Problem Oriented Engineering for Software Safety

Thesis

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Problem Oriented Engineering for Software Safety

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Author's Declaration

Some of the material in this thesis appears in the following papers.


I declare that no part of this material has previously been submitted to a degree or any other qualification at this University or another institution.
I further declare that this thesis is my original work, except for clearly indicated sections where appropriate attributions and acknowledgements are given to work by other authors.

Derek Mannering
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Abstract

Safety critical systems must satisfy stringent safety standards and their development requires the use of specialist safe software system development (SSSD) approaches as the complexity and penetration of these systems increases. These SSSD approaches satisfy certain useful properties that make them suitable for safety system development. The first objective of this thesis is to select a candidate SSSD approach and evaluate its capabilities against a set of useful properties identified from reviewing a group of existing SSSD approaches, and thus show that this candidate SSSD approach is appropriate for use in safety system development.

In addition, a second objective is to use this candidate SSSD approach to improve the early life cycle phase of an existing industrial safety development process used to develop embedded avionics applications. In particular to allow issues to be resolved earlier in the development, which are currently not being uncovered until much later in the development when they are much more difficult and expensive to correct. This involved the identification of further properties and issues that the candidate SSSD approach must address.

The overall aim is to demonstrate that this candidate SSSD approach can be used in the early phase of a safety system development to derive a validated specification that can be subjected to safety analysis to show that it satisfies the identified system safety properties and thus forms a viable basis for the rest of the development.
Chapter 1

Introduction

Embedded computer systems are becoming more pervasive [64, 57] and their scope and complexity is ever increasing [90]. These are used in areas such as avionics, rail and process control and more recently in medical applications [64]. The harm potential of such systems is recognised: the outcry associated with a major rail accident, air crash or nuclear power incident demonstrates the importance of safety as a significant non-functional requirement [96]. This concern has been expressed in a variety of national and international safety standards such as the UK MoD's Defence Standard (DS) 00-56 [125] and the international IEC 61508 [51], and the production of safety critical and safety related systems is increasingly being regulated and controlled. All the major safety standards are concerned with the management and mitigation of risk as a key element. Risk is managed through the concept of a safety life cycle [125, 51, 28], and although terminology differs the basic sequence of hazard identification, hazard analysis and risk mitigation is followed by all [65]. Further, this safety life cycle must run in parallel to and be integrated with the design and development life-cycle. That is, the production of a design artefact is associated with a corresponding safety analysis task. The goal is to ensure that safety is not a "bolt-on" extra performed when the design is finished, but that it has appropriate influence on the design decisions as the system development progresses.
[66, 30, 69]. It follows that there is a need for safe software system development (SSSD) approaches that integrate the safety and development life cycles to manage the safety risks.

1.1 Issues in Current Safety Engineering

The safety standards require hazard identification and preliminary hazard analysis to occur in the early phases of the development process (e.g., [89]). This is consistent with studies that have shown that a large proportion of anomalies occur at the requirements and specification stages of a system development [29, 69]. A study by Lutz concluded that safety-related software errors arose most often from inadequate or misunderstood requirements [79], indicating the need for a more careful analysis of the requirements to ensure adequate assimilation and comprehension of them. Further, other work has highlighted the need to conduct a safety analysis of the requirements [26, 33]. These factors all support the notion that safety must be built into the design, and that the evolving design representations analysed to demonstrate that they have the desired safety properties [70] as early as possible in the life cycle - preferably during the requirements phase. One of the objectives of this work is to propose an approach able to support safety analysis within the early phases of requirements analysis and high-level architectural design.

A direct result of the increasing use and penetration of software intensive systems is the increase in system complexity which it allows [64]. More things can be done with a software system - so they are [19]. In certain sectors system complexity is rising exponentially [91]. There is a need to cope with this increased complexity as part of the development process, and this is often achieved by using reduction techniques [69] and/or abstraction to structure the problem [71]. The complex interaction between diverse system elements (e.g., operators and computer control system) can result in unsafe behaviour due to unexpected emergent properties [72].
As a result increased complexity can arise in a number of forms which must be covered by an adequate safety analysis approach. Another objective of this work is to propose concept tools to deal with the complexity of analysing safety problems and synthesising adequate safety solutions.

Formal specifications have been a focus of software engineering research for many years and have been applied in a wide variety of settings [126], including safety critical applications [80]. Formal specification is required by a number of safety [51] and security [15] standards for their highest integrity applications. The use of such techniques is not universal, but to some they provide a "gold standard" [43] of what can be achieved. However researchers have noted that the perceived benefits of applying formal specification techniques are not being realised [44, 126]. This has been attributed to a number of causes including no methodological guidance for using formal techniques [44]; formal techniques are not well integrated with the system analysis phase - there is a need to analyse the system and its environment before producing the specification [44, 57]; and many of the techniques have poor separation of concerns in that the desired behaviour of the environment is not well distinguished from the extant properties of the environment [126].

As an approach, some have advocated extending the scope of formal techniques within the structure of an integrated RE process based on formality covering elicitation, modelling and analysis, communication and validation, and also stressing the importance of the environment [128][44]. This has been successful in extending the reach of formal methods, but has not overcome the disconnect of Turski's problem [120]: that real-world domains are not necessarily expressible in any single linguistic system; and that the notion of mathematical (logical) proof does not apply to them. This disconnect manifests itself for formal methods in the following ways: they do not adequately bridge the gap between the uncertainty of the real-world and the formality of the formal world; they do not distinguish between the indicative properties of the environment and the optative properties of the requirements; they
neglect the validity aspects of the requirements; and they are not good at validating progress towards the solution. Formal models are precise entities whose properties can be demonstrated by proof. The real world is more variable, and the formal models produced are only approximations to it. Yet another objective of this work is to address Turski's divide and propose an approach in which formality is properly situated within safe engineering practice.

Engineering is different from science and mathematics [82], although the techniques and approaches used in both science and mathematics can be used in an engineering context. In much simplified terms, engineering is concerned with building artefacts which transform the physical world [82], whilst science is concerned with universal properties of the universe and mathematics universal truths [54]. In fact, engineering tools are most useful when they are specific to a particular problem, and different classes of problem may demand different languages to represent them [82]. Further, software engineering itself covers a broad range of quite different application areas, which are best served by specific problem oriented language notations [121].

If software engineering (SE) is to attain the benefits achieved by other engineering professions such as aeronautical engineering, then it must seek to satisfy the "normal design" principles and where possible avoid radical ones [82, 55]. Vincenti [131] defines "normal design" as what the engineer is engaged in when s/he knows from the outset

"how the device in question works, what are its customary features, and that, if properly designed along such lines, it has a good likelihood of accomplishing the desired task."

Much of the routine design encountered in traditional engineering disciplines works normally. Some have recently observed that software engineering does not: Maibaum [82] states that

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“SE ignores the principles of engineering design and almost always adopts radical design methods, to its detriment.”

Jackson states [55]

“Though less conspicuous than radical design, normal design makes up by far the bulk of day-to-day engineering enterprise. Unfortunately, this is not true of software engineering.”

To write useful software it is not enough to deal with just the computer and its software, one must also deal with the complexities of the natural or “real” world in which the application resides – and the gap between the specification and the requirements phenomena must be bridged by the problem domain properties (domain knowledge) [54]. The importance of domain knowledge is identified by a number of authors [54, 82, 121, 127]. Further, Maibaum [82] identifies systemising domain knowledge and the use of architecture to encapsulate design choices as two key requirements for achieving normality in design. A key characteristic of the approach we propose is a clear separation of concerns between the system under design, its desirable properties and the extant properties of its deployment context.

1.2 Aim, Objectives and Method

The first objective of this thesis is to propose and evaluate an SSSD approach for safe software system engineering able to meet the following specific goals:

- integrate safety analysis within the early phases of development, particularly requirement analysis and high level architectural design
- allow for both formal and informal safety analysis techniques to take place
- capture and separate contextual knowledge from the design of the system and its desirable properties
- keep track of safety artefacts for validation and certification purposes
- integrate with current safety engineering practice.

The approach we propose is based on problem orientation [133], and particularly, their embodiment in the Problem Oriented Software Engineering (POSE) framework [41, 39] whose particular choice is argued and justified in Chapter 2.

The second objective is to improve the early phases of an existing safety development process. The work is situated within the safety development process in use in the author’s company; this process is tailored to the production of embedded safety systems with a significant software content and has been used to produce a number of safety critical avionics systems that have been accepted into service. The process is representative of the industry, and is generally acknowledged to be successful and robust. However, a number of issues have been identified with it, particularly in the early stages of the development. One of the major drivers for this research was to investigate how to address these issues. As well as providing a useful driver, situating the work within a practical industrial process is also beneficial in the evaluation of the research outcome, whose impact can be measured directly through industrial application and case studies.

Therefore the method used in this research is a combination of literature survey, problem analysis and the use of case studies. In more detail, the role of the literature survey is to:

- identify the underlying safety principles (the safety context) that impact the research
- identify issues and properties associated with the early phases of a safety development process
- evaluate existing safety analysis and safe software system development approaches

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use this information to produce a set of generic properties that our proposed engineering approach should possess, and against which it can be evaluated.

Problem analysis is performed within the context of the author's company development process and practice, with a view to identify additional specific properties and issues that the candidate engineering approach should also be able to address. The ensuing research work based on case studies is used to evaluate the proposed approach against the established metrics. The overall aim is to demonstrate that POSE, and its extensions developed by this work, can be used in the early phase of a safety system development to derive a validated specification that can be subjected to safety analysis to show that it satisfies the identified system safety properties and thus forms a viable basis for the rest of the development.

1.3 Thesis Structure

The thesis is organised as follows.

The initial task is to scope and investigate the safety context and this is addressed in the early part of Chapter 2. This will consider the impact of safety standards, the use of safety terminology, the safety life cycle, safety analysis techniques and making safety case arguments. A number of approaches that have been successfully used to develop safety systems are then introduced and used later in the chapter to identify a set of properties that an appropriate safety engineering approach should possess. The chapter concludes with the justified selection of POSE as the safety engineering approach.

Chapter 3 introduces the early phases of an industrial safety development process used by the author's company to develop embedded safety systems. Some problems that have been identified with this process are discussed and these are summarised into a number of properties and issues which are used in conjunction with the properties identified in Chapter 2 to evaluate POSE in the remainder of
the thesis.

Chapter 4 introduces POSE in its basic, "vanilla" form through its application to an avionics Decoy Controller case study. Its capabilities in dealing with the identified properties and issues are evaluated and its performance recorded in tabular form. The identified shortfalls provides a focus and target for the major research work that is reported in the chapters that follow.

The goal of Chapter 5 is to develop an algorithm for the POSE Problem Progression Transformation (PPT) that supports its application to allow requirements to be transformed such that the specification of the system can be derived directly. An extension of the Decoy Controller case study introduced in Chapter 4 is used to illustrate the ideas involved and to demonstrate the successful application of the PPT. This chapter also covers the development of a safety analysis process which exploits POSE's characterisation of software problem to achieve an adequate and effective safety analysis. Next, a Stores Management System (SMS) case study is introduced that demonstrates how POSE can be used in conjunction with formal development techniques.

The goal of Chapter 6 is to address the remaining identified issue of early safety analysis. The POSE safety pattern is introduced (section 6.1) to achieve this goal and its utility demonstrated through its application to a third, Audio Warning System, case study. The case study, presented in section 6.3, provides evidence to support the usefulness of all the POSE extensions developed in the earlier chapters and demonstrates that they successfully address all properties and issues identified.

The thesis finishes with a detailed discussion and conclusions of the results obtained in Chapter 7 and possible future work is covered in Chapter 8. The appendices provide additional information that supports aspects of the research work, which are referenced from the main text as appropriate.
Chapter 2

Literature Review

The aim of this chapter is to introduce and discuss in detail the background and basis for the research into problem orientation and in particular the use of Problem Oriented Software Engineering (POSE) to build "safe software". The chapter begins with a discussion of the problems associated with the different definitions that abound in safety engineering and identifies the nomenclature used in this work. Then the important areas of system safety and system safety analysis are reviewed, together with a number of development approaches used to produce safety software, followed by a discussion of problem orientation. An analysis is performed in section 2.5 to identify ten useful properties that a safety development approach should possess which are used to select a candidate approach – POSE – for use in the remainder of this thesis. The chapter ends with a summary.

2.1 Nomenclature

The term requirement [53, 127, 96] covers a number of levels varying from entities at the high level such as the users required behaviour (functional requirements) and dependability requirements (e.g. safety and security) through to lower level entities such as specific requirements allocated to the hardware or software. In this
The term requirement or system requirement is used to refer to the high level entities unless explicitly stated. For example, in the solution of the entailment sequent \( W, S \vdash R \) used extensively in this work, the term \( R \) is the overall system requirement, whilst \( S \) represents the specification of the processing machine. In effect, \( S \) represents the allocated software requirement for the machine, but will be called the specification or machine specification in this document.

Similarly, it is also worth noting that the term architecture \([103, 17, 34]\) also occurs at a number of levels covering system architecture, software architecture and hardware architecture. As this work is concerned with the early phases of a development it is the system architecture that is the main focus. However the prefix of system, software or hardware will be used where this aids comprehension.

This work is concerned with software safety with respect to embedded real-time systems. Actually the term software safety is something of a misnomer, software by itself cannot cause harm. It is only in the context of a system operating in a potentially unsafe environment that "unsafe" software can result in a safety problem \([93]\). For example, an aircraft flight control system operating on a ground-based test rig has far different safety implications to that same flight control system being used to control a fast jet in low level flight operations. That is, software safety is a property requiring software and a potentially unsafe context. In this work the term software safety will be used as an abbreviation for the safety aspects of the software operating in its system context that in turn, is operating in the overall system environment.

Moreover, there is no agreed definition of the terms used in the description of a potentially unsafe environment; in particular, there are differences between the common usage of the terms failure, fault and error in some software developments and common usage in traditional safety engineering \([69]\). However, analysis of the definitions used in IEC 61508 \([51]\), DS 00-56 \([125]\) and by Leveson in her book Safeware \([69]\) does show a good correlation for the important terms harm, hazard,
### Table 2.1: Safety Terminology Comparison

<table>
<thead>
<tr>
<th>Term</th>
<th>Source</th>
<th>Safety Term Definition</th>
</tr>
</thead>
<tbody>
<tr>
<td>Harm</td>
<td>IEC 61508</td>
<td>Physical injury or damage to the health of people either directly or indirectly as a result of damage to property or to the environment</td>
</tr>
<tr>
<td></td>
<td>DS 00-56</td>
<td>Same as IEC 61508</td>
</tr>
<tr>
<td></td>
<td>Leveson</td>
<td>*** Not Used *** (Uses Loss)</td>
</tr>
<tr>
<td>Hazard</td>
<td>IEC 61508</td>
<td>Potential source of harm</td>
</tr>
<tr>
<td></td>
<td>DS 00-56</td>
<td>A physical situation or state of a system, often following from some initiating event, that may lead to an accident</td>
</tr>
<tr>
<td></td>
<td>Leveson</td>
<td>A state or set of conditions that contributes to an accident</td>
</tr>
<tr>
<td>Risk</td>
<td>IEC 61508</td>
<td>Combination of probability of occurrence and the severity of that harm</td>
</tr>
<tr>
<td></td>
<td>DS 00-56</td>
<td>Combination of the likelihood of harm and the severity of that harm</td>
</tr>
<tr>
<td></td>
<td>Leveson</td>
<td>Hazard severity, likelihood and exposure</td>
</tr>
<tr>
<td>Accident</td>
<td>IEC 61508</td>
<td>*** Not Used ***</td>
</tr>
<tr>
<td></td>
<td>DS 00-56</td>
<td>An unintended event, or sequence of events, that causes harm</td>
</tr>
<tr>
<td></td>
<td>Leveson</td>
<td>Undesired and unplanned event that results in a loss</td>
</tr>
</tbody>
</table>

*risk* and *accident* as shown in Table 2.1. Inspection shows that IEC 61508 and DS 00-56 agree on the term *harm* and all three agree on the definition of *risk*. Leveson [69] uses *loss* in place of *harm*, but allowing for this it can be seen that DS 00-56 and Leveson have similar definitions for *accident*. IEC 61508 relates a *hazard* directly to *harm*, whereas both DS 00-56 and Leveson use *accident* as an intermediate part of the definition.

IEC 61508 and DS 00-56 both define *safety* in terms of *risk* acceptability. In contrast, Leveson defines *safety* as freedom from *accident* or *loss*. Using a risk-based definition for safety is more useful from an engineering viewpoint since absolute safety cannot be achieved. Most modern safety standards are based on the principle of reducing risk to acceptable levels [8], accepting the fact that absolute safety (zero risk) cannot be achieved [105, 90]. For example, IEC 61508 requires the identification of the risks posed by the system under development - and that any such risks will be reduced to tolerable levels by including safety functions in the design responsible
for providing the necessary risk reduction. Therefore risk management is an integral part of modern safety system development. IEC 61508 and Leveson do disagree on the relative status of failure and fault, but are similar for error. DS 00-56 has the same definition for error as IEC 61508. This text will use the definitions from the international standard IEC 61508 supplemented with the use of accident (as in DS 00-56). However, the text will avoid the use of the term fault as there is less agreement and more confusion concerning its definition in different texts. This means that a failure is the

“termination of the ability of a functional unit to perform a required function”,

and an error is

“discrepancy between a computed, observed or measured value or condition and the true, specified or theoretically correct value or condition”.

The latter is similar to the Leveson definition of error which is “design flaw or deviation from desired or intended state”.

2.2 System Safety

According to Leveson [69]:

“The primary concern of system safety is the management of hazards: their identification, evaluation, elimination and control through analysis, design and management procedures”

System Safety is governed by a variety of national and international safety standards such as the UK MoD’s Defence Standard (DS) 00-56 [125] and the international IEC 61508 [51]. All the major safety standards contain the notion of a safety life cycle [125], [51], [28], [109], and although terminology differs the basic sequence
of hazard identification, hazard analysis and risk mitigation is followed by all [65].
As noted at the beginning of Chapter 1, this safety life cycle must be integrated with
the design and development life cycle. The safety life cycle expects comprehensive
hazard identification and safety analyses to demonstrate that the implemented sys-
tem is adequately safe with respect to the system’s integrity requirements.

The safety standards are backed up by a legal framework that differs from coun-
try to country [65]. For example in the UK the legal framework includes the Health
& Safety at Work Act (HSWA) 1974, The Management of Health and Safety at
Work Regulations (MHSW Regs), contract law (Tort), Sale of Goods act and other
EU derived legislation. In particular, the ALARP (As Low As Reasonably Prac-
ticable) principle [29] is laid down in law within the HSWA and is an important
aspect of IEC61508 [51] and DS 00-56 [125]. ALARP provides high level adequacy
criteria for determining when you have done enough, although it is not so easy to
apply in practice, since it is difficult to define what constitutes enough. Therefore,
good practice and legal necessity combine to demand that an appropriate (as defined
above) safety life cycle should be followed, and this means that hazard identification
is a key task that must be performed at a suitable early point in the development
process. In DS 00-56/2 1, [123], the early tasks of the safety life cycle (hazard identi-
fication, preliminary analysis and initial risk estimation) are collected together into
the Preliminary Hazard Analysis (PHA) phase. Leveson also uses PHA as the initial
safety life cycle phase [69]. Other standards [28], [109] use a different terminology,
but the task is essentially the same. This research uses the term “Preliminary Safety
Analysis” (PSA) to cover the specific early safety analysis phase it wishes to cover –
the term PSA (refer to section 4.4) being selected so it would not be confused with
the terminology used by the different standards and guidelines.

1Version 2 of DS 00-56 contained a full safety life cycle description, later versions of DS 00-56
adopted a more objective-based stance, and relegated the safety life cycle details to the guidance
text.
2.2.1 Safety Cases

A safety case \cite{125, 62, 12} is a documented body of evidence providing a compelling, comprehensive and valid argument that a system is adequately safe for a given application in a given environment. Safety standard DS 00-56 \cite{125} mandates that a safety case should address:

- the management of risk commensurate with the potential risk posed by the system and its complexity;

- the validity of the safety requirements, i.e., that they are derived through thorough analysis and are traceable with respect to the system as designed and implemented, together with evidence of their satisfaction;

- the well-foundedness of assumptions about the system, its operating environment or modes of use upon which the safety argument is based, with a justification that such assumptions are realistic and reasonable.

Ideally the safety case should be made about the product as product-based evidence is more compelling \cite{93}. However, there is still a need for process evidence to cover the system configuration, and the fact that it is often difficult to provide enough direct supporting evidence for a product, and process evidence has to be used.

The UK safety industry has moved towards the widespread use of safety cases to present the safety argument for system safety, since the Cullen Report \cite{22} on the Piper Alpha disaster. The trend \cite{61} is that recent safety standards such as DS 00-56 Version 4 \cite{125} and CAP 670 \cite{3} have adopted a goal based approach for the presentation of a cogent argument backed by adequate evidence that the developed system is safe for its intended use. The argument is required to show that the safety risks associated with deploying the developed system have been reduced to a tolerable level. Therefore risk management is an integral part of safety
system development. Early safety cases were very large monolithic documents that were difficult to comprehend, this resulted in the development of goal structuring notation (GSN) to present the safety arguments in a more accessible, systematic form [59]. GSN is a graphical means of showing the structure of the overall safety argument, and has become the de facto standard means for presenting safety cases for UK military systems.

In GSN goals represent statements that must be true for the safety argument to hold. One useful strategy is to divide the target goal into a number of sub-goals that are individually addressed. Eventually, the process of refining produces goals that are sufficiently detailed to be supported directly by appropriate evidence (these are termed leaf goals), in which case a solution is used to designate the evidence. Contexts are used in conjunction with the Assumptions to provide a description of the circumstances and constraints under which the safety case is valid. They can also be used to provide explanations of the terms used in the other constructs. Assumptions are used to document statements that are taken to be self-evidently true in the safety case.

Even with goal structures there remain acknowledged difficulties in the construction of safety cases, and here we adopt the characterisation from [35]:

- The difficulty of Disparate Descriptions: that of combining disparate pieces of the evidence, such as narrative, requirements, claims, plans, activities or goals [14, 132]; and

- The difficulty of Post-Hoc Assurance: that, traditionally, safety cases are developed post-design and testing with known drawbacks including: expensive redesign when the current design is indefensible; expensive system over-engineering so that the design can be defended; and loss of the rationale for the safety aspects of the design [60].
The later chapters in this thesis will show how POSE can be used to mitigate these difficulties.

2.2.2 System Safety Analysis

The safety standards expect appropriate safety analysis tasks to be applied early in the life cycle, iteratively and on an ongoing basis. Generally this is taken to mean it should occur during the requirements capture and high level specification phases (e.g., see [89], [110]). As noted at the beginning of Chapter 1, this is consistent with the studies that have shown that a large proportion of anomalies occurs at the requirements and specification stages of a system development [29], [69]. Further, investigations have shown that the anomalies of interest are not restricted to just component or function failures, but include significant contributions from factors that are emergent properties of the interactions of complex systems [69], [98]. The abstract descriptions available in the early phases of the development support the need for a comprehensive analysis of the interactions between the system components, operators and environment - an analysis that becomes much more difficult as the amount of design detail increases. Therefore it would be useful if the PSA consisted of the requirements model being subjected to a comprehensive safety analysis to demonstrate that it can satisfy the required system integrity requirements (including emergent properties), and hence form an adequate basis for the ensuing development [33]. So, there is evidence that supports the notion that the safety analysis should be applied to a suitable representation of the requirements so that its emergent safety and failure behaviour can be investigated.

There are many techniques that underpin modern safety analysis and each technique has its advantages and disadvantages. The most commonly used techniques are inductive techniques such as Functional Failure Analysis (FFA) [109, 92], HAZOPS [6, 106] and Failure Modes and Effect Analysis (FMEA) [95, 27], and deduc-
tive techniques such as Fault Tree Analysis (FTA) [130]. However, they all share a number of common properties. For example, the success of these techniques depends directly on having an appropriate representation model that must be validated, and the validation must cover mis-representation of information [1]. Basically if the model does not include the feature of interest then the analysis is unlikely to capture it. They are systematic, but rely on informal reasoning. This means they can be applied to a large class of representations both formal and informal (e.g. [30, 112]). However, establishing the efficacy and rigour of the results obtained is less easy than for example, those results obtained from formal proof or model checking [99].

Attempts have been made to enhance these techniques specifically for use with embedded real-time systems. For example [106] with HAZOPS, Software Failure Modes and Effects Criticality Analysis (SFMECA) [81], Software Fault Tree Analysis (SFTA) [81] and SHARD [102] have all been used successfully, can be integrated and used to provide productive results. However, a number of significant issues are raised when applying conventional safety analysis techniques to software based systems [107]. These techniques are manual, so depend on human understanding, which can be limited for a complex software system; if a formal model exists then it is possible to harness the power of formal analysis and proof techniques to demonstrate desirable properties [4, 119], by using formal analysis in place of manual (albeit systematic) analysis. For example, a technique called Software Deviation Analysis (SDA) can be applied to an RSML model [107].

There is a consensus (e.g., see [110, 112, 125]) that inductive techniques such as FFA, HAZOPS and FMEA, should be used for the identification of hazards; whilst a deductive technique, such as FTA, should be used for finding the causes of and contributors to an identified hazard. Many current approaches use a single technique, often combined with a checklist based on previous experience. This has its problems as no single technique is ideal for all the required hazard identification and analysis tasks, and therefore is not the most appropriate way to proceed at
such a crucial phase (Leveson notes that 70% - 90% of safety related decisions are made in the concept phase [72]). Ways of combining the capabilities of techniques for safety analysis form one of the objectives of pursuing this research.

### 2.3 Safe Software System Development Approaches

A number of development approaches have been specifically targeted at safety related systems, whilst others have included safety as a significant element. The important safe software system development (SSSD) approaches with significance to this work are summarised in the following, and will be further analysed in section 2.5.

#### 2.3.1 Software Cost Reduction

The Software Cost Reduction (SCR) method follows a four step process for constructing a requirements specification that is based on the concepts defined in the Parnas 4-Variable Model [19, 100] – including the notions of monitored and controlled quantities, and the relations \( \text{NAT} \) and \( \text{REQ} \). An SCR form of this model, from [9], is shown in figure 2.1. The first step creates an idealised SRS (Systems Requirement Specification). The desired system behaviour is documented in the SRS by describing the relations \( \text{NAT} \) and \( \text{REQ} \), where \( \text{NAT} \) represents constraints imposed by the environment (such as physical laws) and \( \text{REQ} \) defines the idealised required behaviour in terms of the monitored and controlled quantities - these are \( M \) and \( C \) respectively in Figure 2.1. The SRS describes the desired behaviour in terms of the system interacting with its environment, and does not include implementation detail (hence the term *idealised*). This demonstrates that the SCR process is consistent with [133], and concentrates on *WHAT* is required, not *HOW* it is to be achieved. The ensuing phases cover the *HOW* aspects, by refining this idealised model by successively adding design detail.
The SDS (System Design Specification) is developed in the second step. This introduces the system's input and output devices (e.g., sensors for monitored and actuators for controlled quantities). Step 3 creates the SoRS (Software Requirements Specification) which refines the SDS by adding input/output design detail. This is achieved by adding modules which use values read from input devices to calculate values of the monitored quantities (\(D_{IN}\)) and which use the computed values of controlled quantities to drive output devices (\(D_{OUT}\)). The Input Device Interface Module (\(D_{IN}\)) takes the input variables output by the sensors and produces an estimate of the monitored quantities, \(M\). This means that the Device Independent Module can produce an estimate for \(REQ\), which mimics the \(REQ\) at the overall system level and hence its requirements are those defined in the SRS. It produces an estimate for \(C\) as its output. This estimate is fed into the Output Device Interface Module (\(D_{OUT}\)), which produces the output variables to drive the actuators.

The fourth step in the SCR process adds further design detail concerned with hardware failure and exceptions. A typical SCR specification will consist of monitored variables, a mode class and its modes, internal terms and controlled (output)
variables, conditions and events. The behaviour of these quantities are related by three types of table: Mode Transition Tables, Condition Tables and Event Tables. A condition is a predicate defined on a system state, whilst an event is a predicate defined on two system states that differ in the value of at least one variable [47]. The notation $\odot T(c)$ denotes an event which has the informal meaning "that condition $c$ becomes true", whereas $\odot F(c)$ means "condition $c$ becomes "false". Formally,

$$\odot T(c) \equiv \neg c \land c'$$

where the unprimed $c$ is evaluated in the old (or current) state, and the primed $c'$ is evaluated in the new (next) state. A conditioned event has the form $\odot T(c) \text{ WHEN } d$ which means condition $c$ becomes true when condition $d$ holds. Its formal meaning is defined by:

$$\odot T(c) \text{ WHEN } d \equiv \neg c \land c' \land d.$$  

A mode class is a state machine whose states are called modes and whose transitions are triggered by events [48]. The Mode Transition Table is a special form of the Event Table which defines the next state relation for the Mode Class.

A term is any function of input variables, modes, or other terms. They are useful for collecting together complex or repetitive behaviours and have a similar role to macros in RSML. Typically, a term will be used to make a specification more concise and its behaviour will be defined by an Event table. Often the controlled output variables can be defined as a condition on the current state, and are hence defined by a Condition Table. SCR has extensive tool support for editing, animation and model checking [46]. It includes tools to demonstrate well-formedness [45] such as: the Consistency Checker that demonstrates the specification is syntactically and type correct with no circular dependencies, no duplicate names or unused/unspecified variables, and no violations of disjointness or coverage properties; the Property Checker Salsa [10] further analyses the state machine; the Dependency Graph Browser graphically displays dependencies among the variables in the SCR tables; the Simulator for executing scenarios and evaluating behaviour; the Invariant Generator for checking that
state invariants hold. SCR has also been integrated/interfaced to model checking and theorem proving tools [45]. Further, SCR is still being developed and enhanced, e.g., currently SCR only supports primitive data types but this is being addressed by providing support for arrays and records [45, 46].

2.3.2 SpecTRM and RSML

SpecTRM [66, 70] is designed to assist in the development of software intensive safety critical systems. It forms part of a human centred, safety-driven process which is supported by an artefact called an intent specification [71]. An intent specification is stratified into a Program Management level (Level 0) and six further levels System Purpose, System Design Principles, Blackbox Behaviour, Design Representation, Physical Representation and System Operations [66]. The whole process is supported by a toolkit consisting of a specification editor, a simulator and analysis tools, and is designed in such a way as to support peer review. The formal model on which the tools operate corresponds to the Blackbox Level 3 of the intent specification, and is written in a language called SpecTRM-RL. A SpecTRM-RL model consists of four main components:

1. A specification of the supervisory modes of the controller being modelled

2. A specification of its control modes

3. A model of the controlled process

4. A specification of the inputs and outputs of the controller.

A major driver for the SpecTRM development has been the desire to remove implementation bias from the model. This is why a SpecTRM-RL model has a greatly simplified graphical representation compared with RSML (which is also based on the Parnas 4-Variable model), to remove internal behaviour which was found to be
problematic [73]. The mode concept has been introduced. A mode is just a collection of states, but its significance is to the user. It represents how a user or operator views the system being developed, it is not an internal implementation detail. For example, operating modes could be start-up, take-off, normal flight and landing for an avionics application. A major reason for including modes is to allow the modelling of the "mode confusion" concept, whereby an Operator action induces an error - perhaps leading to a hazardous situation - because he/she thinks the system is in a different mode of operation. A typical SpecTRM graphical model component has four quadrants, as shown in Figure 2.2.

![SpecTRM Graphical Model](image)

**Figure 2.2: SpecTRM Graphical Model**

The top-left is the supervisory interface, which consists of a model of the operator controls and the means by which status is communicated (displayed) to the operator. The bottom-left quadrant is the control modes of the controller, whilst the RHS represents inferred information about the operating modes and states of the system being controlled.

Interfacing to the component, are the Supervisor (control input, display output), the Controlled Device (Control command out, measured variable in) and the Environment Sensor (inputs measured variables). The graphical model is supported by a series of specification definitions which cover output message definition, input variable definition, and state variable definition. These definitions can be supported by further macro and function definitions which are aimed at improving the structure and readability of the SpecTRM-RL specification by abstracting complexity.

During trials of the RSML approach it was discovered that the use of propositional logic did not scale well to complex expressions in terms of its readability. It
was found to be error prone and that domain experts had difficulty in understanding what it meant [70]. The response was to develop a tabular representation of the complex logic, which presented it in disjunctive normal (DNF) form. These tabular representations were called AND/OR tables, and due to their success were retained for SpecTRM.

The SpecTRM-RL model represents the behaviour of the system as a state machine, and this allows a number of static checks to be applied to the model to verify its consistency (ensure the model is deterministic) and requirements completeness. The toolset supports a simulation capability, and the next phase in the analysis process is to run the simulator to allow the behaviour of the model to be validated. Once the analyst has confirmed consistency, completeness and behaviour of the model, then the final phase is to undertake the more heavyweight safety analysis. The toolset supports SMHA (State Machine Hazard Analysis) which is a backward search technique [104], and SDA (Software Deviation Analysis) [107] which evaluates the robustness of a specification.

### 2.3.3 Parnas 4-Variable Model Developments

Work at the University of York aimed to extend the Parnas 4-Variable model as part of the Practical Formal Specification (PFS) initiative [32] to address a number of development issues. The goal being to apply formality to embedded safety system development by providing two enhancements to the 4-Variable model. The first providing additional structure outside the control computer in the model, the second providing some additional structure within the computer.

The first, "outside", enhancement adds structure to the Parnas 4-Variable model to deal with two key issues. The first issue covers the concern about identifying more clearly the role of the embedding system (the control computer, its software and interfaces) and to ensure it is properly distinguished from its environment context.
This is achieved by enhancing the Parnas 4-Variable model by including embeddingInput and embeddingOutput variables which represent the inputs and outputs of the embedding system directly in the enhanced model. The second issue covers the concern that it is not always possible to monitor and/or control key properties directly through an environment parameter. The solution is to introduce additional variables into the model. These being real-world sensed and actuated variables which are affected directly by the system under development, and which are influenced by and/or influence the monitored/controlled variables in the original Parnas 4-Variable model.

The second, “inside”, enhancement involves elaborating the 4-Variable model by expanding SOFTREQ (the computing system and software level specification) to include the hardware structure and the software architecture covering such issues as digitisation noise, sensor management and actuator dynamics data selection.

This work is based on developing the use of Matlab/Simulink/Stateflow (MSS) [18] by adding formalism to MSS specifications in a non-obtrusive manner (i.e. allowing those competent in using MSS to use formalism without the need for extensive training in formal techniques). This has three core elements which comprise: applying notational restrictions; representing important assumptions about the domain behaviour in MSS specifications; providing rules for “healthiness” of specifications which are checked by a Simulink/Stateflow analyser (SSA) tool.

The PFS/SSA approach addresses some of the identified issues and the authors acknowledge that it should be considered as one component of the work needed to address the major challenge of providing an integrated and usable approach for the development of safety critical systems.
2.3.4 KAOS

KAOS (Knowledge Acquisition in autOmated Specification) [24, 128] is an approach that provides a specification language for capturing why, who, and when aspects as well as the usual what requirements. It has a goal-driven elaboration method and draws on a number of concepts from Artificial Intelligence work on knowledge representation and acquisition [128]. A KAOS specification has a two level structure; an outer semantic net layer for declaring concepts, their attributes and links to other concepts; and an inner formal assertion layer for formally defining the concept. The latter combines a real-time temporal logic for the specification of goals, constraints, and objects, and standard pre/post conditions for the specification of actions and their strengthening to ensure the constraints [25]. KAOS is a form of goal-oriented RE that uses goals for requirements elicitation, elaboration, organisation, specification, analysis, negotiation, documentation and evolution. Goals are objectives to be achieved by the system under consideration. The term "system" refers to the software to be designed and its environment [68]. Goals are formulated in terms of optative statements which may refer to functional or non-functional properties and range from high-level concerns (the system will play audio warning messages to the pilot) through to lower level ones (if the message identifier does not correspond to the selected message then the audio mute discrete will be set active). A suitable goal directed acquisition strategy can be made up of the following steps:

1. Acquisition of goal structure and identification of objects.

2. Preliminary identification of agents and their actions.

3. Operationalisation of goals into constraints.

4. Refinement of objects and actions.

5. Derivation of strengthened conditions.
6. Identification of alternative agent responsibilities.

7. Actual assignment of actions to responsible agents.

Agents are active system components which act as a "processor" for some actions - an action being a mathematical input-output relation over objects. Achieving goals in general requires the cooperation of multiple agents. Although the steps are ordered, the strategy allows for some of them to run concurrently (e.g., 1, 2 and 3) and for backtracking and iteration. Tactics can then be applied to each step of the strategy, as detailed in [24]. For example the tactic "Reduce goals into subgoals so that the latter require co-operation of fewer potential agents to achieve them" can be applied to step 1 of the strategy. A typical model fragment after step 1 would have the form:

```
System Goal Achieve [MeetingRequestSatisfied]
Instance of SatisfactionGoal. Concerns ReducedTo; Informal Def

FormalDef
(∀r: Initiator, m: meeting, p: Participant)
Requesting(r,m) ∧ Feasible(m) ⇒ o_initial Scheduled(m)
∧ Invited(p,m) ⇒ o_initial Know(p,m)
```

The goal refinement process stops when goals are reached that can be assigned as responsibility to single agents. Terminal goals assigned to agents become requirements; terminal goals assigned to agents in the environment become assumptions. The later cannot be enforced by the software to be and have to be validated since the overall design will rely upon their properties.

KAOS supports separation of concerns between domain definitions (the environment) and system requirements and is consistent with the Parnas 4-variable model [19, 67, 133]. Further, the formal layer incorporates a library of reduction templates that are "pre-proved" using standard temporal logic techniques. Thus an analyst can use these templates with the knowledge that they are correct, and will not have to prove this later in the process. It is worth noting that the formal aspects of KAOS
were emphasised in the early work since it was found to be very useful in finding bugs in the resulting specification [128].

The use of KAOS in practice identified a number of issues concerning the very top-down nature of the approach. The solution developed was to introduce scenarios as discussed in detail in [129]. This effectively introduces a hierarchy of goals, requirements and scenarios.

### 2.3.5 AdLS

The AdLS approach is based on the belief that substantial improvement in the dependability of computer based safety-critical systems can be achieved by applying a detailed safety analysis to the requirements specifications of the software before proceeding to any subsequent phases of the development. The approach involves modelling the system and its environment, iterative simultaneous requirements and safety analyses, and documentation of linkages identified between artefacts produced by these analyses with a safety Specification Graph (SSG) [26].

The Methodology for the analysis of safety requirements involves the phases shown in Table 2.2, which provide a framework for partitioning the analysis into smaller phases obtained from a hierarchical model of the structure. AdLS uses a set of informal and formal techniques appropriate to the issues to be analysed. A typical AdLS development begins with an environment analysis to understand the environment context and to identify the accidents relevant to the system. This is followed by plant analysis that identifies rules of operation (assumptions) and plant safety specifications. The latter identify hazards that in conjunction with certain conditions in the environment could result in an accident. Safety constraints are then developed to counter the hazards and these are supported by plant safety strategies which are schemes for maintaining a safety constraint. The accidents, hazards, safety constraints and plant safety strategies can then be formed into a
hierarchical SSG. The SSG is used to direct the vulnerability analysis. The process proceeds with plant safety analysis followed by safety controlling system analysis.

<table>
<thead>
<tr>
<th>Analysis</th>
<th>Purpose</th>
</tr>
</thead>
<tbody>
<tr>
<td>Environment analysis</td>
<td>aim, purpose &amp; accidents</td>
</tr>
<tr>
<td>Safety plant analysis</td>
<td>identifies hazards</td>
</tr>
<tr>
<td>Safety plant interface analysis</td>
<td>behaviour of sensors and actuators</td>
</tr>
<tr>
<td>Safety controlling system analysis</td>
<td>top level organisation for the controlling system</td>
</tr>
</tbody>
</table>

Table 2.2: AdLS Structure

At each phase the requirements analysis produces safety specifications, and the safety analysis checks acceptability - this is an iterative process. The safety specification imposes restrictions, and it is necessary to check these are consistent with the mission goals. Explicitly documenting assumptions enables impact of changes in them to be traced through the SSG.

2.3.6 Agenda-Based Methods

The goal of the agenda-based methods [44] was to counter some significant problems identified with the use of formal specifications: no methodological guidance given for the application of the formal technique; there is a need to perform requirements analysis before writing the specification; the formal techniques are not well integrated with the requirements analysis phase. The solution to these issues was to provide a requirements elicitation agenda to be followed which ensured that due notice was taken of analysing the requirements and distinguishing the environment, along the lines described in [133]. This agenda comprised of six items:

1. fix the domain vocabulary (domain theory, entities (nouns) and relationships (verbs))

2. state facts, assumptions and requirements in natural language

3. identify possible user operations and input/output parameters
4. list all relevant system events and their parameters

5. classify the events

6. formalise facts, assumptions and requirements as constraints on system traces

The starting point is expected to be an informal customer requirements document, and there is a need for communication with the customer to validate the process. The role of the first five steps is to understand the problem, the sixth is to initiate the formalism from which the formal specification can be derived. The latter also includes a heuristic approach for dealing with requirements conflict. The formal specification agenda is a two step process: define a first approximation of the software system state, and augment the specification by incorporating the requirements in turn. Completeness is identified as an important characteristic of the method, directly supported by the first steps of the requirements elicitation agenda and by feedback from the specification phase.

The agenda-based methods are not confined to any particular notation, but can be used with a number of formalisms. For example, later work demonstrated how Problem Frames and architectures could be used as part of a pattern-based specification and design approach following a four step agenda [17]. This involved providing additional problem frame templates to map to particular architecture styles.

The agenda-based approach has many similarities with KAOS. The main distinctions being that KAOS has its own language and takes a much broader perspective modelling the software system and the environment in detail. In contrast the agenda-based approach only models those aspects required to support an adequate specification. This means it is efficient, but raises concerns about how it might handle safety requirements which are system wide - i.e., includes the environment.
2.3.7 Formal Safety Analysis of Models and SCADE

Using a formal model to provide enhanced, formal safety analysis capabilities has emerged as an important research topic in recent years [58], [101], [2], [97]. Traditionally safety engineers perform manual analyses using the techniques described in section 2.2.2. These are based on informal design models and requirements documentation. The results tend to be quite subjective and dependent on the skill and experience of the analyst. There are also concerns that it is difficult to demonstrate that these manual analyses are complete, consistent and error-free [58]. This resulted in work which applied formal safety analysis to formal models of the system with the following advantages:

- close integration between the system and safety analyses as they use the same models
- the ability to perform a meaningful analysis of the architecture early in the development
- the ability to prove that the model has the required properties.

First the system formal model is developed and validated to establish nominal correctness, then failure injection is applied to investigate the system's safety capabilities. One approach identified a manual method for injecting failures [58], but other work noted the increased workload problem on large systems and developed tool support for automatic injection [101], [2]. A potential problem is that if the model is inadequate then so will be the analysis, therefore [97] encourages independence and diversity in the application of safety analysis techniques to ensure adequate coverage. In this work the POSE/Alloy [52] combination will be used to achieve a similar level of formal safety analysis of the formal requirements model and the PSA will be developed to support this task.
Both [58] and [2] used SCADE as the basis for their work, and SCADE was also used in recent work on developing AMBERS [23]. AMBERS also uses the Parnas 4-Variable model (based on the SCR variant) and tables for the requirements phase and targets the SCADE [31] system for the subsequent development. AMBERS has similar goals to and is also compatible with POSE, but it does not include the specific early (PSA) safety analysis feasibility check introduced in this work.

2.3.8 Automated Safety Analysis of Complex Systems

The importance of safety and embedded critical system development has been identified by a number of European Union (EU) funded research projects such as the ESACS (Enhanced Safety Assessment for Complex Systems), ISAAC (Improvement of Safety Activities on Aeronautical Complex systems) and ASSERT (Automated proof-based System and Software Engineering for Real-Time applications) [5] projects and through a number of pan-industrial collaborations using AADL (Architecture Analysis and Design Language) and the AltaRica project – AltaRica was used and further developed on the ESACS, ISAAC and ASSERT projects [11]. These projects have sought to improve the analysis and development of critical systems by addressing process issues and developing supporting analysis tools.

For example, an AltaRica model for use with PSSA [50] focuses on the potential fault propagation inside a system. Abstraction is used to reduce complexity in these models by replacing concrete variables (with potentially numerous values) that would be typically used in a functional model, with more abstract quality variables which have just two values – correct or erroneous. This abstraction produces smaller models, but at the expense of the AltaRica model not being the same as the functional development model - raising the obligation to demonstrate that the two model views are equivalent. The system hazards are represented as “feared events” which are encoded into the model using observer nodes. The analysis then proceeds
using tools to identify sets of unacceptable sequences (sequences where at least one feared event or qualitative system requirement is infringed). These unacceptable sequences are then analysed to identify the smallest set of software events that are required to eliminate these unacceptable sequences. This smallest set of software events is then formed into derived requirements which if satisfied ensure the unacceptable sequences cannot occur, and these derived requirements are added to the software specification.

One of the goals of the ASSERT project which ran from 2004 through to 2007 was to use AADL and proof techniques to improve co-operation between system and software development teams and produce re-usable building blocks to facilitate the development of complex embedded applications.

Automating and integrating the safety analysis tasks to cope with increasing complexity are features of these projects. Two prominent automated safety development approaches [77] used on these projects are those based on Failure Logic Modelling (FLM) and those based on Fault Injection (FI). FLM allows analysts to model the failure behaviour of a system as the design progresses and examples are AltaRica, FPTN and Hip-HOPS [77]. In contrast, FI allows automated analysis of detailed design models and uses SCADE and Simulink models as its input - examples being from the ESACS project and [58] (also refer to section 2.3.7). [77] argues that the two approaches are complementary as they deal with different parts of the development life cycle and they should be integrated - and this work was developed as part of the ISAAC project. [77] also notes that even FLM represents a significant cost and suggests the need for "lightweight" methods to be used in the early phases of a development to assist with such things as architecture evaluation and selection - and notes that [76] is an example of a possible lightweight PSSA approach.

The lightweight PSSA approach described in [76] is based on software architectures (although with some modification to the process it can be extended to cover hardware and system architectures) and consists of three main phases: dependency
modelling with both forward and backward model views; deductive exploratory analysis; inductive verification analysis.

In dependency modelling two views (called Forward and Backward Dependency Views) of the architecture are constructed to capture information about dependencies between services of different modules of the architecture – where a service could be a delivery of a data item, process communication or synchronisation. The two dependency views are then used in the analysis phases of the assessment.

The task of the deductive exploratory analysis is to identify and analyse potentially hazardous chains of dependencies in the architecture. These chains are identified by considering hazards (identified at earlier stages of the safety process), specifying them in terms of the services that modules provide, and then walking through the views in order to establish all the dependencies of critical services, as well as any mechanisms that minimise these dependencies.

Finally, in the inductive verification analysis hypothetical failures of some key modules services are considered and their potential effects on the system as a whole are established. Therefore, the purpose of this phase is to verify both the completeness (in terms of hazardous dependency chains identified) and correctness (especially with respect to potential single causes of failure) of the deductive analysis.

Each of these three main phases is broken down into a number of sub-phases which breaks the overall analysis down into manageable incremental tasks and provides verification for important aspects of these tasks. It will be shown that the development of the POSE/Alloy [52] combination in this work could also form a possible lightweight PSSA approach which could be used at the front end of the overall process described in [77].
2.4 Problem Orientation

By problem orientation (PO) we mean a body of work whose origins can be traced back to the seminal “Four Dark Corners of Requirements Engineering” paper by Zave and Jackson [133]. This paper identified four weak or dark areas in requirements engineering (RE) and concluded that there is a need in RE:

1. for terminology to be grounded in the reality of the environment;
2. to avoid describing the solution machine, rather describe the environment before and after the machine is applied;
3. to identify which entities are controlled by the environment, which are controlled by the machine and which environment entities are shared with the machine;
4. to recognise that the primary role of domain knowledge is in supporting the refinement of requirements into specifications.

The PO approaches find their genesis in these four issues:

1. for terminology to be grounded in the reality of the environment; Problem: the reality of the environment has no precise description so that requirements exist in the real world which consists of some inherently non-formal and hence imprecise elements. The difficulty for software is that software concerns the operation of the machine, a formally describable system, so that software problems (i.e. real-world problems that have software as their solution) consist of partly imprecise and partly precise elements [53]. This complicates the requirements sub-life cycle, identified by Lamsweerde [127] as consisting of Domain analysis, Elicitation, Negotiation and agreement, Specification, Specification analysis, Documentation and Evolution. With major real-world concerns such as sociological, political, organisational and economic issues being apparent to
the requirements, as well as formally describable issues of computation such as control flow, parallelism, etc. the path from requirements to code is required to combine both informality and formality. PO approaches, with their focus on the problem, must attempt to address the informal of the real world and the formal of the machine together. Also, any problem oriented approaches must be sufficiently expressive. This requires two capabilities [133]. The first is that they must provide for the declaration of a finite collection of action types that partition the space of all possible actions. The action types are (a) unshared environment controlled (UEC), (b) shared environment controlled (SEC) and (c) shared machine controlled (SMC). The second expressive capability is that the languages must allow assertions about the three action types, in both the indicative (about the environment) and optative (about the requirement) moods.

2. the source of this dark corner is the mad rush to a solution that overcomes the need to understand a problem before it is solved, avoiding the description of the solution machine in the requirements forces a consideration of the complexity of the context and requirements of the problem. However, it is easy to state that you should concentrate on understanding the problem before undertaking the solution, but this can be very difficult to achieve in practice. As a result, PO approaches tend to provide tools for the manipulation of the problem, rather than the of the solution. The problem world is a big place and it is not always straightforward to identify the relevant parts of the environment. In such cases domain knowledge and experience are essential to success, as is appropriate modelling and analysis [127]. There is a need to include just the right parts of the environment. Too much information involves wasted effort and potential obfuscation by irrelevant detail, too little and essential behaviour may be omitted. The former is wasteful, but the latter is potentially
disastrous for the development since the developed machine will not interact correctly with its environment. Systems theory introduces the concept of "emergence", which is the idea that at a given level of complexity there are properties characteristic of that level [16]. It amounts to the idea that the "sum" is somehow more than the "parts" and presents a problem for the related concept of reductionism, so important in many aspects of science and which has a long history [78, 115]. The reductionist approach to complexity is to partition the problem into simpler tasks and attack these separately, and this has proven to be of immeasurable value in many areas of science, particularly the physical sciences of chemistry and physics [16]. However, the concept of emergence means that checks have to be introduced to ensure that something important is not lost through the application of reductionism. Some problem oriented approaches split the problem into simpler parts and work on these: only considering the composition problem of combining these parts after the solutions to the individual parts has been successfully established. This "divide and conquer" approach follows from the premise "if you cannot solve the smaller problems, then you will not be able to solve their composite" [55]. It recognises that the composition may be difficult, but argues this is facilitated by the knowledge gained from solving the simpler problems and not having to try to solve the simpler problems at the same time as dealing with the composition.

3. the separation of environment and solution is another aid in managing the complexity of the problem as it allows the specification to be distinguished from the requirements. These are both optative entities, but the requirements are formulated in terms of objects in the real world in a vocabulary accessible to the stakeholders. Requirements capture required relations between objects in the environment that are monitored and controlled by the software [19]. In
contrast, the specification is formulated in terms of objects manipulated by
the software in a vocabulary accessible to programmers and captures required
relations between input and output software objects. There is a semantic gap
between the requirements and the specification which has to be bridged for
a successful development to take place, and domain knowledge of the envi-
ronment has a key role in bridging this gap. An important aspect of the PO
approaches is the tools they provide to assist this bridging process. In [133],
Jackson and Zave noted that requirements that are not implementable fail to
be so for three general reasons:

(a) Environment Constraint. Some requirements can only be satisfied by con-
straining an action that is controlled by the environment. For example, in
a turnstile entry system there might be a requirement that the number of
people allowed entry must not exceed the number of payments received.
This represents a constraint on the entry actions which are controlled by
the environment.

(b) Unshared Information. Some requirements are not directly implementable
because they are stated in terms of unshared phenomena. For example, a
lift must arrive at a floor where people are waiting - how can the machine
know that people are waiting? The resolution of this problem requires
request and arrive actions to be shared with the machine. It also relies
on the domain knowledge about human behaviour that people will tend
to wait after they have made a lift request.

(c) Future Reference. Some requirements are not directly implementable be-
cause they are stated in terms of the future. A high-level requirement
from an aircraft stores management system might state “A store on a
store carrier selected for release, must be successfully released before an-
other store from the same carrier can be selected for release. If the first
store is not successfully released, then it must be declared as hung and no further store release attempts are allowed from that carrier". The stores management computer (SM) does not know if the store has gone or not. The SM provides the control signal to set the release process in motion, but it has no way of knowing (by itself) whether the release - which is a future event - is successful or not. To satisfy the requirement, the SM has to take in data from the environment. In this case data from the store carrier stating if the store has gone or not, and knowledge that the explosive devices used in the release mechanism will have completed well within a 500 millisecond limit. This knowledge allows the requirement to be re-expressed in a more implementable form as "A store on a store carrier selected for release, must be successfully released within 500 ms, otherwise the store will be declared as hung and no further release attempts to the carrier should be allowed. Successful release is defined as the store carrier informing the SM that the store has gone". This implementable form of the requirement includes domain knowledge and relies on environment controlled phenomena.

Note that all of these types use domain knowledge to fill-in behaviour information to make them implementable. In fact these three types are not "non-implementable" in the strictest sense, but rather they cannot be implemented directly without the addition of further information. Therefore this text will refer to them as being "non-feasible" rather than "non-implementable" – the idea being that they can be implemented if the required information is supplied. In fact, Zave and Jackson [133] classified requirements into four types, the above three non-feasible requirements and they also identified a fourth class that are directly implementable.

