules:

- \((s, \rho) \xrightarrow{\rho + t} (s, \rho + t) \) if \( t \in \mathbb{R}^* \) and \( \rho + t \vdash \text{Inv}(s) \).
- \((s, \rho) \xrightarrow{a} (s', \rho[r \mapsto 0]) \) if \( s \xrightarrow{a_{Pr}} s', \rho \vdash P \) and \( \rho[r \mapsto 0] \vdash \text{Inv}(s') \).

where \( \rho + t \) and \( \rho[r \mapsto 0] \) are the functions from variables to real-numbers, defined as follows:

\[
\rho(x) + t = \begin{cases} 
\rho(x) + t & \text{if } x \in C, \\
\rho(x) & \text{otherwise.}
\end{cases}
\]

\[
\rho(x)[r \mapsto 0] = \begin{cases} 
0 & \text{if } x \in r, \\
\rho(x) & \text{otherwise.}
\end{cases}
\]

The major difference of periodic timed automata from normal parametric timed automata is that it checks the elapsed time since it is started, and if it is equal to the specified period \( T \), then it resets to its initial state. Moreover, it is assumed that only finitely bounded actions can be performed before returning to the initial state. To ensure the above properties, we define a periodic timed automaton as one obtained by adding reset transitions to a parametric timed automaton with no loops (we refer to such a parametric timed automaton as a finite periodic timed automaton). Formally it is defined as follows.

**Definition 2.3** A finite periodic timed automaton is a parametric timed automaton whose transition graph has no directed cycles, (i.e. it is a Directed Acyclic Graph (DAG)).

**Example 2.2** The parametric timed automaton in Example 2.1 is a finite periodic timed automaton since its transition graph is a tree (so it is also a DAG).

**Definition 2.4** A periodic timed automaton is a parametric timed automaton which is obtained by adding to
a finite parametric timed automaton following some special reset transitions for every state $s$: 

$$s \xrightarrow{(c_{p}=T), (c',c_{p})} s_{init}.$$ 

where $s_{init}$ is an initial state, $C$ is a set of all clocks, $c_{p} \in C$ is a special clock which keeps the elapsed time from the initial state $s_{init}$ (no other transition can reset this clock), $T \in \mathbb{R}^{+}$ is a period, $i \in \text{Act}$ is a special reset action.

**Example 2.3** Fig 2 is an example of a periodic timed automaton. This example is a modified version of Example 2.2 where a special clock $c_{p}$ and some return transitions such as $s_{1} \xrightarrow{(c_{p}=T), (c',c_{p})} s_{2}$ are added. Note that we allow periodic timed automata to terminate instead of returning to the initial state, such as the state $s_{3}$ in Fig 2.

**3 Real-time CTL**

In this section, we define RPCTL, a Real-time and Parametric extension of Computation Tree Logic (CTL)[2].

**Definition 3.1** The syntax of RPCTL formula is defined by the BNF in Fig. 3. where $a \in \text{Act}$ is an action name, $p$ is a linear expression which may contain constant real-numbers and/or a parameter variable, and 

$$f \equiv \text{true},$$

$$\neg f \equiv \text{false},$$

$$f_{1} \land f_{2} \equiv f_{1} \land f_{2},$$

$$f_{1} \lor f_{2} \equiv f_{1} \lor f_{2},$$

$$f \Rightarrow f \equiv f \Rightarrow f,$$

$$\langle a \rangle_{p} f \equiv \langle a \rangle_{p} f,$$

$$\langle E U \rangle_{p} f \equiv \langle E U \rangle_{p} f,$$

$$\langle A U \rangle_{p} f \equiv \langle A U \rangle_{p} f,$$

$$\langle G \rangle_{p} f \equiv \langle G \rangle_{p} f,$$

$$\langle E F \rangle_{p} f \equiv \langle E F \rangle_{p} f,$$

$$\langle A F \rangle_{p} f \equiv \langle A F \rangle_{p} f,$$

$$\langle F \rangle_{p} f \equiv \langle F \rangle_{p} f.$$ 

\(\sim \in \{<,\leq,>,\geq,=\}\) is a comparison operator. We may omit '¬' p' specifier, and in that case '≥ 0' is assumed.

