3rd NASA Langley Formal Methods Workshop

Formal Methods Demonstration Project for Space Applications

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- Joint NASA Code QRTP -
  Jet Propulsion Laboratory*
  Johnson Space Center
  Langley Research Center

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The Requirements Problem in Engineering Software Subsystems

Requirements and design specifications are high priority candidate for better software engineering techniques

- Most hazardous software safety errors found during system integration and test of two NASA spacecraft were the result of requirements discrepancies or interface specifications [Lutz93].
- The highest density of major defects found through the use of software inspections was during the requirements phase. This was 7 times higher than the density of major defects found in code inspections [Kelly92].
- Requirements errors are between 10 and 100 times more costly to fix at later phases of the software lifecycle than at the requirements phase itself [Basili84], [Boehm84], [Kelly92].

Current Requirements Process without Formal Methods

<table>
<thead>
<tr>
<th>Textual Description (&quot;shells&quot;)</th>
<th>Structure Modeling</th>
</tr>
</thead>
<tbody>
<tr>
<td>High-Level Test Plan</td>
<td></td>
</tr>
</tbody>
</table>

Baseline Review

* Note: The word "inspection" is used differently in software than in manufacturing or hardware context. In software the term "inspection" refers to a structured peer review that uses a checklist and includes the collection of defect statistics. In software development, inspections are an upstream quality enhancement technique which support the principles of TQM (refer to NASA Standard 2000-93 or the ISO JTR, Professional Development courses on this topic).
History of Formal Methods POP

Spring 1992 - JSC, JPL and LaRC submit independent Formal Methods proposals to NASA Code Q
Summer and Fall '92 - Code Q funds a Feasibility Study to derive a plan for how the 3 Centers could jointly do a Formal Methods RTOP
Winter '93 - Formal Methods Demonstration Project officially starts with a kick-off meeting at JSC
October '93 - Deliverables for Phase I completed (Formal Methods Specifications, Proofs, etc.)
December '93 - Phase I Report completed for demonstration of Formal Methods on an existing spacecraft
FY94 - Phase II Case Studies
- Formal Methods Guidebook (Vol 1)
FY95 - Phase III Case Studies
- Formal Methods Guidebook (Vol 2)

Introduction: Team Members

- Jet Propulsion Laboratory
  - John Kelly, Ph.D., Rick Cavigillon, Ph.D., Robyn Lutz, Ph.D., Ken Abersieh, Ph.D. (Forman U.)
- Johnson Space Center
  - Ernie Fridge, Dan Bowman (LORAL), Mike Belma (LORAL-Shuttle RA), Chris Fickey (LORAL-Shuttle RA)
- Langley Research Center
  - Ben Divito, Ph.D. (VIGYAN), Judith Crow, Ph.D. (SRI), Rick Butler
- NASA HQ Sponsor: Alice Robinson
- Alumni
  - Betty Cheng, Ph.D. (MSU), Mori Khorrami (JPL), Doc Shankar, Ph.D. (IBM), Scott French (LORAL), Sally Johnson (LaRC), John Rushby, Ph.D. (SRD), Sam Drake (SRD), Al Nikolov (JPL), Brent Auerheime, Ph.D. (CSUF), Yoko Anpoa (NFRC), David Hamilton (HP)

Purpose

- The Goal of this study is to demonstrate the applicability of Formal Methods techniques on critical NASA software subsystems
- Phase I Task: Demonstrate the Applicability of Formal Methods to Shuttle's On-Board Jet Select Software Subsystem (A highly critical, yet relatively stable set of requirements)
- Phase II Tasks: Demonstrate Formal Methods on several smaller projects which are currently developing critical software and provide guidance at the managerial level
- Phase III Tasks: Demonstrate Formal Methods on a large critical project in the early development stages, demonstrate at the design level, and provide guidance at the technical level

Generic approach for using Formal Methods to analyze requirements for Space Applications

- Select a portion of the requirements which is mission critical
- Model the selected requirement subset's structure using an informal approach (Object Modeling Techniques was used on some of the pilots)
- Develop Formal Specification for required functionality and state behavior (PVS was used for this on most of the pilots)
- Translate desired properties of the subsystem into a formal language then attempt to verify them against the Formal Specification with a theorem prover (PVS was used in most cases)
- Feedback lists of issues to Requirements Analysts and Development Engineers throughout this process
Lesson Learned (continued)