4. formally Zave and Jackson express this in the entailment:
In the entailment $W, S \vdash R$ represents the indicative properties of the environment domain (the world context), $S$ is the specification of the machine and $R$ represents the desired or optative properties of the requirement. The entailment is taken to mean that if a machine satisfying the specification $S$ is operating in the world with environment domain (indicative) properties $W$ then the optative properties defined by the requirement $R$ will be satisfied. That is, the relationship between the software solution and the requirements is given by the context into which the solution is deployed. Satisfying this entailment is an important first task in the software development process, and involves understanding the environment domains and establishing the requirements that will result in the desired behaviour before specifying the computer machine that forms the solution.

The completeness of requirements engineering can be formally formulated in terms of this entailment:

(a) There is a set $R$ of requirements. Each member of $R$ has been validated (checked informally) as acceptable to the customer, and $R$ as a whole has been validated as expressing all the customer’s desires with respect to the software development project.

(b) There is a set $W$ of statements of domain knowledge. Each member of $W$ has been validated (checked informally) as true of the environment.

(c) There is a set $S$ of specifications. The members of $S$ do not constrain the environment, they are not stated in terms of any unshared actions or state components, and they do not refer to the future.

(d) A proof shows that $W, S \vdash R$. This proof ensures that an implementation
satisfies the requirements.

(e) There is a proof that $S$ and $W$ are consistent. This ensures that the specification is internally consistent and consistent with the environment.

In the following we will review a number of approaches which have developed from these ideas.

### 2.4.1 Problem Frames

Problem Frames (PF) [53] allows one to construct the specification ($S$) for a machine ($M$), such that the machine $M$ satisfying $S$, in conjunction with properties of the problem world, $W$, satisfies the requirements represented by $R$. This covers part of the $W, S \vdash R$ entailment described in section 2.4 and is represented diagrammatically in Figure 2.3.

![Figure 2.3: A Typical PF Problem Diagram](image)

The machine $M$ and the problem world $W$ are both physical entities, so they are shown as solid lines in Figure 2.3. In contrast, the requirements $R$ are intangible so are shown dashed. The machine interacts with the problem world at an interface represented by the shared phenomena $a$. Shared phenomena are either controlled by one of the machine or the problem world and observed by the other [55]. The requirements refer to the physical phenomena, represented by $b$, of the problem world. The arrow denotes that the requirements place constraints on these phenomena. In general, the requirement phenomena $b$ are distinct from the specification $a$. Although they can be the same and it is often convenient to achieve this, if possible, as it simplifies the analysis.

PF are targeted at real world engineering problems, but not to what might
be called *computational problems* such as factorising a large integer or finding the shortest path in a graph [55]. The latter are ideal candidates for formal development [43] due to their closed nature (i.e., no interface to the real world). PF can also work with formal development systems [113, 114, 17], but as noted in section 1.1 care is required in mapping between the real world entities and their formal equivalents.

The gap between what is desired at the interface b (requirement R) and what can be directly monitored and controlled by the machine at the interface a is bridged by the given properties of the problem world W as shown by \( W, S \vdash R \) and explained in section 2.4. Showing this relationship holds is called the *basic problem concern*. Therefore, a PF development begins with a description in the real world involving \( R, b, W, S, \) and \( a \), and from this a set of related sub-problems are derived – where the sub-problems map to known patterns called basic frames. Jackson identified five basic frames [53] these being:

- **Required Behaviour**: the problem is to build a machine that will control some part of the physical world to satisfy certain conditions.

- **Commanded Behaviour**: the problem is to build a machine that will control some part of the physical world in response to commands issued by an operator.

- **Information Display**: the problem is to build a machine that will obtain information about the physical world and display it appropriately in the required form.

- **Simple Workpieces**: the problem is to build a machine that will allow a user to create and edit certain computer text, graphics or similar objects so that they can be processed as required.

- **Transformation**: the problem is to build a machine that will transform given input files into output files in the required format.
PF are the most researched of the problem oriented approaches and have an active research community developing and extending their scope [20, 21]. Some authors have provided extensions to the basic set of PF templates to cover a particular problem domain. PF have also been used in conjunction with architectural styles to form a systematic software development process based on patterns and the agenda concept [17]. Patterns are a way to reuse software development knowledge at different levels of abstraction. In this scheme PF provides problem patterns and the architectural styles provides solution patterns. The agenda encodes process knowledge. It is the combination of the patterns and the agenda that provides the systematic development process.

A more generic extension to the PF approach is the architectural frame or AFrame, which provides an architecture-driven problem decomposition [103]. This uses AFrames as architectural styles located in the solution space to guide the analysis of the problem space. AFrames have been developed for the linear pipe and filter, and model view controller (MVC) architectures to show the utility and power of the approach. They also address two criticisms raised against PF: the assumption of a green-field development process and expertise is required to guide the appropriate decomposition [103]. The AFrame concept addresses these criticisms as follows. AFrames provide guidance on how the problem needs to be restructured to fit a particular solution form. They also assist in the solution synthesis by guiding the decomposition of sub-problem solutions into a solution of the original problem. The AFrame structure encodes expert knowledge, which directly supports the software development process. In this way, AFrames provide a link between the problem and solution spaces.

In their standard form [53] PF are focussed on the problem domain and do not have tools to bridge the gap and access the solution space. The development of AFrames addresses certain aspects of this issue, while POSE, which is considered in section 2.4.3 below, takes the work even further.
2.4.2 REVEAL

REVEAL [42] provides a process to elicit the real world requirements in the context of the proposed operating environment (domain). It provides a means to develop the specification of a machine that will satisfy the requirements when operating in the context of the environment it is to be used in. The process is supported by checklists to ensure adequacy, quality of expression and self-consistency of the requirements. The process also provides support for managing and resolving requirements conflicts and for managing change. Although REVEAL is a process it is tool independent. It is informal in operation, but can be used as part of a formal development. It can also be used in conjunction with other common requirements tools such as DOORS.

One of the key principles of REVEAL is that Requirements Engineering begins with a description of the whole application domain, including domain entities that do not directly impact with the system. Iteration covers the transformation from high level requirements about the world into specifications about the machine and its interface. Scenarios are used as a tool for describing and exploring such dynamic behaviour. This approach readily establishes traceability, but goes further with its notion of Rich Traceability – which provides heuristics to support the development from the requirements into the specification. For a given requirement, its Rich Traceability consists of an argument that explains:

- which statements (e.g., requirements, specifications or domain knowledge) combine to satisfy it;

- how/why the particular combination achieves the given statement.

Therefore Rich Traceability plays the role of the turnstile (\(\neg\)) in the satisfaction argument.
2.4.3 POSE

Problem Oriented Software Engineering (POSE) [39, 40, 41] is an extension and generalisation of Jackson's Problem Frame approach [53]. The following is a brief summary of its main characteristics based on the more detailed descriptions in [39, 40, 41]. In POSE, software development is viewed as solving a problem, the solution being a machine (a program running in a computer) that will ensure satisfaction of the requirement in the given problem world consisting of real-world domains. Like Problem Frames, POSE views the problem world as a collection of domains described in terms of their known, or indicative, properties, which interact through their sharing of phenomena, i.e. events, commands, states, and so on.

POSE is defined as a transformational system, similar in form to a Gentzen-style sequent calculus [63] that allows problems to be transformed into problems that are easier to solve, or that will lead to problems that are easier to solve. A set of transformation rule schema capture (atomic) discrete steps in development. Each requires a justification of application in order for the transformation to be solution preserving (this means that a solution to a transformed problem is also a solution to the original problem), but the justifications need not be formal. The combination of the justifications is an argument that the solution is adequate as a solution to the original problem.

POSE provides a structure which supports different development activities and allows them to be combined – this includes bringing together both non-formal and formal development activities. Development commences with the instantiation of the null problem about which little is known, and software development then proceeds by the application of problem transformations, each of which develops some aspect of a problem description – including gaining knowledge about the requirement and the environment context. The choice of which transformation to apply at any point is only tentative as each transformation must be justified before being
accepted as contributing adequately to the development. Sometimes a sequence of transformations will lead the problem to a "dead-end" and it will be necessary to backtrack to the point of departure and then follow a different path to an adequate solution. Note that these "dead-ends" provide useful insight into the problem space. This information can be very useful to help avoid cases where for example an over-enthusiastic maintainer may want to follow a path that has previously been shown to be a "dead-end". POSE is the basis of our candidate SSSD approach and will be introduced in detail in Chapter 4.

2.5 Literature Analysis

In this section we analyse the SSSD approaches described in section 2.3 with a view to identify some key properties that they exhibit. We then use such properties to evaluate the PO approaches described in section 2.4 with a view to justify a candidate approach to use in the remainder of this thesis.

2.5.1 Property Identification

Inspection of the SSSD approaches described in section 2.3 allows a number of key properties to be identified that an approach targeted at the development of the early phases of a safety development process should possess. The following paragraphs identify ten such properties.

Understanding the system environment context (Context) is a central feature of the Parnas 4-Variable based techniques such as Parnas Tables, SCR, SpecTRM, AMBERS and the PFS development work (section 2.3.3). It is also important in the AdLS, FLM and KAOS approaches, although in KAOS it is not given the same level of prominence as other features.

One way of reducing the risk of rework is by selecting an appropriate system architecture that facilitates the resolution of the key issues as an integral part of the
development. Without such a selection, then one may end up with an inappropriate architecture that is not capable of assisting with the resolution of all or even some of the key issues. The result is that the development of a satisfactory solution becomes much more problematic and inevitably more expensive. So the capability of modelling different candidate architectures is a highly desirable feature of any proposed approach (Architecture). KAOS, PFS and FLM have features that provide strong support for architecture, whilst the other techniques (Parnas Tables, AdLS, SCR, SpecTRM, and AMBERS) provide some support.

All of the safety techniques discussed in section 2.3, apart from AdLS, have some capabilities in producing a specification that spans the gap between the problem world and the solution space. The full process approaches of KAOS, AMBERS, SCR, SpecTRM and Parnas Tables cover this in some detail, but it is not a specific highlighted feature of PFS or the FLM approaches. It follows that the language of the selected approach must be able to span the problem and solution spaces (Spec. Join).

Implementation bias (Avoid Bias) can result in unnecessary and inappropriate constraints on the solution, and the avoidance of this property is a desirable. The KAOS approach has good capabilities in dealing with this property through its multi-level abstraction and validity checking mechanisms, and the linkage and focus provided by the SSG means AdLS is also good at avoiding bias. The high level of abstraction and other features also mean that the FLM approaches and PFS have good capabilities in avoiding bias - but the other techniques are not so strong in this area.

The Parnas 4-Variable based techniques ensure that the model, domains and interfaces are grounded in reality (Model Reality), and this property is also an important feature of PFS with its enhanced features. The SSG linkages mean AdLS has good capabilities with respect to this property. However, it is not a strong feature in KAOS or the FLM approaches.
All the techniques support the task of validating that the right system is being produced to a certain extent (Validation). Some, like SpecTRM, SCR, PFS, the FLM approaches, KAOS and AMBERS go further by providing tool support for validation, including simulation and/or proof.

KAOS manages complexity through its ability to structure the problem, so that large complex problems can be broken down into smaller problems that are easier to solve (Simplification). The other approaches such as AMBERS, Parnas Tables, SCR and SpecTRM use simplification as part of their development process, but do not have the process support offered by KAOS. PFS offers strong capabilities with its modelling and refinement support, whilst the FLM approaches make use of their "divide and conquer" features such as abstraction to handle complexity.

Tool support (Tool Support) is an important practical consideration with respect to both efficiency, error-avoidance and repeatability, so this is certainly a desirable property and techniques such as the FLM approaches, PFS, KAOS, SCR, SpecTRM and AMBERS support this. Specific tool support is not a feature of Parnas Tables or AdLS.

Safety standards require analysis to be performed early in the life cycle, so the ability to work at a suitably early point, i.e., the right level of abstraction, is also important (Right Abstraction). KAOS, PFS, AdLS and the FLM approaches have very good abstraction capabilities and support comprehensive analysis tasks, as does AMBERS. SCR and SpecTRM also support extensive analysis capabilities although this tends to be relatively later in the life cycle. Parnas Tables do not have analysis tool support but allow a manual analysis to be conducted.

Finally, one of the aims of this work is to improve an existing process (i.e. to support "normal design" principles), so the selected approach must be capable of working with an existing life cycle method (not replacing it!) – i.e. it must integrate with it (Integrates). Approaches such as KAOS, PFS, SCR, SpecTRM, and AMBERS have a specific tool supported process which is different from the existing
process introduced in detail in Chapter 3. These approaches could be adapted, but it would be a significant undertaking. In contrast AdLS and Parnas Tables could be adapted for use with the existing process and the FLM approaches could be used directly.

Although these ten properties were derived from an analysis of the SSSD approaches presented in section 2.3 they are also supported by other sources in the literature and all this is summarised in Table 2.3.

<table>
<thead>
<tr>
<th>Property</th>
<th>Description</th>
<th>Literature Support</th>
</tr>
</thead>
<tbody>
<tr>
<td>Context</td>
<td>Importance of Domain Context</td>
<td>[54, 82, 121, 127]</td>
</tr>
<tr>
<td>Architecture</td>
<td>Architecture to encapsulate</td>
<td>[82]</td>
</tr>
<tr>
<td>Spec. Join</td>
<td>Specification as “join”</td>
<td>[121]</td>
</tr>
<tr>
<td>Avoid Bias</td>
<td>Avoid implementation (solution) bias</td>
<td>[133, 16]</td>
</tr>
<tr>
<td>Model Reality</td>
<td>Model domain and interfaces grounded in reality</td>
<td>[133, 16]</td>
</tr>
<tr>
<td>Validation</td>
<td>Validate the model represents reality</td>
<td>[122, 16]</td>
</tr>
<tr>
<td>Simplification</td>
<td>Support simplification</td>
<td>[69, 16]</td>
</tr>
<tr>
<td>Tool Support</td>
<td>Tools to support application of approach</td>
<td>[96, 45, 90]</td>
</tr>
<tr>
<td>Right Abstraction</td>
<td>Early analysis requires abstraction</td>
<td>[82, 71]</td>
</tr>
<tr>
<td>Integrates</td>
<td>Integration with Existing Life Cycle</td>
<td></td>
</tr>
</tbody>
</table>

Table 2.3: Ten Properties of SSSD Approaches

A comparison of the relevant SSSD approaches with these ten properties is shown in Table 2.4, where the property descriptor from Table 2.3 is used to represent the desired property as appropriate. The FI techniques (section 2.3.8) apply to detailed design models so are not considered for the early development phase work that is the focus of this document. In this comparison table (Table 2.4) “Y” denotes that the approach supports the property based on supporting evidence from the literature, “P” means the approach partially supports the property or might support the property but there is insufficient evidence from the literature, whilst “N” means the approach provides little or no support for the property based on the published literature.

The Parnas Table based methods are strong contenders, since they were developed to produce safety systems, and the system context and handling requirements are an important aspect of their operation, but they are more appropriate to the
Table 2.4: Comparison of Properties by SSSD Approaches

<table>
<thead>
<tr>
<th>Property</th>
<th>SCR</th>
<th>SpecTRM</th>
<th>Parnas</th>
<th>KAOS</th>
<th>AMBERS</th>
<th>AdLS</th>
<th>PFS</th>
<th>FLM</th>
</tr>
</thead>
<tbody>
<tr>
<td>Context</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Architecture</td>
<td>P</td>
<td>P</td>
<td>P</td>
<td>P</td>
<td>Y</td>
<td>Y</td>
<td>P</td>
<td>Y</td>
</tr>
<tr>
<td>Spec. Join</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>P</td>
<td>Y</td>
</tr>
<tr>
<td>Avoid Bias</td>
<td>P</td>
<td>P</td>
<td>P</td>
<td>P</td>
<td>Y</td>
<td>P</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Model Reality</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>P</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>P</td>
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<tr>
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<td>Y</td>
<td>Y</td>
<td>P</td>
<td>Y</td>
<td>Y</td>
</tr>
<tr>
<td>Simplification</td>
<td>P</td>
<td>P</td>
<td>P</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
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<td>N</td>
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<td>Right Abstraction</td>
<td>P</td>
<td>P</td>
<td>P</td>
<td>Y</td>
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</tr>
<tr>
<td>Integrates</td>
<td>N</td>
<td>N</td>
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<td>P</td>
<td>N</td>
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design rather than the early development phases. SCR, SpecTRM and AMBERS have extensive tool support, but the modelling supported by these methods is again more suited to the design phase. Neither are they very strong on the architectural aspects. They provide some support for simplification and can avoid bias, but this is not a specific feature of these approaches. Finally, they offer little direct support for the integrates property. simplification.

AdLS has many good features but lacks tool support for the formal techniques associated with it which affects its validation capabilities, and does not have strong support for the Architecture or Spec. Join properties. However, with some work it could be integrated with different development approaches.

In many respects KAOS is a strong contender, it has good tool support, supports a combination of formal and informal development and has strong elicitation capabilities. However, although KAOS does note the importance of the environment and that it is necessary to distinguish between the requirements and the environment; its environment context capabilities are not strong when compared with the PO approaches, and as a result the KAOS models are not as “grounded in reality” as desired. KAOS is also weak with respect to the integrate property due to its prescriptive nature.

That PFS features strongly is no surprise since it was conceived to handle em-
bedded safety critical applications and took the Parnas 4-Variable model approach as its basis, but added enhancements to the model and formality - "where formality adds engineering value" [32]. The Spec. Join property is not (currently) specifically supported and it is centred on MSS (Matlab/Simulink/Stateflow) – therefore it will not integrate easily with other development approaches.

Finally the FLM approaches have good capabilities and AltaRica was developed for avionics applications. However, they are primarily approaches for achieving automated safety analysis of complex systems (hence Model Reality and Spec. Join are specifically supported) and need to be used in conjunction with an appropriate development approach.

2.5.2 Assessment of the PO Approaches

In this section we assess the problem oriented approaches of section 2.4 against the identified properties:

- **Context**: the importance of context knowledge is one of the basic tenets of problem orientation, hence characteristics of all PO approaches reviewed.

- **Architecture**: This is not part of the original work of [133]. The architecture work of [103] partially addresses architectural design within problem frames. POSE fully supports architectural design as part of its basic transformation (as we will see in Chapter 4).

- **Spec. Join**: of the reviewed approaches, POSE has spanning problem and solution spaces as one of its key objectives.

- **Avoid Bias**: avoiding solution bias is a characteristic of the PO approaches, which stress the importance of fully understanding the problem, before designing a solution, and of expressing requirements solely in terms of the context phenomena.
- **Model Reality**: the concept of designating descriptions and phenomena in the real world is key to many PO approaches, particularly Problem Frames and POSE.

- **Validation**: a notion of validation is present in Problem Frames embodied in the concept of basic problem concern. It is a central concept in POSE where the notion of adequacy with respect to stake-holders and step justification come together to provide explicit tools for validation.

- **Simplification**: the idea of problem progression was introduced within Problem Frames to signify the move from requirements to specification during requirements analysis. It was then developed, independently into techniques by [74, 75, 113, 114]. POSE defines its own transformation notation of problem progression.

- **Tool Support**: none of the PO approaches offer any specific automatic tool support, except perhaps for a prototype Prolog-engine for POSE transformations [38]. From the literature there is no evidence of integration with other tools.

- **Right Abstraction**: all PO approaches are permissive when it comes to the choice of descriptions, so that identifying an appropriate level of abstraction remains an open problem for all of them. However, some guidance might be derived from Zave and Jackson's requirements taxonomy and their characterisation of implementable specification [133].

- **Integrates**: the only PO approach which so far has been integrated into practice is REVEAL, which in fact was defined in an industrial context.

From this analysis it follows that PO approaches in general, and POSE in particular, offer good capabilities with respect to the ten properties identified in Table 2.3.
By definition all PO approaches focus on gaining an adequate understanding of the system context and the requirements. Problem Frames scores well on most of the criteria, except that it is weak in addressing the solution domain and has no tool support. In contrast, POSE is capable of scoring highly on all the criteria except for tool support. Therefore, on balance POSE appears to offer the best fit with respect to the properties identified in Table 2.3. However, evidence will need to be collected to support this proposition, and this will be covered in the chapters that follow.

2.6 Chapter Summary

This chapter began with a definition of the safety terminology to be used in this thesis, followed by an investigation of the safety context that underpins this work – including the need to produce evidence to support a safety case. The need to perform a safety analysis in the early phases of the development life cycle was justified, and some techniques that might be used to achieve this were introduced. Then a number of safe software system development (SSSD) approaches were presented. Next problem orientation was introduced, the concepts involved explored and some problem oriented approaches discussed. The chapter concluded with the identification of the ten generic properties based on the SSSD approaches, against which the SSSD and the problem oriented approaches were compared. The comparison indicated that Problem Oriented Software Engineering (POSE) appeared to be capable of addressing most aspects of the ten properties and was therefore selected as the candidate approach to be used in the rest of this thesis.

Although much of this work will concentrate on the early phases of the development process and the task of deriving a safe specification from the system requirements, it is important to note that the selected method must have capabilities that can span the gap between the problem and solution spaces, because the ultimate aim is to develop safe code to implement the safe specification. POSE has these
capabilities, providing further evidence to support its selection for this work.
Chapter 3

Analysis of an Industrial Safety Process

Chapter 2 identified a set of ten key properties that an appropriate safe software system development (SSSD) approach should possess. The aim of this chapter is to describe and analyse the early phases of an industrial safety development process with a view to identifying additional properties and process issues the discharge of which could lead to a notable improvement of the process, and that our proposed approach should address.

3.1 Process Overview

The specific aspects of the safety development processes followed by different companies depends on the standards they are required to follow and this is often determined by the business sectors they operate in. The author's company (the Company henceforth) operates primarily in the UK defence sector, so its safety process is based around DS 00-56 [125]. As will be explained there are some unique aspects of the process, but generally it is typical of the safety processes used by other UK companies operating in the military sector, and it shares many similarities with safety
processes in general (e.g. those following IEC 61508 [51]).

The Company follows an integrated product development process (IPDP) for all their development projects, including safety - thus satisfying the goal discussed in section 2.2 that the safety process should be integrated with the development process. For developments with functional safety requirements the basic process is augmented with high integrity activities; these will be described where appropriate in the description of the IPDP that follows. The IPDP is split, as shown in Figure 3.1, into an over-arching Management phase and three main technical phases which are historically called: (a) Concept Evaluation (CE), (b) Demonstration/Validation (Dem/Val) and (c) Engineering, Manufacturing and Development (EMD). With the latter phase being by far the major component, it is further sub-divided into the major sub-phases of Preliminary Design, Detailed Design, System Validation and Certification. The IPDP has been used for over 10 years and has evolved as a result of feedback from its use on a wide variety of projects. This evolution has meant that some of the phase/task titles no longer capture completely all the activities undertaken to support them, as will become clear when some of the tasks are described in more detail below. It should be noted that Figure 3.1 concentrates on the initial part of the IPDP since this is the area of interest for this work - namely the CE phase, the Dem/Val phase and the EMD Preliminary Design sub-phase. These phases are further sub-divided into high-level tasks, which in turn are further divided into sub-tasks and so on, to form a hierarchical task structure. That is, the development process is partitioned into a series of inter-related tasks. These tasks cover management, planning, analysis, development, validation, verification and review activities; and as noted, the safety tasks are an integral part of the structure. Each task details the input criteria, what is to be achieved by executing the task and the output criteria. Following this IPDP has given the Company a repeatable, consistent and controlled development process.

The exit from one phase/sub-phase to entry to the next is controlled by a major
Figure 3.1: The Integrated Product Development Process (IPDP)

review - these are the SRR, SDR and PDR on Figure 3.1 and explained in more detail below. The transition between phases is only allowed if appropriate review criteria are satisfied.

The safety management tasks of safety planning (output being the Safety Programme Plan) and safety audit and monitoring are included as part of the Management phase. The IPDP safety tasks are based on a safety life cycle model that follows the approach defined in the second edition of DS 00-56 [123]. These IPDP safety tasks are under continuous development to ensure that they satisfy the safety goals of the products being developed. The later version of DS 00-56 [125] is goal oriented and does not prescribe what sort of life cycle should be followed. However, it does identify the type of safety artefacts that should be produced (including hazard list, hazard analysis and risk mitigation) and requires that a safety case should be developed to provide the argument for safety. A detailed review [84] shows that the IPDP safety tasks provide the required safety artefacts and a safety development process that supports the production of an appropriate safety case argument. Thus the IPDP safety process has been evolved such that it continues to satisfy the
provisions of DS 00-56 as the latter is developed over time.

All projects in the Company have to follow the safety life cycle built into IPDP, since every project has safety obligations that must be discharged. For many projects, these are just non-functional health and safety based obligations which discharge the Company’s obligations to satisfy EU Directives and their corresponding UK safety regulations. However, for safety involved and safety critical developments the level of analysis and need to provide sufficient evidence increases many fold, and the safety case is a much more detailed structure. It is the latter types of system that this work is interested in supporting. Experience within the Company has demonstrated that these safety systems require much more work to cover their functional behaviour aspects. This is characterised by the need for:

- development of a logical argument for safety
- specific architectural features to support the safety argument
- significantly more and diverse evidence, including proof for safety critical work.

Using this process to build these architectures and adopting a policy of “keep it simple” has resulted in systems that have been accepted into service at the highest levels of criticality by the various regulatory authorities. The Company is keen to continue along this successful path, but is also keen to continue to improve the integrity and efficiency of the IPDP safety process. To support this the Company runs a Lessons Learned Database (LLD) which is used to record the good and the not so good elements of all completed programmes. The aim is to capture any problem issues arising so that (a) the lesson is recorded and is learned, and (b) corrective action is implemented to avoid the same problem in later programmes. Discussions on and comparisons with the safety development processes used by other companies operating in the sector indicate that these processes share the same issues and problems.

1The Company works with other industry representatives through its presence on a number of
In the following sections, we describe enough of the early phases of the IPDP to allow the identification of a necessary property and some advantageous properties that we would like our development approach to possess. In addition, we identify six issues, instances which are repeatedly found in the LLD that will be addressed in our work. To this end, we will separate and provide a short description of each issue that will allow them to be traced through the remainder of this work. Although most of the issues are observed in the CE phase, they are also issues with the following phases; after their description and capture from a description of the CE phase, we continue to identify their impact on the subsequent phases in section 3.3 and section 3.4.

The case study work in Appendix A shows an example of the tasks involved in the CE, Dem/Val and EMD Preliminary Design phases – this section can be read without reference to the Appendix, but the latter does provide additional information if required.

3.2 Concept Evaluation (CE) Phase

The first part of the CE phase involves understanding the system context, identifying the main system components and gaining an understanding of how they interact. It proceeds by performing tasks targeted at developing the conceptual design, eliciting the functional requirements and analysing the safety requirements attributed to the system to be developed.

3.2.1 System Context and Conceptual Design Issue

It has been observed that (via the LLD) the CE phase tasks are not systematic in deriving a consistent understanding of the system environment. Similar types

safety working groups such as the GSN User Group, MoD safety forums and the SBAC (Society of British Aerospace Companies).
of entry in the LLD indicates that often too many details are left vague or not investigated with enough rigour. The result of this issue is that the domain and interface descriptions are ambiguous, which results in problems later in the life cycle as different engineers interpret the environmental context features in different ways, which increases the risk of rework. The need to model aspects of behaviour in the Dem/Val phase does highlight some of these ambiguities, but many are not uncovered until the more detailed Use Case modelling that occurs during EMD. The later this issue is uncovered, then the more costly it is to remedy which increases project risk in terms of expense and schedule time. This is identified as our first issue:

[Envir1]: Incomplete understanding of the system context increases the risk of rework.

3.2.2 Initial Functional Requirements Issue

The elicitation tasks involve assimilating requirements from the various stakeholders including the customer, those in the Company responsible for business objectives and those responsible for ensuring that necessary legislation is satisfied. The information sources includes customer documentation, discussions with the customer and interviews with the other stakeholders. At this stage a certain amount of overlap and contradiction is not unexpected, the idea being that these issues are resolved by the analysis work undertaken in the following Dem/Val and EMD phases. The main issue identified with these tasks (from inspection of the LLD) is that of missing a requirement or not completely capturing all the desired aspects of a requirement in line with the findings in [79]. The later a problem is uncovered, then the greater will be the cost of remedying it. This leads to our second issue:

[Requ2]: Incomplete requirements increases risk of rework.
3.2.3 Attributed Safety Requirements

The initial IPDP safety work involves assimilating the contracted customer safety requirements and then performing safety analysis to see if additional hazards apply and to identify failures and behaviour modes that might result in safety issues. The task consists of assessing hazard lists derived using domain knowledge, analysing the issues and problems encountered on similar systems and performing brainstorming sessions to formulate an initial hazard list for the system to be developed.

It has been observed via the LLD that because the detailed models necessary to support a full preliminary safety analysis are not available until relatively late in the early life cycle phases with the existing IPDP, the safety engineering lags the rest of the development and can cause costly re-work when changes are required due to any discovered safety issues. A significant improvement to the safety aspects of IPDP could be effected by moving the safety analysis earlier in the life cycle, without compromising its effectiveness. This results in our third issue:

[LateI3]: Late effective safety analysis increases risk of rework.

Another issue concerns traceability, which is an important aspect of many critical development processes and has a number of forms. Safety standards such as DS 00-56 and guidelines such as DO-178B demand traceability from the top level requirements all the way through to the code that implements them, and require traceability to the evidence (test, code walkthrough etc.) that validates them. A lack of traceability makes it difficult to check that a requirement has been implemented adequately. This identifies another important issue, our fourth, that can be captured as:

[TraceI4]: Traceability incompleteness increases the risk of rework.

3.2.4 The SRR Gateway Review

A System Requirements Review (SRR) is used to validate that all the necessary tasks have been adequately completed and this covers: (a) determining that the system
requirements have been completely and properly identified, (b) reviewing that the
mission requirements definition process has been correctly followed and (c) ensuring
that the system certification and safety needs are appropriately considered from the
outset. The latter includes confirming that a safety plan and safety case are being
developed commensurate with the level of the safety requirements attributed to the
system. The SSR acts as a gateway between the CE phase and the Dem/Val phase.
The programme is only allowed to proceed to the next Dem/Val phase when all the
items listed above are deemed to have been completed to a satisfactory standard.

One major issue that can occur during the SSR (as observed in the LLD) is the
fact that certain tasks are not completed at all because they have been "tailored
out" of the development process. During the initiation of a project, programmes
are allowed to tailor the IPDP to fit in with their particular circumstances. This
can result in tasks being removed that are deemed necessary by the SRR reviewers,
resulting in re-work before the programme is allowed to pass SRR. This can be
considered as part of a broader problem defined as our fifth issue:

[Incom15]: Task incompleteness increases the risk of rework.

3.3 Demonstration/Validation (Dem/Val) Phase

The main purpose of the Dem/Val phase is the development of the system specifica-
tions and it consists of three tasks: (a) develop the system theory of operation,
(b) develop the sub-system theory of operation, and (c) derive the system specifica-
tions. These tasks will now be described and issues identified earlier but also
affecting this Dem/Val phase will be highlighted and any new issues introduced
where appropriate. There are safety analysis activities associated with each of these
tasks.

During Dem/Val the initial requirements are reviewed and where necessary trans-
formed into more detailed requirements. These transformations tend to be informal
and text-based, but are validated through formal peer reviews which check issues concerning soundness, completeness and consistency. The goal is to produce a set of requirements that could be implemented.

3.3.1 System Theory of Operation

This task involves system requirements analysis, identification and analysis of the initial system architecture and the production of various models to support the analysis. The models tend to be informal, based on block diagrams supported by descriptive text that are focussed on satisfying a particular task - thus they only have a limited reasoning capability. Neither are the models particularly well integrated, as each is produced to satisfy a particular need as required. For example, many of the Company's systems have serial links to allow communications between units. These links are modelled by specialist "firmware engineers" (i.e. engineers with extensive experience in implementing communications networks and protocols at the hardware/software interface) to ensure that they have the necessary capacity to support the design and any growth requirements. The analysis and modelling of these links are checked by the project's Software Architect and the Lead System Engineer to ensure they are accurate and complete. However, they are not formally checked by the rest of the team, some of whom have to interact with and make use of these communication links. As noted, the modelling is informal and only the limited reasoning that derives from using the descriptive text is available. In the past this has allowed ambiguity and lack of detail in the descriptions to result in misinterpretations of the design concept, and thus relates to [EnvirI1] defined above. This identifies a need for stronger modelling capabilities, ideally supporting simulation so that the engineers that have to use the links can gain a better understanding of how they operate, their capabilities and their limitations.

The analysis and modelling work culminates in the production of a system theory
of operation document that is also descriptive text. The system theory of operation
document is validated with the customer before embarking on the next set of tasks
which involve more detailed architectural analysis and the development of the sub-
system theory of operation.

A problem observed from the LLD for this and the next task was that of in-
consistent completion of the sub-tasks associated with the task. The amount of
work undertaken to complete a task was found to be variable, and in some cases the
tasks were not completed, with items being poorly addressed or even omitted. In-
vestigations indicated that often the task descriptions were high level and allowed a
wide range of interpretation or engineers thought that other elements of the task had
been covered elsewhere. This is another example of [IncomI5] Task incompleteness,
introduced above.

3.3.2 Sub-System Theory of Operation

The sub-system theory of operation task involves further analysis and modelling and
the development of the solution system architecture. The modelling in this sub-phase
has similar issues to those recorded above. The resulting sub-system theory of oper-
ation document describes the main functional blocks, together with their interfaces
and interactions at a reasonably detailed level such that the following requirements
issues are identified: requirements functionality omitted or not completely covered;
ambiguous or incomplete requirements; requirements inconsistencies and clashes. It
has been observed that there is no support for iteration back to earlier tasks in the
IPDP and the task of deciding where to iterate back to is exacerbated by the parallel
and overlapping nature of some of the tasks. Being able to trace back through the
design is another instance of issue [TraceI4] introduced in section 3.2.3.
3.3.3 System Specifications

Work then develops the specifications and sub-system design descriptions resulting in the Equipment Specifications (ES), the final Interface Requirements Specification (IRS) and the initial allocation of requirements (ASR) to software and/or hardware, including allocation of the safety requirements. These are all textual documents that have to undergo safety analysis as part of the IPDP work, but the LLD has recorded issues with the effectiveness of some of these analyses – which relates to issue [LateI3].

The last part of this System Specifications task and before entry into the SDR, each specification requirement has a validation method defined for it, but there is no way of confirming that overall “the right system is being produced”. That is, without the ability to simulate sets of requirements on a broader scale it is difficult to be confident that the system has the desired behaviour. In fact these issues could not be checked formally until the implementation phase. This increases the risk that the right system is not being produced and is part of issue [RequI2].

3.3.4 Safety Analysis Discussion

As noted above, the Dem/VAL phase includes a number of safety analysis tasks. The abstract and textual descriptive nature of the source information available tends to motivate the use of FFA, which is the most appropriate form of analysis to use with the current IPDP because design instability and lack of design information in a suitable form means that the cost of running a HAZOPS is not justified at this point. Unfortunately, as noted by McDermid [90], FFA relies heavily on human skill, is judgemental and only identifies about 80% of the safety issues - information recorded in the LLD supports this. The initial Dem/Val FFA work for the DC system reported in Appendix A.3 is an example of this problem (related to issue [LateI3]). The need for a sufficiently strong CRC was not identified by the FFA,
even though this information was part of the DS environment information – as shown by the later, specific, serial link analysis which did identify the information and thus highlighted the issue. Thus an adequate safety analysis requires that the system environment is sufficiently understood (part of [EnvirI1]).

As discussed in section 2.2.2 an effective safety analysis requires an appropriate model and inspection of the overall IPDP process indicates that a suitable model to support a HAZOPS could be formed from the architectural information that is available, and from structural (e.g. interface and timing) information that could be derived with some re-ordering of the tasks. For example one of the IPDP safety tasks in this phase requires that a safety analysis is applied to the combination of the sub-system theory of operation and the system block diagram (section 3.3.2). Currently FFA is used, but inspection of the information available prior to SDR indicates that the sub-system theory of operation and the block diagram could be used as the basis for a HAZOPS model during Dem/Val as long as: the architectural analysis was used as the basis of the analysis model, extra information was collated concerning critical timings and sufficient knowledge concerning the interface to the environment (including potential adverse impact on this environment) could be collected. Currently HAZOPS is not used until the later EMD phase, and the ability to move it earlier in the life cycle is a mitigation for issue [LateI3]. This potential improvement to the IPDP safety analysis process is considered further in Chapter 5.

3.3.5 SDR Gateway Review

When Dem/Val is complete a System Design Review (SDR) is held to review the maturity of and assess the risks involved with the allocated requirements and specifications. The SDR also confirms that the safety and certification issues are adequately addressed, i.e. that all requirements have a reasonable validation method assigned and that all appropriate safety analysis has been undertaken. It has been
observed that the existing IPDP approach forms a collection of useful, but disparate, models. Each model performs an important task, but these models are neither well integrated nor easy to validate.

The SDR inspects the artefacts produced during the Dem/Val phase, considers their quality and validates that they are appropriate and fit for purpose before allowing the programme to proceed to the EMD phase. If any of these artefacts are incomplete then rework must be done. However, it has been observed from the LLD that projects that have incomplete validation criteria applied to the requirements encounter significant problems later in the development life cycle. This indicated the need for improved measures to ensure that the validation criteria assigned to each requirement is complete. Therefore another important issue, our sixth, can be captured as:

[ValidI6]: Validation incompleteness increases the risk of rework.

3.4 EMD – Preliminary Design Phase

The Preliminary Design sub-phase is the first set of activities in the EMD phase, and is the only phase of EMD discussed in this document. It uses the documents emanating from the SDR and starts with a detailed analysis of the customer requirements and their allocations to the software, the hardware or both. The architecture is developed and it also produces high level design descriptions to feed into the following more detailed design phases (not considered here). As part of this process the requirements are analysed in more detail and developed to support the evolving design. A variety of safety analysis tasks are conducted during the Preliminary Design phase.
3.4.1 Requirements Allocation and Architecture Design

Requirements are allocated based on hardware/software trade-off activities and all designs, analyses and evaluations are documented and all applicable specifications are updated before proceeding with the next tasks. The design task then splits into its software, hardware and system components, which are handled by the appropriate development teams.

The architectural design refines and develops the system architecture produced during Dem/Val, to add more detailed functional and interface descriptions. This process also identifies derived requirements reflecting the design decisions that are made to support the architectural development.

It has been observed from the LLD that the detailing of the requirements allocations and transformations do not always produce requirements that are feasible, nor are they necessarily sound, consistent or complete. Peer reviews are conducted and these resolve many issues, but some problems can remain – this relates directly to [Req12].

3.4.2 Preliminary Design Tasks

The preliminary design tasks are Preliminary System Design, Preliminary Software Design, and Preliminary Hardware Design. They all involve analysis of the requirements allocated to their discipline in conjunction with a more detailed architectural design (system, software and hardware). For example, the purpose of the software analysis and detailed architectural design activities are to define how the software will realise the requirements on it, and to define a stable software architecture based on the Object Oriented principles [13, 56] used in the development. All designs, analyses and evaluations are documented and all applicable specifications are updated before proceeding with the design. A similar process is followed by the other disciplines.
Detailed design is not allowed to be started until after successful completion of the PDR checkpoint gateway review. Failure to observe this rule on some previous projects (as recorded in the LLD) has resulted in expensive rework – the causes being instances of our six issues identified above.

The hardware development follows a single pass strategy, but it is typical to run the software development over a number of iterations. The first iteration de-risks any software architecture concerns by providing a prototype whose behaviour can be evaluated, and if successful this iteration is used as the basis for the subsequent iterations. Otherwise a viable alternative is produced, informed by the problems identified with the original architecture (system and/or software). This has cost and schedule implications for the development as IPDP does not easily support an iterative loop structure (it has been specifically updated to “hard code in” the software iterations), any identification of problems causes a dislocation in the schedule which is scrutinised by senior management - hence there is pressure to avoid iteration and adopt a “patch and proceed” mentality. The ability to analyse the architecture earlier in the development cycle and the ability to manage iteration have been identified as two significant enhancements to the capability of the IPDP. This demonstrates the need for direct support for iteration, which is a form of traceability issue and thus is part of [TraceI4].

At this point in IPDP a higher integrity process is used for system developments which have functional safety requirements that involves:

- the use of special safety architectures (system, software and hardware) which include protective and defensive features;
- the specifications being written in the Z formal method [116] to define the safety behaviour;
- the use of proof to show that the implemented code satisfies the Z specification.
3.4.3 EMD Preliminary Design Safety Analysis

The EMD Preliminary Design phase includes eight safety analysis tasks including reviews to cover health and safety and the legislative aspects. For developments with functional safety requirements a modified form of HAZOPS is applied to the developed architecture, using the allocated requirements and detailed descriptions of the context derived from the earlier tasks. The analysis begins around PDR and yields good results (no issues recorded in the LLD), albeit rather later in the process than desired – hence it is related to [LateI3].

3.4.4 PDR Gateway Review

The Preliminary Design phase is exited after successful completion of a Preliminary Design Review (PDR). The role of the PDR is to assess that the maturity of the design is appropriate and to approve initiation of the detailed design. It involves formally authenticating all the Development Specifications and releasing them as approved. Further goals are to evaluate the technical adequacy and risk management of the selected design approach, and to confirm that the certification and safety aspects are apposite.

The successful completion of the PDR means that an appropriate design specification, $S$, has been produced, and inspection of the LLD shows that the majority of projects achieve this goal. Therefore a necessary property of any approach that is to be used in conjunction with IPDP is that it should be at least as good as the current IPDP at deriving a design specification. This is captured as the necessary property (NecessaryP):

[NecessaryP]: The approach used must be capable of deriving the design specification.

Any approach which does not satisfy [NecessaryP] cannot be considered for use with IPDP.
A factor influencing why the safety team lags behind the other disciplines (refer to section 3.2.3) is the need to produce a specific safety model to support the safety analysis work and the task of keeping it up to date. If the safety analysis used the same model as the other disciplines then this would be much more efficient and less error prone (no need to validate the safety model). Therefore an advantageous property of an approach can be stated as follows:

\[[\text{SameA1}]: \text{The safety analysis uses the same model as the rest of the development.}\]

For developments with functional safety requirements IPDP follows an augmented process that includes the use of formal specification and proof techniques, therefore it is highly desirable that any approach used should be capable of supporting formal development processes. This is captured as the second advantageous property:

\[[\text{FormalA2}]: \text{The approach used should support formal development processes.}\]

### 3.4.5 Summary of Issues and Properties

In general the Company has found IPDP to be an excellent mechanism for organising and running projects. It promotes completeness and consistency across the projects and has reduced variation significantly. The experience gained from running many projects through IPDP has resulted in improvements to the process to support how the Company organises its work (e.g., inclusion of an iterative software process) and this improvement is an ongoing process. However, as discussed in the previous sections, some significant issues have been observed which the following text summarises.
It is worth noting that these issues and properties apply to safety development processes other than IPDP. That is, the issues and properties identified in the preceding sections are important for any safety process as well as for the IPDP used for safety development and the identified issues are:

1. [EnvirI1]: Incomplete understanding of the system context increases risk of rework.
2. [RequI2]: Incomplete requirements increases risk of rework.
3. [LateI3]: Late effective safety analysis increases risk of rework.
4. [TraceI4]: Traceability incompleteness increases risk of rework.
5. [IncomI5]: Task incompleteness increases risk of rework.
6. [ValidI6]: Validation incompleteness increases risk of rework.

The identified properties are:

1. [NecessaryP]: The approach used must be capable of deriving design specification $S$.
2. [SameAl]: The safety analysis uses the same model as the rest of the development.
3. [FormalA2]: The approach used should support formal development processes.

Any approach introduced to improve the capabilities of an existing process, IPDP in this case, must integrate into this existing process. It must address at least some of the issues identified with the existing process and it must be straightforward to implement, as undue complexity could result in resistance and it not being used effectively. This need for good integration can be added to the list of advantageous properties as follows:
In the remainder of this thesis we show how POSE can be used to address these six identified issues whilst satisfying the properties identified so far (i.e., the ten properties from section 2.5 and the four identified in this chapter). Specifically, Chapter 4 introduces POSE in its basic, “vanilla” form and evaluates its capabilities in dealing with the identified issues and properties. The chapters that follow develop POSE to address any outstanding issues and properties.
Chapter 4

Supporting the Process Using POSE

The aim of this chapter is to investigate whether POSE could be successfully used within the IPDP (addressing property [IntegA3] of Chapter 3), and to which extent in its "vanilla" formulation, as defined by [39, 40, 41], it would be able to address the properties and issues summarised in section 2.5 and section 3.4.5.

Throughout the chapter we make use of a case study, the Decoy Controller (DC), to introduce POSE and its features, illustrate its application, and evaluate its potential for real-time embedded avionics safety systems. The DC case study refers to a real development problem at the Company, which was originally addressed using the IPDP. It was also used by the author in [87] to introduce the capabilities of POSE in the context of embedded avionics applications. Here it is investigated in more detail in the context of working within the IPDP.

4.1 Introduction to Problem Solving with POSE

Our first task is to introduce the Decoy Controller DC case study that will form the basis for the rest of this chapter and will also be used in the initial part of Chapter 5.
4.1.1 Decoy Controller Case Study Description

The Decoy Controller DC system's main components are now introduced (a more complete representation of the case study and its use of IPDP is given in Appendix A). The DC is part of the defensive aids suite (DAS) on an aircraft and its block diagram is shown in Figure 4.1. The DAS is controlled by a Defence System (DS) LRU (Line Replaceable Unit) which sends control and information messages to the DC over a serial link. The DC controls the selection and release of flares from the Dispenser Unit (DU) based on control inputs it receives from the DS, the pilot and the aircraft status. The latter indicates if the aircraft is on the ground or in the air.

![Decoy Controller Block Diagram](image)

Figure 4.1: Decoy Controller (DC) Block Diagram

The IPDP CE phase safety work was conducted on the conceptual model formed from the system block diagram (see Figure 4.1), the system description (derived from the work completed to date) and the system requirement RDC - as described in Appendix A.2. The requirement RDC was the original requirement as used on the project, it does not reflect current good practice based on using the DOORS tool to capture the requirements and their traceability [118]. In particular it does not define only one requirement at a time and includes multiple instances of using conjunctions that make multiple requirements in a single statement. The reason why we use the "original" requirement was to show that POSE could be used successfully with requirements that might be encountered on actual projects and with requirements
that were not doctored to make then easier to use. A re-worked DC case study based on using [118] to re-structure the requirements into a good practice form is shown in Appendix H.

The requirements were further refined and detailed by tasks completed during the Dem/Val phase (refer to section 3.3) to form Rdc as detailed in Appendix A.3. The analysis work for the Dem/Val phase, also recorded in Appendix A.3, identified a number of safety issues and process problems when using the task descriptions in the existing IPDP process. For example, in the DAS the DC has to communicate with the Defence System (DS) over a serial link. The FFA safety analysis identified that a high integrity algorithm should be used to obtain the required integrity for the message passing function. Unfortunately, this was misinterpreted as the standard parity and message block system used for most of the Company's serial link implementations. The specific requirements that demanded the use of a Cyclic Redundancy Check (CRC) algorithm were not assimilated and the problem was not discovered until a specific serial link safety analysis identified the integrity shortfall. As in this case, any such issues are identified during the system analysis and integration phases, but these are well into the development life cycle where changes are costly and have a negative impact on the schedule. Therefore, as noted above, there is an identified improvement to the IPDP in trying to capture such issues earlier in the life cycle – this is issue [LateI3] defined in Chapter 3.

The EMD Preliminary Design phase work of Appendix A.4 shows how the final system architecture for the DC system was derived. It also notes that this system architecture was chosen because it was based on an existing prototype that was known to be capable of satisfying the functional requirements, and it is typical of industrial safety design strategies that attempt to minimise the number and extent of the safety related functions by localising them to simple, distinct blocks.

In what follows we revisit the DC development problem detailed in Appendix A, but this time applying POSE as appropriate to provide specific support to the
relevant IPDP tasks. The case study is cut down only in the sense that some detail
has been removed for brevity: it retains all essential complexity.

At this point it is useful to recall briefly all the phases involved in the process of
eliciting the requirements. As part of the successful contracting process the mechan-
ical outline, approximate weight and power envelope of the system was established.
Further, the initial high level functional requirements, RA - RD, were agreed as
defined in section A.2. Subsequent communications with the customer were used to
clarify the requirements and properties of the system environment and resulted in
agreement that RS defined the safety requirements attributed to the system from
the aircraft and system level hazard analyses. All these requirements formed the
basis under which the remainder of the system was developed.

4.1.2 Software Problems in POSE

Hall, Rapanotti and Jackson [39, 40, 41] introduce a software problem as having
three elements: a real-world context, W, a requirement, R, and a solution, S, which
are related by the entailment W, S \models R.

The problem context is a collection of domains (W = D₁, ..., Dₙ) described in
terms of their known, or indicative, properties, which interact through their sharing
of phenomena (i.e, events, commands, states, etc.. [53]). More precisely, a domain
is a set of related phenomena that are usefully treated as a behavioural unit for
some purpose. A domain can be a unique, physical entity, or it can be an aggregate
of physical entities that are combined to achieve a specific effect – the selection will
depend on the context of the problem being solved.

In POSE all problem solving starts from the null problem, the problem of which
we know nothing other than it exists [41]:

\[
P_{null} : \quad W : \text{null}, S : \text{null} \models R : \text{null}
\]
null is used as the description for $W$, $R$ and $S$ to indicate that nothing is known about them: null has less information than any description that can be written in any language chosen for descriptions.

4.1.2.1 Domain Context in POSE

The environment context is described in terms of domains. A domain $D(p) = N : E$ has name $(N)$ and description $(E)$, the description indicating the possible values and/or states that the domain's phenomena (in $p \cup c \cup o$) can occupy, how those values and states change over time, how phenomena occur, and when. Of the phenomena: $c$ are those controlled by $D$, i.e., visible to, and shareable by, other domains but whose occurrence is controlled by $D$; $o$ are those observed by $D$, i.e., made visible by other domains, whose occurrence is observed by $D$; $p$ are those unshared by $D$, i.e., shareable by no other domain. The $p$ are often termed internal phenomena and can be omitted if they have no impact on the development.

As an example of the first step in using POSE consider the DC case study. This first step involves collecting information about the existing environment which the proposed system is to operate in. Initially this information will just be an identification of the domains involved, but this will be enriched by further investigation and analysis which will ensure a detailed understanding of the environment is amassed that allows the appropriate domains to be identified, together with a knowledge of the properties that they have and an appreciation of how they interface to each other. It maps well with the system environment and initial requirements tasks in the CE phase (see section 3.2). The approach is in line with the "understand the environment before the new system is applied ideas" introduced in section 2.4 which is an important aspect of the problem oriented methods and thus supports property Context from Table 2.3. The domains in the DC case study are drawn from the entities represented in Figure 4.1 and comprise of the pilot Pil\textit{ot}, Defence System DS, Dispenser Unit DU, Safety Pin status SP, the Aircraft Status AS and
the Decoy Controller DC domains. Knowledge about these domains is increased by investigating their respective interface phenomena, the results of this work are shown in Table 4.1 on page 82.

4.1.2.2 Requirements in POSE

A problem's requirement states what is required of the problem solution. Like a domain, a requirement is a named description with phenomena, $R^{cons}_{refs} = N : E$. A requirement description should always be interpreted in the optative mood, i.e., as expressing a wish. As to the requirement's phenomena: cons are those constrained by $R$, i.e., whose occurrence is constrained by the requirement, and whose occurrence the solution affects in providing a solution; refs are those referenced by $R$, i.e., whose occurrence is referred to but not constrained by the requirement. Knowledge about the requirements is assimilated and organised in terms of the identified domain structure and interfaces. This means the requirements are reviewed and articulated into an appropriate form such that they are written in terms of the problem space as a customer would understand them, i.e. in terms of the environment domains. Care is taken to ensure these requirements avoid any implementation bias, and this supports property Avoid Bias from Table 2.3.

As an example, in the DC case study the various information sources - the customer requirements, customer meeting minutes and email communications - were reviewed in-depth to support this work and this allowed the initial problem to be developed (supporting properties Model Reality and Validation from Table 2.3) as follows. The requirements were refined and detailed from $RDC$ to $Rdc = Ra \land Rb \land Rc \land Rd \land RS$ as defined in section A.3 and the requirements represented by $Rdc$ are repeated below:

**Ra** The DS shall command which flare is selected using a field in its con message issued to the DC. The DC shall obtain the selected flare information from this
field in the con message, and use it in its sel message to the DU to control the flare selection in the DU.

**Rb** The DS shall command the DC to issue a fire command in its con message. This shall be the only way in which a flare can be released.

**Rc** The DC shall cause a flare to be released by issuing a fire command to the DU, which will fire the selected flare.

**Rd** The DC shall only issue a fire command if its interlocks are satisfied, i.e. aircraft is in air (AS = on), SP safety pin has been removed (SP = off) and Pilot has issued an allow a release command (Pilot = on).

**RS** The DC shall mitigate H1 and H2 (Target: safety critical 10^{-7} fpfh); where H1 and H2 are defined in Appendix A.2.

### 4.1.2.3 Solution in POSE

From [39], a software solution is a domain, \( S(p)_o = N : E, \) that is intended to solve a problem, i.e., when introduced into the problem context will satisfy the problem’s requirement. The possible descriptions of a solution range over many forms, from high-level specification through to program code. As a domain, a solution has controlled, observed and unshared phenomena; the union of the controlled and observed sets is termed the specification phenomena for the problem. In the initial description of the case study problem the solution domain is DC.

A problem’s elements come together in POSE in a problem sequent[39]:

\[
P : D_1(p_1)_{o_1}, \ldots, D_n(p_n)_{o_n}, S(p)_o \vdash R_{\text{ref}}^{\text{cons}}
\]

where the name \( P \) is optional. By convention (e.g. see [41]), the problem’s solution domain, \( S, \) is always positioned immediately to the left of the \( \vdash \). Note that the
descriptions of a problem's elements may be in any language, different elements
being described in different languages, should that be appropriate [39].