RPCTL is a logic to specify a property of a parametric timed automaton state and its succeeding behavior using temporal operator with timing constraints which may contain parameters. Intuitive meaning of basic constructs of RPCTL is as follows. 'true' is satisfied by all concrete states. '¬f' is satisfied by a concrete state $(s, p)$ if and only if $f$ is not satisfied by $(s, p)$. 'false' is never satisfied by any concrete states, which is equivalent to 'true'. $f_{1} \land f_{2}$ is satisfied if and only if both $f_{1}$ and $f_{2}$ is satisfied. $f_{1} \lor f_{2}$ and $f_{1} \Rightarrow f_{2}$ are defined similarly to classic propositional logic. '⟨a⟩p f' is satisfied by $(s, p)$ if and only if there exists some transition from $(s, p)$ performing a within c units of time, such that $f$ is satisfied by the next (control) state. Since we can define similarly if ¬ is other than $< (\text{case of } \geq, <, >, =)$, we only mention the case of $\leq$ in the following explanation. '⟨a⟩p f' is satisfied if and only if for any transition from the state performing a within c units of time, $f$ is satisfied by the next state, which is the same as $\neg ⟨a⟩p \neg f$. 'f₁ EUₜ₂ p' is satisfied if and only if there exists some transition sequence such that $f₂$ eventually holds within c units of time and until then, $f₁$ is always satisfied. 'f₁ AUₜ₂ p' satisfied if and only if for any transition sequence, $f₂$ eventually holds within c units of time and until then, $f₁$ is always satisfied. 'EFₜ₂ p'.
"AG_{SP}f", "AF_{SP}f" and "EG_{SP}f" are abbreviations for trueEU_{SP}f, \neg EF_{SP}f, trueAU_{SP}f and \neg AF_{SP}f, respectively.

In general, we write \( M, (s, \rho) \models f \) to mean that an RPCTL formula \( f \) is satisfied by a concrete state \((s, \rho)\) of a parametric timed automaton \( M \). If there are no confusions, we omit \( M \) and just write \((s, \rho) \models f \). The formal definition of the relation \( \models \) is as follows. We only give the definitions for six primitive constructs, \( true, \neg f, f_{1} \land f_{2}, f_{1}E_{\leq p}f_{2} \) and \( f_{1}AU_{\sim p}f_{2} \). Rest of the constructs can be rewritten by using the above constructs.

**Definition 3.2** The relation \((s, \rho) \models f\) is formally defined in Fig. 4.

**Example 3.1** The RPCTL formula

\[
[a_{1}].c_{0}(((a_{2})true)EU_{SP}((a_{3})true))
\]

means that for every state reachable after executed the action \( a_{1} \) within \( q_{1} \) units of time, there exists a execution path such that the action \( a_{2} \) is always executable until \( a_{3} \) becomes executable after \( q_{2} \) units of time elapsed.

Note that \( q_{1} \) and \( q_{2} \) are parameter variables.

4 Deriving the Weakest Condition of Parameters

Now we describe our method to derive symbolically the weakest condition of parameters \( WPC(s, f) \) in order that the state \( s \) of the periodic timed automaton satisfies the RPCTL property \( f \). Beforehand, we give the precise definition of our problem.

**Definition 4.1** Let \( M \) be an parametric timed automaton, \( s \) be a state of \( M \), and \( f \) be an RPCTL formula. The parameter condition derivation problem is a problem to derive a first-order formula \( WPC(s, f) \) such that

\[ \rho \models WPC(s, f) \text{ iff } (s, \rho) \models f. \]

At first, we give an algorithm to solve the parameter condition problem for finite parametric timed automata, and then we extend it to periodic timed automata.

4.1 Finite Model Case

As mentioned in Section 1, we define \( WPC(s, f) \) as a recursive function such that

\[ WPC(s, f) \equiv F(WPC(s_{1}, f_{1}), \ldots, WPC(s_{k}, f_{k})). \]

Here we give a concrete definition of the function \( WPC(s, f) \) for every construct of RPCTL formula \( f \).

**Definition 4.2** The function \( WPC(s, f) \), which takes as arguments a state \( s \) of a parametric timed automaton, and a RPCTL formula \( f \), and returns a first order formula, is defined as Fig 5, where \( F[C + t/C] \) \( (0/0/r) \) represents a first order formula \( F \) whose every free occurrence of each variable \( x \in C (x \in r) \) is replaced with \( x + t \) \( (0, \text{respectively}) \).
the following condition holds:

\[ \rho \models (0 \leq t \land t \sim p \land \text{Inv}(s) \land P \land (\text{Inv}(s) \land WPC(s, f')[0/r]))[C + t/C]. \]

Since it is sufficient that some non-negative real-number \( r \) and some transition \( s \xrightarrow{a,P_{i},r_{i}} s' \) exist, we can weaken the above condition as:

\[ \rho \models \exists r(0 \leq t \land t \sim p \land \text{Inv}(s) \land \bigwedge_{i \in I(s)} (P_{i} \land (\text{Inv}(s_{i}) \land WPC(s_{i}, f')[0/r])))[C + t/C]. \]

where \( I(s, a) \) is a set of indices of transitions whose source node is \( s \) and action name is \( a \).