- Be willing to compromise and fill in the requirements
  analysis gaps with traditional techniques in addition to using
  Formal Methods
- Selecting portions of the requirements of large space
  application for which Formal Methods provides the greatest
  analysis leverage is nontrivial
- Formal Methods needs to be integrated with other V&V
  techniques (Fagan Inspections, Traceability Analysis,
  Hazards Analysis, etc.)
- Automated Integration
- Formal Methods should be introduced on projects which
  already have in place good solid V&V procedures ("pick
  fertile ground")

NASA GUIDEBOOK: FORMAL METHODS
SPECIFICATION AND VERIFICATION

- Volume I
  - Written for project decision makers, including managers,
    engineers, and assurance personnel, who are considering the use
    of FM on their project
  - Easily understood overview of important management issues
    associated with the use of formal specifications
  - Useful guide to planning and implementing FM on a project
  - Available: June 1995

NASA GUIDEBOOK: FORMAL METHODS
SPECIFICATION AND VERIFICATION

- Volume II
  - Will contain detailed information for technical practitioners of
    FM
  - Will address the needs of engineers whose role it is to evaluate
    new technologies, to transfer those technologies into practice in
    their organization, and to help projects in planning, training, and
    implementation
  - Available: Fall 1995

Key Issues for Next Steps (FY 96 and beyond)

- Integrate Formal Methods into a full set of verification,
  validation, modeling, and design techniques for critical
  software subsystems of space applications
- Act as a catalyst to transfer Formal Methods techniques to
  critical NASA Space projects
  - Developing a NASA technology transfer training package
  - Train starter groups of additional Formal Methods analysts
    from various NASA projects and centers
  - Act as advisors to NASA projects on the effective use Formal
    Methods
  - Develop focus point for the maturation of applying Formal Methods
    to NASA Space Application projects
The Space Shuttle program is cooperating in a pilot project to apply formal methods to live requirements analysis activities. As one of the larger ongoing Shuttle Change Requests (CRs), the Global Positioning System (GPS) CR involves a significant upgrade to the Shuttle’s navigation capability. Shuttles are to be outfitted with GPS receivers and the primary avionics software will be enhanced to accept GPS-provided positions and integrate them into navigation calculations. Prior to implementing the CR, requirements analysts at Loral Space Information Systems, the Shuttle software contractor, must scrutinize the CR to identify and resolve any requirements issues.

We describe an ongoing task of the Formal Methods Demonstration Project for Space Applications whose goal is to find an effective way to use formal methods in the GPS CR requirements analysis phase. This phase is currently under way and a small team from NASA Langley, ViGYAN Inc. and Loral is now engaged in this task. Background on the GPS CR is provided and an overview of the hardware/software architecture is presented. We outline the approach being taken to formalize the requirements, only a subset of which is being attempted. The approach features the use of the PVS specification language to model “principal functions,” which are major units of Shuttle software. Conventional state machine techniques form the basis of our approach.

Given this background, we present interim results based on a snapshot of work in progress. Samples of requirements specifications rendered in PVS are offered for illustration. We walk through a specification sketch for the principal function known as GPS Receiver State Processing. Results to date are summarized and feedback from Loral requirements analysts is highlighted. Preliminary data is shown comparing issues detected by the formal methods team versus those detected using existing requirements analysis methods. We conclude by discussing our plan to complete the remaining activities of this task.
Using Formal Methods to Analyze the Space Shuttle's GPS Change Request

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Shuttle Program Background

- Contractor organization
  - Rockwell International – Shuttle prime contractor
  - Loral Space Info. Sys. (was IBM) – Software contractor
  - Draper Lab – Experts in Guidance, Navigation and Control
- Software modifications are packaged as Change Requests (CRs)
  - Usually modest in scope, localized in function
  - Provide capabilities to meet specific mission needs
- Software releases are called Operational Increments (OIs)
  - Include one or more CRs – issued around once per year
- Requirements Analysis
  - Conducted by Loral Requirements Analysts (RAs) prior to turning CR over to development team
  - Once in development, problems are more costly to fix