As an example of a Software Problem return again to the DC case study. Prob-
lem solving starts with the null problem ([41], page 230), $P_{null}$, and the target of
the first phase of applying POSE is to form the initial problem, $P_{initial}$, based on
Figure 4.1. Eventually this will have the form:

$$P_{initial} : DS(\text{con})^{con}, DU(\text{fire, sel})^{fire, sel}, SP(\text{out})^{out},$$
$$AS(\text{air})^{air}, P(\text{ok})^{ok}, DC^{fire, sel}_{\text{ok, air, con, out}} \vdash Rd^{\text{fire, sel}}_{\text{con, out, air, ok}}$$

However, before this can be derived we have to introduce a number of POSE trans-
formations.

4.1.3 POSE Problem Transformations

Problem transformations capture discrete steps in the problem solving process [35].
Many classes of transformations are recognised in POSE, reflecting a variety of
software engineering practices reported in the literature or observed elsewhere [39].
Problem transformations relate a problem and a justification to (a set of) problems.
Problem transformations conform to the following general pattern. Suppose we have
problems $W, S \vdash R$, $W_i, S_i \vdash R_i$, $i = 1, \ldots, n$, $(n \geq 0)$ and justification $J$, then we
will write:

$$W_i, S_i \vdash R_i \ldots W_n, S_n \vdash R_n \quad \text{(NAME)}$$

$$W, S \vdash R \quad \langle J \rangle$$

to mean that, derived from an application of the NAME problem transformation
schema (discussed below):
$S$ is a solution of $W, S \vdash R$ with adequacy argument $(CA_1 \land \ldots \land CA_n) \land J$
whenever $S_1, \ldots, S_n$ are solutions of $W_1, S_1 \vdash R_1, \ldots, W_n, S_n \vdash R_n$, with adequacy arguments $CA_1, \ldots, CA_n$, respectively.

This transformation allows $W, S \vdash R$ to be replaced with $W_1, S_1 \vdash R_1, \ldots, W_n, S_n \vdash R_n$ with the justification given by $J$. The idea being that each $W_i, S_i \vdash R_i$ from $W_1, S_1 \vdash R_1, \ldots, W_n, S_n \vdash R_n$ is easier to solve than the original $W, S \vdash R$. This notion of moving from difficult problems to easier to solve sub-problems is an important aspect of the POSE approach, and supports the property Simplification from Table 2.3. POSE problem transformations with appropriate examples are explained in detail in [39].

Therefore, software engineering design under POSE proceeds in a step-wise manner: the initial “null” problem forms the root of a development tree with transformations applied to extend the tree upwards towards its leaves [35]. Branches are completed by problem transformations that leave the empty set of premise problems. Appropriate transformations applied to the null problem transform it to represent an initial form of the software problem to be solved - the initial POSE requirement model. This involves instantiating knowledge about the environment domain context (to address [Envir11]), the requirement (to address [Requ12]) and to introduce the solution domain. The environment domain context information is introduced using the CONTEXT INTERPRETATION transformation ([41], page 228) and the acquired requirements knowledge is introduced using the REQUIREMENTS INTERPRETATION transformation ([41], page 233). The software solution domain is introduced using the SOLUTION INTERPRETATION transformation ([41], page 234), which makes use of the Architectural Structure $AStruct[\ldots]$ ([41], page 236) to introduce known solution components and the solution components to be designed – the $AStruct[\ldots]$ is considered in more detail in section 4.1.3.3 below.
**Table 4.1: Phenomena of the DC Problem**

<table>
<thead>
<tr>
<th>Phenomenon</th>
<th>Designation</th>
</tr>
</thead>
<tbody>
<tr>
<td>fire</td>
<td>Command to release the selected flare</td>
</tr>
<tr>
<td>sel</td>
<td>Indicates which flare type should be selected</td>
</tr>
<tr>
<td>out</td>
<td>Pin status; ( out = yes ) indicates pin has been removed</td>
</tr>
<tr>
<td>con</td>
<td>Contains command to fire and selected flare type</td>
</tr>
<tr>
<td>air</td>
<td>Aircraft status; ( air = yes ) indicates aircraft is in the air</td>
</tr>
<tr>
<td>ok</td>
<td>Pilot intention; ( ok = yes ) indicates allow release</td>
</tr>
</tbody>
</table>

### 4.1.3.1 Introducing Context in POSE

As an example of the use of introducing the context into the software problem return to the DC case study and the information in section 4.1.2.1. The initial environment context work includes the description of \( Sys \) on page 228, which provides an overview that introduces the individual domains that comprise the complete system of interest. These domains are \( Pilot \), \( AS \), \( SP \), \( DS \) and \( DU \). This basic information allows the software problem description to be enhanced from \( P_{null} \) about which nothing is known to \( P_{doms} \) where the domains involved are identified using the CONTEXT INTERPRETATION transformation as follows:

\[
P_{doms} : W: \{P : \text{null}, AS : \text{null}, SP : \text{null}, DS : \text{null}, DU : \text{null}\}, S : \text{null} \vdash R : \text{null} \quad [\text{CI}]
\]

\[
P_{null} : W : \text{null}, S : \text{null} \vdash R : \text{null} \quad (\text{JC})
\]

where CI is CONTEXT INTERPRETATION and the justification JC is that context analysis has identified the listed domains as being relevant to the problem.

Each of these context domains is then investigated in detail to understand its behaviour, note any concerns about its operation and identify its phenomena (supporting the IPDP theory of operation tasks). The descriptions \( Pilot \) through \( DU \) are those listed on page 228, and those are the relevant parts of the domain knowledge gathered from the information sources.

The phenomena associated with these domains are defined in Table 4.1. The
fire and sel phenomena are inputs to the DU and the representation of the DU in POSE is given by $DU_{fire,sel}$. The SP provides the status of the pin out as an output and in POSE this is represented as $SP^{out}$. This means that the SP term in the requirement $R_d$ of $SP = off$ maps to the phenomena $out = yes$, and $SP = on$ maps to $out = no$. Similarly the AS provides the in air status as an output using $air$ ($air = yes$ maps to $AS = on$ in $R_d$), and the Pilot sends the switch selection using $ok$ ($ok = yes$ maps to $Pilot = on$ in $R_d$). In POSE these are respectively represented as $AS^{air}$ and $Pilot^{ok}$. The con command message is an output from the $DS - con$ is also used in $Rdc$ so no mapping is required. In POSE this is represented as $DS^{con}$. The mappings defined above show that the model is grounded in reality (supporting property Model Reality from Table 2.3).

This increased knowledge is then introduced into the software problem using a series of CONTEXT INTERPRETATION transformations - as described in [41] pages 232 to 233 - to form the software problem $P_{Dom}$. In this software problem, $P_{Dom}$, and those that follow we will often omit the denotations “$W:$”, “$S:$” and “$R:$” whenever they can be inferred by context – in $P_{Dom}$ the “$W:$” is omitted.

$$P_{Dom} : DU_{fire,sel}, SP^{out}, DS^{con}, AS^{air}, Pilot^{ok}, S : null \vdash R : null$$

The collective justification for these CONTEXT INTERPRETATION transformations ($J_a$) is that the analysis of the information sources identified that the environment consisted of a $DS$ defence system that can send command messages to the $DC$ which can then control the release of flares from the $DU$ taking due account of the inputs received from the $Pilot$, $AS$ and $SP$ domains. The information sources were then peer reviewed to confirm and validate that these were the only significant environment domains providing evidence for [EnvirI1] and property Context from Table 2.3.
4.1.3.2 Introducing Requirements in POSE

Next the requirements are introduced into the problem model using the REQUIREMENTS INTERPRETATION transformation ([41], page 233). As detailed in Appendix A.2, the initial customer requirements were represented by requirement \textit{RDC} and these requirements were refined and detailed as part of the IPDP CE and Dem/Val phase work to produce the final requirement \textit{Rdc}, which is listed in full above in section 4.1.2.2. In POSE this refining and detailing is achieved using the REQUIREMENTS INTERPRETATION transformation. An example will illustrate the process followed. One of the original requirements from \textit{RDC} concerned the messages sent by the \textit{DS} and had the form:

\textbf{RA} The \textit{DS} shall command which flare is selected for release by using a field in the \textit{con} message it transmits.

This is refined and detailed by the analysis of the initial system architecture shown in Figure 4.1, conducted as part of the tasks in the Dem/Val phase, to form the more detailed requirement:

\textbf{Ra} The \textit{DS} shall command which flare is selected using a field in its \textit{con} message issued to the \textit{DC}. The \textit{DC} shall obtain the selected flare information from this field in the \textit{con} message, and use it in its \textit{sel} message to the \textit{DU} to control the flare selection in the \textit{DU}.

Similar detailing was applied to the other requirements in \textit{RDC} to form \textit{Rdc}, and these can be introduced into the problem using a series of REQUIREMENTS INTERPRETATION transformations. That is, the step from \textit{P_{Dom}} into \textit{P_{Dom&R}} which introduces the requirement \textit{Rdc} into the problem is actually a sequence of REQUIREMENTS INTERPRETATION transformations – a similar arrangement is detailed in [41] for the refinement and detailing of the Package Router requirements.
where the analysis included identifying the requirements phenomena \( \textit{cons} \) and \( \textit{ref} \), which for the \( \textit{DC} \) case study are defined by the following:

\[
\begin{align*}
\text{cons} &= \{ \text{fire}, \text{sel} \} \\
\text{ref} &= \{ \text{out}, \text{air}, \text{ok}, \text{con} \}.
\end{align*}
\]

The justification for this \textit{Requirement Interpretation} transformation \( J_b \) is that the \( Rdc = Ra \land Rb \land Rc \land Rd \land RS \) were validated against the information sources and found to be adequate representations of the intended behaviour of the system and were confirmed as apposite by the customer, providing evidence to support \textit{[RequI2]} and property \textit{Validate} from Table 2.3.

### 4.1.3.3 Introducing Solutions in \textit{POSE}

The Architectural Structure, \( A\text{Struct} \) [41], is used to initially introduce the solution domain, but it is also used to add structure to this solution domain, through an application of \textit{Solution Interpretation}. That is, it can be used to introduce different solution architectures into the \textit{POSE} requirements model. An \( A\text{Struct} \) combines, in a given topology, a number of known solution components\(^1\) (the \( C_i \) below) with solution components yet to be found (the \( S_j \) below). Its general form is:

\[
A\text{StructName}[C_1, \ldots, C_m](S_1, \ldots, S_n)
\]

\(^1\)There are also constraints on the phenomena sets, which we omit here for brevity, refer to \[39\] for the full definition.
with $AStructName$ the $AStruct$ name. Once the solution is interpreted by providing and justifying an $AStruct$, SOLUTION EXPANSION generates premise problems by moving the already known components $C_i$ to the environment—expanding the problem context—whilst simultaneously refocussing the problem to be that of finding the solution components $S_j$ that remain to be designed. The requirement and context of the original problem is propagated to all sub-problems.

A particular case, which is relevant to the case studies, is when there is only one component to be found, that is, the $AStruct$ has the following form:

$$AStructName[C_1, ..., C_m](S)$$

In this case expansion only generates one premise problem as follows:

$$\frac{W, C_1, ..., C_m, S : \text{null} \vdash R}{W, S : AStructName[C_1, ..., C_m](S) \vdash R} \text{[SOLUTION EXPANSION]}$$

An example of an $AStruct$ is used to introduce the solution domain, $DC$, into the software problem as follows. At this point we know that $DC$ is the domain to be designed and there are no known components. The description of the $DC$ is listed in the IPDP:Dem/Val Phase subsection of section A.3, and analysis identifies its interrelationships and the phenomena it shares with the existing domains, such that it can be written as $DC_{\text{fire,sel,ok,ar,con,our}}$. The specification to be found of the $DC$ is introduced through SOLUTION INTERPRETATION using an $AStruct$ ([41], page 236) of the form:

$$S : DCS[\{(DC)_{\text{fire,sel,ok,ar,con,our}}\}$$

The justification for this solution interpretation step ($J_c$) is that it just introduces the solution domain, $DC$, into the software problem. Further, similar system architectures have been used successfully on other aircraft recording the fact that the overall architecture represented by $P_{DomRS}$ has a good track record. The SOLUTION INTERPRETATION transformation ([41], page 234) is applied to transform the
software problem from $P_{Dom&R}$ into $P_{DomRS}$.

\[ P_{DomRS} : \quad DS(\text{con})^{\text{con}}, \ DU(\text{fire}, \text{sel})^{\text{fire}, \text{sel}}, \ SP(\text{out})^{\text{out}}, \]
\[ \quad AS(\text{air})^{\text{air}}, \ P(\text{ok})^{\text{ok}}, \ S : DCS[]^{\text{fire}, \text{sel}}_{\text{ok}, \text{air}, \text{con}, \text{out}} \vdash Rd_{\text{con}, \text{out}, \text{air}, \text{ok}} \]

The next step is to expand $S : DCS[]^{\text{fire}, \text{sel}}_{\text{ok}, \text{air}, \text{con}, \text{out}}$ using SOLUTION EXPANSION to transform the problem from $P_{DomRS}$ into $P_{Initial}$ as follows:

\[ P_{Initial} : \quad DS(\text{con})^{\text{con}}, \ DU(\text{fire}, \text{sel})^{\text{fire}, \text{sel}}, \ SP(\text{out})^{\text{out}}, \]
\[ \quad AS(\text{air})^{\text{air}}, \ P(\text{ok})^{\text{ok}}, \ DC^{\text{fire}, \text{sel}}_{\text{ok}, \text{air}, \text{con}, \text{out}} \vdash Rd_{\text{con}, \text{out}, \text{air}, \text{ok}} \]

Inspection of the process so far shows that the problem derivation is problem oriented and does not involve the introduction of any detailed structures from the solution space. This avoids solution bias issues, providing support for property Avoid Bias from Table 2.3.

4.1.4 Problem Solving Steps

4.1.4.1 Problem Transformation Schema and Templates

The general form of a POSE problem transformation schema was introduced at the beginning of section 4.1.3, and an example of CONTEXT INTERPRETATION presented in section 4.1.3.1. The REQUIREMENTS INTERPRETATION and SOLUTION INTERPRETATION problem transformation schema have a similar form to that of the CONTEXT INTERPRETATION schema. The justification associated with each
problem transformation schema can vary in strength from a vague notion through to an extremely strong and compelling linkage [39, 40]. In general the latter is preferred, but is not essential – it depends on the context, e.g. formal proof might be required for safety critical developments, whilst weaker evidence will be sufficient for less critical ones.

Each transformation has associated with it a number of elements that are an important part of its structure and the transformation must be viewed in conjunction with these elements. For example, some of the transformations in [41] include Concerns and/or Phenomena descriptions as well as the justification – it would be incorrect to present just the transformation part without these elements. We will now present a template structure that allows the transformation and its elements to be conveniently collected into a single unit, with the additional advantage that it separates them from the narrative (following our work in [35]). Suppose we wish to transform the problem \(P(= W, S \vdash R)\) under the NAME transformation schema, then we will write [35, 41]:

```
Application of NAME to problem P

JUSTIFICATION J: describing the named justification (J) for the application of transformation NAME to P. The name can be used elsewhere in the development to refer to this justification. The body of the justification can have many components—prose, formal descriptions, figures, for instance—and any or all elements of the following structure may be present:

INCLUDES: identifying any relationship between this justification and others in the development such as those that occurred from an earlier step, that was subsequently discovered to be inadequate and so backtracked from. The inadequacy can also be described here.

CONCERNS: A collection of standard concerns associated with each transformation
```
schema. Each concern is discharged by argument and evidence supporting a claim of the following form:

**CLAIM:** Claim statement

**ARGUMENT & EVIDENCE:** The reason to believe the claim, or the reason it does not hold.

**PHENOMENA:** Should the schema introduce phenomena, or need to detail their sharing, the details can be included here.

Note that this transformation template construction has used concepts from previous work including “Concerns” from Problem Frames [53] and the use of “Claims, Argument, Evidence” ideas in a similar way to Adelard's ASCE tool [12].

4.1.4.2 Problem Transformation Steps

The individual POSE transformations operate at a detailed level and a number have to be combined in sequence to achieve a useful step in the development process. For example, the formation of $P_{initial}$ in section 4.1.3.3 involved a series of interpretation and expansion transformations. Inspection of the use of POSE in the literature [41, 87, 86, 85, 88] indicates that this formation of an initial software problem is a standard practice and it is a useful extension of the basic POSE approach to capture this sequence, and others like it, as a distinct entity. In this work the collection of a series of POSE problem transformations into a useful step in the development process will be called a Problem Transformation Step and in accordance with the original introduction of the template structure in [35] we will use a template structure to capture each problem transformation step.
4.2 POSE Support for IPDP

The aim of this section is to show how the POSE transformations can assist in supporting the IPDP safety process, although the concepts can equally be applied to other similar safety development processes, by ascertaining to what extent they can address the properties and issues identified in section 2.5 and section 3.4.5, using the ideas and notation introduced in section 4.1.3.

At this point in the case study the context and requirement have been established as part of the IPDP CE phase work, the requirement developed, and the AStruct has been used to establish the initial system architecture (early part of IPDP Dem/Val). Therefore the transformation sequence involved in forming the initial software problem, $P_{Initial}$, can be summarised by the following POSE transformation sequence, where $P_{Initial}$ is the top line of the sequence.

Substituting in for $cons$ and $ref$ (see page 85) allows $P_{Initial}$ to be re-written as:

$$P_{Initial} : DS(\text{con})^{con}, DU(\text{fire}, \text{sel})^{fire}, SP(\text{out})^{out}, AS(\text{air})^{air}, P(\text{ok})^{ok}, DC^{fire, \text{sel}}_{ok, \text{air}, \text{con}, \text{out}} \vdash Rd_{cons}$$


This problem, $P_{Initial}$, can also be represented as an alternative view using the PF problem diagram as shown in Figure 4.2. The model represented by $P_{Initial}$ and
Figure 4.2 corresponds to the output of the System and Sub-System Theory of Operation tasks in the IPDP Dem/Val phase (refer to section 3.3 and Appendix A.3).

The series of transformations followed in developing \( P_{\text{Initial}} \) from \( P_{\text{nul}} \) consisted of gaining knowledge and understanding of the environment context, the requirements, the system architecture and how they all interact. This sequence covers a number of the IPDP tasks in the CE and Dem/Val phases as discussed above, and is typical of those steps required in the initial phases of all developments as discussed in section 4.1.4.2. Therefore, these POSE transformations can be combined into the **PS1 Initial Problem** problem transformation step represented by the structure shown below.

---

**PS1: Initial Problem application to transform problem \( P_{\text{nul}} \) into \( P_{\text{Initial}} \)**

**JUSTIFICATION \( J_1 \):** The identified requirement, domains and their relevant properties are summarised as defined in sections A.1 – A.3 and in the development of \( P_{\text{Initial}} \) above and \( J_1 = J_a \land J_b \land J_c \).

**PHENOMENA:** Phenomena and their control and sharing (see \( P_{\text{Initial}} \)) are known from the existing system components as shown in Table 4.1.

**CLAIM:** The interpretations are well-founded

**ARGUMENT & EVIDENCE:** The choice of domains follows from the aircraft level safety analysis and the required choice of interlocks. The DS, DU, AS and SP are existing components of the avionics system, with well-known, validated properties. The Pilot is trained to follow protocols rigorously.

The customer functional requirements (\( Ra \) to \( Rd \)) were provided as an input to the developer team, and were validated with the customer. The development of the safety requirement \( RS \) is as related in sections A.1 and A.2, and discussed above.
CLAIM: The overall architecture is feasible

ARGUMENT & EVIDENCE: The selected overall system architecture has been used successfully on similar safety systems. Inspection confirms that the identified domains and their associated phenomena can interact as needed - aim being to avoid Unshared Information issues (see section 2.4) later in the development.

CLAIM: Sound judgement followed

ARGUMENT & EVIDENCE: The development is based on IPDP used successfully on many previous developments and enhanced with POSE to mitigate some known issues with IPDP. Claim this follows normal and not radical design concepts as defined in [131].

CLAIM: In-air indicator in Aircraft Status System is reliable

ARGUMENT & EVIDENCE: The in-air indicator is obtained from the weight on wheels and landing gear up indications: if the landing gear is up and there is no weight on the wheels then the aircraft is assumed to be in the air. The landing gear is detected as being up by a number of sensor switches. The switches use a multi-pole arrangement of appropriately selected “Normally open/Normally closed” contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins.

The PS1: Initial Problem structure contains examples of the use of the justification and claims/argument/evidence elements necessary to support the POSE transformation sequence that supports the formation of the initial problem $P_{\text{initial}}$. Just as the justification strength (refer to section 4.1.4) can vary from quite weak (e.g. information based on a data sheet) through to very strong (e.g. diverse evidence from formal proof and test results); so the claim/argument/evidence structure operates similarly. Near the end of a development the evidence to support the final safety case must be strong and compelling. However, at the early stages of a project
a "lighter" approach is reasonable where the route to gaining sufficient supporting evidence is clearly outlined, but not as yet necessarily followed. The idea being that the strong argumentation and evidence required by the final safety case will be supplied later in the development. In the early stages the argument strategy is made extant so it can be reviewed to judge if it is capable of supplying the required strength of supporting evidence. This "lighter" structure is consistent with the early development stages where different candidate solution system architectures are evaluated and the most promising candidate selected. Until the analyst has evidence that the candidate architecture is capable of satisfying its safety obligations (i.e. shown it is feasible) it is potentially wasteful to spend effort collecting too much evidence. However, once the candidate system architecture has been shown to be feasible, then the required evidence collection should proceed – the problem transformation step structures such as PS1 above provide an easy means of ascertaining what the current evidence status is and hence what further evidence might be required.

The claim/argument/evidence structures used in PS1, and in the other transformation steps to be introduced (e.g. PS2 below), are all examples of the "lighter" structure in that they outline the strategy but do not (as yet) provide the full level of argumentation and evidence. For example the Claim in PS1 that The overall
architecture is feasible is based on similarity with previous successful systems and a review of the domain interactions; so it is expected to be feasible, but the analysis to provide this evidence - based on the PSA results - has not been collected at this point.

### 4.3 Refining the Solution Architecture

The IPDP Dem/Val phase has detailed architecture analysis as part of its Sub-system Theory of Operation task (refer to section 3.3). This task involves the development of structures and concepts that will enable the requirements to be satisfied. The POSE solution expansion AStruct (refer to section 4.1.3) is a good candidate to support this work since it allows various candidate system architectures to be investigated. In this case study, the following AStruct encodes the candidate system architecture chosen for the Decoy Controller:

\[
\text{DecoyContAS}[II^{\text{int}}_{\text{ok,air,out}}, DM_{\text{con,sel,fire}}^{\text{sel,fire}}\text{?}, (SC_{\text{int,fire}}^{\text{fire}})]
\]

which includes two extant components, II and DM and one to be found component the safety controller SC. These domains are as defined in section A.4 and in Figure A.2. This architecture can be introduced using the SOLUTION INTERPRETATION and SOLUTION EXPANSION transformations described in section 4.1.3.3. These transformations and the REQUIREMENTS INTERPRETATION transformation can be used to transform the software problem from \( P_{\text{initial}} \) into \( P_{\text{Exp}} \).

\[
P_{\text{Exp}} : D(S(\text{con})_{\text{con}}, D(U(\text{fire}, \text{sel})_{\text{fire,sel}}, \text{SP}(\text{out})_{\text{out}}, A(S(\text{air})_{\text{air}}), P(\text{ok})_{\text{ok}}, II_{\text{ok,air,out}}^{\text{int}}, DM_{\text{con,fire}}^{\text{int,fire}}?, SC_{\text{int,fire}}^{\text{fire}}\text{?} \vdash P_{\text{con,out,air,ok}}^{\text{fire,sel}})
\]
First the SOLUTION INTERPRETATION transformation is used to introduce the architecture represented by the AStruct DecoyContAS[II, ...DM, ...] (SC_{int, fire?}) into the problem, then SOLUTION EXPANSION is used to expand out this AStruct and finally REQUIREMENTS INTERPRETATION is used to appropriately modify the requirement from Rdc into R' to allow for the introduction of the system architecture.

Experience from using POSE on some avionics examples [87, 86, 85, 88] indicates that this sequence of introducing a candidate system architecture is used frequently, and can be combined into the PS2 Solution Interpretation and Expansion problem transformation step represented by the structure shown below.

**PS2: Solution Interpretation and Expansion applied to problem P_{Initial} to form P_{Exp}**

**JUSTIFICATION J_2:** The identified system architecture, its components and relevant properties are as summarised in section A.4 and in Figure A.2. The justification for this (architecture) solution expansion transformation is that this system architecture was successfully developed as a prototype and is known to be capable of satisfying the functional requirements.

The requirements are transformed from Rdc to R' as detailed at the end of section A.4 on page 233 and modified by Table 4.1. However, R'd is modified to include reference to the phenomena int for representing the interlock status. Note that RS is not changed by this transformation. The efficacy of the requirement transformations were validated by independent review. Now R' is:

R'a The DS shall command which flare is selected using a field in its con message issued to the DM. The DM shall obtain the selected flare information from this field in the con message, and use it in its sel message to the DU to control the flare selection in the DU.

R'b The DS shall command the DM to issue a fire? command in its con message.
The **DM** will request the **SC** to send the **fire command**. This shall be the only way in which a flare can be released.

**R'c** The **SC** shall cause a flare to be released by issuing a **fire command** to the **DU**, which will fire the selected flare.

**R'd** The **SC** shall only issue a fire command if its interlocks, represented by **int**, are satisfied, i.e. aircraft is in air (air = yes), **SP** safety pin has been removed (out = yes) and **Pilot** has issued an allow a release command (ok = yes).

**RS** The **DC** shall mitigate **H1 & H2** (Target: safety critical $10^{-7}$ fpfh).

**PExn** is as defined above. An equivalent **PF** representation is shown in Figure 4.3 below.

**CLAIM:** Rdc and R' are equivalent

**ARGUMENT & EVIDENCE:** Rdc and R' refer to and constrain the same phenomena, albeit shared between different domains.

**CLAIM:** The choice of candidate solution architecture exhibits sound safety engineering judgement

**ARGUMENT & EVIDENCE:** The system architecture is chosen to minimise the number and extent of the safety related functions, localising them to simple, distinct blocks in accordance with best practice.

**CLAIM:** The chosen solution architecture does not prevent the satisfaction of R' (Feasibility). This claim is not yet supported.

**PHENOMENA:** The new phenomena introduced by the architecture are:

- **fire?** – Command to release the selected flare type
- **int** – Status of combined interlocks

This POSE system architecture work provides supporting evidence for property Architecture from Table 2.3.
4.4 Preliminary Safety Analysis

The justification of the previous transformation step is incomplete: the *Feasibility concern* remains to be discharged. The related claim is that the chosen system architecture candidate should not prevent an adequately safe solution. In the worst case, to continue the design without checking feasibility uncovers the risk that the final product cannot be argued safe. Traditionally, such risks are mitigated through over-engineering of the solution, but this typically adds to the complexity of the design and increases the development cost.

Here, the risk is managed through a Preliminary Safety Analysis (PSA), applied as part of the IPDP safety analysis tasks in the attempt to discharge the *Feasibility concern*. The goal of a PSA is to:

- confirm the relevance of hazards allocated by the system level hazard analysis;
- identify any further hazards to be added to the list; and
- validate the architecture against the safety targets associated with the identified relevant hazards.

Many techniques can be applied to perform a PSA. In [87] we used a combination of mathematical proof, Functional Failure Analysis (FFA) [109] and functional Fault Tree Analysis (FTA) [130]. The PSA uses the same software problem model as the development, $P_{Exp}$, which provides supporting evidence for [SameA1].
Note that at this point the PSA is not a POSE transformation per se (no POSE schema defines a PSA). Instead it is a technique which we use to discharge one of the claims in the PS2 problem transformation step structure. The continuation of this PS2 structure is shown below.

**PS2: Solution Interpretation and Expansion applied to problem $P_{\text{Init}}$ to form $P_{\text{Exp}}$ (cont'd)**

**CLAIM:** The chosen solution architecture does not prevent the satisfaction of $R'$ (Feasibility). This claim does not hold.

**ARGUMENT & EVIDENCE:** We applied FFA to each architectural component in turn. The results from applying FFA to the DM are shown in Table 4.2, where three problem cases were identified: F2, F3 and F5, with 'Yes' in the Hazard column.

<table>
<thead>
<tr>
<th>Id</th>
<th>Failure Mode</th>
<th>Effect</th>
<th>Haz</th>
</tr>
</thead>
<tbody>
<tr>
<td>F1</td>
<td>No fire?</td>
<td>Release inhibited</td>
<td>No</td>
</tr>
<tr>
<td>F2</td>
<td>fire? at wrong time</td>
<td>Inadvertent release</td>
<td>Yes</td>
</tr>
<tr>
<td>F3</td>
<td>fire? when not required</td>
<td>Inadvertent release</td>
<td>Yes</td>
</tr>
<tr>
<td>F4</td>
<td>Intermittent fire?</td>
<td>Could inhibit release</td>
<td>No</td>
</tr>
<tr>
<td>F5</td>
<td>Continuous fire?</td>
<td>Inadvertent release</td>
<td>Yes</td>
</tr>
</tbody>
</table>

A functional FTA applied to $DM$ based on the model for $P_{\text{Exp}}$ (and Figure 4.3) and using the three FFA problem cases F2, F3 and F5, indicates that a failure in $uP$ (systematic or probabilistic) could result in the fire? failing on. The Pilot's allow input provides some mitigation, but as soon as this is set ($ok = yes$) a flare will be released, which is undesirable behaviour.
In other words, with this system architecture, $H_2$ is only protected by the Pilot's allow input. If fire? failed on, then as soon as the Pilot indicated an intention to allow flare release, by selecting the switch, then the flare would be released, which is not the design intention. Therefore the safety analysis indicates that fire? needs to have a safety involved (but not critical) integrity. The current design does not satisfy the safety requirements.

The safety analysis indicates that fire? needs to have a safety involved integrity. This can only be achieved with the existing design by upgrading all of the design to be safety involved. That is, by assigning fire? to the $uP$, we require that all $uP$ functionality must be at the same safety integrity as fire, which is safety involved. However, the bulk of the $uP$'s functionality (timing, BIT, etc.) is not safety-related. Further, any updates to the $uP$ software have to satisfy the safety involved integrity.

The conclusion of the PSA is that the selected $DM$ system architecture is not a suitable basis for the design – no adequate solution can be derived from its parametrisation. Choices at this point include: designing the $DM$ to be safety related, or re-structuring the $DM$ system architecture to partition the safety and non-safety elements. The first option is undesirable due to the expense and long term impact, i.e. timing and selection are not safety functions and are expected to be fine-tuned to support different flare types. Making this safety-related would have a detrimental impact on the affordability of the solution. The second option is more appealing, and was the option chosen for this development. This case study is continued in Chapter 5.

The fact that PSA could be applied to the POSE problem model, $P_{Exp}$, provides some support for the property Right Abstraction, although more evidence is required to support this fully.
4.5 Discussion

From our initial work on using POSE on the DC case study we can now start to assess the ability of POSE to support the IPDP and address the properties and issues we have identified.

4.5.1 Properties and IPDP Issues

The work reported in section 4.1.3 showed that context interpretation was used to develop a good understanding of the environment context to identify the domains involved and investigate their interfaces and communication mechanisms. The practical result of following this process in IPDP was a thorough understanding of the environment context, which provides mitigation for [Envir1].

The work reported in section 4.1.3 also demonstrated that the effort in applying the requirements interpretation addressed the concerns raised by [Requ2] in comparison with the real development summarised in Appendix A. It showed that the requirements produced using this process were more focussed and had less contradictions and consistency issues, when compared with performing the same tasks without POSE. It made explicit the relationship between the requirements and the environment domain phenomena, which assisted the later modelling work.

The PSA work of section 4.4 demonstrated that POSE has potential with respect to supporting the IPDP safety analysis tasks by providing a suitable model structure on which the analysis could be based. The PSA used the model based on $P_{Exp}$ and Figure 4.3, along with the associated domain, phenomena and behaviour descriptions referenced from the POSE steps PS1 and PS2. That is, the safety analysis used the same model as the development ($P_{Exp}$) in agreement with [SameA].

As expected, POSE (a PO approach) is very good at addressing [Envir1] and [Requ2]. However, this POSE model structure is available much earlier in the development life cycle than the Preliminary Design phase. In fact the model could be
formed at the end of the Dem/Val phase and the feasibility check could be used as a checkpoint in the IPDP SDR. This is a very significant factor because if it can be demonstrated in a more general context, then POSE embedded within IPDP would allow a meaningful safety analysis to be conducted much earlier in the IPDP life cycle than is currently the case - thus satisfying [Late13] identified in section 3.4.5.

At the Dem/Val SDR phase the design is more abstract and compact than at the end of Preliminary Design, and it is much easier to incorporate changes. It follows that any iteration back associated with failing the PSA feasibility check conducted at the end of the Dem/Val phase can be contained within a relatively small number of related IPDP tasks within the phase. In contrast, failing the feasibility check conducted during EMD Preliminary Design involves iterating back over many tasks over a number of phases. Therefore, checking at the Dem/Val phase allows the necessary corrective action to be instigated earlier and have less impact on cost and schedule compared with finding a problem later in the life cycle during Preliminary Design. The inference is that performing the PSA early would address [Late13] and also cover the part of [Trace14] concerned with iteration.

In the DC case study the initial system architecture failed the feasibility check and this showed that there is a need to provide direct support for iteration in the life cycle, and it supported the findings of a significant number of other IPDP projects that required re-working. Basically a decision point is required such that if the architecture model passes the feasibility check then the project can continue to the next phase of the development, otherwise there is a need to iterate back within the current phase to allow corrective action to be applied. As noted above, performing the check during SDR has the advantage that the iteration can be incorporated into a small number of related tasks thus minimising its detrimental impact. Integrated as part of IPDP, iteration then is part of the normal, expected task transactions and does not attract the adverse senior management scrutiny that currently occurs with the existing non-POSE, ad hoc iteration handling mechanisms. The need for
a decision point and how to achieve support for iteration will be considered further in Chapter 6.

Inspection of the model used for the safety analysis (see $P_{Exp}$ and Figure 4.3) indicates that it is more complex than necessary and involved domains that were not directly relevant to the issue under investigation. A more efficient safety analysis would be obtained if it were possible to remove these extraneous domains and just concentrate on the core domains of the safety problem. Another driver for removing extraneous domains is the fact that the requirement $R'$ is still expressed in terms of the system environment, and not in terms of the system to be designed. For example, in the case study $R'd$ involves terms in $\text{air} = \text{yes}$, yet the $SC$ has no interface to the $AS$, so as they stand the requirements $R'$ are not implementable with respect to the $SC$. This means that there is no direct way of extracting the specification of $SC$ using the problem $P_{Exp}$ and thus at this point [NecessaryP] has not been demonstrated. To achieve the goal of extracting the specification, it is necessary to be able to transform $R'$ so that it more directly relates to the $SC$. The next chapter introduces the POSE problem progression transformation (PPT) as a means of mitigating these two issues by removing extraneous domains whilst correctly re-writing the requirements to compensate.

The adequate completion of IPDP task activities was identified as an important factor in the successful application of IPDP and an area where problems have been detected in the past, this was captured in section 3.4.5 as [IncomI5]. The work in section 4.2 suggests that POSE can assist with this completeness issue in three main ways:

- the framework ensures that the environment domains are adequately considered, requirements assimilated and also ensures that the distinction between the indicative and optative properties are well understood;

- the POSE transformations provide a mechanism for completing the objectives
of certain important tasks in the development;

- the POSE problem transformation steps (see section 4.1.4.2) provide a template structure for ensuring that all the relevant factors in completing a development task have been addressed and this can be easily reviewed and validated.

However, more work is required to ensure that all the necessary task activities have been identified and accurately captured. Finally, POSE is known to have the capability of supporting formal development processes [39, 88], but evidence to support this has not been provided as yet.

4.5.2 IPDP Process

These initial results are encouraging and indicate that POSE can be used as part of the IPDP. Further, the DC case study work shows that the early IPDP phases can benefit from the structuring of the requirements that this can bring. In particular, inspection of the POSE capabilities and the safety work presented thus far in section 4.4 indicate that it would be useful and beneficial to develop a front-end process based on the POSE transformations targeted at embedded real-time safety systems (which are the major focus of this work), since there is good evidence from the DC case study that POSE addresses [SameA1], [Envir11] and [Requ12]. However a number of improvements to better achieve these goals (as discussed above in section 4.5.1) pertaining to derivation of the specification $S$, early safety analysis, improved iteration, safety case support, model simplification, requirements transformations, the completion of all the necessary activities and support for formal development processes were identified as needing attention. These will be developed further in the next few chapters.

The use of POSE within IPDP, and a measure of how well POSE integrates with IPDP, can be obtained from inspection of Table 4.3, where the "Ref." entries refer to sections in this document. The table shows that POSE works well with IPDP for
In summary, the DC case study work provides good evidence that using POSE within IPDP will allow [SameA1], [EnvirI1], and [RequI2] to be addressed, and provides some evidence to support [IntegA3]. In addition, it provides some supporting evidence for the Context, Architecture, Avoid Bias, Model Reality, Validation, Simplification and Integrates properties identified in Chapter 2, and to some extent property Right Abstraction too. The problem transformation steps extension introduced in section 4.1.4.2 assists with the applicability of POSE by providing a convenient mechanism for grouping related tasks together into a single entity; e.g. the PS1 structure in section 4.2.

We have summarised the evidence in Table 4.4, where “.” means no evidence has been provided by this work to support the property/issue, “e” means that some evidence has been provided by this work to support the property/issue, “ee” means that good, corroborated evidence (e.g. from two case studies) has been provided, and “E” means that significant corroborated evidence (e.g. multiple case studies) has been provided by this work. Entries shown in bold indicate that evidence is obtained from the results of this chapter. The table also includes references to the external papers, under “Previous Work”, where evidence is provided that POSE
supports the property or mitigates the issue.

<table>
<thead>
<tr>
<th>Property/Issue</th>
<th>Previous Work</th>
<th>Chapter 4</th>
</tr>
</thead>
<tbody>
<tr>
<td>Context</td>
<td>[41, 87]</td>
<td>e</td>
</tr>
<tr>
<td>Architecture</td>
<td>[41, 87]</td>
<td>e</td>
</tr>
<tr>
<td>Spec. Join</td>
<td>[39, 83]</td>
<td>-</td>
</tr>
<tr>
<td>Avoid Bias</td>
<td>[39]</td>
<td>e</td>
</tr>
<tr>
<td>Model Reality</td>
<td>-</td>
<td>e</td>
</tr>
<tr>
<td>Validation</td>
<td>-</td>
<td>e</td>
</tr>
<tr>
<td>Simplification</td>
<td>[41, 87]</td>
<td>e</td>
</tr>
<tr>
<td>Tool Support</td>
<td>[38, 87]</td>
<td>-</td>
</tr>
<tr>
<td>Right Abstraction</td>
<td>[41, 87]</td>
<td>e</td>
</tr>
<tr>
<td>Integrates</td>
<td>[88]</td>
<td>e</td>
</tr>
<tr>
<td>NecessaryP</td>
<td>[41, 83]</td>
<td>-</td>
</tr>
<tr>
<td>SameA1</td>
<td>[88]</td>
<td>e</td>
</tr>
<tr>
<td>FormalA2</td>
<td>[41, 88]</td>
<td>-</td>
</tr>
<tr>
<td>IntegA3</td>
<td>-</td>
<td>e</td>
</tr>
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<td>[87, 88]</td>
<td>e</td>
</tr>
<tr>
<td>RequI2</td>
<td>[87, 88]</td>
<td>e</td>
</tr>
<tr>
<td>LateI3</td>
<td>[85, 88]</td>
<td>-</td>
</tr>
<tr>
<td>TraceI4</td>
<td>[85, 88]</td>
<td>-</td>
</tr>
<tr>
<td>IncomI5</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>ValidI6</td>
<td>[88]</td>
<td>-</td>
</tr>
</tbody>
</table>

Table 4.4: Evidence Status for POSE after Chapter 4

4.6 Chapter Summary

In this chapter we have introduced POSE and evaluated it within IPDP based on the DC case study. The outcomes of this exercise were discussed in section 4.5.2. The latter concluded that POSE within IPDP addressed [SameA1], [EnvirI1] and [RequI2], and that it could address the remaining issues with some development and extensions - these are the subject of the next two chapters.

The contribution of this thesis so far to the knowledge concerning POSE and its use with respect to supporting these properties and mitigating the six issues is summarised in Table 4.5, where “vanilla” POSE is as defined in [41, 39, 40], i.e., not an expansion introduced by this work. The “Reference” column refers to section
numbers unless otherwise stated.
<table>
<thead>
<tr>
<th>Property</th>
<th>Contribution Description</th>
<th>Reference</th>
</tr>
</thead>
<tbody>
<tr>
<td>All of Table 2.3</td>
<td>Identified a set of properties appropriate for SSSD.</td>
<td>2.5 Table 2.3</td>
</tr>
<tr>
<td>[NecessaryP]</td>
<td>Identified necessary property for deriving specification, S.</td>
<td>3.4.4</td>
</tr>
<tr>
<td>[SameA1]</td>
<td>Identified three useful properties that the SSSD approach should support.</td>
<td>3.4.4</td>
</tr>
<tr>
<td>[FormalA2]</td>
<td></td>
<td></td>
</tr>
<tr>
<td>[IntegA3]</td>
<td></td>
<td></td>
</tr>
<tr>
<td>EnvirI1</td>
<td>Identified IPDP issue for mitigation</td>
<td>3.2.1, 3.3.1 &amp; 3.3.4</td>
</tr>
<tr>
<td>RequI2</td>
<td>Identified IPDP issue for mitigation</td>
<td>3.2.2, 3.3.3 &amp; 3.4.1</td>
</tr>
<tr>
<td>LateI3</td>
<td>Identified IPDP issue for mitigation</td>
<td>3.2.3, 3.4.3, 3.3.3, 3.3.4</td>
</tr>
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<td>Identified IPDP issue for mitigation</td>
<td>3.2.3, 3.3.2, 3.4.2</td>
</tr>
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<td>IncomI5</td>
<td>Identified IPDP issue for mitigation</td>
<td>3.2.4, 3.3.1</td>
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<tr>
<td>ValidI6</td>
<td>Identified IPDP issue for mitigation</td>
<td>3.3.5</td>
</tr>
<tr>
<td>EnvirI1</td>
<td><em>DC</em> case study demonstrated “vanilla” POS mitigates this issue.</td>
<td>4.1.3, 4.5.1</td>
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<tr>
<td>RequI2</td>
<td><em>DC</em> case study demonstrated “vanilla” POS mitigates this issue.</td>
<td>4.1.3, 4.5.1</td>
</tr>
<tr>
<td>SameA1</td>
<td><em>DC</em> case study demonstrated “vanilla” POS supports property.</td>
<td>4.4, 4.5.1</td>
</tr>
<tr>
<td>IntegA3</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support. Table 4.3</td>
<td>4.5.2</td>
</tr>
<tr>
<td>Context</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.1.2 &amp; 4.1.3</td>
</tr>
<tr>
<td>Avoid Bias</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.1.2 &amp; 4.1.3</td>
</tr>
<tr>
<td>Model Reality</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.1.2 &amp; 4.1.3</td>
</tr>
<tr>
<td>Architecture</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.3</td>
</tr>
<tr>
<td>Validation</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.1.2</td>
</tr>
<tr>
<td>Simplification</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.1.3</td>
</tr>
<tr>
<td>Right Abstraction</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.4</td>
</tr>
<tr>
<td>Integrates</td>
<td><em>DC</em> case study demonstrated “vanilla” POS provides some support.</td>
<td>4.5.2 &amp; Table 4.3</td>
</tr>
</tbody>
</table>

Table 4.5: Thesis Contribution Summary after Chapter 4
Chapter 5

Enhancing the Process Using POSE

Chapter 5 specifically investigates the properties [NecessaryP], [FormalA2], Validation, Simplification and the issues [TraceI4], [LateI3], [ValidI6]; and it discusses the evidence collected to support them and the other properties through the use of representative case study examples. The chapter concludes by considering this supporting evidence in the status table, first introduced in section 4.6.

5.1 From Problems to Software Solutions

Jackson's work [53] distinguishes between software requirement and specifications. Simply stakeholders should understand the requirement as constraining their context, whereas the specification should be implementable [133]. The requirement should be grounded in the reality of the context for which the machine is to be designed [133], whereas the specification should be defined solely in terms of the phenomena at the interface between the machine and its context.

Other approaches, particularly formal ones [43, 111], recognise the gap between specification and code and provide techniques to bridge it. POSE with its generalised
notion of solution addresses the larger gaps (from requirements in context through the specification to code).

Within Problem Frames a number of authors have suggested approaches to bridge the gap between requirement and specification. Jackson himself in [53] sketches out the idea of problem progression. Starting from this idea, Li [74, 75], expands and completes the idea of problem progression exploiting the concept of causality between phenomena within a graph theoretical framework. Other work by Seater and D. Jackson [113, 114] propose a notion of progression based on the addition of domain assumptions.

In POSE too, there is a notion of progression which is based on the combination of two transformation schemas [36, 39, 40, 41]. This is very general in nature and provides no particular guidance or heuristics for its application. The work in this section will address how to make it practical in the context of safety critical engineering by adopting a similar notion of causality as Li, and demonstrating how this integrates with the theoretical underpinnings provided by POSE.

5.1.1 Problem Progression

In [40], Hall, Rapanotti and Jackson defined transformations from which a POSE notion of problem progression can be derived. Their transformations are perfectly general and assume nothing of a domain, its phenomena, the relationships between phenomena or how the requirements refers to or constrains the phenomena. As a consequence the transformation wrought on the requirement can make no use of domain, phenomena or requirements structure. For embedded systems an assumption of causality between phenomena allows a more grounded engineering view of problem progression. The assumption of causality used in this work is based on the approach outlined in [94]. Our engineering form of problem progression is related to Li's work [74, 75], which is another general theoretical framework but this time based
on the assumption of causality between phenomena within domains. One benefit of Li's approach is that it shows precisely how to construct a new requirement from the old one. However, Li's work applies only in Problem Frames.

5.1.1.1 Problem Progression in Problem Frames

The goal of a problem progression sequence can be explained graphically with reference to the Problem Frame problem progression diagram shown in Figure 5.1. This is an elaboration of the progression shown on Page 103 of [53] and that used by Li [74] (Note that this is only an illustration and not the generic case. Li provides a complete taxonomy in [74]).

![Figure 5.1: Problem Frame Progression Sequence](image)

The goal is to successively remove the domains $D_3$, $D_2$ and $D_1$ whilst rewriting the requirement in a solution preserving form such that $S$ in conjunction with the properties of the removed domains satisfies the original requirement $R_1$. Doing this progression allows $S$ to be directly derived from $\emptyset, S \vdash R_4$ since $R_4$ is written in terms of phenomena, $a$, accessible to $S$, and assumptions derived from the removed domains.

By combining the work of Jackson and Li, progression in Figure 5.1 can be described as follows. In the initial problem, the requirement, $R_1$, is expressed in terms of phenomena in the real world – represented by $d$. Following the notion
of causality used by Li [74], assume that there exists a causal relation between phenomena $c$ and $d$ induced by the properties of the the domain $D_3$, such that if $c$ occurs then $d$ occurs: we call such a relation the *useful behaviour* relation and indicate such a relation as $c \ D_3 \ d$. Then we can omit $D_3$ and define a new requirement, $R_2$, expressed in terms of phenomenon $c$ and derived from $R_1$ with the addition of assumptions capturing the useful behaviour relation $c \ D_3 \ d$. In doing so, the original problem has been progressed to a new problem with a simplified context, in such a way that a solution which satisfies $R_2$ in the progressed problem, will also satisfy $R_1$ in the original problem.

In practice the engineering domains used in the architecture could have a variety of possible behaviours, but we are only interested in that part of the domain's behaviour that corresponds to the relation $c \ D_3 \ d$ – hence it is called the useful behaviour relation. It is also worth noting that this useful behaviour relation corresponds to the *Environment Constraint* introduced in section 2.4.

When progression is based on causality it is important to define relations such as $c \ D_3 \ d$ properly. Li provides a basic taxonomy [74] of relevant types of causal relations. Among them is the notion of *biddable causality* which relates to human behaviour. While in general human behaviour is unpredictable, there are cases in which people can be assumed to follow particular instructions or orders, from which causal relations can also be assumed. This type of causal relation is relevant to our work, as the humans involved in operating the systems produced by the Company tend to be highly trained pilots or other skilled military personnel, so that an approximation of causal behaviour can be claimed for benign scenarios.

5.1.1.2 Problem Progression in POSE

In POSE the domain to be removed is termed the *to-be-progressed domain* and is removed using a two step process as follows [39]:

- first the phenomena associated with the to-be-progressed domain are "un-
shared" by internalising them into it, making an assumption in the requirement equivalent to the constraints that the to-be-progressed domain places on its shared phenomena – this is the SHARING REMOVAL transformation shown below.

- second a domain that shares no phenomena may be removed from the context of a problem – this is the DOMAIN REMOVAL transformation shown below.

The two rules are as follows:

\[
W, D(c, o) : \text{DescD, } S \vdash R' : F' \quad [\text{SHARING REMOVAL}]
\]

\[
W, D_o : \text{DescD, } S \vdash R : F
\]

where the requirement becomes \( R' = R^{\text{ren},c} \) and \( F' = c D o, F \). The relation \( cD o \) is the useful behaviour relation introduced in section 5.1.1.

\[
W, S \vdash R \quad [\text{DOMAIN REMOVAL}]
\]

\[
W, D^\emptyset_\emptyset, S \vdash R
\]

The key point is that constraints that the to-be-progressed domain places on its shared phenomena (the useful behaviour of the domain) are captured within the requirement as an assumption. The requirement before the progression is likely to refer to phenomena that have been removed as part of the progression, therefore a REQUIREMENTS INTERPRETATION transformation is usually necessary to rephrase the requirement in terms of the phenomena extant in the progressed problem description. As noted above, problem progression in POSE is quite general – it can be applied to any domain in the problem context – and there remain difficulties in applying it associated with identifying the appropriate part of the requirement and how it should be refined. The approach adopted in this work is to restrict the application of the progression rules in a way which facilitates the analysis and this is considered in the next section.
5.1.2 POSE Problem Progression for Safety Systems

The approach used to derive the problem progression transformation sequence (PPT) developed in this work is based on the general POSE problem progression introduced above, but it is made more specific to serve the needs of practical engineering. In particular, we apply progression under the following conditions: that causal relations among phenomena are identified and used to establish assumptions in the derived requirements; that only domains whose phenomena are directly referred to or constrained by the requirement are the subject of progression.

We call such domains adjacent to the requirement, as in Problem Frame notation they would be directly linked to the requirement by a dashed line (if referred to) or a dashed arrow (if constrained).

With reference to Figure 5.1, let us assume a causal relation between phenomena c and d, whose derived assumption we denote by \( \text{Assumption}(c, d) \). The first step of progression in the figure corresponds to the following POSE transformations:

\[
\begin{align*}
D_{1a}^b, D_{2b}^c, S^a &\vdash R_2^c & \text{[RequirementInt.]} \ll J_1 \gg \\
D_{1a}^b, D_{2b}^c, S^a &\vdash R_1^d \land \text{Assumption}(c, d) & \text{[DomainRemoval]} \\
D_{1a}^b, D_{2b}^c, D_{2b}^{(c, d)}, S^a &\vdash R_1^d \land \text{Assumption}(c, d) & \text{[SharingRemoval]}
\end{align*}
\]

based on the properties captured by \( \text{Assumption}(c, d) \). In other words, \( J_1 \) has to justify that \( R_2^c \) is in some sense equivalent to \( R_1^d \) through \( \text{Assumption}(c, d) \).

Repeated application of the same combination of POSE rules to the problems in Figure 5.1 will remove domain \( D_2 \) and then domain \( D_1 \). Each requirement interpretation step will need justification, namely that

\( R_2^c \) is in some logical sense equivalent to \( R_2^c \land \text{Assumption}(b, c) \)

and that

\( R_4^b \) is in some logical sense equivalent to \( R_3^b \land \text{Assumption}(a, b) \)
This combination of SHARING REMOVAL, DOMAIN REMOVAL and REQUIREMENTS INTERPRETATION transformations is called the PPT in this work and in the sequel a problem transformation step will be used to control each application of the PPT, as demonstrated in the DC case study problem progressions considered in section 5.1.3.

The PPT is based on domain properties and causal relations between phenomena. As we will see, it is amenable both to informal and formal logical analysis: the latter is possible when both requirements and assumptions can be expressed logically and their equivalence proved through logical implication. In section 5.1.3 we illustrate an informal PPT on the DC case study. Later case studies will illustrate a formal PPT based on the use of Alloy [52].

The PPT approach has the advantage that it is easy to apply since it uses knowledge about the domains and the known requirement to guide the refinement of the requirement; its disadvantage is that only in the last validation step can you demonstrate that the derived specification $S$ satisfies the requirement. In theory it is possible to go through a derivation sequence and derive a specification that does not fully satisfy the requirement, although this did not occur in the case studies reported in this work.

In summary, the PPT uses problem knowledge to guide its application and to refine the requirement as domains are removed. The problem progression can be seen as a form of problem simplification since it allows the specification to be derived by simplifying the problem (by removing domains), thus it provides support for property Simplification identified in section 2.5. The PPT application also validates that the specification, $S$, you derive from applying the PPT is capable of satisfying the original requirement and thus supports the issue [ValidI6] and the Validation property, as well as property [NecessaryP].