We can easily prove that this is the weakest condition of \( \rho \) such that \((s, \rho) \models f\), and \( r \) is some fresh variable which does not appear in either \( \text{Inv}(s) \), \( P_{i} \), \( \text{Inv}(s_{i}) \) or \( WPC(s_{i}, f') \).

Consider the case of \( f = f_{1}EU_{\sim p}f_{2} \). Similar to above, suppose \( \rho \) is a value-assignment such that \((s, \rho) \models f_{1}EU_{\sim p}f_{2}\). From the Definition 3.2, there must exist some transition sequence \((s, \rho) \xrightarrow{a_{1},P_{1},r_{1}} (s_{1}, \rho_{1}) \xrightarrow{a_{2}, \ldots, a_{n}, P_{n}, r_{n}} (s_{n}, \rho_{n}) \xrightarrow{a_{n+1}, P_{n+1}, r_{n+1}} (s_{n+1}, \rho_{n+1}) \) such that \((s_{n}, \rho_{n}) \models f_{2}, t_{1} + \cdots + t_{n} \sim p, \) and for any \( j \) \((1 \leq j \leq k) \) and for any \( t'_{j} \) \((0 \leq t'_{j} < t_{j}) \), \((s_{j}, \rho_{j}) \) holds.

To obtain a recursive definition of \( WPC(s, f) \), we divide the premise of the above statement into two cases, \( k = 1 \) and \( k \geq 2 \).

**Case k = 1:** If \( k = 1 \), then there must exist a transition sequence \((s, \rho) \xrightarrow{a_{1},P_{1},r_{1}} (s_{1}, \rho_{1} + t_{1}) \) such that \((s_{1}, \rho_{1} + t_{1}) \models f_{2}, \) \( t_{1} \sim p \) and for any \( t'_{1} \) \((0 \leq t'_{1} < t_{1}) \), \((s_{1}, \rho_{1} + t'_{1}) \) holds. Similar to the case of \( f = (a)_{-p}f' \), the weakest condition of \( \rho \) is obtained as follows:

\[ \rho \models \exists r(0 \leq t \land t \sim p \land (\text{Inv}(s) \land WPC(s_{1}, f_{2}))[C + t/C] \land \forall t'((0 \leq t' \land t' \leq t) \Rightarrow WPC(s_{1}, f_{2})[C + t'/C])]. \]

**Case k \geq 2:** If we assume \( k \geq 2 \), then there must exist a transition sequence \((s, \rho) = (s_{1}, \rho_{1}) \xrightarrow{a_{2}, P_{2}, r_{2}} (s_{2}, \rho_{2} + t_{2}) \) such that \((s_{2}, \rho_{2} + t_{2}) \models f_{1}EU_{\sim (c-)}f_{2}\), and for any \( t'_{2} \) \((0 \leq t'_{2} \leq t_{2}) \), \((s_{2}, \rho_{2} + t'_{2}) \) holds. Considering that there may exist multiple transitions \( s \xrightarrow{a,P_{i},r_{i}} s_{i} \), the weakest condition of \( \rho \) is obtained as follows:

\[ \rho \models \exists r(0 \leq t \land (\text{Inv}(s) \land \bigwedge_{i \in I(s)} WPC(s_{i}, f_{1}EU_{\sim (c-)}f_{2}))[C + t/C] \land \forall t'((0 \leq t' \land t' \leq t) \Rightarrow WPC(s_{1}, f_{2})[C + t'/C])]. \]

where \( I(s) \) is a set of indices of transitions whose source node is \( s \).

Therefore, the general case is (1) or (2), that is,

\[ \rho \models \exists r(0 \leq t \land \forall t'((0 \leq t' \land t' \leq t) \Rightarrow WPC(s, f_{1})[C + t'/C])] \land (\text{Inv}(s) \land (t \sim p \land WPC(s, f_{2}) \lor \bigwedge_{i \in I(s)} WPC(s_{i}, f_{1}EU_{\sim (c-)}f_{2}))[C + t/C]). \]

The case of \( f = f_{1}AU_{p}f_{2} \) is similar, and we omit the detailed description due to space limitation.