Global Positioning System (GPS)

GPS is a satellite-based navigation system operated by DoD

- Constellation of 24 satellites in high orbits
- Receive-only system requires dedicated hardware
  - Need to track 4 or more satellites simultaneously
  - Separate signals need to be recovered after undergoing code division multiplexing
- Receivers solve for position and velocity (and time)
  - Standard Positioning Service gives 100m accuracy
  - Precise Positioning Service gives 10m accuracy
- DoD phasing out TACAN navigation system by 2000

GPS Change Request

Shuttle Program is undertaking a large and complex CR to add GPS navigation capabilities to the Shuttle fleet

- Motivation: loss of TACAN navigation system
  - Need equivalent navigation aid during entry and landing
- Two-phase integration plan
  - Single-string implementation (one receiver)
  - Full-up implementation (three receivers)
- Integrated architecture
  - GPS receivers provide navigation data to General Purpose Computers (GPCs)
  - Several new Principal Functions added to software
    - Many smaller changes made to existing navigation software
- GPS CR more complex than typical CR
GPS Integrated Architecture

Description of GPS CR Subset

Principal functions are decomposed into subfunctions
- Receiver State Processing
  - GPS IMU Assign
  - GPS Navigation State Propagation
  - GPS State Vector Quality Assessment
  - GPS State Vector Selection
  - GPS Reference State Announced Reset
- Reference State Processing
  - GPS External Data Snap
  - IMU GPS Selection
  - GPS Reference State Initialization and Reset
  - GPS Reference State Propagation

Approach to Applying Formal Methods

We are pursuing a selective application of formal methods
- Focus on core subset involving new principal functions
  - GPS Receiver State Processing
  - GPS Reference State Processing
- Use PVS to model principal function requirements
  - Derive stylized specification approach tailored to Shuttle software
  - Maintain traceability to existing requirements
  - Emphasize readability by nonexperts
- Formulate properties and attempt proving later, if warranted
  - Possible candidate is feedback loop from receivers to Receiver State Processing and back

PVS Modeling of Principal Functions

Principal functions are regularly scheduled software entities
- Execution environment provides a large variable space that is read from and written into
- Interface is defined by explicit inputs and outputs enumerated in tables
- Principal functions are composed of several subfunctions invoked sequentially
  - Inputs are "passed down" to subfunctions
  - Outputs are "passed up" from subfunctions
- Local variables may be either transient or persistent
- We use a simple state machine model encoded in PVS
  - Principal function is represented as a single state-transition function
  \[ M : I \times S \rightarrow \{O \times S\} \]
PVS Modeling of Principal Functions (Cont’d)

Abstract structure in PVS notation:

```pvs
pf_result: TYPE = [\# output: pf_outputs, state: pf_state #]
principal_function (pf_inputs, pf_state, pf_I_loads, pf_K_loads, pf_constants): pf_result =
\# output := \langle output expression \rangle,
state := \langle next-state expression \rangle
```

- Principal functions use two kinds of variable data (input values, previous-state values) and three kinds of constant data (I-loads, K-loads, constants)
- Executing a principal function produces output values and next-state values
- All side effects are to be captured by this model

Requirements for Receiver State Processing (Cont’d)

<table>
<thead>
<tr>
<th>Description</th>
<th>Input</th>
<th>Type</th>
<th>Pos.</th>
<th>Range</th>
<th>Unit</th>
<th>Sample Rate</th>
</tr>
</thead>
<tbody>
<tr>
<td>GPS data good flag</td>
<td>GPS_DG_OK**</td>
<td>*</td>
<td>D</td>
<td>OFF</td>
<td>OFF</td>
<td>Filter rate</td>
</tr>
<tr>
<td>Previous GPS data good flag</td>
<td>GPS_DG_PREV**</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
<tr>
<td>Flag indicating (XAO + GPS enabled state) is not available</td>
<td>GPS_SW_AVAILABLE</td>
<td>D</td>
<td>OFF</td>
<td>OFF</td>
<td>Filter rate</td>
<td></td>
</tr>
<tr>
<td>Last observed number of GPS satellites</td>
<td>GPS_SW枰</td>
<td>D</td>
<td>OFF</td>
<td>OFF</td>
<td>Filter rate</td>
<td></td>
</tr>
<tr>
<td>Last transmitted position estimate in position estimate units</td>
<td>GPS_RANGE**</td>
<td>V</td>
<td>DP</td>
<td>8</td>
<td>Filter rate</td>
<td></td>
</tr>
</tbody>
</table>

* See principal function input list in Table 4.3.3.5-1.
** See Table 4.3.3.5-1.