The assumption of causality among phenomena is an important aspect of the PPT approach which is reasonable for the embedded real time safety systems that
are the focus of this work. A domain is often representative of a piece of avionics equipment that has a particular function – give it the right input and it will produce the desired output. As part of the initial design, these domains are arranged in a particular system architecture to produce the required behaviour.

5.1.3 Problem Progression Applied to the DC

An example of applying the PPT process to remove domains will now be presented based on the DC case study first introduced in Chapter 4. The model of the DC problem $P_{Exp}$ represented in Figure 4.3 is quite complex and the requirement phenomena do not correspond to the SC Machine phenomena, i.e., the current requirement, $R'$, is not feasible with respect to the Machine, SC since it cannot be implemented with the information available. This is resolved by applying the PPT to remove domains and rewrite the requirement accordingly so that the Machine specification can be derived, and then validated that it satisfies $R'$. As noted in section 5.1.2, the problem progression begins with domains adjacent to the requirement. Inspection of Figure 4.3 indicates that the Pilot switch selection domain is a suitable first candidate for removal. The removal proceeds by following the process introduced in section 5.1.2. These steps are captured in the Pilot Domain Removal problem transformation step PS3 shown below.

| PS3: Application of the PPT for Pilot Domain Removal to problem $P_{Exp}$ to form $P_{Red1}$ |
| INCLUDES: None |
| JUSTIFICATION J: The Pilot domain removal is based on the process given in section 5.1.2. The Pilot domain is adjacent to the requirement $R'$. The Pilot domain control phenomena ok maps directly to its output behaviour phenomena which is also ok. Therefore ok will appear in the reference part of the requirement phenomena both |
before and after the transformation. The requirements $R'$ are as detailed in problem transformation step PS2 on page 95. Inspection of $R'$ indicates that only $R'd$ involves a reference to phenomena $ok$ – now consider the transformation from $R'd$ into $R1d$:

$R'd$ : Pilot has issued an allow release command ($ok = yes$).

$R1d$ : II observes pilot input of $ok = yes$.

**Pilot Domain Description**: The pilot sets the Allow switch to active to indicate that the intention is to allow flare release, otherwise it is set inactive. The Allow switch uses a multi-pole arrangement of appropriately selected “Normally open/Normally closed” contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins. The setting of the Allow switch is determined by the Pilot domain and is output using the phenomena $ok$, where $ok = yes$ means the Allow switch is active, whilst $ok = no$ means the allow switch is inactive. Therefore $ok = yes$ corresponds to allow flare release, whilst $ok = no$ corresponds to inhibit flare release.

The justification for this problem progression is that $R1d \land Assumption(ok, ok) \Rightarrow R'd$.

The $A_1 = Assumption(ok, ok)$ is given by the Pilot Domain Description. Inspection of $R1d$ in conjunction with the Pilot Domain Description shows they imply $R'd$ as required.

This requirement transformation does not require additional information not already in the interface nor does it refer to future events. However it does rely on the useful behaviour from the domain being removed being “saved” as part of the assumption that justifies the transformation – it is an example of an Environment Constraint non-feasible requirement which is discussed in a POSE context in [83]. As noted above, this useful behaviour contribution is contained in the Pilot Domain Description.

The PPT application transforms the problem from $P_{Exp}$ into $P_{Red1}$, and $R'$ is transformed into $R1$ as follows:

**R1a** The *DS* shall command which flare is selected using a field in its *con message* issued to the *DM*. The *DM* shall obtain the selected flare information from this
field in the con message, and use it in its sel message to the DU to control the
flare selection in the DU.

R1b The DS shall command the DM to issue a fire? command in its con message.
The DM will request the SC to send the fire command. This shall be the only
way in which a flare can be released.

R1c The SC shall cause a flare to be released by issuing a fire command to the DU,
which will fire the selected flare.

R1d The SC shall only issue a fire command if its interlocks, represented by int,
are satisfied, i.e. aircraft is in air (air = yes), SP safety pin has been removed
(out = yes) and II observes pilot input of ok = yes.

RS The DC shall mitigate H1 & H2 (Target: safety critical 10^-7 fpfh).

The domain Pilot is no longer referenced in the model and can be removed.

The software problem is transformed to P_{Red1}:

\[
P_{Red1} : DS^{con}, DU^{fire, sel}, SP^{out}, AS^{air}, II^{int}, DM^{sel, fire}, SC^{int, fire} \vdash R1^{fire, sel, con, out, air, ok} \land A1
\]

CONCERNS: The control input phenomena ok is the same as the domain behaviour
output phenomena for this reference-type problem progression. This can be a symptom
of over-specification.

CLAIM: The pilot’s intention with respect to the allowing of flare release is represented
by the phenomena ok, so no over-specification requirement issue arises.

ARGUMENT & EVIDENCE: This is covered by the Pilot Domain Description and the
validation as described above.

The first application of the PPT has removed the Pilot domain as detailed in
the problem transformation step PS3 above. The removal of the domains AS, SP and DS are detailed in the problem transformation steps represented by PS4, PS5 and PS6 respectively that are contained in Appendix B.

After four applications of the PPT to remove the Pilot, AS, SP and DS domains the requirement is transformed into R4:

R4a The DM shall decide which flare to select by observing a field in the con message it receives. The DM shall obtain the selected flare information from this field in the con message, and use it in its sel message to the DU to control the flare selection in the DU.

R4b The DM shall observe the con message it receives and issue a fire? command if commanded. The DM will request the SC to send the fire command. This shall be the only way in which a flare can be released.

R4c The SC shall cause a flare to be released by issuing a fire command to the DU, which will fire the selected flare.

R4d The SC shall only issue a fire command if its interlocks, represented by int, are satisfied, i.e. II observes input air = yes, II observes input out = yes and II observes pilot input of ok = yes.

R5 The DC shall mitigate H1 & H2 (Target: safety critical 10^-7 fpfh).

and the software problem is transformed into \( P_{\text{red}} \):

\[
P_{\text{red}} : \quad DU(\text{fire}, \text{sel})_{\text{fire,sel}}, \quad II(\text{ok})_{\text{int,ok,air,out}}, \\
DM_{\text{con,fire}}, \quad SC_{\text{int,fire}} \quad \vdash \quad R4_{\text{fire,sel}} \quad \wedge \quad \text{Assump}
\]

where Assump. is the conjugated collection of assumptions from each PPT application.
In PF problem diagram form, $P_{\text{Red}}$ is as shown in Figure 5.2. At this point the remaining domains are all adjacent to the SC and also adjacent to the requirement $R_4$. Due to the detailed (over-specified) nature of the requirement used in this example, the requirement phenomena associated with $R_4$ relate directly to the domain phenomena visible by the SC. Therefore, the specification of the SC can now be derived directly using the $P_{\text{Red}}$ entailment and thus satisfying property [NecessaryP]. Note that by applying a further REQUIREMENT INTERPRETATION transformation the requirements phenomena (fire, fire?, sel, air, ok, out) can be directly related to their corresponding domain phenomena (int, fire, fire?, sel) through the requirement $R_4$.

![Figure 5.2: DC Problem after PPT, $P_{\text{Red}}$](image)

A problem with the DC case study development is that the effect of a domain and the causal chain phenomena associated with this effect were not clearly distinguished. For example, when applying the PPT to remove the Pilot domain (refer to problem transformation step PS3 on page 115) the causal chain control phenomena $\text{ok}$ appears in the before and after requirement statements. The requirement $R'd$ contains the clause "Pilot has issued an allow a release command ($\text{ok} = \text{yes}$)" , which indicates that $\text{ok} = \text{yes}$ corresponds to the pilot's intention to allow flare release. However, the latter fact was established from the Pilot Domain Description and is not really pertinent to the requirements at this point. In reality, the $\text{ok} = \text{yes}$ term was added because the specifier knew the system well and was tempted to add too much detail and thus over-specify. Similar issues surround the other domains.

The specification could be derived after step PS6 because the requirement is more detailed than necessary. The over-specification is indicated by the fact that
the requirement refers to phenomena and domains that are not adjacent to it, but
are embedded in the problem (e.g., $R' b$ from section 4.3 refers to fire? and DM). A
useful check that can be derived from this is that a requirement is at an appropriate
level of abstraction if it refers to domains and phenomena that are adjacent to it – if
it refers to domains or phenomena that are embedded in the problem then it is too
detailed. This relates to the Right Abstraction property identified in section 2.5.

5.2 Safety Analysis Improvement [LateI3]

The earlier PSA work reported in section 4.4 made use of a combination of FFA to
identify hazards and functional FTA to investigate them. The FFA was applied to
the main system functions and the results obtained from this analysis were found
to be adequate, but the process used did not make full use of the capabilities of
the model derived from the POSE software problem description. Specifically the
model explicitly identifies the domain phenomena and how they inter-relate, and
this information is not directly used in the FFA. Further, FFA has a number of
strengths and weaknesses. Its main strength is that it can be readily applied to
many situations. Its major weakness is that it is only likely to be 80% effective
at detecting the issues of interest [90]. This suggests that it should be used in
conjunction with other, diverse techniques such that the combination is likely to be
more effective than just FFA alone. The availability of the phenomena information
indicates that a HAZOPS style [6, 106] of analysis based on applying the guide-
words to the phenomena might be more apposite for this analysis task. This section
will consider how FFA, HAZOPS and FTA can be used in combination to achieve
an effective safety analysis process to support the PSA; it will then use this safety
analysis process on the PSA re-applied to the DC case study. It will also consider
how safety analysis can be used as part of a formal development. The goal is to
ensure that the safety analysis is effective in support of the issue [LateI3].
5.2.1 Improving the Preliminary Safety Analysis Process

The aim of this section is to consider how the model formed by the POSE software problem description can be used to support the PSA task. First the model will be used to improve the PSA on a non-formal development, and then the use of the model to support the PSA on a formal development using Alloy will be considered.

5.2.1.1 Improving a Non-Formal PSA

Consider the possible hazardous failure modes in a domain $D$ that relates to another domain $SC$ through the phenomena:

\begin{align*}
a & : \text{controlled by } SC, \text{ observed by } D \\
b & : \text{controlled by } D, \text{ observed by } SC.
\end{align*}

These entities are shown in Figure 5.3 along with the failure space of the domain $D$. The failure space of domain $D$ is split into four distinct regions:

1. $D$ fails but not Hazardous
2. $D$ fails Hazardous not related to $a$
3. $D$ fails Hazardous related to $a$
4. $D$ fails & this causes $b$ issue

The failures in the first region are not hazardous, so these failures are not considered further. The failures in the second region are hazardous and are caused by internal phenomena in domain $D$. These failures can be detected by applying an FFA to domain $D$’s functions. However, this identifies the hazard but not which phenomena caused it. Understanding the causality can be important when trying to identify an appropriate mitigation strategy, and FFA on its own does not provide this information.
The failures in the third and fourth regions involve the relationship between the domain $D$ and the domain $SC$ and their shared phenomena $a$ and $b$. The possible causes of hazardous behaviour in $D$ are as follows:

- an anomaly in $SC$ processing of $a$ can cause $a$ to cause hazardous behaviour in $D$
- an anomaly in $D$ can cause $b$ to cause an issue in $SC$ which results in $a$ causing a hazard in $D$
- an anomaly in $SC$ processing of $b$ can result in $a$ causing a hazard in $D$.

These anomalies that cause hazardous behaviour in $D$ involve the domains $D$, $SC$ and their phenomena $a$, $b$. However, as noted above, the relationship between the domains and the phenomena is not explicitly covered by an FFA.

It appears that an improved safety analysis could be obtained if the relationship between the domains and their shared phenomena is analysed in detail. This suggested the use of a HAZOPS style of analysis based on applying the guide words to the phenomena. A proposed set of HAZOPS guide words is shown in Table 5.1.

The first seven Guide Words in Table 5.1 are the "classic" words used in the original Chemical Industries applications of the HAZOPS technique [6], the last four are added to deal explicitly with computer processing and real-time processing systems. In theory, the last four could be covered by the original words (e.g. Early could be covered by Part Of), but it assists and improves the analysis task to make them explicit. These four words are usually included in the analysis of computer-based systems [124].
Table 5.1: HAZOPS Guide Words

<table>
<thead>
<tr>
<th>Word</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>No/None</td>
<td>No part of the intention achieved</td>
</tr>
<tr>
<td>More</td>
<td>Quantitative increase in a physical property</td>
</tr>
<tr>
<td>Less</td>
<td>Quantitative decrease in a physical property</td>
</tr>
<tr>
<td>As Well As</td>
<td>All intentions achieved, but with additional effects</td>
</tr>
<tr>
<td>Part Of</td>
<td>Only some of the intention is achieved</td>
</tr>
<tr>
<td>Other Than</td>
<td>A result other than the intention is achieved</td>
</tr>
<tr>
<td>Reverse</td>
<td>The exact opposite of the intention is achieved</td>
</tr>
<tr>
<td>Early</td>
<td>Intention occurs before it should in time</td>
</tr>
<tr>
<td>Late</td>
<td>Intention occurs after it should in time</td>
</tr>
<tr>
<td>Before</td>
<td>Intention happens before it should in sequence</td>
</tr>
<tr>
<td>After</td>
<td>Intention happens after it should in sequence</td>
</tr>
</tbody>
</table>

Table 5.2: HAZOPS Applied to int

<table>
<thead>
<tr>
<th>Word</th>
<th>Local Effect</th>
<th>System Outcome</th>
</tr>
</thead>
<tbody>
<tr>
<td>No/None</td>
<td>int not active when it should be</td>
<td>No defensive release</td>
</tr>
<tr>
<td>No/None</td>
<td>int active when it should not be</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>As Well As</td>
<td>fire active &amp; int fails active</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>Part Of</td>
<td>intermittently active int</td>
<td>May delay or inhibit defensive release</td>
</tr>
<tr>
<td>Part Of</td>
<td>intermittently inactive int</td>
<td>May result in inadvertent release</td>
</tr>
<tr>
<td>Other Than</td>
<td>int value indeterminate</td>
<td>DR: if int indeterminate then fail-safe to inactive</td>
</tr>
<tr>
<td>Reverse</td>
<td>N/A</td>
<td>N/A</td>
</tr>
<tr>
<td>Early</td>
<td>int value active before it should</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>Early</td>
<td>int value inactive before it should</td>
<td>No defensive release</td>
</tr>
<tr>
<td>Late</td>
<td>int set active later than it should</td>
<td>Release delayed</td>
</tr>
<tr>
<td>Late</td>
<td>int set inactive later than it should</td>
<td>Possible inadvertent release</td>
</tr>
<tr>
<td>After</td>
<td>int after fire? and sel</td>
<td>No release when expected</td>
</tr>
<tr>
<td>Before</td>
<td>int before fire? and sel</td>
<td>Expected behaviour</td>
</tr>
</tbody>
</table>

As an example, consider the application of HAZOPS to the Decoy Controller model of Problem P_{Red} in Figure 5.2. Consider applying the guide words to the phenomena int. The results are shown in Table 5.2.

The HAZOPS analysis is more detailed and more specific than the FFA, and highlights the relationships between causes and the system effects they excite. For example, in Table 5.2 the second entry for Late is concerned with "int set inactive later than it should be". The system effect is a possible inadvertent release. The phenomena int should be set inactive when one of the interlocks air, ok or out becomes inactive. It is potentially hazardous to allow a release when any of these interlocks are not set to indicate it is safe to release. Therefore a delay in setting int from active to inactive could cause a hazard because a release could occur (since
int is active) even though one of the interlocks indicates that release should be inhibited. Therefore, an int Late anomaly can cause an inadvertent release, and the effect inadvertent release is directly associated with its cause int set inactive later than it should be by the analysis.

The advantage of the HAZOPS analysis direct cause to effect relationship is that it facilitates the identification of possible mitigations strategies. For example, in the case when fire is active and then int fails active (it should be inactive, inhibiting releases) then this would result in an inadvertent release. A typical mitigation is to require that a release can only occur if int was active prior to the fire request command, otherwise release is inhibited. Therefore with this mitigation int failing active after a fire would not cause a release. There would also need to be ongoing BIT (built in test) to identify the int failure and to then inhibit releases until it has been rectified.

The goal of the HAZOPS is to cover all possible anomalous behaviours of the system under analysis by careful application of the guide words. Implicit in the analysis approach is the assumption that if the HAZOPS is properly organised then the guide words can cover all the possible anomalous behaviours. This is supported by experience of using the technique on many applications [6, 106]. Further, the use of a diverse team of experts coordinated by an experienced moderator skilled in the use of HAZOPS maximises the chances that the can cover all is actually achieved.

A process for using FFA, HAZOPS and FTA in combination was developed as follows. The FFA was used to identify the hazardous behaviours of a domain (and cover internal phenomena) and HAZOPS applied to the phenomena shared between domains (based on the POSE model). Then FTA was used to investigate specific entities of interest identified by the FFA and HAZOPS work.
5.2.1.2 Improving a Formal PSA

The work on the DC case study has demonstrated that POSE can be used with the traditional safety analysis techniques such as FFA and FTA to achieve useful results. However, using POSE in combination with a formal technique opens up further opportunities for integrating the modelling with the safety analysis task to achieve a significant improvement in the safety analysis capabilities of the development.

Inductive techniques such as FFA are often used to identify possible hazards. In a formal analysis simulation would be used to achieve the same result. The goal of the formal development in this work is to use the POSE problem model to derive a formal behaviour equivalent using Alloy [52].

As noted above, completeness in the HAZOPS on a POSE model relates to the careful application of the guide words to the interface phenomena. In the formal model this translates into selecting representative values of the interface phenomena in time and space that will drive the behaviour of the system through its range of significant, possible behaviours. These behaviours are then checked to identify any problem cases which can be investigated using the proof tools. Fortunately, Alloy models are finite and the models developed from the POSE software problems are reasonably compact with small enumerations, which places an upper limit on the size of the analysis task. The role of the guide words in HAZOPS is to cover all possibilities, in the POSE/Alloy modelling the exhaustive nature of the simulation ensures the coverage/completeness goal is satisfied to a known degree.

The alternative approach is to use the Alloy proof capabilities to check specific safety issues. This is equivalent to a deductive analysis like FTA, and yields a proof that the Alloy specification model satisfies the specified proof condition. This is very strong, powerful, evidence to support the safety case, but does require that suitable proof conditions are identified a priori. Also, it is not always straight-forward to represent the required logic conditions adequately in the Alloy language. In practice,
the proof conditions are based on the high level safety analysis requirements.

In summary, formal analysis of the model can be tailored to achieve similar results to traditional safety analysis techniques, but with the added power of formal analysis and proof. However, as noted by Turski, there is always care needed to relate the formal results to the reality of the real world.

5.2.1.3 Safety Analysis Summary

This section has identified a process that allows FFA, HAZOPS and FTA to be used in combination to achieve an effective safety analysis using the POSE software problem model as its basis. The use of this process is evaluated in the DC case study safety analysis presented in section 5.2.2. This section also indicated how formal analysis could be used to achieve safety analysis based on proof and simulation. The use of formal techniques will be covered in the SMS case study covered in section 5.5.

5.2.2 Safety Analysis of the DC

A PSA using FFA and FTA was applied to the model $P_{E_{np}}$ in section 4.4 and the results are recorded in the PS2 problem transformation step. The application of the PPT has removed domains and simplified the model to $P_{Red}$ and this has been used to derive a specification for the DC. The aim of this section is to evaluate the usefulness of performing the PSA after the simplification on the model $P_{Red}$, and using the combined analysis process of FFA, HAZOPS and FTA described in section 5.2.1.1. Note that the same model used for the derivation of the specification $P_{Red}$ is also used for the PSA – thus providing support for property [SameA1].

FFA was applied to the function of each of the domains, and this include consideration of any internal behaviour functions and phenomena. Then HAZOPS was applied to the shared phenomena between domains and some of the interesting results for the SC domain are shown in Table 5.3.
Table 5.3: HAZOPS Summary for the SC

<table>
<thead>
<tr>
<th>Id</th>
<th>Guide</th>
<th>Effect</th>
<th>Outcome</th>
</tr>
</thead>
<tbody>
<tr>
<td>H1</td>
<td>No/None</td>
<td>No fire?</td>
<td>Release inhibited</td>
</tr>
<tr>
<td>H2</td>
<td>No/None</td>
<td>No int</td>
<td>Release inhibited</td>
</tr>
<tr>
<td>H3</td>
<td>No/None</td>
<td>No fire?</td>
<td>Release inhibited</td>
</tr>
<tr>
<td>H4</td>
<td>As Well As</td>
<td>Continuous fire?</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>H5</td>
<td>As Well As</td>
<td>Continuous fire</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>H6</td>
<td>Part Of</td>
<td>Intermittent fire</td>
<td>Could inhibit release</td>
</tr>
<tr>
<td>H7</td>
<td>Part Of</td>
<td>Intermittent fire</td>
<td>Could inhibit release</td>
</tr>
<tr>
<td>H8</td>
<td>Part Of</td>
<td>Part of int not set</td>
<td>Release inhibited</td>
</tr>
<tr>
<td>H9</td>
<td>Early</td>
<td>fire? when not required</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>H10</td>
<td>Early</td>
<td>fire when not required</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>H11</td>
<td>Late</td>
<td>fire? when not required</td>
<td>Inadvertent release</td>
</tr>
<tr>
<td>H12</td>
<td>Late</td>
<td>fire when not required</td>
<td>Inadvertent release</td>
</tr>
</tbody>
</table>

The hazardous outcomes are shown in bold. The results were more comprehensive than those obtained using just FFA and FTA on $P_{Exp}$, and included all the hazards found from that analysis which were further investigated using FTA as before. The results demonstrated for this example that the combination of FFA, HAZOPS and FTA was effective.

A functional FTA applied to $DM$ (based on the model of Figure 5.2) and using the HAZOPS problem cases (H4, H5, and H9 - H12) indicate that a failure in the uP (systematic or probabilistic) could result in the fire? failing on, which results in the same outcome as described in section 4.4. It is repeated here for completeness. The Pilot’s allow input provides some mitigation, but as soon as this is set ($ok = yes$) a flare will be released, which is undesirable behaviour. In other words, with this system architecture, $H_2$ is only protected by the Pilot’s allow input. If fire? failed on, then as soon as the Pilot indicated an intention to allow flare release, by selecting the switch, then the flare would be released, which is not the design intention. Therefore this safety analysis (as in the PSA reported in the PS2 of section 4.4) indicates that fire? needs to have a safety involved (not critical) integrity. The current design does not satisfy the safety requirements.

Another advantage shown by this work was applying the PSA to the reduced model $P_{Red}$ and its simpler domain structure made the safety analysis task easier.
The original analysis had to trace through the effects of the domains that have now been removed, which complicated the analysis task. The tracing through in the original analysis was informal. In contrast, tracing through to determine an outcome is still required for the reduced model, but the assumptions associated with each problem progression make this task more systematic and easier to apply.

The conclusion after the PSA is that the current system architecture is not a suitable basis for the rest of the development.

5.3 Traceability and Backtracking: [TraceI4]

Traceability is a crucial feature of safety development practice (as discussed in section 3.2.3) and safety standards such as DS 00-56 [125] and the DO-178B [108] guidelines have stringent requirements with respect to demonstrating traceability from the requirements, through the design and onto the testing and analysis that validates the requirements.

A summary of a POSE development can be presented in graph form as [41, 85] where the nodes represent problems and the arcs are justifications of the groups of transformations that lead to the problems. In this work the transformations are grouped into problem transformation steps (henceforth steps) so each node is also a step in the development process — similar groupings are used in [41, 85]. This step information and the requirement associated with it can be annotated onto the graph to provide a richer representation of the development path where each node identifies:

- the software problem name
- the problem transformation step name
- the requirement that results from the step
and as before the arc is the justification that enables the step changes. For example, the graph for the DC problem development up to this point is shown in Figure 5.4. For instance, the tracing of the development of the requirement required by safety standards can be traced through the nodes and the strength of the argument to support the transformations evaluated by inspecting the justifications on the arcs. In Figure 5.4 the last step in the graph (PS6) produced $P_{red}$ and includes the PSA which demonstrated that the selected system architecture was not a suitable basis for the rest of the development – i.e. it is a dead-end in the development path.

The result of reaching a dead-end is the need to iterate back to evaluate alternative architectures, but guided by the knowledge of why the original architecture failed. A graph for the DC development is shown in Figure 5.6. The dead-end in the development records why a path has failed – useful information for any subsequent maintenance or upgrade phases to avoid repeating the mistake. In addition, the graph assists the task of finding out where to iterate back to. For example, in the DC graph of Figure 5.6 the reason for the dead-end at step PS6 was that the architecture failed the PSA and the iteration (as shown) is back to the point where the architecture was introduced, the start of PS2 in the right-hand path of the figure.

The design of the modified system architecture can be undertaken using the POSE AStruct. In the original development the II and DM were existing components and only the SC had to be designed (see section 4.3); in the modified
architecture both the SC and DM' need to be designed, so this is a codesign problem as outlined in [41]. The PSA identified that the fire? phenomena should have a safety involved integrity, and the preferred architecture solution was to separate out the fire? functionality from the non-safety involved timing and BIT functionality. The modified AStruct that supports this has the form:

\[ Decoy\text{ContAS}'[\text{Int}_{\text{ok,air,con}}](\text{DM}_{\text{con}}^{\text{fire}}, \text{SC}_{\text{int,fire}}^{\text{fire}}). \]

In fact this is a simple codesign problem as the shared phenomena do not change, i.e., the redesign is internal to the DM' as shown in Figure H.2 in the problem transformation step PS2' shown below. A PSA was applied at step PS6' and the results were successful.

---

**PS2': Backtracked application of Solution Interpretation AND Expansion to P_{initial}**

**JUSTIFICATION J_2':** The newly identified system architecture, its components and relevant properties are summarised below (where they differ from J_2):

![Diagram of Modified DM' Architecture](image)

**Figure 5.5: Modified DM' Architecture**

The architecture consists of a message buffer (MB), a field programmable gate array (FPGA [49]) and a microcontroller (uP) as shown in Figure H.2. The message buffer MB holds the received control message con; the micro-controller uP decodes it to extract the selected flare type (leading to sel); the FPGA component decodes it to extract a fire command request (leading to fire?).
CLAIM: The choice of candidate solution architecture exhibits sound safety engineering judgement

ARGUMENT & EVIDENCE: The chosen system architecture is similar to the previous one (see J2) except that as a result of the PSA we require the fire? signal to be safety involved (but not safety critical) so as to allow the overall architecture to satisfy its safety target. We do this by taking the safety involved functions out of the uP component and route them through a separate high integrity path. As a result, we choose a new component DM' in which there is a partition between the safety and non-safety elements: the simple safety functions (those associated with the fire? request) are routed separately through MB and FPGA, while the other complex functionality is routed through MB and uP. This means that only MB and FPGA, which have simple functionality, have to be designed to a safety related standard.

CLAIM: The chosen solution architecture does not prevent the satisfaction of R.

ARGUMENT & EVIDENCE: The safety analysis (PSA) is applied to the revised system architecture and is successful - the is claim is supported.

Another benefit is that the graph shows what steps need to be repeated. In this case five steps need to be repeated, but this process is assisted by the fact that much of the information from the earlier analysis can be re-used. The second iteration of the POSE process is similar to the first: although there is new information associated with the revised system architecture, the remainder of the transformations may be carried across from the first iteration with minimal change (just change of name), simplifying this second (and any subsequent) iteration. The second candidate architecture differs from the original in that we replace DM with higher integrity component DM'. The problem transformation development step is shown in PS2' and its associated annotated problem transformation graph is shown as the
right-hand path in Figure 5.6, where apart from $P'_{Exp}$ the others are equivalent, e.g., $P_{Red1}$ is the same as $P'_{Red1}$ apart from a name change caused by introducing the prime character (i.e., $DM$ to $DM'$) and so on. The left-hand sequence in Figure 5.6 shows the original graph, backtracking to the PS2 step (on the right-hand side) after the unsuccessful PSA.

![Figure 5.6: DC Revised Problem Transformation Trace Sequence](image)

5.4 DC Case Study Discussion

The repeated application of the PPT using the process detailed in section 5.1.2 allowed the domain structure to be simplified, which facilitated the safety analysis task - supporting the properties of Simplification and [SameA1], as the same model $P_{Red}$ was used for the safety analysis as for the development. The fact that
similar results were obtained from the earlier more complex safety analysis and
the safety analysis based on the reduced problem $P_{\text{Red}}$ gives some strong evidence
to support the validity of the problem progression process. In fact in the more
complex analysis task the analyst had to work through the domain behaviour links
in an informal manner. With the PPT, the domains are removed systematically and
the necessary behaviour captured as assumptions. This was found to facilitate the
analysis task by providing a structured trace between the domains, and was superior
to the informal approach used earlier.

The DC high level functional requirement represented by $Ra$ to $Rd$, are appro-
priate in that they refer to phenomena in the environment – i.e. they address the
problem, not the solution. However, the goal is to design an SC that can satisfy
these requirements. As shown in section 5.1.1, this requires the requirements to
be made feasible, and section 5.1.2 demonstrated that the POSE PPT was capable
of achieving this goal. $P_{\text{Red}}$ is the simplified software problem after repeated ap-
plication of the PPT to the DC system, and inspection of requirement $R4$ in PS6
(see Appendix B.3) shows that the derived functional requirements ($R4a$ to $R4d$)
concerned with the SC are expressed in terms of phenomena directly accessible to
the SC. That is, the derived requirements in $R4$ are feasible and can be directly im-
plemented. Inspection also shows that the specification can now be derived directly,
supporting the properties [NecessaryP] and Spec. Join.

The combination of FFA, HAZOPS and FFA using the process outline in sec-
tion 5.2.1.1 provides an effective analysis that produces comprehensive results when
applied to a POSE software problem model, providing support for the effectiveness
of the safety analysis aspects of issue [LateI3].

The POSE problem transformation graph is a useful mechanism for identifying
the steps involved in the development, tracing the requirements as they are trans-
formed through the steps, and locating where to backtrack to when a dead-end is
reached in a particular development path. As noted in the DC case study example,
only the step PS2 needed to be updated to form PS2', the other steps could be re-used (apart from the name change). This means that this POSE problem transformation graph provides the early phases of IPDP with a useful iteration facility, as well as providing evidence for mitigating [TraceI4].

In summary, DC case study has provided support for the properties [NecessaryP], [SameA1], Simplification and Spec. Join; and the issues [LateI3] and [TraceI4].

5.5 Combining POSE and Alloy [FormalA2]

This section investigates how POSE can be used with a formal method to provide a high integrity development process in support of property [FormalA2], and how this combination can provide an improvement to an existing safety critical development process based on Z [116] and embedded into the IPDP described in Chapter 3. As introduced in Chapter 2 a requirement was that the formal modelling must support simulation and proof in support of the property Validation. Moreover it must be compatible with Z - given that the original development team were experienced in its use. This suggested the use of the B method [111] or Alloy [52].

Alloy was selected as the tool is freely available and well supported. Alloy is a lightweight formal method developed from the goal of combining the power of a SAT (Boolean satisfiability) solver with the descriptive power of the Z language. It has an active and growing user community and is continuously being developed and enhanced. It has strong simulation and proof capabilities within well-defined limits, and allows complex behaviour to be modelled using clear, simple constructs. As such, it fits well as the modelling tool for use with the POSE transforms.

The case study was concerned with examining the use of the POSE/Alloy combination in improving the early life cycle phase performance of a Z-based safety critical development process used in the author's Company (see section 3.4.2). The original
validation process correctly identified some subtle anomalies with the definition in Z of the high level safety properties, but these were found late in the process and led to substantial changes. The role of this case study is to address the safety questions:

(a) could these anomalies have been discovered earlier using POSE and Alloy, and

(b) would they have been discovered earlier by following a reasonable process based on POSE and Alloy.

In this context, a reasonable process is one in which nothing special or specific is done to identify the anomalies.

The main focus of this case study is the use of POSE in combination with Alloy to address the property [FormalA2]. Therefore the development of the problem steps will be summarised in the main text, with the detail being presented in Appendix D.

5.5.1 The Case Study

The case study investigated in this section is based on a Stores Management System (SMS) and focuses on its selective jettison (SJ) functionality, i.e., the way in which stores are chosen for jettison from the aircraft. Figure 5.7 shows a schematic view of the six release/jettison stations on the aircraft wings together with the SJ panel which is used by the pilot to make jettison selection choices. The Pilot can select SJ to be off, or jettison of all stations (Ship mode) or jettison of selected stations (Station mode).

The SJ sequence does not release all the stores at once, as this could result in a collision hazard, rather the step release sequence used is Out → Mid → In with a delay between each step. That is, the SJ is not an atomic action, but rather a sequence of three atomic actions. A balance algorithm is applied to most jettison sequences to ensure that the aircraft is not put into an unsafe state. The exception is that a single store jettison is always allowed to give the pilot final control under error conditions.
The above information and more is collated as part of the application of the SPS1: Initial Problem problem transformation step using a similar approach to that described in section 4.2 for the DC case study. This captures understanding the environment context, the requirements and the initial system architecture in agreement with the early phases of IPDP. Note that as with the DC case study, the requirements are based on those that were originally presented and have not been put into a good practice form (the case study in Appendix H shows requirements in an appropriate good practice form). The resulting SPS1 problem transformation step is presented in Appendix D and leads to the initial software problem of:

\[ P_{Initial} : S&RE(jet\_stat)_{jetv}, \text{Pilot}(p\_mode, p\_sel, p\_jet)_{smode, sstat, ssj}, \]
\[ SMS(InAir)_{jetv, smode, sstat, ssj} \vdash R^{jet\_stat}_{p\_mode, p\_sel, p\_jet, InAir} \]

In this case study care was taken to ensure that the requirements were at an appropriate level of abstraction using the approach outlined in section 5.1.3 whereby a check was applied to ensure that each requirement referred to phenomena that were adjacent to it.

The next step involves exploring possible solution system architectures and follows a similar format to that used on the DC case study in section 4.3. The result
is the problem transformation step SPS2 reported in Appendix D, which leads to the software problem:

\[
P_{\text{Exp}} : S & RE(jet\_stat)_jetv, \; \text{Pilot}(p\_mode, p\_sel, p\_jet)_{smode, sstat, ssj}, \; SP(InAir)_{invec}_{smode, sstat, ssj}, \; SU_{jetv}, \; SM_{outv} \vdash R'_{jet\_stat, p\_mode, p\_sel, p\_jet, InAir}
\]

The step from \( P_{\text{Initial}} \) to \( P_{\text{Exp}} \) also transforms the requirement from \( R \) to \( R' \) as shown in the model. The PF diagram form of this model is shown in Figure 5.8.

![Figure 5.8: SMS Expanded Problem, \( P_{\text{Exp}} \)](attachment:figure.png)

### 5.5.2 Simplification Through Problem Progression

Inspection of the software problem \( P_{\text{Exp}} \) shows that there is a gap between the requirements \( R' \) and the machine to be designed, \( SM \) (see also Figure 5.8). The requirements phenomena are \( cons = (jet\_stat), \; InAir, \; ref = (p\_mode, p\_sel, p\_jet) \), whilst the \( SM \) phenomena are \( invec, outv \). This indicates the need to apply the PPT to simplify the problem to support the PSA and transform the requirements to be in terms of the \( SM \) phenomena so that the specification of the \( SM \) can be derived. The first domain to be removed is the \( Pilot \) – it fits the criteria of being adjacent to the requirements. It is shown in detail as SPS3 in Appendix D. At this point, after removing the \( Pilot \) domain, the software problem has been transformed into:
Note that the requirements have been transformed from $R'$ into $R_1$, all the SPS3 claims are successfully discharged, and that as in the earlier problem transformation steps, these claims and their discharge evidence correspond to important elements of the safety case argument.

So far the domain removals have all been reference-type PPTs since they cover input data into the system. The six $S&RE$ domains are different as they represent the output of the system (the actual release of stores) and are therefore constrain-type PPTs. Although there are six $S&RE$ domains, they are identical in functionality and can be treated as a single parametrisable domain in terms of applying the PPT to effect domain removal. The problem transformation step SPS4 follows a similar format to SPS3 and covers the $S&RE$ domain removals. The details of these PPT applications are presented in Appendix D, where the requirements transformation from $R_1$ to $R_2$ is presented in some detail to demonstrate the steps involved. This simplification work provides further support for property Simplification.

The software problem model after removing the $S&RE$ domains is given by:

$$P_{Red} : SP(smode, sstat, ssj, InAir)^{invec}, SU(jetv)^{outv}, SM^{invec} \leftarrow R_2^{jetv}_{smode, sstat, ssj, InAir}$$

and this corresponds to the requirement $R_2$. The PF diagram form of this problem is shown in Figure 5.9.

The sequence of problem transformation steps to proceed from the initial problem $P_{Initial}$ through to the reduced problem $P_{Red}$ can be conveniently represented in the
problem transformation graph shown in Figure 5.10.

Figure 5.10: The SMS Problem Transformation Graph

5.5.3 Deriving and Validating the Machine Specification

The POSE model represented by problem $P_{Red}$ and its equivalent PF problem diagram form of Figure 5.9 are almost at an appropriate level of abstraction to support the safety analysis and modelling work. Inspection of these representations indicates there is still a small gap to be resolved between the requirements expressed in terms of the phenomena $jetv$, $smode$, $sstat$ and $ssj$, and the machine to be developed, $SM$, that interfaces to the phenomena $outv$ and $invec$. There is a need to relate $outv$ to $jetv$, and $invec$ to $smode$, $sstat$, $ssj$, and $InAir$.

We could apply the PPT again to remove the $SU$ and $SP$ domains, since this would relate the resulting requirement phenomena directly to the machine $SM$ phenomena. However, the resulting model is not as useful as $P_{Red}$ for the PSA work. A useful way forward is to apply REQUIREMENTS INTERPRETATION to the $SU$ and $SP$ domains to map the phenomena adjacent to the requirement $R2$ to the phenomena adjacent to the machine $SM$. If the relationship involves only Environment Constraint behaviour (i.e., the only difference between the phenomena can...
be directly resolved by reference to the behaviour of the intervening domain the phenomena map through) then this mapping can be used to derive the machine specification and to validate that it satisfies $R2$. In effect, REQUIREMENTS INTERPRETATION is applied to obtain the useful behaviours of the intervening domains which is used to establish the relationship between the machine and the requirement phenomena – this mapping works if the behaviour of the domains corresponds to the Environment Constraint non-feasible requirement. The mapping confirms the correspondence between the phenomena as $outv$ is equivalent to $jeth$ and $invec$ to $(smode, sstat, ssj, InAir)$.

In effect, $jeth$ and $outv$ are functionally equivalent representations. With these relationships established, it is now feasible to derive the specification of the $SC$ directly from the POSE entailment of problem $P_{Equiv}$, which is $P_{Red}$ with $outv$ substituted for $jeth$ and $invec$ substituted for $InAir$, $smode$, $sstat$ and $ssj$ in direct support of properties $[NecessaryP]$ and Spec. Join. The resulting problem is:

$$P_{Equiv} : SP(invec)^{invec}, SU(outv)_{outv}, SM_{invec}^{outv} \vdash R3_{invec}^{outv}$$

and the corresponding requirement, $R3$ is:

**R3a** The $SM$ shall ensure the safe selection of stores through the $SU$ phenomena $outv$ when commanded by the appropriate settings in $invec$.

**R3b** The $SM$ shall have a Selective Jettison ($SJ$) facility which will select all stores for jettison in $outv$ (Ship mode) or select specific stores for jettison in $outv$ (Station mode) from the $SU$ in accordance with $invec$.

**R3c** The $SP$ shall allow each of the six station selection positions in $outv$ to
be selected for **SJ** in accordance with the *invec*. In Station SJ mode, a station must be selected before it can be jettisoned.

**R3d** The *SP* shall have an In Air lamp indication in *invec*, which will be lit if the aircraft is in the air. **SJ** is only allowed if the aircraft is in the air.

**R3e** The *SP* shall have a **SJ** button that allows jettison to be initiated in accordance with *invec* and it must remain pressed for the duration of the jettison sequence. The following must hold prior to initiating the **SJ**:

1. **SJ** mode selected (Ship or Station) in accordance with *invec*.
2. Aircraft is in the air.
3. If Station mode, the appropriate stations are selected on the *SP* in accordance with *invec*.

**R3f** The *SM* shall control the selection of stores for jettison in the *outv* from the *SU*, by controlling the *SUs* to correctly provide conditioned power and drive signals through its output phenomena *outv*.

**R3g** The *SM* shall implement a Balance Algorithm which can remove items from an **SJ** package to ensure aircraft roll moments are contained within safe limits.

**R3h** It shall be possible to **SJ** a store from a single station without regard to the aircraft balance algorithm calculation.

**R3i** The **SJ** release sequence will be Out stores first, then Mid and then In.

At this point the phenomena of the machine *SM* are the same as the phenomena referenced by R3, which therefore represents the specification of the machine. The contribution from the *SP* domain is to confirm that *invec* directly relates to *smode*, *sstat*, *ssj* and *InAir*. The contribution from the *SU* domain is to confirm that *outv* directly relates to *jetv*. From this we have that:
Table 5.4: Definitions of outv and invec in Alloy

<table>
<thead>
<tr>
<th>outv</th>
<th></th>
<th>invec</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>(i) relp</td>
<td>Indicates a valid SJ sequence is in progress;</td>
</tr>
<tr>
<td></td>
<td>(ii) pulses</td>
<td>Defines which stations receive SJ pulses for this time instance;</td>
</tr>
<tr>
<td></td>
<td>(iii) balan</td>
<td>Indicates whether the SJ is to satisfy the balance condition.</td>
</tr>
<tr>
<td></td>
<td>(iv) fl</td>
<td>Indicates if the aircraft is in the air (air) or on the ground (grd).</td>
</tr>
<tr>
<td></td>
<td></td>
<td>(i) mode</td>
</tr>
<tr>
<td></td>
<td>(ii) sel</td>
<td>Set defining the status of the SJ station selection switches;</td>
</tr>
<tr>
<td></td>
<td>(iii) sj</td>
<td>Indicates whether the SJ Button has been pressed;</td>
</tr>
</tbody>
</table>

\[ \text{spec.}(R3) \land \text{domaincontrib.}(SU) \land \text{domaincontrib.}(SP) \Rightarrow \text{requirement}(R2). \]

Therefore the validation step is to demonstrate that the specification (R3) in combination with the domain contributions from SU and SP leads to the requirement (R2). Inspection of R2, R3 and the domain contributions confirmed the validity step informally. The next task was to develop a formal model and use formal analysis to confirm this validity step.

5.5.4 Development of the POSE/Alloy Model

The Alloy formal model was derived directly from the POSE problem $P_{\text{equiv}}$ and the first task was to define the outv and invec phenomena as Alloy variables. These are defined as in Table 5.4.

The phenomena balan (indicating whether the balance algorithm has been applied to the SJ package) is an implicit modelling parameter that is not an input to the SU. It is included in outv because it facilitates the model validation task. It is not required in the implementation because its effect is manifested in the pulses value — in fact its value can be derived from analysing the pulses value.

As noted earlier, the SJ sequence does not release all the stores at once, as this could result in a collision hazard, rather it releases stores in the step sequence Out → Mid → In with a delay between each step. This is captured by the requirement R3i and the use of cnt in the Alloy model. That is, the SJ is not an atomic action, but rather a sequence of three atomic actions in sequence.

If a set of heavy stores were jettisoned from only one wing, the aircraft would
be subjected to a potentially lethal roll moment. To avoid this problem, jettison packages (including Ship) are subjected to a balance algorithm calculation, which can remove items from the SJ package to ensure that the aircraft remains within safe roll moment limits. This is captured as requirement R3g. Store on Station (SoS) indications are used to signify if a store is present or not, these are used by the balance algorithm to make its calculations. However, it is recognised that these SoS indications could fail in such a way as to fool the balance algorithm. In particular, this might result in the balance algorithm inhibiting a jettison of a store when in fact jettisoning the store could result in a more benign residual roll moment. To counter this problem, the Pilot is allowed to SJ a single store, irrespective of the Balance algorithm. This is captured as requirement R3h.

The requirements specification Alloy model of the SM was developed directly from the POSE model, using the same interface and phenomena as used in \( P_{\text{equiv}} \). It is shown in full in Appendix E. The functionality of this Alloy model was based on the information collected in support of the POSE problem transformation step development from SPS1 through to SPS4 (it includes the domain description information and the existing Z specifications). In Alloy terms [52], the SM module makes use of an extension to the standard Alloy Natural numbers utility file. The extension just involves defining terms for Two to Ten, in addition to the Zero and One already provided. The full Alloy specification is outlined in [52], so the following presents the main points of the model relevant to our case study.

The signature (set) type definitions are based on an abstract set, with distinct single subsets. A typical definition for the type SJMode is shown below:

abstract sig SJMode {}
one sig off, ship, stat extends SJMode {}

where off and ship correspond directly to there respective SJ mode switch settings and stat corresponds to station mode. Similar definitions were defined for (a) SSet
{son, soff} to represent the SJ button and whether a valid jettison release pulse is allowed, (b) StatsSel {s0, s1, s2, s3, s4} where each sn covers a particular SJ switch station selection set, (c) InAir {air, grd} to represent the In Air indication, (d) SPu1 {p0, p10, p01, p2} to represent the jettison release pulse patterns, and (e) BAL {nob, no_bal, is_bal} to represent if the SJ package is required to satisfy the balance algorithm. Where nob represents not applicable, no_bal represents balance algorithm not applied and is_bal means the balance algorithm is applied to the SJ package. These types are used to define the overall state of the SM as follows:

\[
\text{sig SMState} \{ ntime : \text{Natural}, \\
\text{mode} : \text{SJMode}, \quad \text{repl} : SSet, \\
\text{seis} : \text{StatsSel}, \text{pulses} : \text{SPu1}, \\
\text{sj} : \text{SSet}, \text{balan} : \text{BAL}, \\
\text{fl} : \text{InAir}, \quad \text{cnt} : \text{Natural} \} \
\]

In SMState ntime represents the system simulation time reference and is modelled as a natural number, and cnt is a local time counter used for timing the SJ release sequence. Effectively, the other state components on the LHS are inputs from the SP and were defined using the SP! invec phenomena from the POSE model. The other RHS state components are outputs to the SU defined using the SM! outv phenomena. The repl = son means it is valid to provide SJ pulses, and pulses defines the pattern of pulses to be output at this time (note p0 means no pulses output). The initial conditions are defined by the predicate init [], which places the system in a known safe state. This is an important aspect of any system development and it also satisfies the initialisation concern identified by Jackson [53].

\[
\text{pred init} (\text{sm: SMState}) \{ \text{sm.mode=off} \&\& \text{sm.seis}=s0 \&\& \text{sm.sj}=soff \&\& \text{sm.fl}=grd \&\& \text{sm.ntime}=\text{Zero} \&\& \text{sm.repl}=soff \&\& \text{sm.pulses}=p0 \&\& \text{sm.balan}=\text{nob} \&\& \text{sm.cnt}=\text{Zero}\} \\
\]

The trace model used is based on that used in Chapter 2 of [52] and involves using a linear ordering to order the traces with init as the first trace. In the following the
InVec() represents the input vector to the SM and Stim() represents the simulation
time increment predicate. The trace timing simulation covers five slots from Zero
through to Four. This can be extended as required.

fact traces {
  init[smss/first[]]
  all sm: SMState-smss/last[] | let sm'=smss/next[sm] | some m: SJMode, sel: StatSel, s: SSet, f: InAir |
  (InVec[sm.ntime,Zero,m.stat, sel,s0,s.soff,f.grd] & Stim[sm,sm'] & SMfun[sm,sm',m,sel,s,f]) or // 1
  (InVec[sm.ntime,One, m.stat, sel,s0,s.soff,f,air] & Stim[sm,sm'] & SMfun[sm,sm',m,sel,s,f]) or // 2
  (InVec[sm.ntime,Two, m.stat, sel,s1,s.soff,f,air] & Stim[sm,sm'] & SMfun[sm,sm',m,sel,s,f]) or // 3
  (InVec[sm.ntime,Three,m.stat,sel,s1,s.soff,f,air] & Stim[sm,sm'] & SMfun[sm,sm',m,sel,s,f]) or // 4
  (nat/gte[sm.ntime,Four] & m = off & sel = s0 & s = soff & f = air & SMfun[sm,sm',m,sel,s,f]) }

The behaviour of the SM is defined by the predicate SMfun. This sets the valid
SJ pulse indicator (sm'.relp=son), checks balance (balance(sm')) and outputs SJ
pulses in sequence (pulTab(sm')) if a valid SJ button press is detected or the SJ
sequence is still valid and continues. Otherwise, it resets the SM state to a safe
value.

pred SMfun [sm, sm' : SMState, m : SJMode, sel : StatSel, s : SSet, f : InAir] {
  (sm'.mode = m & & sm'.sj = s & & sm'.fl = f & & sm'.ssel = sel) & &
  ( ( sm.mode = stat & & sm.sels := s0 & & sm.sj = soff & & sm.fl = air & &
      m = stat & & sel = sm.sels & & s = son & & f = air)
    => sm'.relp = son & & sm'.cnt = One & & pulTab[sm'] & & balance[sm']) & &
  ( ( sm.mode = stat & & sm.sels := s0 & & sm.sj = son & & sm.fl = air & & sm.relps = sonic & &
      m = stat & & sel = sm.sels & & s = son & & f = air)
    => sm'.relp = sonic & & sm'.cnt = incnt[sm.cnt] & & pulTab[sm'] & & balance[sm']) & &
  ( ( not(s = stat & & sel := s0 & & sel = sm.sels & & s = son & & f = air)
    => sm'.relp = soff & & sm'.cnt = Zero & & sm'.pulses = p0 & & sm'.balan = nob &)
  )
}

The function incnt() increments cnt, except if cnt is Three when it resets it to
One. The predicate pulTab() is used to define the SJ pulse sequence timing, with
sm.cnt=One corresponding to SJ from the Out stations, Two from Mid and so on.
By varying the content of the s1 to s4 definitions, the complete range of SJ package

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selections can be covered – the full definition of PulTab() is given in the Alloy code in Appendix E.

pred pulTab [sm : SMState] {

    /* s1 -- Port Out & Starboard In selected for SJ */
    (sm.sels = s1 && sm.cnt = One => sm.pulses = p01) &&
    (sm.sels = s1 && sm.cnt = Two => sm.pulses = p0) &&
    (sm.sels = s1 && sm.cnt = Three => sm.pulses = p10) &&

    /* similar definitions for S2, S3 and S4 */

    /* s0 -- No stores selected for SJ */
    (sm.sels = s0 => sm.pulses = p0) }

The balance algorithm is covered by the predicate balance(), where if there are one or zero SJ pulses, then no balance (no_bal) otherwise balance is required.

pred balance[sm : SMState] { sm.relP = son &&
    ((sm.pulses = p10 or sm.pulses = p01 or sm.pulses = p0) => sm.balan = no_bal
    else sm.balan = is_bal ) }

5.5.5 Model Validation and PSA

Having produced the formal Alloy model of the specification (R3) – the full model shown in Appendix E – the next step is to validate that this model does satisfy R3. That is, we need to validate that the Alloy model adequately represents the specification R3. This was achieved by performing a variety of simulation runs, where each run used a different combination of InVec() values to explore the behaviour of the model over its range of inputs. The results validated that the Alloy model satisfied the specification given by R3.

The next task was to validate that the validated specification R3 (represented by the Alloy model) in combination with the useful behaviours (domain contributions)

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from the SU and SP satisfied the requirement represented by \( R2 \). This being part of the process of validating that the machine specification \( R3 \) satisfies the original requirement \( R \) (as described in section 5.1.2).

The useful behaviour relations (domain contributions) of the domains SU and SP are introduced into the Alloy model as Alloy facts (using Alloy "fact" construct and model structure respectively) since they represent indicative properties of the environment context. In contrast, the optative behaviour of the requirement, \( R2 \) is introduced using predicates, and these predicates were proved using the Alloy "Assert" mechanism. The end result was validation that the specification \( (R3) \) satisfies its requirement \( (R2) \).

After validating that the Alloy model adequately represented the specification, and then validating that this specification satisfied its requirement, there is now enough supporting validation evidence to make it reasonable to apply the PSA. The PSA task has two main components to cover the complex functionality aspects represented by the Alloy model, and the more straightforward behaviour of the existing hardware components. The latter are addressed using the non-formal approach outlined in section 5.2.1.1, and is not considered further in this case study work. The complex behaviour is addressed using the approach outlined in section 5.2.1.2 and this work concentrates on these issues. Simulation was used to investigate the behaviour of the model looking for cases that violated one of the safety requirements. For example, consider the original requirement for \( Rg \) (see Appendix D):

\( Rg \) The SMS shall implement a Balance Algorithm which can remove items from an SJ package to ensure aircraft roll moments are contained within safe limits.

qualified by \( Rh \) which always allows a single SJ. From these can be derived a hazard "Multiple station SJ \( (Rh \) not active) but balance not applied \( (Rg \) issue)".

Simulation of the Alloy model using the \( s1 \) station selection set (refer to In-Vec() definition above) indicated that balan = no_bal for this set. However, \( s1 \)
is a multiple SJ—Port Out and Starboard In, so the release pulse sequence should be p01;p0;p10 for cnt of One, Two and Three respectively—so balance should be applied. Simulating with other station selection sets indicated that balance was only applied when more than one pulse was required at a particular time (i.e. p2) and only for that time. The required behaviour is that balance should always be applied unless the SJ package consists of a single release (a single p10/p01 with two p0s). The problem occurs in the high level Z specification of the SM, which contains the term:

\[(\#\text{releaseLocations} > 1 = \theta \text{SM} \in \text{balanced})\]

where \# means the cardinality of the set and \(\theta \text{SM}\) means the bound values of SM. Now releaseLocations is the number of jettison pulses being applied—this is modelled in Alloy by the function balance(), which specifies no balance only if there are zero (p0) or a single (p10/p01) pulse. The problem is that (as noted above) SJ is not an atomic action, but rather three: one each for Out, Mid and In. The functionality given above ensures each atomic action satisfies the balance, but does not ensure the entire SJ sequence does. Hence selection set s1 which results in the pulse sequence p01;p0;p10 meets the criteria for each of its atomic components, indicating that the model does not require it to be balanced, when it should be. The solution is to base the balance calculation on the SJ station selection and not the jettison pulses. Implementing this change, results in balance() being updated as follows:

\[
\text{pred balance}\text{[sm : SMState]}\} \text{ { sm.relP = son &} }
\]

\[
(\text{sm.sels = s4 or sm.sels = s5}) \Rightarrow \text{ sm.balan = no_bal}
\]

\[
\text{else sm.balan = is_bal }
\]

Simulating with this form resulted in the correct behaviour for s1 and the other selection set combinations. Aspects of this behaviour were then proved.