If the transition graph contains no loops, there are no cases that \( WPC(s, f) \) is recursively called during the computation of \( WPC(s, f) \) itself. Thus, the function \( WPC(s, f) \) is ensured to terminate. Hence, a recursive function \( WPC(s, f) \) is an algorithm to obtain the parameter condition for DAG-formed models (i.e., finite parametric timed automata).

**Theorem 4.1** For every state \( s \) of a finite parametric timed automaton \( M \) and every RPCTL formula \( f \), a recursive function \( WPC(s, f) \) always terminates and returns a correct solution of a parameter condition derivation problem, i.e.:

\[ \forall \rho. [\rho \models WPC(s, f) \iff (s, \rho) \models f]. \]

**4.2 Periodic Model Case**

If parametric timed automata have some loops, the algorithm \( WPC(s, f) \) in Theorem 4.1 may not terminate. In this section, we prove that if models are periodic timed automata, we have only to check a finite fragment of the computation tree to derive the weakest condition of parameters.

At first, we introduce the notion of unfolding. Replace all returning transitions of a periodic timed automaton (Fig. 6-(a)) with transitions to special terminating states. We obtain the corresponding finite parametric timed automaton (Fig. 6-(b)). Then, attach the copies of the corresponding finite parametric timed automaton to each special terminating state of itself, once for all. Finally, we have the timed automaton which represents the first 2 period behavior (Fig. 6-(c)). We refer to such a model as an unfolding of the periodic timed automaton. Similarly, we can also define a \( k \)-unfolding of a periodic timed automaton as the finite parametric timed automaton which represents the first \( k \) period behavior.

Our result is that without loss of generality, we have only to check 3-unfolding of periodic timed automata for each subformula including 'until' operators \( EU \) and \( AU \), to derive the paths whose execution times is within 3 periods.

Formally, it is proved by the following lemma:
Lemma 4.1 For any concrete state \( (s, \rho) \) of periodic timed automata, the following condition holds:

\[
(s, \rho) \models f_{1}EU_{\sim p}f_{2} \iff (s, \rho) \models f_{1}EU_{\sim \rho}f_{2}
\]

where \( T \) is the period of the periodic timed automata, \( p' \overset{\text{def}}{=} \rho - m \times T \) and \( m \) is the minimum nonnegative integer s.t. \( p - m \times T < 3T \). The same condition also holds for \( f_{1}AU_{\sim p}f_{2} \).

(proof) Detailed proof is omitted due to space limitation, but we can prove that if there exists an execution path \( \alpha \) which satisfies the \"until\" property and whose execution time \( ET(\alpha) \) is greater than 3 periods, there also exists a path \( \alpha' \) whose execution time is less than 3 periods, and satisfy the same property, and vice versa (illustrated in Fig. 7).

We define another algorithm \( WPC3(s, f) \) instead of \( WPC(s, f) \) for periodic timed automata. \( WPC3(s, f) \) is almost the same as \( WPC(s, f) \), except that \( WPC3(s, f_{1}op_{\sim p}f_{2}) \) (\( op \) is one of \"until\" operators) is applied to 3-unfolding of the given periodic timed automaton. Specifically, for each subformula \( f_{1}op_{\sim p}f_{2} \), \( WPC3(s, f_{1}op_{\sim p}f_{2}) \) traverses the 3-unfolding where \( s \) is assumed to be the state of the first period. Unlike \( WPC(s, f) \), \( WPC3(s, f) \) is ensured to terminate. By Lemma 4.1, it is sufficient to consider finite paths whose execution time is at most \( 3T \) in order to derive the weakest condition of parameters. Therefore, we obtain the following main theorem:

**Theorem 4.2** For every state \( s \) of a periodic timed automaton \( M \) and every RPCTL formula \( f \), a recursive function \( WPC3(s, f) \) always terminates and returns a correct solution of a parameter condition derivation problem, i.e.:

\[
\forall \rho. [\rho \models WPC3(s, f) \iff (s, \rho) \models f] 
\]

5 Concluding Remarks

In this paper, we propose a method to derive a parameter condition for a periodic timed automaton which satisfies a property written in a temporal logic RPCTL formula.

Although our method applies to only restricted class of timed automata, many real-time applications such as audio/video streaming, time sharing task schedulers, etc. can be specified as a periodic timed automaton. Therefore, our method may be useful for system designers choose correct parameters to guarantee the specified correctness properties of such periodic systems.

The future works are to extend our method to handle some internal variables, and to apply the method to a practical application to evaluate the efficiency.

References