Requirements for Receiver State Processing

2.0 Step 2.1 is performed for each receiver up to the software designed maximum, whether or not the receiver has been actually installed on the vehicle.

```
DO FOR i = 1 to GPS_SW_CAP
```

2.1 For each GPS receiver that has a valid state (GPS_DG_OK = ON) and has not been disabled by the user (CREW_DISABLE_RECV = OFF), perform the following:

```
IF (GPS_DG_OK = ON and CREW_DISABLE_RECV = OFF) THEN
```

- If all receivers have been forced to be candidates for selection (GPS_AVP_RECV = “FORCE”), independent of their quality assessment status, or if the quality assessment status for that receiver has been overridden (CREW_QUAL_OVERRIDE = ON) or the receiver’s state has passed all quality assessment tests (GPS_FULL_QM = OFF), qualify that the state is a candidate for selection by setting the selection command for that receiver and increasing the count of candidates status:

```
IF (GPS_AVP_RECV = “FORCE” or CREW_QUAL_OVERRIDE = ON) or GPS_FULL_QM = OFF THEN
SSEL_CMD = 1
```

3.0 If the number of GPS states identified as candidates is greater than 0 (NQUAL_GPS_SSEL > 0), then the selected GPS states are formed from the eligible candidates as described:

```
S_GPS_SEL = S_GPS
V_GPS_SEL = V_GPS
```

Modeling of Receiver State Processing

Selected data types rendered in PVS

- major_mode_code: TYPE = nat
- mission_time: TYPE = real
- GPS_id: TYPE = {n: nat | 1 <= n <= 3}
- receiver_mode: TYPE = {init, test, nav}
- AIF_flag: TYPE = {auto, inhibit, force}
- N50_axis: TYPE = {x, y, z}
- position_vector: TYPE = [N50_axis -> real]
- velocity_vector: TYPE = [N50_axis -> real]
- GPS.positions: TYPE = [GPS_id -> position_vector]
- GPS.velocities: TYPE = [GPS_id -> velocity_vector]
- GPS predicates: TYPE = [GPS_id -> bool]
- GPS_times: TYPE = [GPS_id -> mission_time]
- GPS_FSM: vector: TYPE = [GPS_id -> GPS.figure_of_merit]
- tolerance_vector: TYPE = [GPS_id -> real]
- WGS84_to_EF_matrix: TYPE = [earth_fixed_axis -> [WGS84_axis -> real]]
Sample Subfunction of Receiver State Processing

ref_state_anncd_reset_out: TYPE = [#
  GPS_anncd_reset: GPS_predicate,
  GPS_anncd_reset_avail: GPS_predicate,
  T_ref_anncd_reset: GPS_positions,
  T_anncd_reset: mission_time,
  V_ref_anncd_reset: velocity_vector,
  V_anncd: GPS_velocities
#]

ref_state_announced_reset(DT_anncd_reset,
  GPS_DG,
  GPS_SW_cap,
  R_GPS,
  T_anncd_reset,
  T_current_flt,
  T_gps,
  V_current_GPS,
  V_GPS): ref_state_anncd_reset_out

Principal Function Interface Types

rec_sp_inputs: TYPE = [#
  crew_deselect_rcvr: GPS Predicate,
  V_GPS_ECEF: GPS_velocities_WGS84,
  V_1M22_save: GPS_velocities
#]

rec_sp_state: TYPE = [#
  GPS_DG_prev: GPS_predicate,
  V_last_GPS_sel: velocity_vector
#]

rec_sp_I_loads: TYPE = [#
  acc_prop_min: real,
  M_WGS84_to_EF: WGS84_to_EF_matrix,
  sig_diag_GPS npm: cov_diagonal_vector
#]