Other safety issues were addressed in a similar fashion, and the modelling iden-
tified the further known anomaly and a not previously identified one. The latter concerned an inconsistency between two of the Customer supplied requirements documents. In all these cases the implementation was checked and it was confirmed that it operated as intended. That is, the problem was with the requirements specification.

An alternative approach would have been to represent the hazard as a logical assertion and use the model to prove whether the model does or does not satisfy the condition. This is the second part of the formal safety approach described in section 5.2.1.2.

5.6 Discussion

The early work in the chapter has shown that the POSE PPT can be usefully applied to transform requirements to make them feasible and allow the specification $S$ to be derived in direct support of property [NecessaryP] and also support for Spec. Join. This was supported with evidence from the case study work, where the DC case study (section 5.1.3) demonstrated the derivation and validation of the specification using non-formal techniques, whilst the SMS case study (section 5.5.3 onwards) did the same for a formal model, this validation providing support for the property Validation and mitigation of issue [ValidI6]. The formal model provided stronger validation evidence, but there is always an extra step corresponding to the need to relate the formal model to reality. In the SMS case study this involved the need to confirm that the Alloy model did represent the specification represented by $R3$.

In Chapter 4 the safety analysis was conducted on a more complex model involving all the domains (e.g. compare $P_{Exp}$ and Figure 4.2 with $P_{Red}$ and Figure 5.2) and relating the events at the machine interface to corresponding events at the system boundary involved establishing informal relationships. The advantages of the
PPT-based approach of this chapter are that the analysis is easier because a simpler model is used, and the effect at the system boundary can be established by tracing through the relevant domain assumptions, which are established and validated as part of the PPT application.

Application of the PPT transforms complex problem descriptions into simpler ones, therefore the PPT application provides support for the property Simplification. It provides other benefits, for example, the discussion about the DC case study in section 5.4 noted that an improved safety analysis and feasible requirements can be achieved through application of the PPT. The information gathered about what a domain contributes to the overall system function so that it can be successfully removed is just the information necessary to complete the validation of a successful analysis. The PPT gathers this information in a systematic way that provides the traceability required by the safety standards and guidelines and thus provides some mitigation for issue [TraceI4]. The traceability aspects are further enhanced by the use of annotated problem transformation graphs as described in section 5.3. A problem transformation graph was used in section 5.5.2 to depict the progress of the application of the problem transformation steps in the SMS case study.

Processes for improving the PSA using non-formal and formal techniques were introduced in section 5.2. These were used to support the PSA in both the DC and the SMS (section 5.5.5) case studies – providing mitigation for the effective safety analysis aspect of issue [LateI3].

In both the DC and the SMS case studies the same model used for the development, the POSE software problem model, is also used for the safety analysis which provides evidence to support property [SameA1]. The case study work also introduced a check to ensure that the requirement was at an appropriate level of abstraction, providing support for the property Right Abstraction. This was used successfully in the SMS case study.
The SMS case study work agrees with the earlier case study that POSE is flexible in use, and integrates well with the overall development process – IPDP in this case. This ability to work with existing development processes is important, because it supports the evolution and improvement, rather than the replacement, of these processes. This is in line with the goal of improving the ‘normal’ design, and avoids the damaging ‘radical’ design cycle [131]. It also addresses the property [IntegA3] identified in section 3.4.5, and property Integrates from Table 2.3, of improving and integrating well with IPDP.

The task of using the POSE/Alloy combination to improve the front-end of a safety critical development process asked two questions. The first, and easiest to address, was whether the POSE/Alloy combination could detect the anomalies. The SMS case study results demonstrate that both POSE and Alloy can be used in combination to detect the anomalies of interest, and thus provides direct support for property [IntegA3]. The second question is whether the POSE/Alloy combination would have detected these anomalies. This is more difficult to answer because it is a process question. A plausible answer can be gleaned from the development of the POSE model from SPS1 through to SPS4, and then the use of this model to produce the Alloy model described in section 5.5.4. This work shows that POSE and Alloy were used as recommended and found the anomalies of interest. This imparts a certain degree of confidence that the process used with the POSE/Alloy combination would be able to detect these and similar anomalies, and at an early phase in the development life cycle. Therefore technically the POSE/Alloy combination could and would be expected to provide the required process improvement for the safety critical development process.

The development of the formal model in section 5.5.4, and the results obtained in section 5.5.5 of the SMS case study also demonstrate strong support for property [FormalA2].

In summary, completion of the DC case study and the results of the SMS case
study both provided strong evidence to support the properties [NecessaryP], Spec. Join, Validation, [ValidI6], Simplification, [TraceI4], [SameA1], Right Abstraction, [IntegA3], Integrates and [FormalA2], and some support for issue [LateI3]. Also, the early problem transformation steps in the SMS case study provided further support for the issues [EnvirI1] and [RequI2], and for properties Context, Architecture, Avoid Bias and Model Reality as discussed in Chapter 4 for the DC case study.

5.7 Chapter Summary

The chapter began with an introduction to the POSE PPT (Problem Progression Transformation), developed a process for applying it and then showed how it could be used to derive a specification $S$ by transforming high level requirements into feasible requirements that apply directly to the machine to be developed. The completion of the DC case study and the results of the SMS case study provided examples of the successful use of the PPT to derive $S$ and also to facilitate the safety analysis task which used the same POSE model – providing evidence to support the properties [NecessaryP] and [SameA1]. The SMS case study also showed that POSE could support a formal development process as required by the safety critical standards and also in support of property [FormalA2].

The traceability and backtracking (iteration) capabilities of POSE were developed in section 5.3 and shown to be effective at managing the backtracking required in the DC case study, providing evidence to support [TraceI4]. The case studies also demonstrated the usefulness of the safety process improvements investigated in section 5.2.

In summary, this chapter has developed some of the POSE capabilities such that there is now evidence that this expanded POSE is capable of addressing many of the properties and issues identified earlier - these results are summarised in Table 5.5.
as shown below. As before the top portion of Table 5.5 refers to the capabilities identified in section 2.5, the lower portion to the issues and properties summarised in section 3.4.5. The meaning of "E", "ee" and "e" is as defined in section 4.6.

<table>
<thead>
<tr>
<th>Property/Issue</th>
<th>Previous Work</th>
<th>Chapter 4</th>
<th>Chapter 5</th>
</tr>
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<tr>
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<td>[41, 87]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Architecture</td>
<td>[41, 87]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Avoid Bias</td>
<td>[39]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Model Reality</td>
<td>-</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Validation</td>
<td>-</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Simplification</td>
<td>[41, 87]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Tool Support</td>
<td>[35, 87]</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>Right Abstraction</td>
<td>[41, 87]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Integrates</td>
<td>[88]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>NecessaryP</td>
<td>[41, 83]</td>
<td>-</td>
<td>e</td>
</tr>
<tr>
<td>SameA1</td>
<td>[88]</td>
<td>e</td>
<td>ee</td>
</tr>
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<td>[41, 88]</td>
<td>-</td>
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<td>-</td>
<td>e</td>
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</tr>
<tr>
<td>Envir11</td>
<td>[87, 88]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
<td>Requ12</td>
<td>[87, 88]</td>
<td>e</td>
<td>ee</td>
</tr>
<tr>
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<td>[85, 88]</td>
<td>-</td>
<td>e</td>
</tr>
<tr>
<td>TraceI4</td>
<td>[85, 88]</td>
<td>-</td>
<td>e</td>
</tr>
<tr>
<td>IncomI5</td>
<td>-</td>
<td>-</td>
<td>-</td>
</tr>
<tr>
<td>ValidI6</td>
<td>[88]</td>
<td>-</td>
<td>e</td>
</tr>
</tbody>
</table>

Table 5.5: Evidence Status for POSE after Chapter 5
The contribution of this thesis so far to the knowledge concerning POSE and its use is summarised in Table 5.6. The “Reference” column refers to section numbers unless otherwise stated.

<table>
<thead>
<tr>
<th>Property</th>
<th>Contribution Description</th>
<th>Reference</th>
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<tbody>
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<td>NecessaryP</td>
<td>Demonstrated support by POSE PPT process</td>
<td>5.1.2, 5.1.3, 5.5.5</td>
</tr>
<tr>
<td>Spec. Join</td>
<td>Demonstrated support by POSE PPT process</td>
<td>5.1.2, 5.5.3, 5.5.5</td>
</tr>
<tr>
<td>Validation</td>
<td>SMS case study supports property</td>
<td>5.1.3, 5.5.5</td>
</tr>
<tr>
<td>Valid16</td>
<td>DC and SMC case study support</td>
<td>5.1.3, 5.5.5</td>
</tr>
<tr>
<td>Late13</td>
<td>DC and SMC case study support</td>
<td>5.2.2, 5.5.5</td>
</tr>
<tr>
<td>Simplification</td>
<td>Demonstrated support by POSE PPT process</td>
<td>5.1.2, 5.5.2, 5.5.5</td>
</tr>
<tr>
<td>Trace14</td>
<td>Showed trace&amp;iteration mitigation</td>
<td>5.3</td>
</tr>
<tr>
<td>SameA1</td>
<td>Showed PSA uses same model as Development</td>
<td>5.1.3, 5.5.5</td>
</tr>
<tr>
<td>Right Abstraction</td>
<td>SMS case study supports property</td>
<td>5.1.3, 5.5.1</td>
</tr>
<tr>
<td>IntegA3</td>
<td>SMS case study supports property</td>
<td>5.5.1</td>
</tr>
<tr>
<td>Integrates</td>
<td>SMS case study supports property</td>
<td>5.5.1</td>
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</tr>
<tr>
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<td>SMS case study initial steps</td>
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</tr>
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<td>Requi12</td>
<td>SMC case study initial steps</td>
<td>5.5.1</td>
</tr>
<tr>
<td>Architecture</td>
<td>SMS case study initial steps</td>
<td>5.5.1</td>
</tr>
<tr>
<td>Context</td>
<td>SMS case study supports property</td>
<td>5.5.1</td>
</tr>
<tr>
<td>Avoid Bias</td>
<td>SMS case study supports property</td>
<td>5.5.1</td>
</tr>
<tr>
<td>Model Reality</td>
<td>SMS case study supports property</td>
<td>5.5.1</td>
</tr>
</tbody>
</table>

Table 5.6: Thesis Contribution Summary after Chapter 5
Chapter 6

Further Process Improvement Using POSE

The aim of this chapter is consider how POSE can address the three items currently outstanding as indicated by Table 5.5. The first task is to demonstrate how POSE can improve support for the early application of preliminary safety analysis to provide mitigation for [LateI3]. The second task is to investigate what support POSE can provide for the issue [IncomI5] and the third is to consider Tool Support. The investigation will be conducted through the use of an Audio Warning System case study, which, as we will see, will also provide additional evidence for the properties and issues already addressed in earlier chapters, and further demonstrate the use of POSE in support of a formal process that is suitable for a safety critical system development.

6.1 A POSE Safety Pattern Identified: [LateI3]

Inspection of the DC case study of sections 4.2 – 4.3 and the SMS case study of section 5.5 shows a definite recurring sequence of problem transformation steps emerging for covering the early requirements engineering stages of a system develop-
ment. This sequence of events was also identified in other case study work conducted by the author at the Company, but not reported here. For example, the first problem transformation step in both the DC case study (PS1 on page 91) and the SMS case study (SPS1 on page 244) was concerned with understanding the system problem, the environment and the requirement. Further, the second problem transformation step (PS2 for the DC and SPS2 for the SMS) was concerned with identifying an appropriate solution architecture and expanding the problem context to include it. The subsequent problem transformation steps (e.g., PS3 to PS6 for the DC case study) were concerned with applying the PPT to simplify the problem to facilitate both the PSA and the derivation of the machine specification of the machine to be designed. This sequence of problem transformation steps can be captured by the following activities:

1. **Initial Problem Understanding**: used to capture increasing knowledge and detail in the context (i.e., the environment into which the solution will be introduced) and requirement of the problem.

2. **Solution Interpretation and Expansion**: the choice and subsequent structuring of the solution according to a candidate solution architecture. Domain knowledge and experience are used to investigate potential solution architectures (logical and/or physical), and the most promising candidate is selected to transform the problem. This involves an expansion step which requires the introduction of architectural features that are known to have a high likelihood of success.

3. **Problem Simplification**: the removal of domains by repeated application of the PPT with the goal of simplifying the problem structure to focus on the machine domain to be designed. This simplification facilitates the specification derivation and validation, and the safety analysis tasks.
Figure 6.1: The POSE Safety Pattern

4. **PSA Feasibility Check**: the application of safety analysis techniques to the POSE model resulting from the simplification task to ensure a feasible solution architecture has been chosen.

These activities can be put together in what we define as the POSE safety pattern (Pattern, for short), which is captured by the UML activity diagram of Figure 6.1. The choice point (labelled 4) uses the outcome of the PSA to determine whether:

- PSA OK: the current architecture is viable as the basis of a solution; or
- PSA Not OK: backtracking and (re-)development of the problem (Activity 1) and/or another candidate architecture (Activity 2) is required.

The Pattern is iterative, ending when the PSA of a validated specification that satisfies its safety requirements is achieved.

The Pattern has evolved through its development but has retained the same basic form. The earliest form was presented in [87] and included an additional requirements interpretation task prior to the PSA. After further development of the POSE transformations the POSE safety pattern was modified by the removal of this additional task and the inclusion of a PSA activity that combined the problem simplification and the safety analysis tasks – this was the form used in [88].
combined PSA task that mixed the PPT with the PSA activity was not really satisfactory and this resulted in a further modification to the Pattern to its current form. This modification has the virtue that the POSE transformations and the PSA are distinct. That is, in the current pattern shown in Figure 6.1, Activities refer to POSE problem transformation steps, whilst the decision diamond represents the PSA.

Validation is an essential aspect of the POSE transformation process, and it is instantiated in the POSE safety pattern through the notions of justification and claim used in the problem transformation step representation (e.g. see PS1 on page 91). However, it is not explicitly represented in Figure 6.1. Validation after each step is implicit in the diagram. Ongoing work [37] has developed the process pattern further to explicitly include the validation tasks for particular problem contexts. However, the form shown in Figure 6.1 is apposite for this work to support the safety process development.

The mechanics of how to use the POSE safety pattern are represented by the diagram in Figure 6.1 and defined by the Agenda-based method description [17] (refer to section 2.3.6) shown in Table 6.1. The Validation fields in Table 6.1 are based on using IPDP, but the Description and Result fields are general. Inspection of these fields show they represent required features of any safety development process required to satisfy the safety standards and guidelines such as DS 00-56, IEC 61508 and DO-178B. Therefore the POSE safety pattern Agenda description can be readily adapted for use with other safety critical design approaches, with just the Validation fields requiring tailoring to cover the specific artefacts resulting from the actual development process used.

The POSE safety pattern was tried out on some small case study examples (not reported here) and “re-played” on the Decoy Controller and SMS case studies – refer also to Appendix H. The results obtained validated its effectiveness. The information from the IPDP sub-system theory of operation task in the Dem/Val phase is
Table 6.1: POSE Safety Pattern Agenda Description

used in the POSE safety pattern Activity 2 task to expand the architecture. The simplification (Activity 3) just uses information from the earlier steps. The latter did require clarification of some of the IPDP Dem/Val tasks to ensure that the appropriate information was always made available (ambiguity in the task description was removed). Therefore the PSA check (Activity 4) can be performed as part of the SDR work at the end of Dem/Val as desired. This fully supports the mitigation of [Late13] by allowing the safety analysis (PSA) to be performed before EMD in the life cycle. It also demonstrates that the POSE safety pattern integrates well with IPDP in support of Integrates and [IntegA3].

6.2 Remaining Issue and Property

The aim of this section is to consider what mitigation/support is or could be given to the outstanding issue of task incompleteness [Incom15] and the property of Tool Support.
6.2.1 Support for [IncomI5]

The problem transformation steps we have defined collect together basic POSE transformations into meaningful units that achieve an identifiable development task, such as problem simplification using the PPT. The POSE safety pattern organises the steps into a repeatable process pattern that covers the tasks necessary to complete the early life cycle phases of a safety development. Following the pattern/step combination ensures that all the necessary tasks are performed in the appropriate order, and this provides some mitigation for issue [IncomI5].

6.2.2 Tool Support

A proof-of-concept tool has been developed to support POSE development written in Prolog as reported in [38], but this is rather primitive and it has not been used as part of this work. Instead, the SMS case study has demonstrated that POSE works well with Alloy to produce satisfactory results, and that the Alloy formal model was derived directly from the POSE problem model and its associated information. This will be investigated further in the FAS case study considered next. Therefore, although POSE does not provide any tool support directly, this is mitigated by the ability of using POSE models within other tools, like Alloy.

6.3 Audio Warning System Case Study

The case study concerns the design of a Failure Annunciation System (FAS) that is part of the warning system on a military aircraft. The FAS provides audio warnings to the pilot if certain critical monitored systems have failed. The case study assumes that aircraft level and system level safety analyses have been completed and have allocated safety requirements to the FAS - these being H1 and H2 which are defined as follows:
H1: Inadvertent indication of the Catastrophic message.

H2: Failure to indicate the Catastrophic message.

where the catastrophic message reports a major system failure such that the pilot is required to prepare for ejection.

These two hazards do not have the same nature: hazard H1 is particularly problematic because of the action the pilot has to take if the Catastrophic message is played. As a result, it is classified as safety critical, and assigned a target failure probability of $10^{-7} \text{fpfh}$ (failures per flight hour). In contrast, hazard H2, the failure to indicate a Catastrophic message, is mitigated by other, diverse, aircraft warning systems. Hence H2 is classified only as safety related, and assigned a target failure probability of $10^{-5} \text{fpfh}$. The importance of HCI is increasingly recognised, but the ergonomic aspects are handled at the (higher) aircraft level and factored into the safety requirements. That is, at this level the pilot is assumed not to impact any allocated safety budget and to behave as trained for the purposes of operating the system to be developed.

6.3.1 POSE Safety Pattern: Activity 1

The POSE safety pattern, developed in section 6.1 and shown in Figure 6.1, was applied to the case study. The first activity in applying the pattern is Initial Problem Understanding and the tasks associated with this activity are represented in the problem transformation step WPS1 detailed in Appendix F.1. This captures understanding the environment context, the requirements and setting up the initial software problem via the AStruct as detailed in section 4.1.3. This work uses information from the IPDP CE and early Dem/Val phases. As with the DC case study the goal was to use the original requirements unmodified as far as possible to show that POSE can work with real problems, although some clarifications were incorporated to ensure that the requirements were at an appropriate level of abstraction.
6.3.2 POSE Safety Pattern: Activity 2

The second Pattern activity of Solution Interpretation and Expansion involves expanding the FAS to include a candidate solution system architecture and thus supports the property Architecture from Table 2.3. The activities associated with this task are represented in the WPS2 Step shown below and based on the PS2 Step from section 4.3. It uses information obtained from the IPDP sub-system Theory of Operation task in the Dem/Val phase.
JUSTIFICATION J2: The expanded FAS solution system architecture consists of four types of domain. The domain components in this architecture have been prototyped to show they can handle the required functionality, and the intent is to use these components in the actual design to reduce cost and risk. The initial design for the FAS is to make use of these off-the-shelf components for Failure Detection (the FD domain), for Audio Output Selection (the AO Selector domain) and for Audio Output Decoding (the AO Decoder domain), combining them together with a (still to be designed) Failure Annunciator Controller (FA) domain.

The FD receives status information from (a) the CS system via the discrete cat signal, and (b) the other SYS systems via sys. These are decoded by FD and sent to the FA via its status signal. The FD prioritises the failure data to send to the FA - cat is the highest priority.

The combined role of the AO Selector (AOS) and AO Decoder (AOD) is to output the audio signal of the message selected by the FA. The AOS is an FPGA-based device [49], containing a library of digital audio messages stored in PROM (Programmable Read-Only Memory). The AOD decodes the selected digital message and turns it into an audio wave for the speaker. If no failures are reported by the FD, then the FA sends no message request to the AOS, otherwise the FA sends out the highest priority message request.

The justification for this (architecture) solution expansion transformation, J2, is that this system architecture has been successfully prototyped and has also been used on a number of other similar developments. Therefore it is known to be capable of satisfying the functional requirements.

PHENOMENA: The new phenomena introduced by the architecture are:

messdig The selected message in digital form.

status Combined status indication of the health of the CS and other SYS systems.

sel The identifier of the message selected for playing to the Pilot.
Given the initial representation of the problem $P_{initial}$, the POSE expansion transformation results in the software problem becoming $P_{Exp}$, as shown below.

$$
P_{Exp} : CS(stat\_cat)^{cat} , SYS(stat\_sys)^{sys} , Pilot(sel\_audio)^{audio} , Speaker^{audio} ,
AOS^{messdig} , AOD^{messdig} , FD^{status} , FA^{status} \models R1^{sel\_audio}$$

The system architecture and resulting system design is shown in PF problem diagram form in Figure 6.3.

The transformed requirement $R1$ is similar to $R$ apart from the changes introduced by expanding the domains from $FAS$ to $FA$, $FD$, $AOS$, and $AOD$. This only results in a change to $R1a$, where $FAS$ is replaced by $FA$.

**R1a** When the $CS$ or a monitored system has failed, the $FA$ shall control the system to play the correct audio message to the pilot.

**R1b** Message levels shall be comfortably heard by the Pilot.

**R1c** If more than one system has failed messages shall be selected for play in the order: $stat\_cat$ fail , $stat\_sys$ fail.

**R1d** If no system failures are detected, then no message shall be played.
RS For hazards H1 and H2 defined above, their respective safety targets (10^{-7}fpfh and 10^{-5}fpfh) shall be satisfied.

CLAIM: Justification for selection of the solution architecture

ARGUMENT & EVIDENCE: This system architecture has been successfully prototyped and has also been used on a number of other similar developments. Therefore it is known to be capable of satisfying the functional requirements.

CLAIM: The choice of candidate solution architecture exhibits sound safety engineering judgement

ARGUMENT & EVIDENCE: The system architecture is chosen to maximise integrity by partitioning the functionality into simple, distinct blocks. The goal is to isolate any problems to specific blocks which will allow local mitigation. This strategy has proven successful on previous designs.

CLAIM: The Speaker is reliable

ARGUMENT & EVIDENCE: The Speaker is an integral part of the Pilot's headphones. These headphones have been in-service for many years and are known to be adequately reliable and give satisfactory performance.

CLAIM: The chosen solution architecture does not prevent the satisfaction of R. This claim is not yet supported - deferred until PSA after PPT.

6.3.3 POSE Safety Pattern: Activity 3

The third pattern activity is Problem Simplification using the PPT. The goal of this activity is to simplify $P_{Exp}$ to facilitate the safety analysis (PSA) task and allow the derivation of the specification. Domains adjacent to the requirement are removed
first, following the process introduced in section 5.1.2 - in this case the first domain to be removed will be the Pilot. The step WPS3, is detailed in Appendix F.2 and is based on the PS3 Step from section 5.1.3.

The first application of the PPT transforms the software problem from $P_{Exp}$ into $P_{Red1}$ as follows.

$P_{Red1} : \begin{align*} &CS(stat\_cat)^{cat}, SYS(stat\_sys)^{sys}, Speaker(audio)_{message}, \\
&\text{AOS}_{sel}^{messdig}, AOD_{messdig}, FD_{cat,sys}^{status}, FA_{sel}^{status} \vdash R2_{audio}^{stat\_cat,stat\_sys} \end{align*}$

At the same time the requirement is transformed from R1 into R2.

The simplification goal requires additional applications of the PPT to remove domains from the model. For brevity, these are not listed here, but are recorded in Appendix F. As the PPTs are applied, the requirements progress from R2 through to R6. As noted at the beginning of section 6.3, the Pilot does not impact the allocated safety budget. However, this is not the case for the $AOD$ and $CS$ domains removed in the problem simplification sequence, and appropriate amounts of the budget have to be allocated for them as described in Appendix F. These affects on the safety budget are reflected in $R6_S$. Inspection shows that the domain removals from Appendix F are all examples of Environment Constraint requirements. These domain removals remove the $Speaker$, $AOD$, $SYS$ and $CS$ domains and result in the reduced software problem $P_{Red}$ shown below.

$P_{Red} : \begin{align*} &AOS^{messdig}_{sel}, FD(cat, sys)^{status}, FA_{sel}^{status} \vdash R6_{messdig}^{cat,sys} \end{align*}$

This sequence of domain removals simplifies the problem structure and provides sup-
port for the property Simplification from Table 2.3. The requirement associated with this software problem, $R_6$, is presented below.

$R_6a$ When the CS or a monitored system has failed, the $FA$ shall control the system to generate the correct digital message stream sequence, $messdig$, at the output of $AOS$.

$R_6b$ Null

$R_6c$ If more than one system has failed messages shall be selected for play in the order: $cat$ fail, $sys$ fail.

$R_6d$ If no system failures are detected, then no digital message stream shall be generated.

$R_6S$ For hazards $H_1$ & $H_2$ defined above, their respective safety targets ($10^{-7}$fpfh & $10^{-5}$fpfh) shall be satisfied. (Note some of $H_1$ budget used for CS; some of $H_2$ budget used for AOD and CS, but SYS has no impact).

The reduced Warning System is shown in PF problem diagram form in Figure 6.4.

To derive an Alloy model from $P_{red}$ requires reconciliation of the requirements and domain phenomena, i.e., the relationship between them needs to be established. This could be achieved by applying the PPT to remove the $AOS$ and $FD$ domains to allow the specification to be derived, but as in the $SMS$ case study the preferred way forward (as the model is useful for the PSA) is to just apply the REQUIREMENTS
INTERPRETATION transformation to extract the relationship between the phenomena. This can be captured as the PrePSA problem transformation step below, which forms the last part of the Pattern Problem Simplification task.

The PrePSA Step manages the transformation of $P_{\text{Red}}$ into $P_{\text{Equiv}}$, which can be used to directly derive the specification of the FA and forms the basis of the PSA work.

---

**PrePSA: Application of REQUIREMENT INTERPRETATION to problem $P_{\text{Red}}$ to form $P_{\text{Equiv}}$**

**CONCERNS:** Reconciliation of the requirements and domain phenomena. The requirements $R_6$ (associated with $P_{\text{Red}}$) refer to cat, sys and messdig, whilst the FA relates to status and sel. Therefore there is a need to apply REQUIREMENTS INTERPRETATION to identify the relationship between these phenomena, as in section 5.5.3.

**JUSTIFICATION J:** Inspection of the useful behaviour relation for the AOS and FD domains indicate the logical equivalence of sel to messdig and status to cat and sys.

This is justified by identifying the useful behaviour relations (domain contributions) of the AOS and FD domains. The FD domain is a reference-type, so its effect the health status information of cat, sys is represented by status which combines the health status information in priority order. The AOS domain is a constrain-type, so its effect the digital message output stream messdig is caused by the input phenomena sel as follows. The AOS consists of a PROM which contains all the warning messages as strings of consecutive digital bytes, as shown in Figure 6.5(a). The input phenomena sel indexes into the PROM to select the message to be played. The bytes from this selected message are then output in sequence as the digital message stream messdig. Therefore status relates to cat and sys, whilst sel relates to messdig. This means that the requirements $R_6$ can be updated to $R_7$ as follows:

**R7a** When the CS or a monitored system has failed, the FA shall control the system
to select the correct message to be output.

R7b Null

R7c If more than one system has failed messages shall be selected for play in the correct priority order by status – catastrophic failures have the highest priority.

R7d If no system failures are detected, then no digital message shall be selected for output.

R7S For hazards H1 and H2 defined above, their respective safety targets (10^{-7}fpfh and 10^{-5}fpfh) shall be satisfied. (Note some of H1 budget used for CS; some of H2 budget used for AOD and CS, but SYS has no impact).

These updates allow the problem to be transformed from $P_{Red}$ into $P_{Equiv}$ as follows.

$$P_{Equiv} : AOS(sel), FD(status)^{status}, FA_{sel}^{status} \vdash R7_{status}^{sel}$$

CLAIM: The software problem $P_{Equiv}$ allows the specification of FA to be derived.

ARGUMENT & EVIDENCE: The requirement R7 uses the same phenomena as the domains, i.e., R7 is the specification. This allows the specification of FA to be derived as shown in the Alloy model development of section 6.3.4.

CLAIM: The requirements model is a valid representation of the system

ARGUMENT & EVIDENCE: Informally, R7a and the AOS contribution mean that sel and the AOS useful behaviour result in messdig, whilst R7c and the FD contribution mean that status and the FD useful behaviour result in cat, sys. This will be formally checked as part of the Alloy simulation and proof work.
6.3.4 POSE Safety Pattern: Activity 4

The PSA process developed in section 5.2 was applied to the FAS case study to check the feasibility of the design. The safety analysis used mathematical proof on Alloy models for the functional behaviour and a combination of FFA, HAZOPS and functional FTA to investigate the (hardware) random failure aspects.

6.3.4.1 Model Development

The first part of the PSA was to check and validate the functional behaviour of the system, and the simplified POSE problem, $P_{Red}$, was used to form an Alloy model of it. The model form used was a development of the style used on the SMS model of section 5.5.4, and is therefore based on the models given in Chapter 6 of [52]. In this case, the domains are modelled as individual abstract data types and the Alloy model forms a template which can be re-used to directly encode subsequent POSE requirements models. Note again that the same model used in the development ($P_{Red}$) is used as the basis for the safety analysis.

Producing the formal requirements model in Alloy has two main benefits: the requirements model can be simulated to show that it has the desired behaviour, and the individual requirements (e.g., R6a, R6c) can be encoded as predicates which can then be proved against the requirements model using Alloy's check predicate facility. The first step is to build the requirements model as discussed above, and this model is shown in full in Figure 6.6.
In the following text a reference to "#" identifies the part of Figure 6.6 being discussed. Time is modelled as a simple linear ordering using the supplied utility ordering. The interface phenomena (e.g., sel and status) are modelled as types. For example status defined at #1 in Figure 6.6, consists of catnon meaning only the CS system has failed, sysnon meaning only a SYS has failed, catsys meaning both the CS and SYS indicate failures and non meaning no failures detected. The sel (#2) and mess (#3) phenomena can be modelled similarly. The domains are defined as data types shown in #4 in Figure 6.6. The behaviour of these domains is defined using predicates which define the changes from the current time (t) to the next time (t'). These behaviour predicates are shown at #5 in Figure 6.6, where FA is represented by FABehave, FD by FDBehave and AOS by AOSBehave.

The function extract/1 (#7) defines how the FA interprets the status information from the FD. The function decode/1 (#8) translates the message selection given by sel into the appropriate message. There are two models for the FD behaviour. The first as shown in Figure 6.6 is the generic one as used in [52]. This model is good for the proof work, but is problematic for the simulation work since the user has little control over which trace behaviour is selected. To overcome this limitation a second model was introduced which allows control over the time range when phenomena were selected – this is an evolution of the time model used in the SMS case study of section 5.5.4. This second model uses the function trange(t, lower, upper] to set phenomena values over times ranging from lower to upper, and is shown below.

```
pred FDBehave (t,t' : Time) { trange[t, 0, 1] => FDSame[t,t']
   else trange[t, 2, 4] => (FD.status.t' = catnon )
   else trange[t, 5, 6] => (FD.status.t' = non )
   else trange[t,7,9] => (FD.status.t' = sysnon )
   else trange[t,10,11] => (FD.status.t' = non )
   else trange[t,12,13] => (FD.status.t' = catsys )
   else trange[t,14,15] => (FD.status.t' = non )
   else trange[t,16,24] => (FD.status.t' = catnon )
   else trange[t, 25, 26] => (FD.status.t' = non )
   else FDSame[t,t'] }
```

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The function \textit{trange[]} (#6 in Figure 6.6) uses the fact that time is modelled as a linear ordering, so the function \textit{prevs[]} can be used to effectively "count" the previous time instants. This allows the range of values to be set up as required, e.g. \textit{trange}[t,2,4] \Rightarrow FD.status.t' = \text{catnon} is true if \( t \) is in the range from 2 to 4, and sets \( FD.status.t' \) to \text{catnon} over this range.

The trace behaviour (#9) is defined using the function \textit{init[]} and the fact \textit{traces{}} and follows the model presented in [52]. The function \textit{init[]} places the system in a known safe state (satisfies the initialisation concern). The simulation is run by invoking the predicate \textit{show1} (#10) which runs through this trace behaviour.

### 6.3.4.2 Model Validation

The \textit{SMS} case study formal modelling work showed that the simulation was quicker to set up but the exhaustive testing was time consuming. In contrast the proof took longer to set up but gave stronger results more quickly. This suggested using the simulation to set up the model, and then use proof to complete the validation and to check any safety properties. In addition, any problem areas identified by analysis of the safety requirements could be investigated using simulation. This was the approach adopted on this \textit{FAS} case study.

The model was developed to support the PSA, so it is based on \( P_{\text{Red}} \) and its associated phenomena (and also the PF diagram shown in Figure 6.4). The problem \( P_{\text{Equiv}} \) was used to derive the specification (\( R7 \)) of the machine to be designed, \( FA \), and this was checked using simulation runs. The rest of the model (including \( AOS \) and \( FD \)) was then checked also using simulation runs. At this point there was enough confidence in the behaviour of the model developed in section 6.3.4.1 to begin proof validation.

The first proof task was to demonstrate that the model of \( FA \) satisfied its specification \( R7 \). This required the sub-parts of \( R7 \) to be encoded into Alloy as "Assert" statements. These were carefully reviewed to ensure they were accurate (to ensure
open util/ordering[Time] as Ti

sig Time {}

ft## Define Phenomena #1#

sig OK {}

one sig yes, noo extends OK {}

sig Status {} // Covers FD input cat, sys or no message
one sig catnon, sysnon, catsys, non extends Status {} //#1

sig Sel {} //##
one sig m1, m2, m3, n1 extends Sel {} //#2

sig Mess {} // Covers AOS output messdig
one sig mes1, mes2, mes3, noni extends Mess {} //#3

// ## Define Domains ##

one sig FA { sel : Sol -> Time } {}

one sig FD {status : Status -> Time} {}

one sig AOS {mes : Mess -> Time} {}

// ** DEFINE OPERATIONS **

prod FABehave(t, t': Time) { FA.sel.t' = extract(FD.status.t] } //#6

prod FDBehave (t, t': Time) {FD.status.t' = catnon or FD.status.t' = catsys or FD.status.t' = sysnon or FD.status.t' = non} //#6

prod AOSBehave (t, t': Time) { AOS.mes.t' = decode[FA.sel.t] } //#6

// ** Define the Trace Model **

prod trans (t: Time, ts: Time, ti: Time) {#prevs[t] >= ts && #prevs[t] =< ti} //#6

fun extract[st : Status] : Sel { (st = catnon or st = catsys) -> m1 else st = sysnon -> m2 else n1} //#7

fun decode[s : Sel : Mess] { a- 21 > mes1 else a- m2 -> mes2 else noni} //#8

// ** Define the Trace Model **

prod init (t : Time) {FD.status.t = non && FA.sel.t = m1 && AOS.mes.t = noni}

fact traces { init[Ti/first[]] all t : Time - Ti/last[] | let t' = Ti/next[t] | FABehave[t, t'] && FABehave[t, t'] && AOSBehave[t, t'] } // #9

// **## PROPERTIES ##**

prod show1() {} run show1 for 16 but 5 int //Set bit width to cover -16 to +15

assert Rsa (all ti, t2 : Time |
(t1 in prevs[t2] && FD.status.t1 = catnon && ti = prev[prev[t2]] => AOS.mes.t2 = mes1) &&
(t1 in prevs[t2] && FD.status.t1 = catsys && ti = prev[prev[t2]] => AOS.mes.t2 = mes1) &&
(t1 in prevs[t2] && FD.status.t1 = sysnon && ti = prev[prev[t2]] => AOS.mes.t2 = mes1) &&
(t1 in prevs[t2] && FD.status.t1 = non && ti = prev[prev[t2]] => AOS.mes.t2 = noni)}

check Rsa for 16 but 5 int

Figure 6.6: Audio Warning System: Original AOS

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the model represented reality). The "Assert" statement to represent $R7a$ is shown below.

```
assert $R7a$ {all $t_1$, $t_2$ : Time |
  ($t_1$ in prevs[$t_2$] & FA.sel.$t_1$ = $m_1$ & $t_1$ = prev[$t_2$] => AOS.mes.$t_2$ = mes$1$) &
  ($t_1$ in prevs[$t_2$] & FA.sel.$t_1$ = $m_2$ & $t_1$ = prev[$t_2$] => AOS.mes.$t_2$ = mes$2$) &
  ($t_1$ in prevs[$t_2$] & FA.sel.$t_1$ = $n_i$ & $t_1$ = prev[$t_2$] => AOS.mes.$t_2$ = non$1$)
}
```

check $R7a$ for 16 but 5 int

The first term in $R7a$ states that if $t_1$ is one time unit before $t_2$, and if $FA.sel$ is $m_1$ at time $t_1$ then the message, $AOS.mes$, that is sent at time $t_2$ must be $mes_1$. Now, $FA.sel.t_1=ml$ means that the FD has reported a cat failure to the FA at time $t_1$. From $R6a$, this requires the FA to select the correct message for output (via $AOS$). Inspection of the Alloy model at #7 indicates that $m_1$ corresponds to cat being detected, and this in turn corresponds to $mes_1$ being sent to the $AOS$ (via #8). Therefore, the model selects $mes_1$ in response to a cat failure being reported ($catnon$ or $catsys$), it selects $mes_2$ if $sys$ ($sysnon$) is reported and it selects nothing ($non_i$) if no failures ($ni$) are reported. This agrees with the requirement $R7a$ and was validated by the proof of assert $R7a$.

A similar "Assert" was developed for $R7c$ involving combinations of $FD.status.t_1$ and $FA.sel.t_2$, and this was also validated by proof. These two proofs also covered $R7d$.

The second proof task was to validate that the PSA model represented by $P_{Red}$ satisfied its requirement, $R6$. This covers the validation that the specification, $R7$, and the useful behaviours of the domains $AOS$ and $FD$ satisfy the requirement $R6$.

The Alloy "Assert" statement to cover $R6a$ is shown below.

```
assert $R6a$ {all $t_1$, $t_2$ : Time |
  ($t_1$ in prevs[$t_2$] & FD.status.$t_1$ = catnon & $t_1$ = prev(prev[$t_2$]) => AOS.mes.$t_2$ = mes$1$) &
  ($t_1$ in prevs[$t_2$] & FD.status.$t_1$ = catsys & $t_1$ = prev(prev[$t_2$]) => AOS.mes.$t_2$ = mes$1$) &
  ($t_1$ in prevs[$t_2$] & FD.status.$t_1$ = sysnon & $t_1$ = prev(prev[$t_2$]) => AOS.mes.$t_2$ = mes$2$) &
  ($t_1$ in prevs[$t_2$] & FD.status.$t_1$ = non & $t_1$ = prev(prev[$t_2$]) => AOS.mes.$t_2$ = non$1$)
}
```

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check R6a for 16 but 5 int

The first term in R6a states that if t1 is two time units before t2, and if FD.status is catnon at time t1 then the message, AOS.mes, that is sent at time t2 must be mes1. Now, FD.status.t1=catnon means that the CS has reported a cat failure to the FD at time t1. From R6a, this requires the FA to select the correct message for output (via AOS). Inspection of the Alloy model at #7 indicates that m1 corresponds to cat being detected, and this in turn corresponds to mes1 being sent to the AOS (via #8). Therefore, the model selects mes1 in response to a cat failure being reported (catnon or catsys), it selects mes2 if sys (sysnon) is reported and it selects nothing (noni) if no failures (ni) are reported. This agrees with the requirement R6a and is validated by the proof of assert R6a. It is worth noting that R6a also validates requirement R6c concerning message priorities and requirement R6d concerning selecting no messages if no failures are detected.

In summary, this work has validated that the machine specification represented by R7 satisfies its requirement represented by R6.

The functional safety requirements of the system represented by problem $P_{Red}$ are covered by the sub-parts R6a to R6d of R6; the non-functional safety aspects are represented by R6S. Therefore the validation proof of "Assert R6a" also validates that the functional safety aspects of the PSA are satisfied - so no specific safety property proof work was required. In addition, further simulation work was undertaken to check the behaviour using intermittent cat health problems to confirm the model behaved correctly in the presence of rapid input changes. The results were satisfactory, and supported the proof work.

The second part of the PSA was to check the random failure characteristics of the proposed system. The FFA and HAZOPS were applied as described in the improved non-formal safety analysis of section 5.2.1.1. Functional FTA was then used to analyse if the events identified by the FFA and HAZOPS satisfy the targets.
Table 6.2: AOS Safety Analysis Results

<table>
<thead>
<tr>
<th>Id.</th>
<th>Failure Mode</th>
<th>Haz.</th>
</tr>
</thead>
<tbody>
<tr>
<td>F1</td>
<td>Plays no messages - no Cat fail when required.</td>
<td>H2</td>
</tr>
<tr>
<td>F2</td>
<td>Plays Cat fail message too late.</td>
<td>H2</td>
</tr>
<tr>
<td>F3</td>
<td>Plays wrong message - inadvertent Cat fail.</td>
<td>H1</td>
</tr>
<tr>
<td>F4</td>
<td>Plays wrong message - no Cat fail when required.</td>
<td>H2</td>
</tr>
<tr>
<td>F5</td>
<td>Plays too loud - Pilot switches system off.</td>
<td>H2</td>
</tr>
<tr>
<td>F6</td>
<td>Plays too softly - Cat fail not heard.</td>
<td>H2</td>
</tr>
</tbody>
</table>

contained in R6S. For reasons of brevity we summarise only the main elements of the AOS analysis to demonstrate the process followed. The significant results from applying the FFA and HAZOPS analysis to the AOS are shown in Table 6.2, where each functional failure is associated with the hazard it excites.

FTA, applied to the original AOS system architecture (refer back to Figure 6.5(a)), with F1 to F6 as the top events, was used to establish if the architecture can satisfy its targets. F3 is dominated by the known failure rate of the FPGA that would implement the AOS functionality. This indicates that the failure rate for F3 is $3 \times 10^{-7}$ fpfh \(^1\) which, therefore, does not satisfy the target for H1. Therefore the random failure part of the PSA has identified problems with the design. The result is that the FPGA AOS component will need to be re-thought in order to meet all safety requirements.

The PSA as recorded above was completed after the Pattern Activity 3 Problem Simplification, which in turn was completed at the end of the IPDP Dem/Val phase when all the necessary information was available. This meant the PSA results were used to support the SDR.

\(^1\)The manufacturers specification for the FPGA indicates a gate failure rate of $3 \times 10^{-7}$ per hour of operation. A pessimistic view is adopted that a single gate failure will cause the effect of concern, F3.
6.3.5 POSE Safety Pattern: Backtracking

The POSE development sequence so far is captured by Figure 6.7 as a problem transformation graph. This sequence is notable in that, from the PSA, $P_{Red}$ has no solution, so we must backtrack the development to the point at which the system architecture was introduced, and continue afresh. The architecture was introduced as part of WPS2 to form problem $P_{Exp}$. Therefore, from the diagram, it can be seen there is a need to backtrack to the end of WPS1, after problem $P_{Initial}$.

![Figure 6.7: The Audio Warning Problem](image)

The PSA problem concerns the expected reliability of the AOS FPGA and the fact that if it goes wrong then there is nothing the FA can do about it. A number of solution candidates were considered and the selected solution candidate involved including a derived requirement, $DR$, as follows:

Each message will have a unique identifier and if the selected message identifier does not correspond to that of the currently playing message, then audio must be inhibited, audio otherwise being allowed.

To implement this derived requirement it is necessary to update the functionality of the FA and the AOS domains, and that these domains share the appropriate information concerning messages, message identifiers and the need to mute messages. This is another example of a codesign problem as outlined in [41].

Inspection of $P_{Red}$ shows that the available phenomena are messdig, sel, status, cat and sys. None of these are suitable carriers for the required information to...
support the derived requirement. That is, the information required to implement the derived requirement is not shared between the pertinent domains – this is an example of the Unshared Information non-feasible requirement identified in section 2.4.

Therefore to implement DR it is necessary to introduce additional shared phenomena between the FA and AOS domains and to appropriately update the functionality of these domains. This results in a modified FPGA AOS component that is developed to: include sending back the message identifier of the currently playing message to the FA in a status message; and add a mute input to the FA control that allows the FA to mute audio output if the message identifier does not tally with the required message to be played. The changes to the AO Selector (AOS') are shown in Figure 6.5(b).

The information gained through WPS1 is re-used, the change occurs at the expansion stage in WPS2 where the additional phenomena id, mute and the derived requirement DR are introduced into the problem. These changes are captured by transforming WPS2 into WPS2'. The fact that much of WPS2 is re-used can be seen from inspection of the WPS2' step shown below.

\[
\text{WPS2': Application of Solution Interpretation and Expansion to problem P_initial}
\]

\text{JUSTIFICATION J_2': The justification description is same as that in WPS2 (refer to page 163) together with the description of the additional phenomena id, mute, and the derived requirement DR given above.}

The justification (J_2') for the revised system architecture has two parts and is that:
(a) this basic architecture structure has been successfully prototyped and has also been used on a number of other similar developments. Therefore it is known to be capable of satisfying the functional requirements. (b) "the original POSE development sequence was infeasible because it did not satisfy the safety requirements; the revised architec-
ture can satisfy both the functional and safety requirements". That is, the revised justification includes the original pruned part of the sequence and its shortcomings (the issue identified with F3 by the PSA of the original development sequence shown in Figure 6.7), as a rationale for selecting the revised architecture that now includes id, mute, and DR.

PHENOMENA: The phenomena introduced by the architecture are as in WPS2 with the further addition of id and mute.

Given the initial representation of the problem $P_{\text{initial}}$, the POSE expansion transformation results in the software problem becoming $P_{\text{Exp'}}$, as shown below.

\[
P_{\text{Exp'}} : \begin{align*}
CS(\text{stat_cat})^{\text{cat}}, & \quad SYS(\text{stat_sys})^{\text{sys}}, \quad \text{Pilot}(\text{sel_audio})^{\text{audio}}, \quad \text{Speaker}^{\text{audio}}_{\text{message}}, \\
AOS_{\text{sel,mute}}^{\text{messdig, id}}, & \quad AOD^{\text{message}}_{\text{cat,sys}}, \quad FD_{\text{status}}^{\text{stat,sys, id}}, \quad FA_{\text{sel,mute}}^{\text{status, id}} \quad \vdash \quad R_{1}^{\text{sel, audio, mute}}_{\text{stat_cat, stat_sys, id}}
\end{align*}
\]

The transformed requirements $R_{1}'$ are the same as $R_{1}$ apart from the addition of $DR$.

The claim/argument combinations same as WPS2 on page 163, apart from addition of the following claim.

CLAIM: Requirements $R_{1}$ with $DR$ are consistent

ARGUMENT & EVIDENCE: Comparison of $DR$ with $R_{1}$ indicates potential issue with $R_{1a}$ concerning the playing of warning messages, others are OK. Defer until section 6.3.7.

The revised WPS2' step, is essentially WPS2 with the changes associated with id, mute and DR added. This includes the additional claim/argument concerned with establishing the consistency of the revised requirements of $R_{1}$ with $DR$, the
resolution of which is deferred until section 6.3.7. The addition and capture of this important claim/argument provides further evidence to mitigate [IncomI5].

The next task was to revisit the WPS3 step (refer to page 269). Inspection of the transformations involved with WPS3 (Pilot domain removal) reveal that the addition of id, mute and DR do not affect the transformation. That is, technically WPS3 and WPS3' are the same apart from DR added to R2 to form R2' and this R2', along with id and mute, added to the appropriate parts of P_{Red1} to form P_{Red1}'. This follows because although R2a is affected by the domain removal, it is only changed with respect to the original phenomena. The change does not involve the new phenomena id and mute, nor does it impact the behaviour defined by DR.

A similar argument can be applied to the remaining domain removals which are not impacted by the addition of id, mute and DR. Therefore the POSE transformation sequence outlined in section 6.3.3 and shown in Appendix F was repeated and the revised justifications map directly to J3 to J7. This resulted in the reduced, simplified, software problem of P_{Red} given by:

\[ P_{Red} : FD(cat, sys) \rightarrow status, \ AOS(messdig)\rightarrow id, \ mute, \ FA_{sel,mute} \rightarrow status, \ id \rightarrow R6'(messdig, mute) \]

The corresponding PF problem diagram form is shown in Figure 6.8.
PrePSA' will also have a similar form to PrePSA, but is affected by the phenomena \(id\), \(mute\) and derived requirement \(DR\). This resulted in \(P'_{\text{equiv}}\) shown below.

\[
P'_{\text{equiv}} : F(\text{status})^{\text{status}}_{\text{status}}, AOS(\text{sel})^{\text{id}}_{\text{sel}, \text{mute}}, FA^{\text{sel}, \text{mute}}_{\text{status}, \text{id}} \Rightarrow R^{\text{sel}, \text{mute}}_{\text{status}, \text{id}}
\]

### 6.3.6 PSA Applied to Modified Model

As before the feasibility of \(P'_{\text{red}}\) is checked by applying the PSA tasks to investigate the functional and random failure behaviour of the revised model. The functional behaviour was validated using an Alloy model derived directly from the POSE model structure and using the POSE domains and phenomena as its basis. This was similar to the earlier model, but included the behaviour of the additional \(mute\) and \(id\) phenomena. This model is shown in full in Appendix F.7. The main changes occur in the definitions of the abstract data types for \(FA\) and \(AOS'\) as shown below.

```alloy
// Define the single FA State - sel and mute
one sig FA { sel : Sel -> Time, mute : OK -> Time } {}

// Define the single FD State domain - status
one sig FD {status : Status -> Time} {}

// Define the single AUS' State domain - messdig and id
one sig AUS' {mess : Mess -> Time, id : OK -> Time} {}
```

The behaviour of \(FA\) (\(FA\text{Behave}\)) and \(AOS'\) (\(AOS'\text{Behave}\)) were modified to include the \(mute\) and \(id\) phenomena as shown below.

```alloy
// FABehave models the behaviour of the safety critical controller.
pred FABehave(t,t' : Time) { FA.sel.t' = extract(FD.status,t) &&
FA.mute.t' = checkid[t,t'] }
```

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// AOSBehave models the behaviour of the AOS' domain. If mute is
// active then the message is set to noni (no message).

pred AOSBehave (t, t' : Time) { AOS.mee.t' = (FA.mute.t = noo =>
  decode[FA.sel.t] else noni) &
  AOS.id.t' = setid[t, t']}

// Fun checkid confirms message id corresponds to selected message #11

fun checkid(t, t' : Time): OK {AOS.id.t = yes => noo else yes

The function checkid/[] returns noo if the selected message agrees with the id
returned from the AOS', and the audio is not muted. If the result is yes, then audio
is muted as required.

The analysis approach adopted the same strategy introduced in section 6.3.4.2
which used simulation to set up the formal model, then proof to validate the spec-
ification and the requirement, proof to validate any safety properties (none in this
case, as the requirement covered the safety properties), with the option of further
simulation to explore any specific problem behaviours such as rapidly changing in-
puts. In this case, the behaviour of the system was simulated over a wide range of
input combinations using the modified input value-time trace model (introduced on
page 144) to control the simulation timing. The simulation explored the expected
behaviour of the model, especially the operation associated with the mute and id
phenomena. The results indicated that the requirements specification model be-
haved as intended. Next the proof work on the requirements was undertaken, and
the full results are considered in section 6.3.7.

The second part of the PSA checked the random failure performance of the
revised system. Note that DR also introduces additional failure modes. For example,
mute failing on is a form of F6 (see Table 6.2). Table 6.3 shows the results of
repeating the FFA/HAZOPS analysis, collating results and then performing the
FTA with the new system architecture. The Target - shown in brackets after the FTA calculation result - is the most severe probability applicable (e.g., the H1 target, \(10^{-7}\) fpfh, used for first two terms).

The worst effect of “Message played too loud” is considered to be that the pilot switches the Audio Warning System, FAS, off to avoid the distraction - this equates to hazard H2, so the H2 target is used. Mitigation for this failure mode is provided by the Volume Limiter circuitry which is part of the AOD (refer to WPS5 on page 274). Inspection of the analysis results in Table 6.3 indicates that the modified AOS' architecture is adequate for this aspect of the safety targets, and therefore it is valid to use it to continue with the development.

A similar analysis was applied to the FD domain and satisfactory results were obtained. Therefore, the modified Audio Warning System architecture can be argued not to prevent satisfaction of both the functional and safety target requirements, and hence is a suitable basis for the remainder of the development process, that is, designing the FA. However, this is only valid if the requirements are shown to be consistent.

### 6.3.7 PSA Requirements Validation

The next step was to try to formally prove that the revised model satisfied its specification given by \(R7'\), its requirement given by \(R6'\) (including its functional safety requirement) and also to cover the consistency of the requirement. The check for \(R6'\) produced a counter example (i.e., the proof failed). The fact that the failure
was expected follows from inspection of DR, and R6’a shown below:

R6’a When the CS or a monitored system has failed, the FA shall control the system to generate the correct digital message stream sequence, messdig, at the output of AOS’.

R6’a requires the correct operation of the selection mechanism, whilst DR ensures safe operation by muting audio if there is a discrepancy between the selection and the message output functions. Therefore, when the R6’a predicate is applied to the modified system architecture it produces a counterexample at the point where a message should be output but the mute is in operation due to an identified problem with the message id. The resolution requires R6’a to take due account of the derived requirement DR. This can be achieved by modifying R6’a to become:

R6’aM When the CS or a monitored system has failed, the FA shall control the system to generate the correct digital message stream sequence, messdig, at the output of AOS’, except when a discrepancy is identified with the message identifier.

With this modification R6’aM and DR are consistent. This is demonstrated by proving that the modified predicate corresponding to R6’aM does not produce a counterexample. For example, the assert R6aM fragment shown below covers the “positive” behaviour showing that if there is no problem with the message identifier id, then mute is off (noo) and the systems outputs the correct message.

```
assert R6aM {all tl, t2, t3 : Time | (t3 = prev[t2] & &
FA.mute.t1 = noo & & FA.mute.t3 = noo & & FA.mute.t2 = noo & &
t1 in prevs[t2] & & FD.status.t1 = catsys & &
t1 = prev(prev[t2]) => AOS.mes.t2 = mes1)
& &
### Similar terms for catsys, sysnon and non ### }
```

The proof work was extended to the other aspects of the requirements to demonstrate that the requirements model satisfied them, and that they were consistent.
This validated that the functional requirements $R6'a$, $R6'c$, $R6'd$ and $DR$ of $R6'$ were satisfied, demonstrating that the revised model satisfies its functional behaviour requirements.

After this PSA application it has been demonstrated that the specification ($R7'$) satisfies its requirements, including its safety requirements, and the requirements are known to be consistent.

6.4 Discussion

The POSE safety pattern was identified and introduced to manage the early phases of a safety development process in section 6.1. The Audio Warning System case study of section 6.3 demonstrated the successful use of the pattern on a realistic example, and also showed that it was capable of supporting the PSA as part of the IPDP SDR in section 6.3.4. The PSA at SDR supports the goal of achieving an appropriately early safety analysis which provides strong evidence to mitigate [LateI3]. Further, the pattern diagram of Figure 6.1 and its associated Agenda description of Table 6.1 were found to be useful ways of representing what needs to be done to successfully apply the POSE safety pattern.

The FAS case study PSA work reported in section 6.3.4, section 6.3.6 and section 6.3.7 also demonstrated the successful use of the safety analysis approach introduced in section 5.2 – providing further mitigation for [LateI3] with respect to its aspects concerned with effective analysis.

The formal modelling work discussed in section 6.3.4 and section 6.3.6 further demonstrated that POSE integrates well with Alloy. In particular the Alloy formal model can be derived directly from the POSE software problem using a systematic process. The validation followed the sequence of validating the specification, then the requirement and then considering the functional safety requirements. In the case study these were included in the requirement, but the formal model could be used
to investigate and prove formal safety properties. Further, this work also showed the advantages of using a four-part process in applying the formal modelling:

1. use simulation to develop the model and gain confidence it has the required behaviour;

2. perform formal proof to validate the model;

3. use the model to prove safety properties (if necessary)

4. investigate any specific problem areas using simulation.

This process is efficient because the more expensive proof work is only undertaken once simulation has provided confidence in the efficacy of the model. The work also showed how the Alloy model could be derived directly from the POSE problem model structure using a systematic, repeatable process. In fact this process has been used subsequently at the Company to develop a large number of Alloy models to provide formal validation evidence in support of a number of POSE safety pattern applications. The results obtained from applying this formal analysis shows that POSE and Alloy are a good, effective combination for performing this early life cycle phase work since they: provide an effective, successful safety analysis supporting the mitigation of [LateI3]; use the same model as the development, supporting property [SameA1]; use a formal process satisfying property [FormalA2] and provide strong validation evidence in mitigation of [ValidI6] and the property Validation.

The FAS case study also demonstrated how the POSE problem transformation graph (e.g., see Figure 6.7) can be used to represent the sequence of problem transformation steps involved in transforming a complex problem into a simpler one for analysis, and how this can be used to assist with backtracking, providing support for property [TraceI4]. This simplification using the PPT reported in section 6.3.3 and section 6.3.5 provides support for property Simplification.
The case study did not demonstrate tool support for POSE, but it did provide further evidence that POSE integrates well with Alloy to provide a powerful development toolset, providing further evidence for property Tool Support. The case study also demonstrated that the POSE safety pattern integrates well within IPDP (see section 6.3.1 and section 6.3.2) in support of property IntegA3 and property Integrates.

Following the POSE safety pattern means that Activity 1, based on the Initial Problem step, is completed before starting Activity 2 (Solution Interpretation and Expansion step), which ensures that a comprehensive understanding of the problem space (environment context and requirement) is obtained before starting to develop a solution architecture. The approach used for the FAS case study in section 6.3.1 was similar to the approach used for the DC case study which is detailed in section 4.1.2.1, section 4.1.3.1, section 4.1.3.2 and section 4.2. This provides strong evidence for the mitigation of the first two issues of understanding the environment context ([EnvirI1]) and requirements acquisition ([RequI2]). It also strongly supports property Context.

The FAS case study in section 6.3.1 used the same approach as the DC case study reported in section 4.1.2.2, section 4.1.3.2, and section 4.1.3.3. Therefore, it also provides evidence to support the property Avoid Bias. Similarly, the FAS case study in section 6.3.1 used the same approach as the DC case study reported in section 4.1.2.2 and section 4.1.3.1, thus also providing support for property Model Reality. The FAS case study in section 6.3.2 covering Activity 2 of the pattern, used the same approach as the DC case study reported in section 4.3 and this supports the Architecture property.

The case study work also provided support for the mitigation of [IncomI5] concerning task incompleteness with respect to the use of the POSE safety pattern and Problem Transformation steps. The FAS case study formal validation work, reported in section 6.3.4.2 and section 6.3.7, directly supports the mitigation of [Re-
concerning sound, consistent and complete requirements as well as [ValidI6] and property Validation. In addition, the derivation of a validated formal specification provides support for property Spec. Join. Care was taken in the FAS case study work to ensure that the requirements were at an appropriate level of abstraction (section 6.3.1) and the successful PSA and validation work reported in sections 6.3.4-6.3.7 provide support for property Right Abstraction.

The successful application of the POSE safety pattern in conjunction with the formal safety analysis and validation provide strong evidence concerning the feasibility of the requirements model and specification that results from the work.

6.5 Chapter Summary

The primary goal of this chapter was to introduce the POSE safety pattern and through the FAS case study demonstrate how it can be used to derive a specification that is capable of satisfying its requirement – including the safety requirements allocated to it. The case study also demonstrated that the POSE safety pattern could be used as part of the IPDP to mitigate the issue [LateI3]. In addition this chapter discussed mitigation and support for the other two outstanding items – as shown in the Chapter 5 column of Table 6.4 – namely [IncomI5] and Tool Support.

As in previous chapters, the top portion of Table 6.4 refers to the capabilities identified in Table 2.3. The FAS case study work has provided supporting evidence for the Context, Architecture, Avoid Bias, Model Reality, Validation, Integrates, Spec. Join, Simplification and Right Abstraction properties identified in Table 2.3. The case study also shows that POSE works well with Alloy, providing some indirect supporting evidence for Tool Support. The meaning of "e", "ee", "E" etc. is as defined in section 4.6.

The lower portion of Table 6.4 demonstrates that the case studies (DC, SMS and
FAS) have provided evidence to satisfy the properties \([\text{NecessaryP}], [\text{SameA1}], [\text{FormalA2}]\) and \([\text{IntegA3}]\) identified in section 3.4.5. Further, these case studies have also provided evidence to mitigate the issues \([\text{EnvirI1}], [\text{RequI2}], [\text{LateI3}], [\text{TraceI4}], [\text{IncomI5}]\) and \([\text{ValidI6}]\) also from section 3.4.5.

In conclusion the FAS case study demonstrates that the POSE safety pattern, incorporating the other POSE extensions described in this chapter and in Chapter 5, can support a formal development process that is suitable for safety critical system development.

The contribution of this thesis to the knowledge concerning POSE and its use is summarised in Table 6.5. The “Reference” column refers to section numbers unless otherwise stated, and pattern refers to the POSE safety pattern introduced in section 6.1.

<table>
<thead>
<tr>
<th>Property/Issue</th>
<th>Previous Work</th>
<th>Chapter 4</th>
<th>Chapter 5</th>
<th>Chapter 6</th>
</tr>
</thead>
<tbody>
<tr>
<td>Context</td>
<td>[41, 87]</td>
<td>e</td>
<td>ee</td>
<td>E</td>
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<td>Avoid Bias</td>
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<tr>
<td>Model Reality</td>
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<td>-</td>
<td>e</td>
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<td>Tool Support</td>
<td>[35, 87]</td>
<td>-</td>
<td>-</td>
<td>e</td>
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<td>Right Abstraction</td>
<td>[41, 87]</td>
<td>e</td>
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<td>Integrates</td>
<td>[88]</td>
<td>e</td>
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<td>NecessaryP</td>
<td>[41, 83]</td>
<td>-</td>
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<td>[41, 88]</td>
<td>-</td>
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Table 6.4: Evidence Status for POSE after Chapter 6
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<th>Contribution Description</th>
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<td>Pattern developed by this work provides a structure that supports safety development</td>
<td>6.1, 6.3</td>
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<tr>
<td>Pattern</td>
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<tr>
<td>[Late13]</td>
<td>Pattern supports mitigation of issue</td>
<td>6.1, 6.3.4</td>
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<tr>
<td>[Valid16]</td>
<td>Pattern mitigates validation to issue</td>
<td>6.3.4, 6.3.7</td>
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<tr>
<td>[Envir11]</td>
<td>Pattern Activity1 mitigates issue</td>
<td>6.3.1</td>
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<td>[Requ12]</td>
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<td>6.3.1</td>
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<td>Avoid Bias</td>
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<tr>
<td>Model Reality</td>
<td>Pattern Activity1 supports property</td>
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<td>Validation</td>
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<tr>
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<td>6.3.3, 6.3.4, 6.3.6, 6.3.7</td>
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<td>Pattern Activity3/4 supports property</td>
<td>6.3.3, 6.3.4, 6.3.6, 6.3.7</td>
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<tr>
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<td>Pattern Activity4 supports property</td>
<td>6.3.4</td>
</tr>
<tr>
<td>FormalA2</td>
<td>Pattern Activity4 supports property</td>
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<td>Pattern Backtracking mitigates issue.</td>
<td>6.3.5</td>
</tr>
<tr>
<td>[IncomI5]</td>
<td>Pattern activities mitigate issue.</td>
<td>6.2.1, 6.3.2, 6.3.5</td>
</tr>
<tr>
<td>IntegA3</td>
<td>The FAS analysis provides evidence</td>
<td>6.4</td>
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<tr>
<td>Right Abstraction</td>
<td>The FAS analysis provides evidence</td>
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<td>Integrates</td>
<td>The FAS analysis provides evidence</td>
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<td>Tool Support</td>
<td>The FAS analysis provides evidence</td>
<td>6.2.2, 6.4</td>
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Table 6.5: Thesis Contribution Summary: Chapter 6
Chapter 7

Discussion and Conclusions

The aim and objectives of this work were discussed in section 1.2 and concern the following. The overall aim of this work is to show that the early phases of a development process suitable for embedded safety systems development can be enhanced such that it allows a requirement model to be produced early in the development process, a specification to be derived from this model, and the safety feasibility of this model to be evaluated. The end result is a model that is known to be able to satisfy its safety requirements and thus forms a good basis for the rest of the development.

The overall aim was addressed by evaluating POSE, and the extensions introduced by this work, against two objectives. The first involved considering whether the extended POSE could address the ten SSSD approach properties identified in the literature review of Chapter 2 and summarised in Table 2.3. This first objective is discussed in section 7.1.

The second objective was to demonstrate that the extended POSE could be used to improve the early phases of an existing safety development process (IPDP) by evaluating it against a further four properties and six issues summarised in section 3.4.5. These latter properties and issues were targeted at improving the existing IPDP which is used to develop the type of embedded avionics safety systems that
are of interest to this work. This second objective is considered in section 7.2, with additional supporting evidence from an industrial case study discussed in section 7.3.

The overall conclusion of this work is given in section 7.6.

7.1 Investigation of the ten SSSD Approach Properties

The final section 2.5 of Chapter 2 defined ten desirable properties (see Table 2.3) that an SSSD approach targeted at the early phases of the development of real-time safety systems should possess. The extent to which POSE satisfied these properties was evaluated in Chapter 4, Chapter 5 and Chapter 6 using existing published work, analysis and case study evidence as appropriate. How POSE addressed each of these ten properties will now be summarised in turn. In the following, step will be used to indicate the problem transformation step concept introduced in section 4.1.4.2, pattern will be used to indicate the POSE safety pattern introduced in section 6.1 and the SSSD approaches are those reviewed in section 2.3.

7.1.1 The property Context

The property Context is concerned with ensuring that an approach is capable of acquiring information that supports a comprehensive understanding of the system environment context which can adequately support the system development activities. This property is related to the concept of understanding the problem before attempting the solution and is therefore a fundamental aspect of the problem oriented approaches like POSE. It was identified from the Parnas 4-variable based SSSD approaches (Parnas Table, SCR, SpecTRM, AMBERS, PFS), and is also an important part of AdLS, and KAOS. It also has much support in the published literature [54, 82, 121, 127].
The concept of “context” is a key component of POSE and one way this is indicated is by the existence of a CONTEXT INTERPRETATION transformation, and which is carried through into its use in the Initial Problem step and as Activity 1 in the pattern. The first part of the DC case study (section 4.1.2.1) was concerned with collecting information about the environment context and this information was used in the application of the CONTEXT INTERPRETATION transformation in section 4.1.3.1 to introduce the context into the initial problem as part of the Initial Problem step detailed in section 4.2. The Initial Problem step was also used in the SMS (section 5.5.1) and FAS (section 6.3.1) case studies, so these provide further evidence to support the property. Further, the successful application of the PPT relies on an accurate understanding of the useful behaviour relation of the domain to be progressed (part of the problem context), since this becomes the assumption which is used as part of the validation of the PPT step.

In conclusion, the property of Context is addressed by POSE and the use of the pattern, and there is significant evidence in the thesis to demonstrate that POSE supports this property as indicated by Table 7.1.

7.1.2 The property Architecture

The property Architecture is the capability of an approach to structure the development model so as to resolve architectural issues. All of the reviewed SSSD approaches support this property and there is also support for it in the published literature [82].

The existence of SOLUTION INTERPRETATION and SOLUTION EXPANSION transformations highlight the importance of this property to POSE. This is consolidated in the Solution Interpretation and Expansion step (Activity 2 of the pattern) which allows candidate solution architectures to be evaluated – refer to section 4.3.

The Solution Interpretation and Expansion step was used in all of the case studies.
to introduce candidate system architectures: the DC in section 4.3, the SMS in section 5.5.1, and the FAS in section 6.3.2. Further, this step was used again in the DC and FAS case studies to introduce modified architectures to solve the identified problems (DC in section 5.3 and the FAS in section 6.3.5).

In conclusion, the property Architecture is addressed in POSE and the use of the POSE safety pattern, and there is significant evidence in the thesis from the three case studies to demonstrate that POSE supports this property as indicated by Table 7.1.

7.1.3 The property Spec. Join

The property Spec. Join covers the ability of an approach to span both the problem space and the solution space. That is, the approach satisfies the property if it can develop the specification from the requirements in the problem space and then develop the solution from the specification in the solution space. This property is supported by all the SSSD approaches and in the published literature [121].

The POSE transformations CONTEXT INTERPRETATION and REQUIREMENT INTERPRETATION show the POSE capabilities in the problem space, whilst SOLUTION INTERPRETATION demonstrates some of the POSE capabilities in the solution space. The PPT work in section 5.1.2 showed that POSE can be used to derive a validated specification from requirements in context. This was demonstrated for a non-formal development in the DC case study of section 5.1.3 and section 5.4, and for formal developments in the SMS and FAS cases studies of sections 5.5.3–5.5.5 and section 6.3.3 respectively, and also in the rework of the FAS in sections 6.3.5–6.3.7.

As noted in section 2.6, the main focus of this work has been the early phases of the development process, hence it was classed as "ee" in Table 6.4. However, when the results of this work are considered together with the published POSE literature that shows how a POSE derived specification can be used to develop a solution (e.g.,
we conclude that there is sufficient evidence to demonstrate that POSE supports this property. Therefore it is classed as “E” – significant evidence – in Table 7.1.

7.1.4 The property Avoid Bias

The property Avoid Bias relates to the avoidance of structures in the problem development that result in unnecessary and/or inappropriate constraints on the solution. The importance of this property is highlighted in the published literature [133, 16], and as detailed in section 2.5.2, avoiding solution bias is a characteristic of the PO approaches, which stress the importance of fully understanding the problem before designing a solution, and of expressing requirements solely in terms of the context phenomena.

The detailed presentation concerning REQUIREMENTS INTERPRETATION in section 4.1.2.2 and section 4.1.3.2, and introducing the solution in section 4.1.3.3 on the DC case study provide evidence to show that POSE supports this property. Further evidence is provided by the SMS case study in section 5.5.1 and the FAS case study discussion (section 6.4) which refers to section 6.3.1. The conclusion is that there is good evidence to show that POSE supports this property as indicated by Table 7.1.

7.1.5 The property Model Reality

The property Model Reality is the ability of the approach to represent the problem in terms of the phenomena, relations and concepts that exist in the real world. All the SSSD approaches support this property to some degree, it is supported in the literature [133, 16], and the concept of designating descriptions and phenomena in the real world is an important aspect of POSE (section 2.5.2).

For the DC case study the REQUIREMENTS INTERPRETATION work detailed in
section 4.1.2.2 and the context mapping discussed in section 4.1.3.1 provide evidence to support this property. Further evidence is provided by the SMS case study in section 5.5.1 and the FAS case study discussion (section 6.4) which refers to section 6.3.1. The conclusion is that there is good evidence to show that POSE supports this property.

7.1.6 The property Validation

The property Validation is concerned with the ability of the approach to ensure that the right system is being produced by applying analysis to the models as they are developed. All the SSSD approaches support this property, and some (e.g. SpecTRM, SCR, KAOS, AMBERS, PFS offer tool support for simulation and proof. There is also much support in the published literature including [122, 16]. Validation is an important aspect of POSE through its notion of transformation justification. The PPT work in section 5.1.2 shows how problem progression can be validated using the useful behaviour relation of the domain to be progressed. The DC case study demonstrated this for a non-formal development in section 5.1.3, whilst the SMS case study provided evidence for a formal validation in section 5.5.5. The FAS case study provides further support for validation using a formal development in section 6.3.4.2 and section 6.3.7. Further, one of the purposes of the POSE safety pattern introduced in section 6.1 was to allow an early effective safety analysis that determined whether the system model was capable of satisfying its safety requirements and would thus be a viable basis for the rest of the development. This safety validation was demonstrated on the FAS case study, and also in the PSA work reported for the DC and SMS case studies. The conclusion is that there is strong evidence to show that POSE (particularly in combination with Alloy) supports this property as indicated by Table 7.1.
7.1.7 The property Simplification

The property Simplification is the ability of the approach to manage complexity by structuring the problem, so that large complex problems can be broken down into smaller problems that are easier to solve. The SSSD approaches recognise the importance of this property, although only KAOS, AdLS and to a lesser extent AMBERS offer process support. There is also much published literature including [69, 16].

The DC case study in section 5.4 and the SMS case study in section 5.5.2 provide evidence that POSE supports this property. Problem Simplification is Activity 3 in the POSE safety pattern used in the FAS case study and this involves application of the PPT to make the problem of deriving a specification easier to solve (refer to section 6.3.3 and section 6.3.5). In conclusion, the case study results provide sufficient evidence to show that POSE supports the property Simplification as indicated by Table 7.1.

7.1.8 The property Tool Support

The property Tool Support relates to the efficiency, error-avoidance and repeatability advantages that can accrue if the approach has adequate tool support. Most of the SSSD approaches offer tool support and the desirability of tool support is noted in the published literature, e.g., [96, 45, 90]. As noted in the discussion in section 6.2.2, although POSE does not provide any tool support directly, this is mitigated by the ability of using POSE models within other tools, like Alloy. The FAS case study provided further evidence to support this view. In conclusion, although POSE would benefit from its own tool support, the ability of its models to be used within other tools means it is feasible to use it as part of the development process. This is an area that would benefit from further work, for example the development of the proof-of-concept tool mentioned in section 6.2.2 would be a useful improve-
ment – this will be discussed further in Chapter 8 – hence this property is “e” in Table 7.1.

7.1.9 The property Right Abstraction

The property Right Abstraction is the ability of the approach to operate at the level of detail appropriate to the problem at hand. For example the approach should be able to describe the range from high level requirements through to detailed specifications. The importance of this property is noted in the published literature, e.g., [82, 71].

Application of PSA to the POSE models in the case studies provide some evidence that POSE supports this property. Further support was provided by the DC case study in section 5.1.3 and the SMS case study in section 5.5.1. The discussion in section 6.4 indicates how support for this property is provided by the FAS case study. In conclusion, the case studies provide sufficient evidence that POSE does support this property as indicated by Table 7.1.

7.1.10 The property Integrates

The property Integrates is concerned with the ability of the approach to work and integrate with an existing development process. The DC case study work reported in section 4.5.2 indicated that the POSE transformations could be integrated with the IPDP, but that further supporting evidence was required. The discussion in section 5.6 noted that the SMS case study provided evidence to support the view that POSE can integrate well with IPDP. Further evidence of good integration is provided by the FAS case study discussion in section 6.4. The conclusion is that POSE integrates well with the IPDP as indicated by Table 7.1.
7.2 Discussion of the IPDP Issues and Properties

Chapter 3 described a successful process (IPDP) used to develop a variety of safety critical and safety related embedded real-time systems. Although IPDP has been successful, a number of issues with it and possible improvements to it have been identified through its use. These were identified in the chapter as six issues and four properties. The extent to which POSE can mitigate these issues and support these properties will now be discussed for each of them.

7.2.1 Mitigation for Issue [EnvirI1]

The first of the six IPDP issues, [EnvirI1], concerns the risk that insufficient understanding of the system context increases the risk of later rework:

[EnvirI1]: Incomplete understanding of the system context increases risk of rework.

In the past this has allowed ambiguity and lack of detail in the descriptions to result in misinterpretations of the design concept and further, an adequate safety analysis requires that the system environment is sufficiently understood. This issue is closely related to the property Context discussed in section 7.1.1, which details how understanding the environment context is a fundamental concept in POSE.

From an IPDP perspective the context understanding work corresponds to the CE phase. For example, in the DC case study the initial understanding work (section 4.1.2.1 and Appendix A.2) occurs at the beginning of the CE phase and this is refined and developed as the various CE phase tasks are completed leading to the use of the CONTEXT INTERPRETATION transformation to introduce context into the problem to form $P_{Domx}$ (section 4.1.3.1). Towards the end of the CE phase work further understanding of the domains resulted in a series of additional CONTEXT
INTERPRETATION transformations that transformed the problem into $P_{Dom}$—these were validated by review. A similar process was followed in the SMS case study (section 5.5.1, discussed in section 5.6) and in the FAS case study (section 6.3.1 Activity 1 of the POSE safety pattern, discussed in section 6.4). In conclusion, POSE and the POSE safety pattern provide significant mitigation concerning this issue as indicated by Table 7.1.

7.2.2 Mitigation for Issue [RequI2]

The second of the six IPDP issues, [RequI2], concerns the risk of rework associated with not adequately understanding and acquiring the requirements:

[RequI2]: Incomplete requirements increases risk of rework.

This increases the risk that the right system is not being produced and it has been observed following IPDP that the detailing of the requirements allocations and transformations do not always produce requirements that are feasible, nor are they necessarily sound, consistent or complete.

The issue [RequI2] is concerned with understanding the customer requirement. For example, in the DC case study the work begins in the IPDP CE phase (see section 4.1.2.2 and Appendix A.2) where the requirement is elicited and developed in conjunction with the customer. As system understanding increases the requirement is developed accordingly. In the case study a REQUIREMENT INTERPRETATION transformation was used to introduce the initial requirement, $RDC$, into the problem. This was developed into $Rdc$ through a series of further REQUIREMENT INTERPRETATION transformations as detailed in section 4.1.3.2 as the tasks in the CE phase were progressed and the Dem/Val phase started (refer to Appendix A.3). The Initial Problem work in the SMS case study (section 5.5.1, discussed in section 5.6) and the FAS case study (section 6.3.1 Activity 1 of the POSE safety pattern, discussed in section 6.4) provide further supporting evidence. In conclusion, POSE
and the POSE safety pattern provide significant mitigation concerning this issue as indicated by Table 7.1.

7.2.3 Mitigation for Issue [LateI3]

The risk of rework caused by performing the safety analysis relatively late in the development life cycle was captured as the third IPDP issue:

[LateI3]: Late effective safety analysis increases risk of rework.

Developing the capability to perform an effective safety analysis earlier in the (IPDP) development process was one of the major drivers for this work. An effective analysis requires an accurate understanding of the context, the requirement and an appropriate model to analyse (see section 3.2.3, section 3.3.4 and section 2.2.2). The work in section 5.2 indicated how an improved PSA could be achieved for non-formal (section 5.2.1.1) and formal (section 5.2.1.2) developments using the POSE problem model available after problem progression ($P_{RD}$). The DC case study demonstrated the process for a non-formal development in section 5.2.2, whilst the SMS case study demonstrated the process for a formal development using POSE and Alloy in section 5.5.5. The FAS case study demonstrated how a formal PSA could be conducted as a result of following the POSE safety pattern in section 6.3.4 and in sections 6.3.6–6.3.7. The work demonstrated that an effective safety analysis can be achieved as long as $P_{RD}$ is available.

In the original DC development (Appendix A.3) FFA was applied during the Dem/Val phase, but this missed an issue – HAZOPS was not applied until Preliminary Design in the EMD phase. In section 4.4 PSA was applied using FFA and FTA, whilst in section 5.2.2 a combination of FFA, HAZOPS and FTA were used. The latter required that the context (domains and phenomena) and requirement information was available to support a HAZOPS. The information collected to support the development from $P_{null}$ through to $P_{RD}$ ensured that the required information
was available. The work in section 6.1 noted that by structuring the IPDP tasks through the use of the POSE safety pattern then it could be ensured that the necessary information to support a comprehensive PSA (i.e., one using the techniques introduced in section 5.2) could be made available at the end of the Dem/Val phase, prior to the SDR. This work demonstrates that an effective safety analysis can be applied at an earlier part of the IPDP (end of Dem/Val, prior to SDR) than was achieved with the existing IPDP (after SDR).

The results of the revised DC case study in Appendix H provides further evidence to corroborate that this property has been satisfied – this additional evidence progresses the “ee” in Table 6.4 to “E” in Table 7.1. The conclusion is that POSE and the POSE safety pattern provide significant evidence to mitigate this issue.

7.2.4 Mitigation for Issue [TraceI4]

The fourth IPDP issue, [TraceI4], concerns traceability incompleteness and can be split into two main themes: traceability of requirements through the design, and the ability to trace back through a design to establish what information can be re-used and what needs to be developed, including the ability to know where to trace back to.

[TraceI4]: Traceability incompleteness increases risk of rework.

The ability to support iteration is also considered a form of traceability issue by this work.

The work in Section 5.3 introduced an enhanced problem transformation trace graph as a graphical representation of the relationship between the software problem descriptions and their associated requirements transformations – an example is shown in Figure 5.4. This graphical form allows the path of the requirements transformations to be traced from the original high level system requirements through to
the detailed requirements that directly support the specification derivation, based on the software problem transformation sequence.

The work on the DC case study in section 5.3 provides strong evidence that both aspects of the issue [Trace14] are mitigated by the POSE transformations and use of the pattern. The graph was also used in the SMS case study (section 5.5.2) to represent the development and simplification (problem progression) sequence from $P_{\text{initial}}$ to $P_{\text{red}}$. The graph in Figure 6.7 performed a similar role on the FAS case study, except it was also used to assist with the backtracking (see section 6.3.5). In conclusion, the POSE and POSE safety pattern provides good evidence to mitigate this issue although more development work of these traceability techniques is required to realise their full potential – this will be discussed further in Chapter 8 – hence this issue is “ee” in Table 7.1.

7.2.5 Mitigation for Issue [Incom15]

The fifth IPDP issue concerns the problems associated with not completing all of the work items associated with a task and was captured as:

[Incom15]: Task incompleteness increases risk of rework.

Task incompleteness includes the problems associated with tailoring out (removing) tasks from the schedule.

The FAS case study in section 6.3 demonstrated that the POSE safety pattern organised the development tasks such that a successful PSA could be applied before the end of the Dem/Val phase. The pattern activities ensure that, at a high level, all the necessary tasks to support the formation and feasibility/validation checking of a problem model are undertaken and in the correct sequence. Further, each activity is associated with a problem transformation step which ensures that all the necessary tasks associated with that activity are completed. For example, PS1 on page 91 includes the justifications for the transformation sequence ($J_1 = J_a \land J_b \land J_c$), and the
necessary concerns/claims/evidence that the interpretations are well-founded, the system architecture is feasible, sound judgement followed and important equipment has the necessary reliability.

Inspection of the problem transformation steps shows each is associated with a set of concern/claim/evidence elements that validate a particular concern associated with the use of that step, and this mechanism could be developed further to ensure that the necessary tasks to support a transformation step are included in the structure used for that step. In conclusion this thesis work has demonstrated that the POSE safety pattern and the problem transformation steps it uses provide some evidence to mitigate this issue, but that further opportunities exist to improve this mitigation further - these will be discussed in more detail in Chapter 8 – hence this issue is “e” in Table 7.1.

7.2.6 Mitigation for Issue [ValidI6]

Validation is a key part of the development process and is captured as the sixth IPDP issue as:

[ValidI6]: Validation incompleteness increases the risk of rework.

Validation includes validating that the requirement (as it is interpreted through the development) meets the customer’s expectations, i.e., that the right system is being developed.

The PPT for safety systems introduced in section 5.1.2 and the SMS case study provide mitigation for this issue. Further, the Validation property considered in section 7.1.6 shows how POSE supports validation in a general sense, but validation is also an important feature of IPDP and features prominently in all the phases. The POSE safety pattern organises the POSE problem transformation steps so they integrate with their associated IPDP tasks to ensure that an effective PSA and a specification can be derived prior to SDR. This is discussed in section 6.1 and
demonstrated in the FAS case study in section 6.3 - particularly the validation work in section 6.3.4.2 and section 6.3.7. The work in section 6.3.7 demonstrates that the problem model satisfies its requirements, satisfies its safety requirements and the requirements are shown to be consistent. In addition, the revised DC case study in Appendix H provides further evidence to mitigate this issue. This additional evidence progresses the “ee” in Table 6.4 to “E” in Table 7.1. In conclusion, this thesis work has shown that POSE and the POSE safety pattern provide significant mitigation for this issue.

7.2.7 Support for [NecessaryP]

The necessary property identified in Chapter 3, [NecessaryP], requires that:

[NecessaryP]: The approach used must be capable of deriving design specification.

which is a necessary feature of any approach to be used in the early phases of embedded system development. The POSE PPT developed in section 5.1.2 demonstrated how problem progression could be applied to remove domains to simplify a problem under certain conditions: that causal relations among phenomena are identified and used to establish assumptions in the derived requirements; that only domains whose phenomena are adjacent to the requirement are the subject of progression. The first criterion is reasonable for the real-time embedded avionics systems that are the subject of this work, and the second follows from the application of the POSE safety pattern which ensures progression (Activity 3) follows after Activity 2. The output of Activity 2 is a model (called P_{E\mathcal{T}} in the case studies) in which the requirement is well understood, interpreted, validated and at the right level of abstraction, thus forming an appropriate candidate requirement for the initial progression. The PPT then removes the domains in turn, each time re-interpreting the requirement into an appropriate form and capturing the useful behaviour relation of the progressed
domain as an assumption. This allows the new requirement to be validated against the original requirement through the assumption.

The work in section 5.1.3 demonstrated the use of the PPT to simplify a non-formal development problem, where the validation was completed using an informal review process. In the SMS case study of section 5.5 the PPT was applied in a formal development, and the final step was formally evaluated (i.e., that the derived specification satisfied the requirement of the problem model $P_{Red}$) in section 5.5.5. A formal approach based on simulation and proof was used in the FAS case study to validate that the specification derived from the repeated application of the PPT (Activity 3 of the POSE safety pattern) satisfied its requirement – refer to sections 6.3.3–6.3.4 and also sections 6.3.5–6.3.7 for the rework. In addition, the revised DC case study in Appendix H provides further evidence to support this property. This additional evidence progresses the “ee” in Table 6.4 to “E” in Table 7.1. In conclusion this thesis work has provided significant evidence to demonstrate that POSE and the POSE safety pattern support this property.

### 7.2.8 Support for [SameA1]

The desirable property that promotes efficient analysis identified in Chapter 3, [SameA1], requires that:

**[SameA1]:** The safety analysis uses the same model as the rest of the development.

In the DC case study the PSA was applied to the $P_{Exp}$ model in section 4.4 and to the $P_{Red}$ model in section 5.2.2. In both cases the PSA model was the same as the development model. The SMS case study in section 5.5.5 and the FAS case study in section 6.3.4 and sections 6.3.6–6.3.7 provide further evidence to support this property. In conclusion this thesis work has provided significant evidence to demonstrate that POSE supports this property as indicated by Table 7.1.
7.2.9 Support for [FormalA2]

The desirable property that promotes effective analysis identified in Chapter 3, [FormalA2], requires that:

[FormalA2]: The approach used should support formal development processes.

The SMS case study in section 5.5 and the FAS case study in section 6.3 both provided strong evidence that POSE works well with the Alloy formal system, such that POSE problem models could be directly encoded into Alloy to allow formal validation and proof to be applied. That is, the thesis work showed a good synergy between the POSE problem model and the Alloy formal system, and this included the following features of note:

1. an Alloy model formed directly from the structure of the POSE problem model (using domain and phenomena knowledge).

2. a timing model for use with the Alloy simulation was developed to allow fine control over the setting of phenomena values.

3. a four part analysis approach was developed based on:

   - the use of simulation to develop the model and gain confidence it has the intended operational behaviour;
   - the development of formal versions of the requirements and proof that the model satisfies them – the latter also validates consistency;
   - the development of safety properties (if required) and proof that the model satisfies them;
   - the use of simulation to explore problem situations, e.g., rapidly changing inputs.
In addition, the revised DC case study in Appendix H provides further evidence to support this property. In conclusion this thesis work has provided significant evidence to demonstrate that POSE in conjunction with Alloy supports this property. However, more work is required to evaluate how POSE operates with other formal techniques and this will be discussed further in Chapter 8 -- hence this property remains "ee" in Table 7.1.

7.2.10 Support for [IntegA3]

The desirable property that promotes an efficient development identified in Chapter 3, [SameA1], requires that:

[IntegA3]: The approach used should integrate with IPDP.

This property is directly related to the property Integrates covered in section 7.1.10, and the analysis presented there applies here. From an IPDP perspective, Table 4.3 provides strong evidence that POSE integrates well with IPDP. This is confirmed in the Chapter 6 work on the POSE safety pattern and how it integrates with the IPDP (see section 6.1), and in the FAS case study which shows the successful application of the pattern. Finally, further evidence to support this property is provided by the industrial case study discussed in more detail below. In conclusion this thesis work has provided significant evidence to demonstrate that POSE supports this property as indicated by Table 7.1.

7.3 Industrial Case Studies

The development of the POSE safety pattern, summarised in section 6.1, and the successful use of it on the case study in section 6.3 provided enough confidence to use it in the form of the POSE/Alloy combination at the front end of a number of real development tasks. The first two examples were modules from the same
safety related LRU, the third was a full safety critical LRU system development of a stores management system (SMS). Further, the fact that this actual SMS was similar in structure to the SMS case study investigated in section 5.5 provided additional confidence for using the pattern. The goal in applying the pattern was to provide additional complementary evidence to support the normal IPDP activities and in particular to provide early evidence that the proposed design was capable of satisfying the safety properties identified for it. The pattern was applied during the IPDP Dem/Val phase and the safety analysis work was completed prior to SDR - thus satisfying the early safety analysis issue represented by [Late13].

The first trial of the POSE safety pattern involved modelling two safety related modules of a communications control and routing function in a fast jet aircraft - these being the control module and the warning tones module (WTM). The POSE/Alloy modelling of the control module identified some requirements issues which were subsequently resolved. The modelling of the WTM identified a shortfall in the safety analysis task which was addressed. The WTM consisted of 41 requirements (excluding BIT), of which 27 of these were functional requirements. The POSE safety pattern was applied to these functional requirements and this produced an initial POSE safety problem description to which problem simplification was applied to allow the specification of the WTM to be derived directly. The latter was used to form an Alloy model which had a total of nine phenomena and the four-part process described in section 6.4 was applied. The POSE modelling of the WTM from first read of the requirements document through to being ready to begin the Alloy modelling process took one day of effort. Setting up and validating the Alloy simulation model took a further day of effort and this was followed by just under two days of effort to perform the proof and safety analysis tasks - about four days in all. The control module had a few more requirements, more phenomena (14) and a more complicated behaviour, but this was still fully analysed in just over a week (five days) of effort. The usual IPDP effort for this work was one to two days
to perform an in-depth manual review of the document, but this standard IPDP approach did not identify the issues.

The third trial of the POSE safety pattern "in the real" was the full modelling of a SMS development - this was a much larger enterprise being based on a 26 page Z model and involving 30 phenomena. Due to the complexity of the behaviour, the Alloy modelling was partitioned into a number of major functional areas to avoid memory resource problems with the simulation work. The modelling work identified nine issues with the requirements and their interpretation, which were resolved before development progressed. The POSE/Alloy modelling effort took two weeks and this was run in conjunction with the normal (IPDP) development process. The normal process effort for this phase would have been two to three days - but this did not identify the nine anomalies!

One of the complications in performing this work was overcoming the limitations imposed by the Alloy tool. The Alloy modelling was applied by successively adding functionality until the full behaviour was covered, but this increased complexity often resulted in the tool running out of memory resources as the number of tokens in the model increased. Strategies for addressing this problem included abstraction (e.g. combining phenomena with similar functionality to reduce the number of inputs) and slicing - where the overall functionality was broken down into its major functions, and these major function "slices" were modelled individually. As noted above, the latter was used on the SMS task.

Unfortunately due to security and confidentiality reasons little of the detail concerning these industrial case studies can be recorded here, apart from the fact that in all three cases the application of the pattern prompted a series of questions concerning the interpretation and clarification of: the requirements, the proposed system architecture and the safety analysis. The answer to these questions improved the early modelling work, the key point being that to produce the simulation model required that much of the ambiguity in the textual requirements had to be resolved.
This improved the quality of the requirements and the integrity of the design based upon them, by ensuring (and validating) that the requirements modelled reality and avoided any implementation bias – thus addressing the properties Model Reality, Validation and Avoid Bias from Table 2.3.

The industrial case studies also provided further strong evidence that POSE, through the use of the pattern, integrates well with the IPDP – thus satisfying the properties [IntegA3] (see section 3.4.5) and Integrates (from Table 2.3). The use of the pattern on the industrial case studies was carefully monitored to identify any task incompleteness issues. No such issues were identified and the conclusion was that the pattern, and the problem transformation step structure used in the pattern were very good at ensuring that all the necessary tasks were identified. Additional review items were added to the IPDP SDR review checklist to ensure that these identified tasks were successfully discharged. This work provided further direct supporting evidence for mitigating the issue [Incompl5].

Finally, this section has discussed the use of the pattern on actual industrial case study developments – where POSE was used in parallel to the actual development, but did provide safety analysis and evidence to support the early phases of the development. This demonstrated that POSE could be scaled up to support real development activities and that it did complement and improve the existing IPDP.

7.4 Development Process Context

Many developments have a target technology or group of technologies as an overall approach since using well understood technologies can significantly reduce the overall project risks and is consistent with the normal design ideas discussed in section 1.1. This is the case at the author's Company, where the goal with the avionics developments is to use a hardware architecture consisting of processor and input/output card assemblies as the target technologies. The design function then
revolves around modifying the functionality to achieve the requirements, with the benefit that the underlying card assembly technology is well understood and known to be capable of success – significantly reducing unknowns and de-risking many aspects of the project. Therefore such projects include elements of bottom-up as well as top-down in the development process.

One of the advantages of using the POSE safety pattern is that it fits well with this approach of targeting known hardware architecture technologies through its use of the target machine specification, which defines the specification for the generic computing element which maps to the hardware processor card in the design. The POSE safety pattern aims to capture essential elements of the requirements and context, define the machine specification and validate that the high level system architecture represented by the POSE model is capable of satisfying its safety obligations. However it is used within the context of a top-down and bottom-up design approach. Further, although the derivation of the machine specification, \( S \), from the requirement, \( R \), using the entailment sequent \( W, S \vdash R \) is top-down, the validation from \( S \) to \( R \) is bottom-up. Basically the POSE safety pattern application is the first phase of a top-down/bottom-up process that seeks to map the users requirements into a well understood target hardware architecture technology.

Further, the safety analysis associated with the application of the POSE safety pattern is essentially a de-risking exercise to validate that it is feasible to and hence worth continuing with the design process. As the development progresses more design decisions and target technology will be included into the design which will require further safety analysis to validate that it remains capable of satisfying its safety obligations.
7.5 Summary of Research Contribution

The aim of this section is to consolidate and summarise my research contribution on using POSE in the early stages of a safety critical system development as detailed in this document. My research covers the three areas of: theory development, developing the means of application, and providing initial or partial validation of the approach. In more detail, my contribution has three main parts:

- developing and extending the theory of Problem Orientation;
- applying the extended theory in a safety critical engineering setting;
- providing partial validation for the extended theory within that setting.

Together these discharge my overall research aim (refer to section 1.2), which can be summarised as:

"Improving the safety process by providing the means of applying safety analysis to the early stages of a development."

The validation is only initial or partial as more extensive case studies and trials are required before full validation of the approach is feasible. However, I would argue that the partial validation achieved is commensurate with the work associated with the thesis development. The latter consisting of the case studies and some industrial use (as reported in section 7.3) – hence it is termed part-validation in the remainder of this section and in Appendix I which provides further details on my contribution.

7.5.1 Develop and extend the Theory

POSE, as it was, was of mainly theoretical interest lacking evidence of its applicability and use on realistic examples that might validate its practical use. Firstly, it lacked any guidance as to which transformation to apply next. This made it unsuitable for real engineering. My first contribution was to extend the theory with
knowledge of how to sequence the transformations applied. This was the topic that was first published in FASE07 [87] and developed in subsequent papers.

Secondly, at that time, there was a theoretical presentation of problem progression along the lines suggested by Professor Jackson, but from an engineering perspective the details were sketchy. My second contribution was to provide detailed guidance as to how to use problem progressions for safety critical engineering – published in the FASE07 [87] paper for informal presentation, and developed in detail in the IWAAPF08 [83] paper.

### 7.5.2 Demonstrate the applicability of the extended Theory

When I started, other than for some toy examples, POSE was not extensively tested through application. My third contribution to knowledge is given by the development of case studies to test POSE's applicability and the applicability of the extensions to POSE that I provided (of course, the process was iterative, and theory extension and application went hand in hand).

There were three main case studies; all realistic, taken from practice and used in the published papers. All were retrospective but demonstrated that POSE could be applied in an engineering context and could find the issues of interest – as discussed in this thesis for the SMS case study.

- **FASE07 [87]** – *DC Case Study in Chapter 4 and Chapter 5.*
- **HASE07 [35]** – *DC Case Study in Chapter 4 and Chapter 5.*
- **SAFECOMP07 [86]** – *SMS Case Study in Chapter 5.*
- **IET07 [85]** – *FAS Case Study in Chapter 6.*
- **IWAAPF08 [83]** – *FAS Case Study in Chapter 6.*
- **SSS08 [88]** – *FAS Case Study in Chapter 6.*
My fourth contribution to knowledge concerned applicability with respect to the Research Aim and included the development of safety analysis technique improvements and the derivation of formal models based on the capabilities provided by extended POSE. This work also included developments to support the formal modelling work.

7.5.3 Partial Validation of the extended theory in an engineering setting

My fifth contribution to knowledge is the improvement of current engineering practice. We have shown how the engineering extended POSE forms a good fit for IPDP, and we have assessed it as improving aspects of IPDP. As IPDP is typical of processes within the industry we consider that there is some evidence that such support can assist processes based on similar safety standards and regulatory frameworks.

In a nutshell, the work has taken a promising theory and extended it to produce an approach suitable for improving the early phases of a safety development process.

7.6 Conclusion

The aim of this work was to demonstrate that POSE, with the extensions introduced in this work, could satisfy two main objectives. The first was that it could address the ten SSSD approach properties identified in section 2.5 and thus be used as an SSSD approach that is appropriate for safety system development. The second objective was that it could be used to improve the early phases of a typical safety development process by mitigating or overcoming issues identified with the requirements engineering aspects of the IPDP. The required enhancements to the IPDP were identified in section 3.4.5 in terms of six issues to be mitigated and four properties to be supported. The discussion points in section 7.1 provide sufficient
evidence to show that POSE and the POSE safety pattern address the ten SSSD approach properties and thus satisfy the first objective. The discussion points in section 7.2, with further supporting evidence from section 7.3, demonstrate that POSE and the POSE safety pattern adequately mitigate the issues and support the properties such that they do improve the early phases of the IPDP, and thus satisfy the second objective. The case study work also demonstrated that POSE could be used for non-formal and formal safety system developments.

The work reported in [32] (see section 2.3.3) to provide enhancements to the Parnas 4-Variable model are compatible with the POSE approach presented in this document. In particular the “outside” enhancements described in [32] map well to the development of the POSE model, which also distinguishes the embedded system represented by the specification $S$, the environment context represented by $W$ and the platform represented by the requirement $R$ through the sequent $W, S \vdash R$ and handles the indirection issue through the non-feasible requirements mechanism.

Inspection of the case study work shows that the POSE and Alloy combination were used successfully in the early phases of the development life cycle, which is consistent with when the “lightweight” PSSA identified in section 2.3.8 should be applied. Therefore, the work presented here could be integrated as the front-end of the FLM/FI approach outlined in [77].

The contribution that this work makes is summarised at the end of each of Chapter 4 (Table 4.5), Chapter 5 (Table 5.6) and Chapter 6 (Table 6.5), and is presented in more detail in section 7.5 and Appendix I. The contribution has three main parts: developing and extending the theory of Problem Orientation; applying the extended theory in a safety critical engineering setting; providing partial validation for the extended theory within that setting. The summary of the work presented in section 7.5, with further detail in Appendix I, is that POSE, as extended by the research work reported in this thesis, does satisfy the research objectives as listed in section 1.2 and thus satisfies the overall goal of:
"Improving the safety process by providing the means of applying safety analysis to the early stages of a development."

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<tr>
<th>Property/Issue</th>
<th>Previous Work</th>
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Table 7.1: Final Evidence Status for POSE

Table 7.1 provides the final evidence status for POSE, it extends Table 6.4 by including additional evidence from the industrial case studies reported in section 7.3 (shown as [Ind._Case] under the "Previous Work" column), and the revised DC case study in Appendix H – where the entries for Simplification, NecessaryP and LateI3 are further corroborated, as described in section 7.1 and section 7.2. This additional support is incorporated into Table 7.1.

In conclusion, this work has demonstrated that POSE and the POSE safety pattern can be used in the early phases of a safety system development to produce a validated specification that can be subjected to a comprehensive safety analysis to show that it satisfies its identified safety properties, and thus forms a viable basis.
for the rest of the development process.
Chapter 8

Future Work

The conclusion presented in Chapter 7 was that this work has demonstrated that POSE and the POSE safety pattern can be successfully used as an SSSD approach for developing safety systems and can also be used in conjunction with an existing safety development process to achieve improvements in the early development phases. The research work has identified a number of areas that would benefit from further investigation and these will now be discussed.

The first area concerns the direct development of the Alloy formal model from the POSE requirements model that is formed by following the pattern. Alloy was selected for this work because it had the required capabilities, is easily available and has an active user community. However it is not the only candidate; as noted earlier in this work, the B-tool [111] has many positive characteristics, not the least being that it is being used in industry to address real safety problems. Further Z [116] is still being used actively for safety development work. Z has the advantage that it relates well to the Praxis SPARK toolset [7] (used with the IPDP) and is also well known to the high integrity development software engineers who use the IPDP. Therefore an important area of future work is to investigate the use of the pattern with other formal techniques used by the safety community to establish if a similar level of synergy can be achieved as that obtained from the POSE/Alloy
combination. A particularly important aspect is whether it is as easy to develop the formal models from the POSE requirements model.

Related to this is the important area of tool support. A prototype POSE tool has been developed to support the POSE transformations and facilitate the development of a POSE requirements model. This could be further developed in a number of important areas to provide: facilities to support the correct use of the pattern could be built into the tool – including the step templates; checks to ensure that the necessary validation text has been entered for each of the problem transformation steps\(^1\) could be included; facilities to produce Alloy code templates to facilitate the derivation of the Alloy model from the POSE requirements model could be developed. The output of the latter would be a text file containing the phenomena and predicate names – the analyst would then add the behavioural information.

Experience of using the POSE safety pattern when feasibility issues are identified, indicates that the location of where to iterate back to follows easily from inspection of the problem transformation graph and that much of the original work can be re-used. This notion was explored in the Warning System FAS case study in Chapter 6, where it was shown that even in the problem transformation steps that needed to be updated (WPS2 and PrePSA) the changes were quite localised and most of the rest of the activities in the step could be read across from the original. The remaining steps could be re-used directly with only the additional phenomena and derived requirement needing to be added. Further work is required to demonstrate that these benefits are general, however the initial indications from this case study and other work are that this is a fruitful area for further research. Therefore in summary, when re-work is required the POSE safety pattern structure allows much of the original design and validation work to be re-used so that only the modified areas require re-work and the problem transformation step structure identifies these

\(^1\)This is likely only to be a syntactic check that text has been entered; but a useful check nevertheless.
areas clearly. This allows change to be enacted with minimal impact, making this iteration efficient.

The discussion in section 7.2.5 noted how the POSE safety pattern and the problem transformation steps it uses provide a structure that can be used to ensure that all the necessary tasks are started and in the correct sequence. That discussion also noted that the concern/claim/evidence mechanism can be used at a more detailed level to ensure that the necessary tasks to support a transformation step are included in the structure used for that step. Moreover, it was noted that each type of problem transformation step (e.g., an Initial Problem step or a PPT step) was associated with certain concerns and that the set of concerns was different for different step types. For example, the PS1, SPS1 and WPS1 are all Initial Problem transformation steps and they have similar concerns. In contrast, PS1 and PS2 are different types of step and they have different concerns. This information could be used to produce problem transformation step templates for each of the steps used in the POSE safety pattern — namely the Initial Problem, Solution Interpretation and Expansion, PPT and PrePSA (used at end of Activity 3) steps. The concerns for each type of step would be included in its template, thus providing a further mechanism for ensuring that all the necessary tasks are completed. Therefore exploring the development of problem transformation step templates would be a useful area for future work.

The safety standards (refer to section 2.2) require a safety case to present the safety argument that the system being developed is safe for entry into service. In Europe, and increasingly further afield [34], GSN is the preferred way for presenting this safety argument (refer to section 2.2.1). Further, the standards expect the safety and development life-cycles to be appropriately integrated (e.g., [125]). The Assurance Based Development (ABD) approach [117, 34] is a means of achieving this integration through the context of the safety argument, and the expectation is that the full benefits of using the POSE safety pattern will be achieved by following
ABD or a similar approach.

A major advantage of integrating the safety case generation with the system development is that issues can be identified and mitigated as they arise [34], minimising the impact on the development schedule. Finding problems later in the life cycle is always more expensive and problematic. Further, this integrated approach is both more efficient and effective [34], since it avoids the waste of producing evidence that does not support an argument (hence it is not needed), and in conjunction with the use of the concept of SALs (Safety Assurance Levels) [132], it provides sufficient evidence to support the safety argumentation.

Determining system context accurately and completely is a major element of ABD [117], and this aspect conforms to Activity 1: Initial Problem Understanding of the POSE safety pattern. Evaluating candidate architectures is also an important part of ABD [34], which identifies seven criteria for determining the suitability of an architecture - including feasibility. This area is covered by Activity 2: Solution Interpretation and Expansion of the pattern, with the feasibility being checked by the pattern PSA. Further, ABD and the POSE safety pattern are complimentary in that they both allow the major effort to be focussed on the key safety areas. One of the problems with applying formal techniques is there is little incentive to use them if their benefits (in supporting the safety argument) are not clear [34]. However, as noted earlier, the Alloy formal model follows directly from the POSE problem model and has the defined goal of providing evidence to support the feasibility of this POSE problem model. Therefore in this context formal methods are efficient to use and effective, because their benefit is to provide direct evidence with respect to the feasibility of a candidate design.

A further advantage of ABD is that it is known to work well with problem oriented approaches, the successful synthesis of an assurance case with Problem Frames being reported in [117], noting that the techniques were complementary as each enhances the other by addressing weaknesses and shortfalls. Further, their
synthesis is accomplished with the artefacts that must be created in the normal course of system development, i.e., no new additional artefacts are required. Hence the process is efficient as well as effective. Initial work with POSE indicates that using the ABD approach with the safety argument in GSN and the pattern used to drive the development could provide an effective, integrated and efficient safety process and would benefit from further research and development.
Appendix A

IPDP applied to the $DC$ Case Study

A.1 Problem Description and Scope

The goal of the first case study is to demonstrate the tasks and activities involved in applying the Company’s IPDP to a typical safety critical development. This case study is based on the development of a Decoy Controller ($DC$), which is part of the defensive aids suite (DAS) on an aircraft. Only the initial phases of the IPDP up to the end of PDR (refer to Figure 3.1) are covered as these phases form the focus for this work. As the case study was developed following IPDP, so the first set of activities were concerned with the IPDP CE phase.