Principal Function Interface Types (Cont’d)

rec_sp_K_loads: TYPE = [#
  GPS_SW_cap: num_GPS
#]

rec_sp_constants: TYPE = [#
  deg_to_rad: real,
  earth_rate: real,
  GO: real,
  nautical_per_ft: real
#]

rec_sp_outputs: TYPE = [#
  corr_coff_GPS: real,
  DELR_ratio_Q42_display: GPS_ratios,
  V_ref_anncd Reset: GPS_velocities
#]

rec_sp_result: TYPE = [# output: rec_sp_outputs, state: rec_sp_state #]
Principal Function Specification (Cont'd)

SV_qual_assessment_out =
  state_vector_quality_assessment(
    GPS_DD (rec_sp_inputs),
    ...
    V_GPS (nav_state_prop_out)),
  ...
state_vec_SEL_out =
  state_vector_selection(
    corr_coeff_GPS_nom (rec_sp_I_loads),
    ...
    V_GPS_sel (nav_state_prop_out)),
ref_st_ann_reset_out =
  ref_state_announced_reset(
    DT_anncd_reset (rec_sp_I_loads),
    ...
    V_GPS (nav_state_prop_out))

Results (In Progress)

Experience with effort so far:

- Outlook is promising, but it's still early
- CR requirements are still converging
  - Another revision cycle is likely
  - After next cycle, FM results should be more meaningful
- FM-based review is helping requirements analysis
  - Many interface errors being detected
- PVS can be used effectively to formalize this application
  - Custom specification approach should be easy to duplicate
  - Good prospects for continuation by nonexperts
  - Specification activity assisted by tools, but doing manual specification is also feasible here

Principal Function Specification (Cont'd)

(state_vec_SEL_out),
  ...
  GPS_DD := GPS_DD (SV_qual_assessment_out),
  ...
  GPS_sel := GPS_sel (state_vec_SEL_out),
  ...
  V_GPS := V_GPS (state_vec_SEL_out)
state := (#
  GPS_DD := GPS_DD (SV_qual_assessment_out),
  ...
  GPS_sel := GPS_sel (state_vec_SEL_out),
  ...
  V_GPS := V_GPS (state_vec_SEL_out)
#)

Feedback from Requirements Analysts

Some RAs are optimistic about potential impact of FM

- Approach used is helpful in detecting two classes of errors:
  - "Requirements meet the CR author's intent; CR will work"
  - "Interfaces Documented and Consistent"
- Preliminary comparison with conventional process
  - Errors detected in Reference State Processing versus those also found by current process

<table>
<thead>
<tr>
<th>Error Severity</th>
<th>With FM</th>
<th>Existing</th>
</tr>
</thead>
<tbody>
<tr>
<td>High Major</td>
<td>2</td>
<td>0</td>
</tr>
<tr>
<td>Low Major</td>
<td>5</td>
<td>1</td>
</tr>
<tr>
<td>High Minor</td>
<td>17</td>
<td>3</td>
</tr>
<tr>
<td>Low Minor</td>
<td>6</td>
<td>0</td>
</tr>
<tr>
<td>Totals</td>
<td>30</td>
<td>4</td>
</tr>
</tbody>
</table>
Continuation Plans

Plan for near term CR analysis
- Continue elaborating formal specifications using current style
  - Complete two principal functions under way
  - Consider adding other functions as resources allow
  - Collect feedback and data from RAs
- Go down to moderate level of detail
  - Incorporate enough detail to capture branching conditions
- Evaluate tradeoffs of formalizing subsystem properties
  - Properties based on sequences of state vectors
  - Limited proving may be worthwhile

Summary

- Formal methods aiding requirements analysis on a significant Shuttle CR
- Specification techniques customized for Shuttle software
- So far, keeping up with requirements analysis process
  - Enables meaningful comparisons
- Early results are encouraging
- Remains to be seen whether techniques can be transferred to and adopted by RAs
Session 5: Software Systems (2)

C. Michael Holloway, Chair

- Ada 9X Language Precision Team, by David Guaspari, Odyssey Research Associates
- Introduction to Penelope and Its Applications, by David Guaspari, Odyssey Research Associates