UK military applications make use of DS 00-56, but a similar hierarchy of safety analyses takes place for other safety standards and guidelines (e.g. ARP4761 [109]). For aircraft applications typically the Company provides a Line Replaceable Unit (LRU). The LRU is a system component that slots into one of the major sub-systems on the aircraft. For example, the Decoy Controller ($DC$) LRU introduced in section 4.1.1 below is part of the Defensive Aids Suite (DAS) sub-system on the aircraft. The aircraft manufacturer (and the Company’s customer) is responsible for
the aircraft level safety analysis (equivalent to the Aircraft FHA in ARP4761) and for the major sub-system safety analysis (equivalent to the System FHA). These FHA analyses identify and allocate the safety targets that the individual LRUs that form the sub-system must satisfy. For example, for the DAS sub-system, the customer identifies the safety targets \( H1 \) and \( H2 \) that the \( DC \) LRU must satisfy. These targets are flowed down to the Company as the safety requirement that the \( DC \) must comply with. Thus the early safety analysis tasks undertaken in IPDP that form the major focus of this work, correspond to the PSSA phase of ARP4761.

### A.2 CE Phase for the DC Case Study

The first activity in CE involves gaining an understanding of the system context, which includes understanding the system environment, identifying what the main components of the system environment are, what they do and how they interact with each other. The requirement of the proposed system is then elicited and the safety requirement analysed with respect to the system context. All this information is then collated, which allows a candidate conceptual design to be formed. The conceptual design for the \( DC \) consists of the block diagram shown in Figure A.1 together with the ensuing descriptive text, informed by the requirement (also presented below).

![Decoy Controller (DC) Block Diagram](image)

Figure A.1: Decoy Controller (DC) Block Diagram

The role of the \textit{Decoy Controller (DC)} is to control the release of decoy flares providing defence against incoming missile attack. The \( DC \) interfaces with the \textit{De-
fence System (DS) computer, which is responsible for controlling and orchestrating all the defensive aids on the aircraft. The DS and other domains (see Figure A.1) already exist, and the task is to design the DC.

The conceptual design was discussed with the Customer and the initial functional requirement was revised and agreed accordingly.

The Customer FHA work (at the aircraft and major sub-system level) identified two safety hazards which were allocated to the DC, concerned with the inadvertent firing of the decoy flares, as follows:

H1 Inadvertent firing of decoy flare on ground. Safety Target: safety critical, \(10^{-7}\) fpfh\(^1\); and

H2 Inadvertent firing of decoy flare in air. Safety Target: safety critical, \(10^{-7}\) fpfh.

Further preliminary safety analysis work was conducted using the conceptual model and the hazards H1 and H2 as a basis. The model was explored to ascertain if any other hazards or safety issues might be relevant. This involved using the domain knowledge of experienced engineers, comparison with similar systems and a brainstorming session which was used to bring this knowledge and experience together. The conclusion of this work was that H1 and H2 were the pertinent hazards for this system as represented by the conceptual model. It should be noted that the conceptual model is high level and abstract. It is sufficient for generating a hazard list, but not detailed enough to discharge the obligations raised by the remaining IPDP preliminary hazard analysis tasks. These require the more detailed models generated by the later phases of the IPDP. This means that there is always a risk that further safety issues may be identified later in the life cycle, with all the attendant cost and schedule impact that this might have. These hazards were then collected together to form the DC system safety requirement RS. As a result of this work the customer requirement RDC for the DC can be expressed as follows:

\(^1\text{fpfh is 'failures per flight hour.'}\)
RA The DS shall command which flare is selected for release by using a field in the con message it transmits.

RB The DS shall command the DC to issue a fire command in its con message. This shall be the only way in which a flare can be released.

RC The DC shall cause a flare to be released by issuing a fire command to the DU, which will fire the selected flare.

RD The DC shall only issue a fire command if its interlocks are satisfied, i.e. aircraft is in air, the SP safety pin has been removed and the Pilot has issued an allow a release command.

RS The DC shall mitigate H1 & H2 (Target: safety critical 10⁻⁷ fpfh).

Therefore, the overall requirement is \( RDC = RA \land RB \land RC \land RD \land RS \)

A complete statement of R should also include requirements that cover space, weight, environmental performance, interfaces and so on, but these are beyond the scope of this work. The SRR validated the high level system and safety requirement detailed above as being suitable for the next phase of the development – Dem/Val.

A.3 Dem/Val Phase for the DC Case Study

The initial part of the Dem/Val phase involves analysis and modelling to gain a better understanding of the system and its environment. This includes more detailed analysis of the requirement and an analysis of the safety requirement. A summary of this work for the DC case study now follows. The hazards H1 and H2 have both systematic (safety related) and probabilistic components. The initial safety analysis work identified that to counter these hazards the architectural design of the defensive aids system should contain a number of safety interlocks in the DC to provide safety protection. These are: an input from the pilot indicating whether
the release should be allowed; an input indicating whether the aircraft is in the air; and an input indicating whether the safety pin, present when the aircraft is on the ground, is in place. The expected behaviour is that flare dispensing should be inhibited if any of the following conditions hold: a) the pilot disallows flares; b) the aircraft is not in the air; or c) the safety pin has not been removed. It transpires that the interlocks b) and c) provide extra assurance for hazard H1 but not for H2. Therefore, the safety task is to demonstrate that H2 can be satisfied using just interlock a), with the knowledge that if H2 can be satisfied, then so can H1. Note, flare selection and timing are not safety related, it is only applying an inadvertent fire command to any flare that is regarded as a safety issue.

The analysis and modelling work, reported in the previous paragraph, is collated to produce a system theory of operation document that is also descriptive text. This is validated with the customer before embarking on the next set of tasks which involve more detailed architectural analysis and the development of the sub-system theory of operation. The functional part of the sub-system theory of operation task is presented below for the DC system.

Sys The Decoy Controller (DC) system consists of the DC, the Pilot selection switch (Pilot), the Dispenser Unit (DU), the Aircraft Status (AS), the Safety Pin status (SPS) and the Defence System (DS) as shown in Figure A.1.

Pilot The DC receives an input from the Pilot, which is a boolean switch selection. When the pilot selects the switch to on (Pilot = on) this means that the dispensing of flares is allowed by the DU under the control of the DC. If the pilot selects the switch to off (Pilot = off) then the DC will inhibit the dispensing of flares by the DU.

AS The DC receives an input from the Aircraft Status which is a boolean input that defines if the aircraft is in the air (AS = on) or the aircraft is on the ground (AS = off).
The DC receives an input concerning the status of the Safety Pin which is a boolean input. If the Safety Pin is in place (SP = on) then it is not possible for DU to dispense flares. The Safety Pin has to be removed (SP = off) before the DU can dispense flares.

The DC receives an input message con from the DS which contains the flare selection and whether to release the flare or not. The message is sent at a rate of 20 messages per second. The DS is responsible for controlling and orchestrating all the defensive aids on the aircraft.

The DU receives a fire and a sel input from the DC. The sel input selects which flare type to release. The fire input commands the DU to release a flare if active (i.e. fire discrete set to on).

The DC will stop the DU from dispensing flares by setting the fire discrete to off whenever its inputs Pilot = off or AS = off or SP = on. The DC will select which flare is to be dispensed by setting the sel input to the DU, the value of sel is derived from the con message received from the DS. The DC will command the DU to release a flare by setting its fire discrete to on as long as the other inputs to the DC support this.

This sub-system theory of operation and analysis work was used as the basis for producing the Equipment Specifications (ES), the final Interface Requirements Specification (IRS) and the initial allocation of requirements (ASR) to software and/or hardware. The requirement was refined from RDC to Rdc by this work. The requirement Rdc is presented below.

The DS shall command which flare is selected using a field in its con message issued to the DC. The DC shall obtain the selected flare information from this field in the con message, and use it in its sel message to the DU to control the flare selection in the DU.
Rb The DS shall command the DC to issue a fire command in its con message. This shall be the only way in which a flare can be released.

Rc The DC shall cause a flare to be released by issuing a fire command to the DU, which will fire the selected flare.

Rd The DC shall only issue a fire command if its interlocks are satisfied, i.e. aircraft is in air (AS = on), SP safety pin has been removed (SP = off) and Pilot has issued an allow a release command (Pilot = on).

RS The DC shall mitigate H1 & H2 (Target: safety critical 10^-7 fpfh).

Therefore, the overall requirement is Rdc = Ra ∧ Rb ∧ Rc ∧ Rd ∧ RS.

One of the IPDP safety tasks requires that a safety analysis is applied to the combination of the sub-system theory of operation and the system block diagram shown in Figure A.1. The results of this analysis being recorded in the Preliminary Hazard Analysis Report (PHAR) – which has a document structure that was introduced to improve the safety management in IPDP. The abstract nature of the specification (and missing timing details etc.) indicate that an FFA is the most appropriate form of analysis to use in this case (design instability and not enough information to support a HAZOPS). The main FFA guide words [90] are as follows:

- Function not provided when required;
- Function provided when not intended;
- Function provided incorrectly.

These were applied to each of the descriptive blocks in turn. For example, consider the descriptive text for the DS given above. This description has three parts as shown below:

- The DC receives an input message con from the DS which contains the flare selection
Table A.1: FFA of the DS to DC Serial Link

<table>
<thead>
<tr>
<th>FFA Guide Word</th>
<th>Potential Failure Mode</th>
</tr>
</thead>
<tbody>
<tr>
<td>Select: Function not provided</td>
<td>Wrong flare type selected for release</td>
</tr>
<tr>
<td>Select: Function when not intended</td>
<td>Wrong flare type selected for release</td>
</tr>
<tr>
<td>Select: Function incorrect</td>
<td>Wrong flare type selected for release</td>
</tr>
<tr>
<td>Fire: Function not provided</td>
<td>Flare not released when required</td>
</tr>
<tr>
<td>Fire: Function when not intended</td>
<td>Flare release too early or late</td>
</tr>
<tr>
<td>Fire: Function incorrect</td>
<td>Flare released inadvertently</td>
</tr>
<tr>
<td>Rate: Function not provided</td>
<td>No flare release possible</td>
</tr>
<tr>
<td>Rate: Function when not intended</td>
<td>Flare release too early or late</td>
</tr>
<tr>
<td>Rate: Function incorrect</td>
<td>Flare release too early or late</td>
</tr>
</tbody>
</table>

• and whether to release the flare or not.

• The message is sent at a rate of 20 messages per second.

Applying the guide words to these three terms (Select, Fire and Rate) yields Table A.1.

The FFA from Table A.1 identified that a function incorrect on the Fire message could result in “Flare released inadvertently” which corresponds to the identified hazards H1 and H2. The function incorrect could be caused by a systematic problem in the DS or by errors occurring during the transmission of the con message. The interface between the DS and the DC was not fully explored during the initial IPDP work and this resulted in only a simple parity check mechanism being proposed for the serial link. However, serial link integrity issues identified on another Company project resulted in a specific serial link safety investigation being applied to the DC system. This investigated the behaviour of the DS, its environment and the serial link in more depth, and identified that a much stronger cyclic redundancy check (CRC) algorithm was required to obtain the desired level of integrity. This information was associated with the DS environment, but had been omitted from the FFA work. It was also noted that a HAZOPS (due to the serial link expertise contained in the HAZOPS team) rather than a FFA (produced by a single safety engineer) would have identified the serial link issue earlier.
All these artefacts produced during the Dem/Val phase were checked as part of the IPDP SDR checkpoint gate review. This included confirmation that each requirement had an appropriate verification method assigned to it, and checking that any issues identified by the safety analysis had been investigated and resolved.

A related issue is that IPDP allows projects to “tailor out” (i.e. remove) tasks that are not thought to be directly relevant. In the past over-zealous (and optimistic!) project managers have tailored out some of the safety analysis tasks. The rationale for this was the misunderstanding that there were already other safety tasks, without realising that each IPDP safety task has a specific purpose. This was another factor in creating the PHAR to manage the early safety analysis activities and provide a framework to ensure that all the necessary analysis work was undertaken. As noted above, this does ensure that the necessary safety analysis work is undertaken, but it does not ensure its technical quality, completeness or consistency.

A.4 EMD: Preliminary Design Phase for the DC Case Study

The activities and tasks associated with the EMD Preliminary Design Phase, and how it makes use of the validated outputs from the SDR (namely the ES, ISR and ASR documents) are described in section 3.4. The DC system was put through this process and as an example of the work involved, the detailed architectural analysis work is summarised below.

The architectural analysis identified an expansion of the DC into the three sub-components shown in Fig. A.2. The DC system architecture consists of three components, the Safety Controller (SC), the Decoy Micro-controller (DM, shown further expanded in Fig. A.2(b)) and the Interlock Input (II), as shown in Fig. A.2(a). This choice of architecture was selected because it was based on an existing prototype
that was known to be capable of satisfying the functional requirement. Further, it is typical of industrial safety design strategies that attempt to minimise the number and extent of the safety related functions by localising them to simple, distinct blocks.

Briefly, component II collects together the interlock inputs and passes their status to SC (int). Component DM is a microcontroller used to decode messages from the Defence System (con), and when appropriate to issue the fire command request to the SC (via fire?). The Message Buffer (MB, in Fig. A.2(b)) holds the received control message con from the DS. The micro-controller uP decodes this message to extract: a) the fire command request status (fire?) sent to the SC, and b) the selected flare type (sel) sent to the DU. The SC, the component to be designed, is intended as a simple block that handles the safety critical elements of the interlocking. SC is, therefore, expected to relate an active fire? request to the DU (through phenomenon fire) if the interlocks are satisfied.

The introduction of the DC system architecture affects the high level Customer requirement Rdc and this needs to be refined such that terms in DC are replaced by terms in DM, SC and II as appropriate. This is a non-trivial transformation and is carefully checked by independent expert review. The result is a new requirement statement

\[ R' = R'a \land R'b \land R'c \land R'd \land R'S \]

in which R'a is Ra with DC replaced by DM; similarly for R'c and R'd, mutandis
mutatis. The most significant change occurs for R’b (changes in bold):

R’b The DS shall command the DM to issue a fire? command in its con message.

The DM will request the SC to send the fire command. This shall be the only way in which a flare can be released.

During Preliminary Design a HAZOPS is conducted to confirm the system model is a suitable basis for further development in terms of its ability to satisfy the identified safety requirement placed on it. At this point the required supporting design information is available and the design is more stable – so HAZOPS is cost-effective to apply at this time.
Appendix B

More PPTs Applied to the DC Case Study

B.1 PPT Applied to the AS Domain

\[ PS4: \text{Application of the PPT for AS Domain Removal to problem} \]

\[ P_{\text{Red1}} \text{ to form } P_{\text{Red2}} \]

\text{JUSTIFICATION J:} \quad \text{The AS domain removal is based on the process given in section 5.1.2. The AS domain is adjacent to the requirement R1. The AS domain control phenomena \textit{air} maps directly to its output behaviour phenomena which is also \textit{air}. Therefore \textit{air} will appear in the reference part of the requirement phenomena both before and after the transformation. The requirement R1 is as detailed in step PS3 on page 115. Inspection of R1 indicates that only R1d involves a reference to \textit{air}. Consider the transformation from R1d into R2d which involves the phenomena \textit{air} as noted above.}

R1d : \text{aircraft is in air (air = yes).}

R2d : II observes input \textit{air = yes}.  

\text{AS Domain Description:} \quad \text{The in-air indicator is obtained from the weight on wheels}
and landing gear up indications: if the landing gear is up and there is no weight on the wheels then the aircraft is assumed to be in the air. The landing gear is detected as being up by a number of sensor switches. The switches use a multi-pole arrangement of appropriately selected “Normally open/Normally closed” contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins. The setting of the in-air indicator is determined by the AS domain and is output using the phenomena air, where air = yes means the aircraft is in the air, whilst air = no means the aircraft is on the ground.

The \( A_2 = \text{Assumption}(\text{air, air}) \) is given by the AS Domain Description. Inspection of \( R2d \) in conjunction with the AS Domain Description shows they imply \( R1d \) as required.

Therefore the PPT application transforms the problem from \( P_{Red1} \) into \( P_{Red2} \), and \( R1 \) is transformed into \( R2 \) as follows:

\( R2a \) The DS shall command which flare is selected using a field in its \textit{con} message issued to the DM. The DM shall obtain the selected flare information from this field in the \textit{con} message, and use it in its \textit{sel} message to the DU to control the flare selection in the DU.

\( R2b \) The DS shall command the DM to issue a \textit{fire?} command in its \textit{con} message.

The DM will request the SC to send the \textit{fire} command. This shall be the only way in which a flare can be released.

\( R2c \) The SC shall cause a flare to be released by issuing a \textit{fire} command to the DU, which will fire the selected flare.

\( R2d \) The SC shall only issue a \textit{fire} command if its interlocks, represented by \textit{int}, are satisfied, i.e. \( II \text{ observes input } \text{air} = \text{yes} \), \( SP \text{ safety pin has been removed } (\text{out} = \text{yes}) \) and \( II \text{ observes pilot input of } \text{ok} = \text{yes} \).

\( RS \) The DC shall mitigate \( H1 \) & \( H2 \) (Target: safety critical \( 10^{-7} \) fpfh).

The constraint being relied upon is that \( \text{air} = \text{yes} \) means the aircraft is in the air – see claim below.
The domain AS is no longer referenced in the model and can be removed.

The software problem is transformed to $P_{\text{Red2}}$:

$$P_{\text{Red2}} : DS(\text{con})_{\text{con}}, DU(\text{fire, sel})_{\text{fire, sel}}, SP(\text{out})_{\text{out}}, II(\text{ok})_{\text{ok, air, out}}, DM_{\text{con, fire}}, SC_{\text{int, fire}} \vdash R^2_{\text{con, out, air, ok, fire, sel}} \land A_1 \land A_2$$

CONCERNS: The control input phenomena air is the same as the domain behaviour output phenomena for this reference-type problem progression. This can be a symptom of over-specification.

CLAIM: The AS intention with respect to interlocking flare release is represented by the phenomena air, so no over-specification requirement issue arises.

ARGUMENT & EVIDENCE: This is covered by the AS Domain Description and the validation as described above.

CLAIM: The in-air status of the aircraft is represented by the phenomena air.

ARGUMENT & EVIDENCE: This is covered by the AS Domain Description.

PHENOMENA: None

Note that often the useful behaviour assumptions are omitted from the Problem description, but they are always a necessary part of the reduction process.

B.2 PPT Applied to the SP Domain

$PS5$: Application of the PPT for SP Domain Removal to problem $P_{\text{Red2}}$ to form $P_{\text{Red3}}$

JUSTIFICATION J: The SP domain removal is based on the process given in section 237
5.1.2. The SP domain is adjacent to the requirement R2. The SP domain control phenomena out maps directly to its output behaviour phenomena which is also out. Therefore out will appear in the reference part of the requirement phenomena both before and after the transformation. The requirement R2 is as detailed in step PS4 on page 235. Inspection of R2 indicates that only R2d involves a reference to out.

Consider the transformation from R2d into R3d which involves the phenomena out as noted above.

R2d : SP safety pin has been removed (out = yes).

R3d : II observes input out = yes.

SP Domain Description : The safety pin status is obtained from sensor switches. The switches use a multi-pole arrangement of appropriately selected “Normally open/Normally closed” contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins. The setting of the safety pin status is determined by the SP domain and is output using the phenomena out, where out = yes means the safety pin has been removed, whilst out = no means the safety pin is present (and inhibiting flare release).

The A3 = Assumption(out, out) is given by the SP Domain Description. Inspection of R3d in conjunction with the SP Domain Description shows they imply R2d as required.

Therefore the PPT application transforms the problem from PRed2 into PRed3, and R2 is transformed into R3 as follows:

R3a The DS shall command which flare is selected using a field in its con message issued to the DM. The DM shall obtain the selected flare information from this field in the con message, and use it in its sel message to the DU to control the flare selection in the DU.

R3b The DS shall command the DM to issue a fire? command in its con message. The DM will request the SC to send the fire command. This shall be the only way in which a flare can be released.
R3c The SC shall cause a flare to be released by issuing a fire command to the DU, which will fire the selected flare.

R3d The SC shall only issue a fire command if its interlocks, represented by \( \text{int} \), are satisfied, i.e. \( \text{II} \) observes input \( \text{air} = \text{yes} \), \( \text{II} \) observes input \( \text{out} = \text{yes} \) and \( \text{II} \) observes pilot input of \( \text{ok} = \text{yes} \).

RS The DC shall mitigate \( \text{H1} \& \text{H2} \) (Target: safety critical \( 10^{-7} \) fpfh).

The constraint being relied upon is that \( \text{out} = \text{yes} \) means the safety pin has been removed – see claim below.

The domain SP is no longer referenced in the model and can be removed.

The software problem is transformed to \( P_{Red3} \):

\[
P_{Red3} : \quad DS, DU(\text{fire, sel})_{\text{fire}, \text{sel}}, \\
\text{II}(\text{ok})_{\text{ok, air, out}} \quad DM_{\text{con}, \text{fire}}^\text{sel}, \quad SC_{\text{int}, \text{fire}}^\text{fire} \quad \dashv \quad R_{\text{con, out, air, ok}}^\text{fire, sel} \wedge A_1 \wedge A_2 \wedge A_3
\]

CONCERNS: The control input phenomena \( \text{out} \) is the same as the domain behaviour output phenomena for this reference-type problem progression. This can be a symptom of over-specification.

CLAIM: The SP intention with respect to interlocking flare release is represented by the phenomena \( \text{out} \), so no over-specification requirement issue arises.

ARGUMENT & EVIDENCE: This is covered by the SP Domain Description and the validation as described above.

CLAIM: The safety pin status is represented by the phenomena \( \text{out} \).

ARGUMENT & EVIDENCE: This is covered by the SP Domain Description.

PHENOMENA: None
B.3 PPT Applied to the DS Domain

**PS6: Application of the PPT for DS Domain Removal to problem**

\[ P_{\text{Red3}} \text{ to form } P_{\text{Red}} \]

**JUSTIFICATION J:** The DS domain removal is based on the process given in section 5.1.2. The DS domain is adjacent to the requirement R3. The DS domain control phenomena con maps directly to its output behaviour phenomena which is also con. Therefore con will appear in the reference part of the requirement phenomena both before and after the transformation. The requirement R3 is as detailed in step PS5 on page 237. Inspection of R3 indicates that both R3a and R3b involve references to con.

Consider the transformation from R3a into R4a which involves the phenomena con as noted above.

**R3a:** The DS shall command which flare is selected using a field in its con message.

**R4a:** The DM shall decide which flare to select by observing a field in the con message it receives.

A similar arrangement can be constructed for flare release for covering the transformation from R3b into R4b.

**DS Domain Description:** The DS monitors many systems (e.g. early warning radar, GPS/INS positioning) to determine any threats to the aircraft. These systems are not pertinent to this problem so are abstracted through the statement:

The DS is the defensive aids suite controller function which selects the flare type for release and if and when a flare is released in response to any threats it determines from its monitoring functions. The DS achieves this by formatting the flare selection and fire commands into its con message which it transmits to the DM.

The \( A_4 = \text{Assumption}(\text{con}, \text{con}) \) is given by the DS Domain Description. Inspection
of R4a in conjunction with the DS Domain Description shows they imply R3a as required.

The DM knows the structure of the con message it receives from the DS, so it can decode the con message to determine the flare selection (sei) and fire (fire) components. Therefore the PPT application transforms the problem from $P_{Red3}$ into $P_{Red}$, and R3 is transformed into R4 as follows:

R4a The DM shall decide which flare to select by observing a field in the con message it receives. The DM shall obtain the selected flare information from this field in the con message, and use it in its sel message to the DU to control the flare selection in the DU.

R4b The DM shall observe the con message it receives and issue a fire? command if commanded. The DM will request the SC to send the fire command. This shall be the only way in which a flare can be released.

R4c The SC shall cause a flare to be released by issuing a fire command to the DU, which will fire the selected flare.

R4d The SC shall only issue a fire command if its interlocks, represented by int, are satisfied, i.e. II observes input air = yes, II observes input out = yes and II observes pilot input of ok = yes.

R5 The DC shall mitigate H1 & H2 (Target: safety critical $10^{-7}$ fpfh).

The domain DS is no longer referenced in the model and can be removed.

The REQUIREMENTS INTERPRETATION transformation associated with the PPT establishes that con is equivalent to (fire?, sel), this information is used in the software problem $P_{Red}$:

$$P_{Red}: \quad DU(fire, sel)_{fire, sel}, \quad II(ok)^{int}_{ok, air, out},$$
$$DM_{con, fire}, \quad SC_{fire}, \quad S_{\text{int, fire}} \quad \vdash \quad R_{4\text{fire, sel}}_{con, out, air, ok} \land A_1 \land A_2 \land A_3 \land A_4$$
CLAIM: The flare selection and flare fire commands are represented by the phenomena con.

ARGUMENT & EVIDENCE: This is covered by the DS Domain Description.

The following directly support the analysis tasks:

Note1: R4a and R4b relate the requirement phenomena con to the causal chain phenomena fire? and sel.

Note2: R4d relates the requirement phenomena air, out and ok to the causal chain phenomena int.

CLAIM: The chosen solution architecture does not prevent the satisfaction of R. This claim does not hold.

ARGUMENT & EVIDENCE: PSA (FFA, HAZOPS and FTA) was again applied to each architectural component in turn. The results are presented in section 5.2.2 and show that the current design does not satisfy the safety requirement.

PHENOMENA: None
Appendix C

High Integrity IPDP Safety Process

The existing successful Z-based safety critical development process has the following characteristics. Briefly, system safety properties are formally captured in Z and transcribed (rather than refined) into a detailed Z design specification, against which formal code proof using SPARK [7] is performed. An important validation step is the proof of conformance of the Z design specification against the formal Z safety properties. This process provides a formal path from the high level safety properties down to the code that implements them. However, validation occurs well into the design process and it has uncovered anomalies with the Z safety properties. That is, this safety critical development approach has uncovered anomalies in the Z safety properties rather late in the IPDP than is optimal. The anomalies uncovered ranged from a misinterpretation of the actual physical sequence (a modelling error), through to contradictory requirements. One of the aims of this case study is to show that, using the POSE/Alloy combination, those anomalies could have been identified and resolved earlier in the development life cycle. The ultimate goal of this work is to enhance and evolve what is already a successful safety critical development process, not to change to some novel process of unknown pedigree.
Appendix D

POSE Steps for the SMS Case Study

One of the major initial tasks in IPDP CE phase is to fully understand the problem context. The initial requirement is introduced into the problem during the CE phase, and developed through into the early part of Dem/Val. The initial system architecture is introduced during Dem/Val. The information collected through this work is collated into the step SPS1 shown below.

<table>
<thead>
<tr>
<th>SPS1: Application of Initial Problem understanding to problem</th>
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<tbody>
<tr>
<td>$P_{\text{null}}$</td>
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</tbody>
</table>

**JUSTIFICATION $J_1$:** The justifications for the initial POSE transformations are as follows:

[Domain Interpretation, $J_a$] The analysis of the information sources identified that the environment consisted of the SMS, the S&RE $^1$ and the Pilot and that their interactions were as discussed above in section 5.5.1.

$^1$S&RE: Suspension and Release Equipment. Holds the stores on the aircraft until a release or jettison is enacted.
[Requirement Interpretation, \( J_b \)] The identified requirement was based on information provided by the customer and was validated through reviews, email correspondence and meetings. It is presented as \( R (Ra \text{ to } Ri) \) below.

[Solution Interpretation, \( J_c \)] This is a typical representation of an SMS.

The domains and their relevant properties are summarised in \( P_{\text{Initial}} \) presented below, where the justification for this initial software problem is \( J_1 = J_a \wedge J_b \wedge J_c \).

**PHENOMENA:** Phenomena and their control and sharing are as follows: The Pilot controls SJ in the SMS using three phenomena: (a) \( p_{\text{mode}} \): a selection of SJ mode (Off, Ship or Station); (b) \( p_{\text{sel}} \): a set of stations selected for jettison if Station mode selected; (c) \( p_{\text{jet}} \): an SJ button that initiates jettison and must be held on for the duration of the jettison sequence.

The SMS controls the S&RE using the phenomena \( jetv \), a vector of station positions to which jettison is to be applied. The SMS also takes in the aircraft in air status using the phenomena \( \text{InAir} \).

The referenced requirement phenomena, \( \text{ref} \), are concerned with the Pilots intention to select the SJ mode (\( p_{\text{mode}} \)), the stations for SJ (\( p_{\text{sel}} \)) and requesting jettison (\( p_{\text{jet}} \)). The requirement also references the \( \text{InAir} \) status. The constrained requirement phenomena, \( \text{cons} \), are concerned with selecting which S&RE stations are to be jettisoned (\( jet_{\text{stat}} \)).

Where: \( \text{cons} = \{jet_{\text{stat}}\} \) and \( \text{ref} = \{p_{\text{mode}}, p_{\text{sel}}, p_{\text{jet}}\} \)

The initial software problem is as follows:

\[
P_{\text{Initial}} : \quad S&RE(jet_{\text{stat}})_{jetv}, \quad \text{Pilot}(p_{\text{mode}}, p_{\text{sel}}, p_{\text{jet}})_{smode, sstat, sj}, \quad \text{SMS}(\text{InAir})_{jetv} \quad \Rightarrow \quad jet_{\text{stat}}_{p_{\text{mode}}, p_{\text{sel}}, p_{\text{jet}}, \text{InAir}}^p
\]

A PF problem diagram representation of \( P_{\text{Initial}} \) is shown in Figure D.1.
The high level SMS requirement, $R$, is as follows:

**Ra** The SMS shall ensure the safe release of stores from the S&RE when commanded by the Pilot using $p_{\text{mode}}$, $p_{\text{sel}}$ and $p_{\text{jet}}$.

**Rb** The SMS shall have a Selective Jettison (SJ) facility which shall allow the Pilot, using $p_{\text{mode}}$, to jettison all of the stores (Ship mode) or the jettison of selected stores (Station mode) from the S&RE.

**Rc** The SMS shall allow the Pilot to select each of the six S&RE stations for SJ using $p_{\text{sel}}$. In Station SJ mode, a station must be selected before it can be jettisoned.

**Rd** The SMS shall have an In Air lamp, which will be lit if the aircraft is in the air. SJ is only allowed if the aircraft is in the air.

**Re** The SMS shall have a SJ button to allow the Pilot to initiate the jettison using $p_{\text{jet}}$, and it must remain pressed for the duration of the jettison sequence. The following must hold prior to initiating the SJ:

1. SJ mode selected (Ship or Station).
2. Aircraft is in the air.
3. If Station mode, the appropriate stations are selected in the SMS.

**Rf** The SMS shall control the selection and jettison of stores from the S&RE, by providing the conditioned power and drive signals to correctly drive and control the S&RE.

**Rg** The SMS shall implement a Balance Algorithm which can remove items from an SJ package to ensure aircraft roll moments are contained within safe limits.

**Rh** It shall be possible to SJ a store from a single station without regard to the aircraft balance algorithm calculation.

**Ri** The SJ release sequence will be Out stores first, then Mid and then In.

**Claim:** The interpretations are well-founded

**Argument & Evidence:** The choice of domains follows from the aircraft level safety analysis and the required choice of interlocks. The S&RE, is an existing component.
of the avionics system, with well-known, validated properties. The Pilot is trained to follow protocols rigorously. The SMS is to be designed, but the Company are domain experts for this type of system.

The customer functional requirement (Ra to Ri) was provided as an input to the developer team, and was validated with the customer.

CLAIM: The architecture is feasible

ARGUMENT & EVIDENCE: The selected overall system architecture has been used successfully on similar SMS safety systems.

CLAIM: Sound judgement followed

ARGUMENT & EVIDENCE: Development based on IPDP used successfully on many previous developments and enhanced with POSE to mitigate some known IPDP issues. Therefore it follows normal and not radical design concepts as defined in [131].

CLAIM: The S&RE component sub-systems have sufficient reliability to allow the overall system to satisfy its objectives

ARGUMENT & EVIDENCE: The reliability claims are justifiable since the S&RE components are part of an established successful design, but are not included in detail for reasons of brevity.

Figure D.1: SMS Initial Problem, P_initial

The next stage is to investigate candidate system architectures. The most promising candidate is shown in step SPS2 presented below.
SPS2: Application of Solution Interpretation and Expansion to problem $P_{\text{Initial}}$

JUSTIFICATION $J_2$: The expanded SMS solution architecture consists of three types of domain one of Safety Monitor ($SM$), six of Store Unit ($SU$) and one of Selective Jettison Panel ($SP$).

The $SP$ shown in Figure 5.7 indicates the aircraft has six release stations—corresponding to Outer, Middle and Inner positions on each of the Starboard and Port wings. The pilot ($Pilot$) controls store jettison via the $SP$, using (a) six selection switches, one for each station, (b) a three position $SJ$ mode selection switch, (c) an $InAir$ indicator lamp and (d) the $SJ$ button which initiates the jettison. The $InAir$ indicator is fed from another system (not developed further here).

Each $SU$ is connected to one of the six $S&RE$ units and provides the conditioned power signal to release the store attached to the $S&RE$. Each $SU$ is controlled by the $SM$.

The $SM$ is the control function for the $SMS$. It reads in the $SP$ status for mode, selected stations, the $SJ$ initiation button, and the $InAir$ status.

The justification for this (architecture) solution expansion transformation is that this system architecture has been successfully used on a number of other $SMS$ developments and is known to be capable of satisfying the functional requirement.

PHENOMENA: The new phenomena introduced by the architecture are:

- $invec$ – Status of the $SJ$ mode, station selection, $InAir$ and $SJ$ button inputs
- $outv$ – A vector of discrete release/jettison control signals, one to each of the six $SUs$.

The expanded software problem is as follows:
A PF problem diagram representation of $P_{Exp}$ is shown in Figure D.2.

The transformed requirement $R'$ is similar to $R$ apart from the changes introduced by expanding the domains from SMS to SP, SM and SU. For example all references to the Pilot in $R$ controlling the SMS are replaced with references to SP, as the SP is the means by which the Pilot interfaces to the stores management system. The biggest change is to $R'_f$ where SMS is replaced by references to SM and its control of the SUs.

The updated requirement $R'$ is as follows:

R'a The SM shall ensure the safe release of stores from the S&RE when commanded by the Pilot using $p_{-mode}$, $p_{-sel}$ and $p_{-jet}$.

R'b The SM shall have a Selective Jettison (SJ) facility which shall allow the Pilot, using $p_{-mode}$, to jettison all of the stores (Ship mode) or the jettison of selected stores (Station mode) from the S&RE.

R'c The SP shall allow the Pilot to select each of the six S&RE stations for SJ using $p_{-sel}$. In Station SJ mode, a station must be selected before it can be jettisoned.

R'd The SP shall have an In Air lamp, which will be lit if the aircraft is in the air. SJ is only allowed if the aircraft is in the air.

R'e The SP shall have a SJ button to allow the Pilot to initiate the jettison using $p_{-jet}$, and it must remain pressed for the duration of the jettison sequence. The following must hold prior to initiating the SJ:

1. SJ mode selected (Ship or Station).
2. Aircraft is in the air.
3. If Station mode, the appropriate stations are selected on the SP.
R'f The SM shall control the selection and jettison of stores from the S&RE, by controlling the SU's to provide conditioned power and drive signals to correctly drive and control the S&RE's.

R'g The SM shall implement a Balance Algorithm which can remove items from an SJ package to ensure aircraft roll moments are contained within safe limits.

R'h It shall be possible to SJ a store from a single station without regard to the aircraft balance algorithm calculation.

R'i The SJ release sequence will be Out stores first, then Mid and then In.

CLAIM: Justification for selection of the solution architecture

ARGUMENT & EVIDENCE: This system architecture has been successfully used on a number of other SMS developments and is known to be capable of satisfying the functional requirement.

CLAIM: The choice of candidate solution architecture exhibits sound safety engineering judgement

ARGUMENT & EVIDENCE: The architecture is chosen to maximise integrity. The jettison status information from the SP to the SM is transferred by the serial link message invec which includes a cyclic redundancy check (CRC) for error detection. The control information from the SM to the SU's is transferred as a vector of discrete signals outv (one for each station).

CLAIM: SJ push-button switch on the SP is reliable

ARGUMENT & EVIDENCE: The SJ push-button switch indication is obtained from a number of sensor switches. The switches use a multi-pole arrangement of appropriately selected "Normally open/Normally closed" contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins.
Similar reliability claims can be made for the mode SJ mode switch and the station selection switches on the SP – not shown for brevity.

CLAIM: The chosen solution architecture does not prevent the satisfaction of R. This claim is not yet supported - deferred until PSA after PPT.

Figure D.2: SMS Expanded Problem, $P_{Exp}$

First application of the PPT to simplify $P_{Exp}$ by removing the Pilot domain.

SPS3: Application of the PPT for Pilot Domain Removal to problem $P_{Exp}$ to form $P_{Red1}$

INCLUDES: None

JUSTIFICATION J: The Pilot domain removal is based on the process given in section 5.1.2. The Pilot domain is adjacent to the requirement $R'$. The Pilot domain is a reference-type. The Pilot domain effect is to control the jettison function using the mode, station selection and SJ button on the SP. In PF terms the Pilot is a biddable domain. That is, although the Pilot is trained to follow protocol rigorously, there is a chance a mistake could be made and any analysis has to take due account of this – this information is stored as part of the justification for the removal.

Inspection of $R'$ in SPS2 indicates that $R'a$, $R'b$, $R'c$, and $R'e$ involve a reference to Pilot. These will be updated in $R1$. 

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The Pilot effect is controlling the SP using the requirement phenomena \( p\text{-mode} \), \( p\text{-sel} \) and \( p\text{-jet} \), in the causal chain these respectively relate directly to the phenomena \( smode, sstat, ssj \).

Consider the transformation from \( R'a \) involving "commanded by the Pilot". Commanded by the Pilot corresponds to appropriately setting the phenomena \( p\text{-mode}, p\text{-sel}, \) and \( p\text{-jet} \) on the SP. This is achieved through the phenomena \( smode, sstat \) and \( ssj \). Therefore \( R1a \) has the form shown below.

Consider the transformation from \( R'b \) involving "Pilot using \( p\text{-mode} \)" to jettison all stores or selected stores. In the causal chain the \( p\text{-mode} \) effect is related to \( smode \). Therefore the \( Rlb \) text is rewritten as "The SM shall have a Selective Jettison (SJ) facility which will allow the jettison of all stores (Ship mode) or the jettison of selected stores (Station mode) from the S&RE in accordance with \( smode \)."

Consider the transformation from \( R'c \) involving "allow the Pilot to select each of the six S&RE stations for SJ". The Pilot selects stations through \( p\text{-sel} \), in the causal chain this effect is related to \( sstat \). Therefore in \( R1c \) the text is re-written as "allows each of the six S&RE stations to be selected for SJ in accordance with the \( sstat \)."

Consider the transformation from \( R'e \) involving "to allow the Pilot to initiate the jettison". The Pilot initiates jettison through \( p\text{-jet} \), in the causal chain this effect is related to \( ssj \). Therefore in \( R1e \) the text is re-written as "that allows jettison to be initiated in accordance with \( ssj \)." In addition other terms in \( R'e \) are updated as appropriate to be in accordance with \( smode \) and \( sstat \) to form \( R1e \).

These requirement transformations do not require additional information not already in the interface nor do they refer to future events. However they do rely on information from the domain being removed being "saved" as part of the assumption that justifies the transformation. That is, we have that the Pilot useful behaviour relation (saved as part of the assumption) in conjunction with \( R' \) leads to \( R1 \). Therefore this is an example of an Environment Constraint requirement.

Therefore the PPT application transforms the problem from \( P\text{Exp} \) into \( P\text{Red1} \), and \( R' \) is transformed into \( R1 \) as follows (where items in bold denote the areas that have been
R1a The SM shall ensure the safe release of stores from the S&RE when commanded by the appropriate settings of smode, sstat, and ssj.

R1b The SM shall have a Selective Jettison (SJ) facility which will allow the jettison of all stores (Ship mode) or the jettison of selected stores (Station mode) from the S&RE in accordance with smode.

R1c The SP shall allow each of the six S&RE stations to be selected for SJ in accordance with the sstat. In Station SJ mode, a station must be selected before it can be jettisoned.

R1d The SP shall have an In Air lamp, which will be lit if the aircraft is in the air. SJ is only allowed if the aircraft is in the air.

R1e The SP shall have a SJ button that allows jettison to be initiated in accordance with ssj and it must remain pressed for the duration of the jettison sequence. The following must hold prior to initiating the SJ:

1. SJ mode selected (Ship or Station) in accordance with smode.
2. Aircraft is in the air.
3. If Station mode, the appropriate stations are selected on the SP in accordance with sstat.

R1f The SM shall control the selection and jettison of stores from the S&RE, by controlling the SUs to provide conditioned power and drive signals to correctly drive and control the S&REs.

R1g The SM shall implement a Balance Algorithm which can remove items from an SJ package to ensure aircraft roll moments are contained within safe limits.

R1h It shall be possible to SJ a store from a single station without regard to the aircraft balance algorithm calculation.

R1i The SJ release sequence will be Out stores first, then Mid and then In.
The constraint being relied upon is that the Pilot effects p_mode, p_sel and p_jet correspond directly to the phenomena smode, sstat and ssj respectively. This is the useful behaviour assumption for this domain removal transformation step.

The domain Pilot is no longer referenced in the model and can be removed.

The problem is transformed from $P_{Exp}$ into $P_{Red1}$ which is shown in POSE sequent form as follows:

$$P_{Red1}: S&RE(jet\_stat)_{jetv}, SP(smode, sstat, ssj, InAir)^{invect}, SU_{outv}, SM_{outv}^{invect} - R1^{jet\_stat \_stat}_{smode, sstat, ssj, InAir}$$

Note that the usual convention is not to show the useful behaviour assumption explicitly with the software problem and this is adopted for $P_{Red1}$ and in the other domain removals that follow.

CLAIM: The pilot’s intention with respect to performing jettison is represented by the phenomena smode, sstat and ssj.

ARGUMENT & EVIDENCE: This is covered by the justification given above.

PHENOMENA: None

The removal of the S&RE domains is typified by the following problem transformation step.

**SPS4: Application of the PPT for S&RE Domain Removal to problem $P_{Red1}$ to form $P_{Red}$**

**JUSTIFICATION J:** The S&RE domains removal is based on the process given in section 5.1.2. The S&RE domains are adjacent to the requirement R1. The S&RE domains are constrain-type PPTs. The S&RE domains effect is to release the selected
stores. The phenomena jetv is a vector quantity that causes this store release effect for each of the selected stations. This is achieved by providing the selected S&RE stations with conditioned drive power.

The requirement R1 constrains the behaviour of the S&RE through the phenomena jet_stat. In the domain removal the requirement will be transformed from R1 to R2. Inspection of R1 in SPS3 indicates that R1a, R1b, R1c, and R1f involve a reference to S&RE. These will be updated in R2.

Consider the transformation from R1a involving “safe release of stores from the S&RE”. In this PPT the S&RE effect of store release is replaced by the SU phenomena jetv that selects stores to receive the conditioned release drive signals. Therefore R2a has the form “safe selection of stores through the SU phenomena jetv.”.

Consider the transformation from R1b involving “will allow the jettison of all stores (Ship mode) or the jettison of selected stores (Station mode) from the S&RE in accordance with smode”. In this PPT the S&RE effect of store release is replaced by the SU phenomena jetv that selects stores to receive the conditioned release drive signals. Therefore R2b has the form “will select all stores for jettison in jetv (Ship mode) or select specific stores for jettison in jetv (Station mode) from the SU in accordance with smode.”.

Consider the transformation from R1c involving “allows each of the six S&RE stations to be selected for SJ”. In this PPT the S&RE effect of store release is replaced by the SU phenomena jetv that selects stores to receive the conditioned release drive signals. Therefore R2c has the form “allow each of the six station selection positions in jetv to be selected for SJ”.

Consider the transformation from R1f involving “the selection and jettison of stores from the S&RE” and “to correctly drive and control the S&RE”. In this PPT the S&RE effect of store release is replaced by the SU phenomena jetv that selects stores to receive the conditioned release drive signals. Therefore R2f has the form “the selection of stores for jettison in the jetv from the SU” and “through its output phenomena jetv” and adding the term “correctly” earlier in the phrase.
These requirement transformations do not require additional information not already in the interface nor do they refer to future events. However they do rely on information from the domain being removed being “saved” as part of the assumption that justifies the transformation. That is, we have that $S&RE, R2 \vdash R1$ which states that $R2$ requires assistance from the $S&RE$ domain environment to satisfy the higher level requirement $R1$. Therefore this is an example of an Environment Constraint requirement.

Therefore the PPT application transforms the problem from $P_{Red_1}$ into $P_{Red}$, and $R1$ is transformed into $R2$ as follows (where items in bold denote the areas that have been changed):

R2a The SM shall ensure the safe selection of stores through the SU phenomena $jetu$ when commanded by the appropriate settings of $smode$, $sstat$, and $ssj$.

R2b The SM shall have a Selective Jettison (SJ) facility which will select all stores for jettison in $jetu$ (Ship mode) or select specific stores for jettison in $jetu$ (Station mode) from the SU in accordance with $smode$.

R2c The SP shall allow each of the six station selection positions in $jetu$ to be selected for SJ in accordance with the $sstat$. In Station SJ mode, a station must be selected before it can be jettisoned.

R2d The SP shall have an In Air lamp, which will be lit if the aircraft is in the air. SJ is only allowed if the aircraft is in the air.

R2e The SP shall have a SJ button that allows jettison to be initiated in accordance with $ssj$ and it must remain pressed for the duration of the jettison sequence. The following must hold prior to initiating the SJ:

1. SJ mode selected (Ship or Station) in accordance with $smode$.
2. Aircraft is in the air.
3. If Station mode, the appropriate stations are selected on the SP in accordance with $sstat$. 

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R2f The SM shall control the selection of stores for jettison in the jetv from the SU, by controlling the SUs to correctly provide conditioned power and drive signals through its output phenomena jetv.

R2g The SM shall implement a Balance Algorithm which can remove items from an SJ package to ensure aircraft roll moments are contained within safe limits.

R2h It shall be possible to SJ a store from a single station without regard to the aircraft balance algorithm calculation.

R2i The SJ release sequence will be Out stores first, then Mid and then In.

The software problem model after removing the S&RE domains is given by:

$$P_{Red} : SP(smode, sstat, ssj, InAir)^{inv}, SU(jetv)_{outv}, SM_{outv}^{invc}, R2^jetv_{smode, sstat, ssj, InAir}$$

The useful behaviour assumption associated with this domain removal is based on the relationship between the S&RE effect of store release that is replaced by the SU phenomena jetv that selects stores to receive the conditioned release drive signals. As noted in SPS3, this presentation follows the convention of not showing the useful behaviour assumption with the software problem model – given by $P_{Red}$

Reliability and other concerns and associated claim/evidence to mitigate are not presented in detail.
Appendix E

POSE/Alloy Model of the SMS Case Study
module examples/DPM/smsystem3

// Second (improved) version of model, with Balance determined by overall sequence as required

open util/ordering[SMState] as sms
open Alloy_Files/Alloy4/NatNumbers as nat

// Define the SM System Objects
abstract sig SJMode {}
one sig off, ship, stat extends SJMode {}

abstract sig StatSel {}
one sig s0, s1, s2, s3, s4, s5, s6, s7 extends StatSel {}

abstract sig SSet {}
one sig son, soff extends SSet {}

abstract sig InAir {}
one sig air, grd extends InAir {}

abstract sig SPu1 {}
one sig p0, p01, p10, p2 extends SPu1 {}

abstract sig BAL *
one sig nob, no_bal, is_bal extends BAL {}

// Define the SM State
sig SMState {
  ntime : Natural,
  mode : SJMode,
  sels : StatSel,
  sj : SSet,
  fl : InAir,
  relp : SSet,
  pulses : SPu1,
  balan : BAL,
  cnt : Natural }

// Set up the ordering of SMState
pred init (sm : SMState) {sm.mode = off & sm.sels = s0 & sm.sj = soff & sm.fl = grd &
  sm.ntime = Zero & sm.relp = soff & sm.pulses = p0 & sm.balan = nob & sm.cnt = Zero}
fact cnt3 { all sm : SMState | sm.cnt = Zero or sm.cnt = One or sm.cnt = Two or sm.cnt = Three }

fact traces {
  init[sms/first[]]
  all sm : SMState = sms/last[] | let sm' = sms/next[sm] | some m : SJMode, sel : StatSel, s : SSet, f : InAir | ( Stim[sm, sm'] & & SMfun[sm, sm', m, sel, s, f] )
}

// DEFINE OPERATIONS

// System Time Clock
pred Stim(sm, sm' : SMState) { sm'.ntime = nat/inc[sm.ntime] }

// Input Vector
pred InVec(smtim, systim : Natural, inmod, mode : SJMode, insel, sel : StatSel, ej, sj : SSet, infl, fl : InAir) { smtim = systim & & inmod = mode & & insel = sel & & ej = sj & & infl = fl }

// Operation SM Function
  // If valid start of SJ sequence ........
  ( sm.mode = stat & & sm.sels != s0 & & sm.jsel = soff & & sm.fl = air & & sm.relp = soff & & m = stat & & sel = sm.sels & & s = son & & f = air )
  => sm'.reelp = son & & sm'.cnt = One & & pulTab[sm'] & & balance[sm']
  else
  // If valid continuation of SJ sequence ........
  ( sm.mode = stat & & sm.sels != s0 & & sm.jsel = son & & sm.fl = air & & sm.relp = son & & m = stat & & sel = sm.sels & & s = son & & f = air )
  => sm'.relop = son & & sm'.cnt = incnt[sm.cnt] & & pulTab[sm'] & & balance[sm']
  else
  // Otherwise, reset to safe state.
  sm'.relop = soff & & sm'.cnt = Zero & & sm'.pulses = p0 & & sm'.balan = nob )

// Function for incrementing the pulse sequence count indicator

// Operation Station Pulses sequences
pred pulTab [sm : SMState] {
/* s1 -- Port Out & Starboard In selected for SJ */
(sm.sels = s1 && sm.cnt = One => sm.pulses = p01) &&
(sm.sels = s1 && sm.cnt = Two => sm.pulses = p0) &&
(sm.sels = s1 && sm.cnt = Three => sm.pulses = p10) &&

/* s2 -- Port Out, Starboard Out & Port Mid selected for SJ */
(sm.sels = s2 && sm.cnt = One => sm.pulses = p02) &&
(sm.sels = s2 && sm.cnt = Two => sm.pulses = p01) &&
(sm.sels = s2 && sm.cnt = Three => sm.pulses = p0) &&

/* s3 -- Starboard Out, Starboard Mid, Port In & Starboard In selected for SJ */
(sm.sels = s3 && sm.cnt = One => sm.pulses = p10) &&
(sm.sels = s3 && sm.cnt = Two => sm.pulses = p10) &&
(sm.sels = s3 && sm.cnt = Three => sm.pulses = p2) &&

/* s4 -- Starboard Mid only selected for SJ */
(sm.sels = s4 && sm.cnt = One => sm.pulses = p0) &&
(sm.sels = s4 && sm.cnt = Two => sm.pulses = p10) &&
(sm.sels = s4 && sm.cnt = Three => sm.pulses = p0) &&

/* s5 -- Port Out only selected for SJ */
(sm.sels = s5 && sm.cnt = One => sm.pulses = p01) &&
(sm.sels = s5 && sm.cnt = Two => sm.pulses = p0) &&
(sm.sels = s5 && sm.cnt = Three => sm.pulses = p0) &&

/* s6 -- Starboard Mid & Port Mid selected for SJ */
(sm.sels = s6 && sm.cnt = One => sm.pulses = p0) &&
(sm.sels = s6 && sm.cnt = Two => sm.pulses = p2) &&
(sm.sels = s6 && sm.cnt = Three => sm.pulses = p0) &&

/* s7 -- Starboard Out, Mid & In selected for SJ */
(sm.sels = s7 && sm.cnt = One => sm.pulses = p10) &&
(sm.sels = s7 && sm.cnt = Two => sm.pulses = p10) &&
(sm.sels = s7 && sm.cnt = Three => sm.pulses = p10) &&

/* s0 -- No stores selected for SJ */
(sm.sels = s0 => sm.pulses = p0) )

// ### Operation Balance: Improved Based on Sequence ###
prod balance[sm : SMState] { sm.relp = son &&
\[(\text{sm.sels} = \text{s4 or sm.sels} = \text{s5}) \Rightarrow \text{sm.balan} = \text{no_bal}
\]
\[\text{else } \text{sm.balan} = \text{is_bal}\]

// ### Operation Balance: Original Based on pulses ###

// \text{pred balance[sm : SMState]} \{ \text{sm.relP} = \text{son } \& \&
// \text{((sm.pulses} = \text{p01 or sm.pulses} = \text{p0 or sm.pulses} = \text{p10}) \Rightarrow \text{sm.balan} = \text{no_bal}
// \text{else } \text{sm.balan} = \text{is_bal} \}

\text{pred checkp1[sm1, sm2, sm3 : SMState]} \{
\text{(sm1.pulses} = \text{p01 } \& \& \text{(sm2.pulses} = \text{p01 or sm3.pulses} = \text{p01)})
\text{or}
\text{(sm2.pulses} = \text{p01 } \& \& \text{(sm1.pulses} = \text{p01 or sm3.pulses} = \text{p01)})
\text{or}
\text{(sm3.pulses} = \text{p01 } \& \& \text{(sm1.pulses} = \text{p01 or sm2.pulses} = \text{p01)})
\}

\text{pred checkp2[sm1, sm2, sm3 : SMState]} \{
\text{(sm1.pulses} = \text{p2 or sm2.pulses} = \text{p2 or sm3.pulses} = \text{p2})
\text{or checkp1[sm1, sm2, sm3]}
\}

// ###### PROPERTIES ######

// Pass
\text{assert balanceCon1} \{ \text{all sm : SMState} |
\text{sm.relP} = \text{son } \& \& \text{sm.sels} = \text{s1} \Rightarrow \text{sm.balan} = \text{is_bal} \}
// Fail
\text{assert balanceCon2} \{ \text{all sm : SMState} |
\text{sm.relP} = \text{son } \& \& \text{sm.sels} = \text{s1} \Rightarrow \text{sm.balan} = \text{no_bal} \}

// All pass:
\text{assert balanceCon3} \{ \text{all sm : SMState} |
\text{sm.relP} = \text{son } \& \& \text{(sm.sels} = \text{s4 or sm.sels} = \text{s5}) \Rightarrow \text{sm.balan} = \text{no_bal} \}
\text{assert balanceCon4} \{ \text{all sm : SMState} |
\text{sm.relP} = \text{son } \& \& \text{not(sm.sels} = \text{s4 or sm.sels} = \text{s5}) \Rightarrow \text{sm.balan} = \text{is_bal} \}
\text{assert balanceCon5} \{ \text{all sm : SMState} | \text{(sm.pulses} = \text{p2} \Rightarrow \text{sm.balan} = \text{is_bal}) \}

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assert balanceCon6 { all sm : SMState | all n : Natural | all s : StatSel | sm.smels = s &&
    nat/gte[n,One] && nat/lte[n,Three] && sm.cnt = n && sm.relpl = son &&
    sm.pulses = p2 => sm.balan = is_bal }

assert balanceCon7 { all sm1, sm2, sm3 : SMState |
  ( sm3 = next[sm2] && sm2 = next[sm1] && sm1.cnt = One && sm2.cnt = Two && sm3.cnt = Three)
    &&
    sm1.pulses = p10 && (sm2.pulses = p10 || sm3.pulses = p10) =>
    (sm1.balan = is_bal && sm2.balan = is_bal && sm3.balan = is_bal )
}

assert balanceCon8 { all sm1, sm2, sm3 : SMState |
  ( sm3 = next[sm2] && sm2 = next[sm1] && sm1.cnt = One && sm2.cnt = Two && sm3.cnt = Three)
    &&
    sm2.pulses = p10 && (sm1.pulses = p10 || sm3.pulses = p10) =>
    (sm1.balan = is_bal && sm2.balan = is_bal && sm3.balan = is_bal )
}

assert balanceCon9 { all sm1, sm2, sm3 : SMState |
  ( sm3 = next[sm2] && sm2 = next[sm1] && sm1.cnt = One && sm2.cnt = Two && sm3.cnt = Three)
    &&
    checkpl[sm1, sm2, sm3]
    (sm1.balan = is_bal && sm2.balan = is_bal && sm3.balan = is_bal )
}

assert balanceCon10 { all sm1, sm2, sm3 : SMState |
  ( sm3 = next[sm2] && sm2 = next[sm1] && sm1.cnt = One && sm2.cnt = Two && sm3.cnt = Three)
    &&
    checkps[sm1, sm2, sm3]
    (sm1.balan = is_bal && sm2.balan = is_bal && sm3.balan = is_bal )
}

check balanceCon1 for 52
check balanceCon2 for 3
check balanceCon3 for 52
check balanceCon4 for 52
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check balanceCon5 for 8
check balanceCon6 for 6

check balanceCon7 for 6
check balanceCon8 for 6

check balanceCon9 for 6
check balanceCon10 for 16

pred show1() {}
run show1 for 52
Appendix F

POSE Safety Pattern Applied to the Warning System Case Study

This work is based on the POSE safety pattern shown in Figure 6.1, and follows the Agenda given in Table 6.1.

F.1 Initial Problem Understanding step for the FAS

The first part of the POSE safety pattern is Activity 1 Initial Problem understanding which is based on the format used for PS1 (DC case study) and SPS1 (SMS case study). This work uses information gained from the IPDP CE (context and requirement) and early Dem/Val (for requirement and initial architecture) phases.

\[ WPS1: \text{Application of Initial Problem Understanding to problem } P_{\text{null}} \]

\textbf{JUSTIFICATION J}_1: The justifications for the initial POSE transformations are:
In the FAS environment, the monitored systems typically include: inertial navigation; GPS navigation; aircraft data and environment data. Failure of these systems will not prove insurmountable to the pilot. The health status of these systems is input into the SYS domain. In contrast, a failure in the Catastrophic System, CS, (part of the flight control system) could result in the loss of the aircraft. Therefore the SYS and the CS domains provide health status information to the FAS. If the health status information indicates a problem, then the FAS plays an appropriate warning message to the pilot through the pilot's headphones.

[Domain Interpretation, $J_a$] The analysis of the information sources identified that the significant environment components consisted of the FAS, the SYS, the CS, the Pilot and the pilot's headphones, Speaker.

[Requirement Interpretation, $J_b$] The identified requirement was based on information provided by the customer and validated through reviews, email correspondence and meetings. It is presented as $R$ (Ra to Rd and RS) below.

[Solution Interpretation, $J_c$] This high-level system architecture representation of the FAS was based on an existing, successful design.

The domains and their relevant properties are summarised in $P_{Initial}$ presented below, where the justification for this initial software problem is $J_1 = J_a \land J_b \land J_c$.

**PHENOMENA:** Phenomena and their control and sharing are as follows: The FAS can be seen to monitor directly the status of the Catastrophic System (CS) using a discrete input cat. It also monitors the status of the other critical aircraft systems (SYS) and this is represented by the generic sys status message. The FAS issues warning audio messages to the pilot via the pilot's headphones.

The referenced requirement phenomena, ref, are concerned with monitoring the status of the system health signal, stat_cat, provided by the CS and the combined health status of the monitored systems, stat_sys, provided by SYS. The constrained requirement phenomena, cons, are concerned with playing the selected warning message, sel_audio,
to the pilot.

Where: \( cons = \{sel\_audio\} \) and \( ref = \{stat\_cat, stat\_sys\} \)

The initial software problem is as follows:

\[
\begin{align*}
P_{\text{Initial}} : & CS(stat\_cat)^{\text{cat}}, SYS(stat\_sys)^{\text{sys}}, Pilot(sel\_audio)^{\text{audio}}, \\
& Speaker^{\text{audio}}, FAS^{\text{message}} \\
& \rightarrow \ P_{sel\_audio}^{stat\_cat, stat\_sys}
\end{align*}
\]

This model can be represented as a PF problem diagram as shown in Figure F.1.

The high level FAS requirement, \( R \), is as follows:

**Ra** When the \( CS \) or a monitored system has failed, the FAS system shall play the correct audio message to the pilot.

**Rb** Message levels shall be comfortably heard by the Pilot.

**Rc** If more than one system has failed messages shall be selected for play in the order: \( \text{stat\_cat fail}, \text{stat\_sys fail} \).

**Rd** If no system failures are detected, then no message shall be played.

**RS** For hazards H1 and H2 defined above, their respective safety targets (\( 10^{-7}\)fpfh and \( 10^{-5}\)fpfh) shall be satisfied.
Note that a complete statement of R should also include requirements that cover space, weight, interfaces, maintenance and so on, but these are beyond the scope of this work.

CLAIM: *The interpretations are well-founded*

ARGUMENT & EVIDENCE: The choice of domains follows from the aircraft level safety analysis and the previous successful developments that used the CS and SYS domain structure. The pilot headphones, Speaker, is an existing component of the avionics system, with well-known, validated properties. The Pilot is trained to follow protocols rigorously. The FAS is to be designed, but the Company are domain experts for this type of system and have the success of a prototype to base the development on.

The customer functional requirement (Ra to Rd) was provided as an input to the developer team, and was validated with the customer.

CLAIM: *The architecture is feasible*

ARGUMENT & EVIDENCE: The selected high-level system architecture has been used successfully on previous developments.

CLAIM: *Sound judgement followed*

ARGUMENT & EVIDENCE: Development based on IPDP used successfully on many previous developments and enhanced with POSE to mitigate some known IPDP issues. Therefore it follows normal and not radical design concepts as defined in [131].

CLAIM: *Domain components are reliable*

ARGUMENT & EVIDENCE: The CS, SYS and Speaker domains have the required reliability, details omitted for reasons of brevity. The Pilot is a highly trained, competent individual.

The second POSE safety pattern activity of Solution Interpretation and Expansion involves expanding the FAS to include a candidate solution architecture.
The activities associated with this task are represented in the step WPS2 shown in section 6.3.2.

**F.2 PPT Applied to the Pilot Domain**

Use the POSE PPT to remove a domain adjacent to the requirement – this is the Pilot domain.

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**WPS3: Application of the PPT for Pilot Domain Removal to problem \( P_{\text{Exp}} \) to form \( P_{\text{Red1}} \)**

**INCLUDES:** None

**JUSTIFICATION \( J_3 \):** The Pilot domain removal is based on the process given in section 5.1.2. The Pilot domain is adjacent to the requirement \( R1 \). The Pilot domain is constrain-type. The Pilot domain effect is hear the warning message audio played through the headphones, and (implicitly) understand it. However, although the Pilot is trained to follow protocol rigorously, there is a chance a mistake could be made with respect to hearing the message (albeit unlikely) and any analysis has to take due account of this – this information is stored as part of the assumption and justification for the removal. The assumption (A31) is that if the warning message audio is correctly sent to the headphones, then the Pilot will (highly likely) hear and understand the correct message.

The requirement relating to the Pilot is transformed to relate to the Speaker domain. For example, \( R1a \) contains the term “play the correct audio message to the Pilot”. Under the transformation, this will be rephrased in \( R2a \) to refer to the Speaker by making (and justifying) transformations from Pilot-oriented phenomena into Speaker-oriented phenomena. In this case the re-phrase will be to “play the correct audio message through the Speaker”. \( R1b \) will be updated in \( R2b \) to require that the audio
message sound levels are adequately above the ambient level (in this case 60 dB). This will add the assumption (A32) that the Pilot can actually hear the message as it issues from the Speaker, i.e. 60 dB above ambient is adequate. That we rely on the assumptions A31 and A32 holding is the justification $J_3$ for this progression.

Transforming $R_1$ in this way yields a new requirement called $R_2$, in which $R_{1a}$ becomes $R_{2a}$ and $R_{1b}$ becomes $R_{2b}$. Requirements $R_{1c}$ and $R_{1d}$ are not changed by the transformation (they do not mention Pilot phenomena) and become $R_{2c}$ and $R_{2d}$ unchanged, respectively. $RS$ also remains unchanged.

These requirement transformations do not require additional information not already in the interface nor do they refer to future events. However they do rely on information from the domain being removed being "saved" as part of the assumption that justifies the transformation. That is, we have that $Pilot, R_2 \vdash R_1$ which states that $R_2$ requires assistance from the $Pilot$ domain environment to satisfy the higher level requirement $R_1$. Therefore this is an example of an Environment Constraint requirement.

**R2a** When the $CS$ or a monitored system has failed, the $FA$ shall control the system to play the correct audio message through the Speaker.

**R2b** Message levels shall be at 60dB above the ambient cockpit level.

**R2c** If more than one system has failed messages shall be selected for play in the order: $stat\_cat$ fail, $stat\_sys$ fail.

**R2d** If no system failures are detected, then no message shall be played.

**RS** For hazards $H_1$ and $H_2$ defined above, their respective safety targets ($10^{-7}fpfh$ and $10^{-5}fpfh$) shall be satisfied.

The domain $Pilot$ is no longer referenced in the model and can be removed.

The problem is transformed from $P_{Esp}$ into $P_{Red\_1}$ which is shown in POSE sequent form as follows.
Figure F.2: The Warning System After Pilot Removal

\[ P_{Red} : \quad CS(stat\_cat)^{cat}, SYS(stat\_sys)^{sys}, Speaker(audio)_{message}, \\
AOS_{sel}, AOD_{message}, FD_{status}, FA_{sel} \quad \rightarrow \quad R2^{audio}_{stat\_cat, stat\_sys} \]

The reduced Warning System is shown in PF problem diagram form in Figure F.2.
CLAIM: The pilot's intention is correctly represented by the phenomena relationships

ARGUMENT & EVIDENCE: The constraint being relied upon is that the Pilot effect of hearing and understanding the audio $sel_{audio}$ corresponds directly to the phenomena audio generated by the Speaker domain. This is satisfied as noted above (e.g. refer to the derivation of R2b).

PHENOMENA: None

F.3 PPT Applied to the Speaker Domain

The next domain removed is the Speaker.

WPS4: Application of the PPT for Speaker Domain Removal to problem $P_{Red1}$ to form $P_{Red2}$

INCLUDES: None

JUSTIFICATION J4: The Speaker domain removal is based on the process given in section 5.1.2. The Speaker domain is adjacent to the requirement R2. The Speaker domain is constrain-type. The Speaker domain effect is play the selected warning message audio through the headphones. This audio effect is caused by the message audio signal output from the AOD.

In this case R2 is transformed into R3. This time R2a that refers to the Speaker has to be re-phrased in terms of the AOD audio output stream (message) that drives the Speaker, to become R3a. R2b requires the message audio signal levels to be 60 dB above ambient, this translates into R3b requiring the message audio amplitude to be within the defined range (to achieve the 60 dB above ambient at the headphones). As before R1c becomes R2c without change. Next consider transforming R2d into R3d. The term “no message played” through the Speaker translates into “no analogue audio message generated” at the AOD. The Speaker is a component of the headphones.
system which has a high reliability and is checked/validated by other audio functions – so no failure budget is required for the Speaker domain and therefore RS is also unchanged.

The domain removal assumption (A4) is that generating the correct audio message at the output of AOD will cause the correct audio message stream to correctly drive the Speaker within the specified comfortable audio range, to produce the desired warning message (justification J4).

Therefore the PPT application transforms the problem from \( P_{Red1} \) into \( P_{Red2} \), and \( R2 \) is transformed into \( R3 \) as follows:

**R3a** When the CS or a monitored system has failed, the FA shall control the system to generate the correct audio message sequence at the output of AOD.

**R3b** The AOD message audio amplitude levels shall be within the defined range.

**R3c** If more than one system has failed messages shall be selected for play in the order: `stat_cat fail`, `stat_sys fail`.

**R3d** If no system failures are detected, then no analogue audio message shall be generated.

**RS** For hazards H1 and H2 defined above, their respective safety targets \((10^{-7}\text{fpfh} \text{ and } 10^{-5}\text{fpfh})\) shall be satisfied.

The constraint being relied upon is that the Speaker effect audio output level corresponds directly to the input phenomena message audio signal level generated by the AOD domain.

The domain Speaker is no longer referenced in the model and can be removed.
The software problem is transformed into $P_{\text{Red2}}$, which is shown in POSE sequent form as follows.

$$
P_{\text{Red2}} : \quad CS(\text{stat_cat})^{\text{cat}}, \quad SYS(\text{stat_sys})^{\text{sys}}, \quad AOS^{\text{messdig}}, \quad AOD(\text{message})^{\text{messdig}}; \quad FD^{\text{stat_status}}, \quad FA^{\text{stat_status}} \vdash R_3^{\text{message}}
$$

The reduced Warning System is shown in PF problem diagram form in Figure F.3.

**PHENOMENA:** None

**F.4 PPT Applied to the AOD Domain**

**WPS5:** Application of the PPT for AOD Domain Removal to problem $P_{\text{Red2}}$ to form $P_{\text{Red3}}$

**INCLUDES:** None

**JUSTIFICATION J5:** The AOD domain removal is based on the process given in section 5.1.2. The AOD domain is adjacent to the requirement R3. The AOD domain is constrain-type. The AOD domain effect is output correct analogue audio stream of the selected message. This audio effect is caused by the messdig digital input stream.
of the selected message from the AOS. The AOD consists of a Digital-to-Analogue Converter (DAC) to convert the digital input stream into an analogue signal equivalent, this is then passed through an amplifier to boost the signal to a level that ensures the analogue output is capable of driving the headphones at an appropriate level – there is also volume limiting circuitry to ensure that the output signal does not overdrive the headphones. The AOD does not affect H1, but its failure to produce an analogue output can cause H2, so some of the H2 failure budget (10⁻⁵fpfh) must be allocated to it.

In this case R3 is transformed into R4. Therefore R3a that refers to the AOD and message needs to be re-phrased as R4a in terms of the input stream messdig and the domain AOS. R3b refers to signal levels being within a defined range. This is implicitly encoded in the operation of the AOD domain and has no relevance once the AOD has been removed. As before R1c becomes R2c without change. Next consider transforming R3d into R4d. The term “no analogue audio message shall be generated” translates into “no digital message stream shall be generated”. RS is also unchanged apart from noting that some of the failure budget for H2 must be assigned to the AOD. This is captured as part of the assumption generated by the removal of AOD. Therefore RS becomes R4S.

The assumption (A5) associated with removing the AOD domain is that “the AOD converts the selected digital input message stream into an analogue equivalent signal which is amplified to a level to ensure that it will adequately drive the pilot’s headphones. Part of the H2 failure budget must be assigned to the AOD”.

Therefore the PPT application transforms the problem from P_{Red2} into P_{Red3}, and R3 is transformed into R4 as follows:

R4a When the CS or a monitored system has failed, the FA shall control the system to generate the correct digital message stream sequence, messdig, at the
output of AOS

R4b Null

R4c If more than one system has failed messages shall be selected for play in the order: 
\[ \text{stat\_cat fail}, \text{stat\_sys fail}. \]

R4d If no system failures are detected, then no digital message stream shall be generated.

R4S For hazards H1 and H2 defined above, their respective safety targets \((10^{-7}\text{fpfh} \text{ and } 10^{-5}\text{fpfh})\) shall be satisfied. (Note some of H2 budget used for AOD).

The constraint being relied upon is that the AOD effect message (analogue output) signal corresponds directly to the digital input phenomena \text{messdig} signal generated by the AOS domain.

The domain AOD is no longer referenced in the model and can be removed.

The software problem is \(P_{Red3}\), which is shown in POSE sequent form as follows.

\[
P_{Red3} : \frac{\text{CS(stat\_cat)} \cap, \text{SYS(stat\_sys)} \cap, \text{AOS(messdig)} \cap,}{\text{FD(stat\_cat, stat\_sys), FA_{status}} \cap, R4_{\text{messdig}}} \quad \text{Stat}\_\text{sys}
\]

The reduced Warning System is shown in PF problem diagram form in Figure F.4.
F.5 PPT Applied to the SYS Domain

WPS6: Application of the PPT for SYS Domain Removal to problem \( P_{Rd3} \) to form \( P_{Rd4} \)

**INCLUDES:** None

**JUSTIFICATION J6:** The SYS domain removal is based on the process given in section 5.1.2. The SYS domain is adjacent to the requirement \( R4 \). The SYS domain is reference-type. The SYS domain effect is output the health status, \( \text{stat}_\text{sys} \), of the monitored systems. This \( \text{stat}_\text{sys} \) effect causes the \( \text{sys} \) phenomena at the input to the FD.

In this case \( R4 \) is transformed into \( R5 \). The phenomena \( \text{stat}_\text{sys} \) is not involved in \( R4a, R4b \) or \( R4d \), so these remain unchanged for \( R5 \). However \( \text{stat}_\text{sys} \) does occur in \( R4c \) and this is modified by replacing the effect \( \text{stat}_\text{sys} \) with the phenomena \( \text{sys} \) that it causes in \( R5c \). The failure of SYS cannot impact on H1 or H2 which relate to the cat phenomena because of the selected architecture – therefore \( R4S \) becomes \( R5S \).

The assumption (A6) associated with removing the SYS domain is that “the SYS converts the individual health statuses of the monitored systems into a combined health status value represented by \( \text{sys} \)”.

Therefore the PPT application transforms the problem from \( P_{Rd3} \) into \( P_{Rd4} \), and \( R4 \) is transformed into \( R5 \) as follows:

**R5a** When the CS or a monitored system has failed, the FA shall control the system
to generate the correct digital message stream sequence, \textit{messdig}, at the output of AOS.

R5b Null

R5c If more than one system has failed messages shall be selected for play in the order: \textit{stat\_cat fail}, \textit{sys fail}.

R5d If no system failures are detected, then no digital message stream shall be generated.

R5S For hazards H1 and H2 defined above, their respective safety targets ($10^{-7}$fpfh and $10^{-5}$fpfh) shall be satisfied. (Note some of H2 budget used for AOD, but SYS has no impact).

The constraint being relied upon is that the SYS effect \textit{stat\_sys} corresponds directly to the phenomena \textit{sys} that is input to the FD domain.

The domain SYS is no longer referenced in the model and can be removed.

The software problem is $P_{Red4}$, which is shown in POSE sequent form as follows.

$$P_{Red4} : \begin{align*}
CS(\text{stat\_cat})^{\text{cat}},
AOS(\text{messdig})^{\text{sel}},
FD(\text{sys})^{\text{status}},
F_{\text{stat}}^{\text{stat\_sys}},
& \vdash R_{\text{messdig}}^{\text{stat\_cat,sys}}
\end{align*}$$

The reduced Warning System is shown in PF problem diagram form in Figure F.5.

\textbf{PHENOMENA: None}
F.6 PPT Applied to the CS Domain

**WPS7**: Application of the PPT for CS Domain Removal to

problem $P_{Red4}$ to form $P_{Red}$

**INCLUDES**: None

**JUSTIFICATION J7**: The CS domain removal is based on the process given in section 5.1.2. The CS domain is adjacent to the requirement R5. The CS domain is reference-type. The CS domain effect is output the health status, stat_cat, of the Catastrophic System, CS. This stat_cat effect causes the cat phenomena at the input to the FD.

In this case R5 is transformed into R6. The phenomena stat_cat is not involved in R5a, R5b or R5d, so these remain unchanged for R6. However stat_cat does occur in R5c and this is modified by replacing the effect stat_cat with the phenomena cat that it causes in R6c. The failure of CS can impact on both H1 or H2, therefore some of the failure budgets for both H1 and H2 must be allocated to this CS domain – R5S becomes R6S.

The assumption (A7) associated with removing the CS domain is that “the CS converts the health status of the Catastrophic System into a health status value represented by cat. Some of the failure budget for H1 and H2 must be allocated to CS”.

Therefore the PPT application transforms the problem from $P_{Red4}$ into $P_{Red}$, and R5 is transformed into R6 as follows:
Figure F.6: The Warning System After CS Removal

R6a When the CS or a monitored system has failed, the FA shall control the system to generate the correct digital message stream sequence, \( messdig \), at the output of AOS.

R6b Null

R6c If more than one system has failed messages shall be selected for play in the order: cat fail, sys fail.

R6d If no system failures are detected, then no digital message stream shall be generated.

R6s For hazards H1 and H2 defined above, their respective safety targets (\( 10^{-7} \)fpfh and \( 10^{-5} \)fpfh) shall be satisfied. (Note some of H1 budget used for CS; some of H2 budget used for AOD and CS, but SYS has no impact).

The constraint being relied upon is that the CS effect stat_cat output level corresponds directly to the phenomena cat that is input to the FD domain.

The domain CS is no longer referenced in the model and can be removed.

The software problem is \( P_{Red} \), which is shown in POSE sequent form as follows.

\[
P_{Red}: AOS(messdig)_{sel}, FD(cat, sys)_{status}, FA_{sel} \rightarrow R6_{messdig}
\]

The reduced Warning System is shown in PF problem diagram form in Figure F.6.

**PHENOMENA:** None
F.7 POSE/Alloy Model of the Modified Audio Warning System

//### Problem P'Equiv: Modified ADS & Time Control FD ###
module Audio Warn

open util/ordering[Time] as Ti
// open NatNumbers as nat
// open Derek/Alloy4/NatNumbers as nat

// Define the Time Component
sig Time {}

// Define the OK Component
sig OK {}
one sig yes, no extends OK {}

// Define the Status Component
sig Status {}
one sig catnon, sysnon, catsys, non extends Status {}

// Define the Select Message Component
sig Sel {}
one sig ml, m2, m3, ni extends Sel {}

// Define the Message Component
sig Mess {}
one sig mes1, mes2, mes3, noni extends Mess {}

// Define the single FA State - sel and mute
one sig FA { sel : Sel -> Time, mute : OK -> Time } {}

// Define the single FD State domain - status
one sig FD { status : Status -> Time } {}

// Define the single AOS' State domain - messidig and id
one sig ADS { mes : Mess -> Time, id : OK -> Time } {}

// #### DEFINE OPERATIONS ####
// FABehave models the behaviour of the safety critical controller.
pred FABehave(t, t' : Time) { FA.sel.t' = extract(FD.status.t) &
    FA.mute.t' = checkid[t, t'] }

// FDBehave models the behaviour of the FD domain
pred FDBehave(t, t' : Time) { trange[t, 0, 1] => FDSame[t, t']
    else trange[t, 2, 4] => (FD.status.t' = catnon )
    else trange[t, 5, 6] => (FD.status.t' = non )
    else trange[t, 7, 9] => (FD.status.t' = sysnon )
    else trange[t, 10, 11] => (FD.status.t' = non )
    else trange[t, 12, 13] => (FD.status.t' = catsys )
    else trange[t, 14, 15] => (FD.status.t' = non )
    else trange[t, 16, 24] => (FD.status.t' = catnon )
    else trange[t, 25, 26] => (FD.status.t' = non )
    else FDSame[t, t'] }

// AOSBehave models the behaviour of the AOS' domain. If activate is
// active then the message is set to noni (no message).
pred AOSBehave(t, t' : Time) { AOS.mes.t' = (FA.mute.t = noo =>
    decode[FA.sel.t] else noni) &
    AOS.id.t' = setid[t, t'] }

pred FDSame(t, t' : Time) { FD.status.t' = FD.status.t }

// Predicate trange returns true if t is in the range from ts to tf.
pred trange(t: Time, ts, tf: Int) {#prevs[t] >= ts &&
    #prevs[t] <= tf}

// Fun extract returns the message selected by the FD status input (status)
fun extract(st: Status) : Sel {#switch(st = catnon or st = catsys) #7
    => m1 else st = sysnon => m2 else n1}

// Fun decode returns the message selected by the FA status input (sel)
fun decode[s: Sel] : Mess { s = m1 => mes1 //8
    else s = m2 => mes2 else noni}
// Fun checkid confirms message id corresponds to selected message #11
fun checkid[t, t' : Time]: OK {AOS.id.t = yes => noo else yes}

// Fun setid determines if message identifier, id, in AOS' is ok at specified time #12
fun setid[t, t' : Time]: OK {trange[t, 0, 18] => yes
else trange[t, 19, 23] => noo
else yes}

//////// Define Trace Model ######

pred init [t : Time] {FD.status.t = non & FA.sel.t = ni & AOS.mes.t = noni
& FA.mute.t = yes & AOS.id.t = noo}

fact traces {
    init[Ti/first[]]
    all t : Time - Ti/last[] | let t' = Ti/next[t] | FDBehave[t, t'] & FABehave[t, t'] &
    AOSBehave[t, t']
}

// #### PROPERTIES #####

pred show1() {}
run show1 for 30 but 6 int //Set bit width to cover -32 to +31
Appendix G

Some Further Feasible Requirement Examples

This chapter considers the other two examples of non-feasible/feasible requirement as discussed in section 2.4.

G.1 A Future Reference Example

*Future Reference* covers the case when the satisfaction of the overall system requirement \( R \) requires information that is available only in the future. Its solution often involves either (a) sharing additional information (similar to Unshared Information) or (b) making reasonable assumptions about the required behaviour. In both cases use is made of domain information to provide a solution.

In the Audio Warning FAS messages are played in a hierarchy (e.g. R7c) with *cat* fail messages having the highest priority. Therefore, if a *sys* message is being played, and a *cat* message is detected, then the required behaviour is that the *sys* warning message should be stopped, and the *cat* warning message started as quickly as possible. If a *sys* message is being played and another *sys* failure is reported from a different monitored system, the question arises as to when should this new
message be played? The desired behaviour is that it should be played after the current message has finished. However, how does the system know when a message has finished? This is a Future Reference issue and there are two possible design solutions based on the solution types discussed above, namely: (a) based on sharing additional information and (b) based on making reasonable assumptions about a known property of the system.

The first alternative solution requires the derived requirement $DR - A$ to be added to the requirement associated with the software problem $P_{Equiv}$. $DR - A$ has the form:

Include a flag mechanism for denoting the end of a message, which is flagged to the $FA$ from the $AOS'$ when detected, so that the $FA$ knows the currently playing message is completing and the next can be started.

In addition the phenomena $eom$ (End Of Message) needs to be added to allow the $AOS'$ to flag to the $FA$ that the current message has finished. These behaviour refinements are added to the problem domain through a series of POSE transformations. These are included into the problem domain through a step, WPS8A, which includes the appropriate justifications. The step will include the following transformations (with associated justifications): (a) requirement interpretation to include $DR - A$, (b) domain interpretation to introduce the phenomena $eom$ into $AOS'$, (c) solution interpretation to include a reference to the phenomena $eom$ into $FA$, and (d) the expansion transformations that include these interpretation transformations into the software problem which transforms from $P_{Equiv}$ into $P_{solA}$.

The second alternative solution requires the derived requirement $DR - B$ to be added to the requirement associated with the software problem $P_{Equiv'}$. $DR - B$ has the form:

All messages last less than five seconds in duration and the $FA$ knows when a message is started. Use this information to start playing the next
message, five seconds after the current message was started and so on.

No new interface phenomena are need to be added to the problem, since FA knows when it requested the start of a message and it can run a clock to count off the 5 second duration of the message. Therefore the step, WPS8B, associated with this alternative solution only requires a requirement interpretation/expansion transformation pair to be justified.

Comparison of the two alternatives indicates that the second approach is the easiest to implement and so it was adopted in this case. The main factor favouring the second alternative was that there was no need to complicate the interface between the FA and the AOS' with new phenomena.

G.2 Directly Implementable Requirement: Emergency Stop function

The fourth type of requirement discussed in section 2.4 are those that are directly implementable. A typical example is shown in Figure G.1 which satisfies a requirement for an emergency stop (ES) that is added to the list of the Audio Warning, FAS, requirement with the aim of mitigating the “Message played too loud” issue identified in section 6.3.6. The idea being that the Pilot uses the emergency stop button to terminate warning messages from the FAS that are uncomfortably loud.

![Figure G.1: The Emergency Stop Function](image)

The requirement is that message processing in the FA should halt immediately if the emergency stop button is pressed. In Figure G.1 the emergency stop button
is represented by the ES domain which shares the stop phenomena with the FA. When the ES button is pressed, the stop input to the FA causes the FA to halt processing as required. The diagram shows that the requirement phenomena (halt, stop) relate directly to the FA phenomena relevant to the emergency stop processing. There are no intervening domains that need to be removed or requirement phenomena that have to be transformed. Therefore a directly implementable requirement can be identified from the PF diagram by (a) there is at most a single functional domain between the to be designed domain (FA in this case) and the requirement, and (b) the requirement phenomena are equivalent to the design phenomena. In situations where the requirement phenomena and design phenomena are close, but do not quite coincide, then the application of Sharing Removal from the PPT can solve the problem. This is similar to its use to transform \( P_{\text{red}} \) into \( P_{\text{equiv}} \) at the end of section 6.3.3. Also, the term “functional domain” is used to preclude the introduction of dummy identity domains which in theory could introduce an arbitrary number of domains between the to be designed domain and the requirement without affecting functionality.
Appendix H

Revised $DC$ Case Study

The aim of this case study is to show that POSE works well with requirements presented in a standardised good practice form based on [118], and to again show that utility of applying the full POSE safety pattern based on the work in Chapter 6.

H.1 POSE Safety Pattern Activity 1

The goal is to derive a machine specification that can satisfy its safety requirements ($H1$ and $H2$) and thus form a good basis for the rest of the development process, and this is achieved by applying the POSE safety pattern introduced in Chapter 6. The first activity is Context and Requirement Interpretation and this uses the requirements and domain information based on Appendix A.3, except this time the aim is to use a structured form of the requirements based on current Company procedures [118] and the abstraction heuristic check (i.e. a requirement should only refer to domains and phenomena that are adjacent to it). The resulting set of requirements $R$ are:

R.1 The DS shall command (DS Sel) which flare is selected for release from the DU (flare select).
R.2 The DS shall command (DS\_fire) when a flare is to be released by the DU (flare\_fire).

R.3 The selected flare shall only be released from the DU if the DS has issued a flare release command when the input interlocks are satisfied.

R.4 The three input interlocks are:

R.4.1 The aircraft shall be in the air (air\_gnd).

R.4.2 The safety pin shall be removed (pin\_st).

R.4.3 The Pilot has issued an allow release command (p\_int).

RS The DC shall mitigate H1 & H2 (Target: safety critical $10^{-7}$ fpfh).

These requirements were reviewed and found to be apposite. The result is the Initial Problem transformation step, PSA1.

\begin{center}
\textit{PSA1: Initial Problem application to transform problem $P_{null}$ into $P_{initial}$}
\end{center}

\textbf{JUSTIFICATION $J_1$}: The identified requirement, domains and their relevant properties are summarised above. The combined justification for the set of transformations used to introduce the context, requirements and initial solution system architecture are: 

\[ J_1 = J_a \land J_b \land J_c. \]

The resulting software problem is $P_{initial}$ as follows:

\[ DS(DS\_sel, DS\_fire)_{cont}, DU(flare\_select, flare\_fire)_{fire, sel}, \]

\[ P_{initial}: SP(pin\_st)_{pin}, AS(air\_gnd)_{st}, \]

\[ P(p\_int)_{allow}, DC_{sel, fire}^{st, pin, allow, cont} \vdash R_{DS\_sel, DS\_fire, air\_gnd, pin\_st, p\_int} \]
PHENOMENA: Phenomena and their control and sharing (see $P_{\text{Init}}$) are known from the existing system components.

CLAIM: The interpretations are well-founded

ARGUMENT & EVIDENCE: The choice of domains follows from the aircraft level safety analysis and the required choice of interlocks. The $DS$, $DU$, $AS$ and $SP$ are existing components of the avionics system, with well-known, validated properties. The Pilot is trained to follow protocols rigorously.

The customer functional requirements (R.1 to R.4) were provided as an input to the developer team, and were validated with the customer. The development of the safety requirement RS is as discussed in section 4.1.1.

CLAIM: The overall architecture is feasible

ARGUMENT & EVIDENCE: The selected overall system architecture has been used successfully on similar safety systems. Inspection confirms that the identified domains and their associated phenomena can interact as needed - aim being to avoid Unshared Information issues later in the development.

CLAIM: Sound judgement followed

ARGUMENT & EVIDENCE: The development is based on IPDP used successfully on many previous developments and enhanced with POSE to mitigate some known issues with IPDP. Claim this follows normal and not radical design concepts as defined in [131].

CLAIM: In-air indicator in Aircraft Status System is reliable

ARGUMENT & EVIDENCE: The in-air indicator is obtained from the weight on wheels and landing gear up indications: if the landing gear is up and there is no weight on the wheels then the aircraft is assumed to be in the air. The landing gear is detected as being up by a number of sensor switches. The switches use a multi-pole arrangement.
of appropriately selected “Normally open/Normally closed” contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins.

The corresponding PF diagram form is shown in Figure H.1.

Figure H.1: PF Problem Diagram for the DC Problem, $P_{Initial}$

Figure H.2: Modified $DM'$ Architecture
H.2  POSE Safety Pattern Activity 2

The second activity in the POSE safety pattern is Solution Interpretation and Expansion. In this case the results of the previous analysis work will be assumed and the expanded system architecture to replace the DC domain will be the domains SC, II and DM and where the DM domain has the modified form shown in Figure H.2. The result of this activity is the problem transformation step PSA2 shown below.

PSA2: Solution Interpretation and Expansion applied to problem $P_{\text{initial}}$ to form $P_{\text{Exp}}$

**JUSTIFICATION $J_2$:** The identified system architecture, its components and relevant properties are as summarised in Figure H.3. The justification for this (architecture) solution expansion transformation is that this system architecture was successfully developed as a prototype and is known to be capable of satisfying the functional requirements.

The requirements are left unchanged by this expansion because the changes occur to domains that are not adjacent to the requirements.

The software problem is transformed from $P_{\text{initial}}$ to $P_{\text{Exp}}$ as shown below, and an equivalent PF representation is shown in Figure H.3.

$$DS(DS_{\text{sel}}, DS_{\text{fire}})^{\text{cont}}, DU(\text{flare}\_\text{select}, \text{flare}\_\text{fire})_{\text{fire}, \text{sel}}$$

$$P_{\text{Exp}} = SP(\text{pin}_\text{st})^{\text{pin}}, AS(\text{air}_\text{gnd})^{\text{st}}, P(\text{p} \_\text{int})^{\text{allow}},$$

$$\text{II}_{\text{st}, \text{pin}, \text{allow}}, DM_{\text{sel}, \text{fire}}^{\text{cont}}, SC_{\text{int, fire}}^{\text{fire}} \vdash R_{DS_{\text{sel}}, DS_{\text{fire}}, \text{air}_\text{gnd}, \text{pin}_\text{st}, \text{p} \_\text{int}}^{\text{flare, select, flare, fire}}$$

The solution system architecture is introduced using the Solution Interpretation transformation and the AStruct[...].

**CLAIM:** $P_{\text{initial}}$ and $P_{\text{Exp}}$ are equivalent
ARGUMENT & EVIDENCE: The requirement $R$ and the interface phenomena adjacent to $R$ are not changed by the transformation, although new phenomena are introduced to represent the interactions between the introduced domains.

CLAIM: The choice of candidate solution architecture exhibits sound safety engineering judgement

ARGUMENT & EVIDENCE: The system architecture is chosen to minimise the number and extent of the safety related functions, localising them to simple, distinct blocks in accordance with best practice.

CLAIM: The chosen solution architecture does not prevent the satisfaction of $R'$ (Feasibility). This claim is not yet supported.

PHENOMENA: The new phenomena introduced by the architecture are:

- $fire?$ – Command to release the selected flare type
- $int$ – Status of combined interlocks

![Diagram](image)

Figure H.3: Problem $P_{Esp}$ after Solution Interpretation and Expansion

**H.3 POSE Safety Pattern Activity 3**

The third activity in the POSE safety pattern is problem progression and involves applying the PPT introduced in section 5.1.2 to remove domains from the problem to
allow the machine specification to be recovered. The first domain to be transformed is the pilot domain \( P \) and the activities involved are captured in the PSA3 problem transformation step.

**H.3.1 PSA3 Pilot Domain Removal**

**PSA3: Application of the PPT for Pilot Domain Removal to problem \( P_{Exp} \) to form \( P_{Red1} \)**

**INCLUDES:** None

**JUSTIFICATION J:** The Pilot domain removal is based on the process given in section 5.1.2. The pilot \( P \) domain is adjacent to the requirement \( R \). The \( P \) domain control phenomena \( allow \) maps directly to its output behaviour phenomena which is \( p\_int \). Therefore \( p\_int \) (representing the pilot’s intention) appears in the reference part of the requirement phenomena before the transformation, but will be replaced with its effect, \( allow \), by the transformation. The requirement \( R \) is as detailed at the beginning of this section, and inspecting it indicates that only \( R.4.3 \) involves a reference to \( p\_int \).

Consider the transformation from \( R.4.3 \) into \( R1.4.3 \) which involves the phenomena \( p\_int \) and \( allow \) as noted above.

\( R.4.3 : \) The Pilot has issued an allow release command (\( p\_int \)).

\( R1.4.3 : II \) observes pilot input of \( allow \).

**Pilot Domain Description:** The pilot sets the Allow switch to active to indicate that the intention is to allow flare release, otherwise it is set inactive. The Allow switch uses a multi-pole arrangement of appropriately selected "Normally open/ Normally closed" contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins. The setting of the Allow switch is determined by the pilot \( P \) domain and is output using the phenomena \( allow \), where \( allow = yes \) means the Allow switch is active, whilst \( allow = no \) means the allow switch is inactive. Therefore \( allow = yes \) corresponds to allow flare release, whilst \( allow = no \)
corresponds to inhibit flare release.

The justification for this problem progression is that:

\[ R1.4.3 \land \text{Assumption}(p_{\text{int}}, \text{allow}) \Rightarrow R.4.3. \]

The \( A_1 = \text{Assumption}(p_{\text{int}}, \text{allow}) \) is given by the Pilot Domain Description. Inspection of \( R1.4.3 \) in conjunction with the Pilot Domain Description shows they imply \( R.4.3 \) as required.

This requirement transformation does not require additional information not already in the interface nor does it refer to future events. However it does rely on the useful behaviour from the domain being removed being “saved” as part of the assumption that justifies the transformation – it is an example of an Environment Constraint non-feasible requirement which is discussed in a POSE context in [83]. As noted above, this useful behaviour contribution is contained in the Pilot Domain Description.

The PPT application transforms the problem from \( P_{\text{Exp}} \) into \( P_{\text{Red1}} \), and \( R \) is transformed into \( R1 \) (using the Requirements Interpretation part of the PPT) as follows:

\begin{enumerate}
    \item \textbf{R1.1} The DS shall command (DS\_sel) which flare is selected for release from the DU (flare\_select).
    \item \textbf{R1.2} The DS shall command (DS\_fire) when a flare is to be released by the DU (flare\_fire).
    \item \textbf{R1.3} The selected flare shall only be released from the DU if the DS has issued a flare release command when the input interlocks are satisfied.
    \item \textbf{R1.4} The three input interlocks are:
        \begin{enumerate}
            \item \textbf{R1.4.1} The aircraft shall be in the air (air\_gnd).
            \item \textbf{R1.4.2} The safety pin shall be removed (pin\_st).
            \item \textbf{R1.4.3} II observes pilot input of allow.
        \end{enumerate}
\end{enumerate}
RS The DC shall mitigate H1 & H2 (Target: safety critical $10^{-7}$ fpfh).

The pilot domain $P$ is no longer referenced in the model and can be removed.

The software problem is transformed to $P_{Red1}$:

$$DS(DS_{sel}, DS_{fire})_{cont}, DU(flare_{select}, flare_{fire})_{fire, sel},$$

$$P_{Red1}: SP(pin_{st})^{pin}, AS(air_{gnd})^{st},$$

$$II(allow)^{int}_{st,pin}, DM_{sel, fire}^{cont}, SC_{int, fire}^{fire} \vdash R1_{flare_{select}, flare_{fire}, DS_{sel}, DS_{fire}, air_{gnd}, pin_{st}, allow}$$

An equivalent PF representation is shown in Figure H.4.

CLAIM: The pilot’s intention with respect to allowing flare release is represented by the phenomena allow.

ARGUMENT & EVIDENCE: This is covered by the Pilot Domain Description.

PHENOMENA: None

Figure H.4: Problem $P_{Red1}$ after Pilot Domain removal
H.3.2 PSA4 SP Domain Removal

The next domain to be removed is the safety pin domain \( SP \), and the activities involved are captured in the PSA4 problem transformation step shown below.

\[
\text{PSA4: Application of the PPT for SP Domain Removal to problem } P_{\text{red}1} \text{ to form } P_{\text{red}2}
\]

**INCLUDES:** None

**JUSTIFICATION J:** The SP domain removal is based on the process given in section 5.1.2. The SP domain is adjacent to the requirement R1. The SP domain control phenomena \( \text{pin} \_st \) maps directly to its output behaviour phenomena \( \text{pin} \). Therefore \( \text{pin} \_st \) will appear in the reference part of the requirement phenomena before the transformation, but will be replaced with the effect it causes, \( \text{pin} \), after the transformation. The requirement R1 is as detailed in step PSA3 on page 294. Inspection of R1 indicates that only R1.4.2 involves a reference to \( \text{pin} \_st \).

Consider the transformation from R1.4.2 into R2.4.2 which involves the phenomena \( \text{pin} \_st \) and \( \text{pin} \) as noted above.

\[
\text{R1.4.2 : The safety pin shall be removed (\( \text{pin} \_st \)).}
\]

\[
\text{R2.4.2 : II observes input } \text{pin} = \text{out}.
\]

**SP Domain Description:** The safety pin status is obtained from sensor switches. The switches use a multi-pole arrangement of appropriately selected "Normally open/Normally closed" contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins. The setting of the safety pin status is determined by the SP domain and is output using the phenomena \( \text{pin} \), where \( \text{pin} = \text{out} \) means the safety pin has been removed, whilst \( \text{pin} = \text{in} \) means the safety pin is present (and inhibiting flare release).

The justification for this problem progression is that:
The $A_2 = \text{Assumption}(\text{pin}_{\text{st}}, \text{pin})$ is given by the SP Domain Description. Inspection of $R2.4.2$ in conjunction with the SP Domain Description shows they imply $R1.4.2$ as required. The constraint being relied upon is that $\text{pin} = \text{out}$ means the safety pin has been removed – see claim below.

This requirement transformation does not require additional information not already in the interface nor does it refer to future events. However it does rely on the useful behaviour from the domain being removed being "saved" as part of the assumption that justifies the transformation – it is an example of an Environment Constraint non-feasible requirement which is discussed in a POSE context in [83]. As noted above, this useful behaviour contribution is contained in the SP Domain Description.

The PPT application transforms the problem from $P_{\text{Red1}}$ into $P_{\text{Red2}}$, and $R1$ is transformed into $R2$ (using the Requirements Interpretation part of the PPT) as follows:

**R2.1** The DS shall command (DS.sel) which flare is selected for release from the DU (flare.select).

**R2.2** The DS shall command (DS.fire) when a flare is to be released by the DU (flare.fire).

**R2.3** The selected flare shall only be released from the DU if the DS has issued a flare release command when the input interlocks are satisfied.

**R2.4** The three input interlocks are:

**R2.4.1** The aircraft shall be in the air ($\text{air}_{\text{gnd}}$).

**R2.4.2** II observes input $\text{pin} = \text{out}$.

**R2.4.3** II observes pilot input of allow.

**RS** The DC shall mitigate H1 & H2 (Target: safety critical $10^{-7}$ fpfh).

The domain SP is no longer referenced in the model and can be removed.
The software problem is transformed to $P_{Red2}$:

$$DS(DS_{sel}, DS_{fire})_{cont}, DU(flare_{select}, flare_{fire})_{fire, sel},$$

$$P_{Red2} : AS(air_{-gnd})_{st}, II(allow, pin)_{int},$$

$$DM_{sel, fire?}^\text{cont}, SC_{int, fire?}^\text{fire} \vdash R2^{flare_{select}, flare_{fire}}_{DS_{sel}, DS_{fire}, air_{-gnd}, pin, allow}$$

An equivalent PF representation is shown in Figure H.5.

CLAIM: The safety pin status is represented by the phenomena pin.

ARGUMENT & EVIDENCE: This is covered by the SP Domain Description.

PHENOMENA: None

Figure H.5: Problem $P_{Red2}$ after SP Domain removal
H.3.3 PSA5 AS Domain Removal

The next domain to be removed is the air status domain AS, and the activities involved are captured in the PSA5 problem transformation step shown below.

| PSA5: Application of the PPT for AS Domain Removal to problem PRed2 to form PRed3 |

INCLUDES: None

JUSTIFICATION J: The AS domain removal is based on the process given in section 5.1.2. The AS domain is adjacent to the requirement R2. The AS domain control phenomena air\_gnd maps directly to its output behaviour phenomena st. Therefore air\_gnd will appear in the reference part of the requirement phenomena before the transformation, but will be replaced with the effect it causes, st, after the transformation. The requirement R2 is as detailed in step PSA4 on page 297. Inspection of R2 indicates that only R2.4.1 involves a reference to air\_gnd.

Consider the transformation from R2.4.1 into R3.4.1 which involves the phenomena air\_gnd and st as noted above.

R2.4.1 : The aircraft shall be in the air (air\_gnd).

R3.4.1 : III observes input st = air.

AS Domain Description: The in-air indicator is obtained from the weight on wheels and landing gear up indications: if the landing gear is up and there is no weight on the wheels then the aircraft is assumed to be in the air. The landing gear is detected as being up by a number of sensor switches. The switches use a multi-pole arrangement of appropriately selected "Normally open/Normally closed" contacts. This imbues an error detection capability that is used to achieve very good failure rates, well within the required margins. The setting of the in-air indicator is determined by the AS domain and is output using the phenomena st, where st = air means the aircraft is in the air, whilst st = gnd means the aircraft is on the ground.

The justification for this problem progression is that:
\[ R3.4.1 \land \text{Assumption}(\text{air-gnd}, st) \Rightarrow R2.4.1. \]

The \( A_3 = \text{Assumption}(\text{air-gnd}, st) \) is given by the AS Domain Description. Inspection of \( R3.4.1 \) in conjunction with the AS Domain Description shows they imply \( R2.4.1 \) as required. The constraint being relied upon is that \( st = \text{air} \) means the aircraft is in the air – see claim below.

This requirement transformation does not require additional information not already in the interface nor does it refer to future events. However it does rely on the useful behaviour from the domain being removed being “saved” as part of the assumption that justifies the transformation – it is an example of an Environment Constraint non-feasible requirement which is discussed in a POSE context in [83]. As noted above, this useful behaviour contribution is contained in the AS Domain Description.

The PPT application transforms the problem from \( P_{Red2} \) into \( P_{Red3} \), and \( R2 \) is transformed into \( R3 \) (using the Requirements Interpretation part of the PPT) as follows:

**R3.1** The DS shall command (DS.sel) which flare is selected for release from the DU (flare.select).

**R3.2** The DS shall command (DS.fire) when a flare is to be released by the DU (flare.fire).

**R3.3** The selected flare shall only be released from the DU if the DS has issued a flare release command when the input interlocks are satisfied.

**R3.4** The three input interlocks are:

**R3.4.1** \( II \) observes input \( st = \text{air} \).

**R3.4.2** \( II \) observes input \( pin = \text{out} \).

**R3.4.3** \( II \) observes pilot input of allow.

**RS** The DC shall mitigate H1 & H2 (Target: safety critical \( 10^{-7} \) fpfh).
The domain AS is no longer referenced in the model and can be removed.

The software problem is transformed to $P_{Red3}$:

$$DS(DS_{sel}, DS_{fire})^{cont}, DU(flare_{select}, flare_{fire})_{fire, sel},$$

$$P_{Red3} : \ II(allow, pin, st)^{int},$$

$$DM_{sel, fire}^{cont}, SC_{int, fire}^{fire} \vdash R3^{flare_{select}, flare_{fire}}_{DS_{sel}, DS_{fire}, st, pin, allow}$$

An equivalent PF representation is shown in Figure H.6.

**Claim:** The in-air status of the aircraft is represented by the phenomena st.

**Argument & Evidence:** This is covered by the AS Domain Description.

**Phenomena:** None

![Figure H.6: Problem $P_{Red3}$ after AS Domain removal](image)
H.3.4 PSA6 DS Domain Removal

The next domain to be removed is the Defence System domain DS, and the activities involved are captured in the PSA6 problem transformation step shown below.

PSA6: Application of the PPT for DS Domain Removal to

problem $P_{Red3}$ to form $P_{Red4}$

INCLUDES: None

JUSTIFICATION J: The DS domain removal is based on the process given in section 5.1.2. The DS domain is adjacent to the requirement R3. The DS domain control phenomena DS_sel and DS_fire map directly to its output behaviour phenomena cont. Therefore DS_sel and DS_fire will appear in the reference part of the requirement phenomena before the transformation, but will be replaced with the effect they cause, cont, after the transformation. The requirement R3 is as detailed in step PSA5 on page 300. Inspection of R3 indicates that R3.1 refers to DS_sel, R3.2 involves a reference to DS_fire and R3.3 refers to the DS.

Consider the transformation from R3.1 into R4.1 which involves the phenomena DS_sel and cont as noted above.

R3.1: The DS shall command (DS_sel) which flare is selected for release from the DU (flare_select).

R4.1: The DM shall decide which flare to select by observing a field in the cont message it receives.

Next consider the transformation from R3.2 into R4.2 which involves the phenomena DS_fire and cont as noted above.

R3.2: The DS shall command (DS_fire) when a flare is to be released by the DU (flare_fire).

R4.2: The DM shall decide to release a flare by observing a field in the cont message it receives.
Next consider the transformation from **R3.3** into **R4.3** which involves **DS** as noted above.

**R3.3**: The selected flare shall only be released from the DU if the DS has issued a flare release command and the input interlocks are satisfied.

**R4.3**: The selected flare shall only be released from the DU if the **DM** has received a flare release command and the input interlocks are satisfied.

**DS Domain Description**: The DS monitors many systems (e.g. early warning radar, GPS/INS positioning) to determine any threats to the aircraft. These systems are not pertinent to this problem so are abstracted through the statement:

The DS is the defensive aids suite controller function which selects the flare type for release and if and when a flare is released in response to any threats it determines from its monitoring functions. The DS achieves this by formatting the flare selection and fire commands into its **cont** message which it transmits to the DM.

The DM knows the structure of the **cont** message it receives from the DS, so it can decode the **cont** message to determine the flare selection (**sel**) and fire (**fire**) components.

The justification for this problem progression is that:

\[ R4.1 \land \text{Assumption}(DS\_sel, \text{cont}) \Rightarrow R3.1. \]

\[ R4.2 \land \text{Assumption}(DS\_fire, \text{cont}) \Rightarrow R3.2. \]

\[ R4.3 \land \text{Assumption}(DS, DM) \Rightarrow R3.3. \]

The \( A_4 = \text{Assumption}(DS\_sel, DS\_fire, cont, DS, DM) \) is given by the **AS Domain Description**. Inspection of **R4.1**, **R4.2** and **R4.3** in conjunction with the **DS Domain Description** shows they imply **R3.1**, **R3.2** and **R3.3** as required. The constraints being relied upon is that **cont** contains the fire and select commands issued by the DS, and that the DM decodes them using **cont**.
This requirement transformation does not require additional information not already in the interface nor does it refer to future events. However it does rely on the useful behaviour from the domain being removed being “saved” as part of the assumption that justifies the transformation – it is an example of an Environment Constraint non-feasible requirement which is discussed in a POSE context in [83]. As noted above, this useful behaviour contribution is contained in the DS Domain Description.

The PPT application transforms the problem from $P_{Red3}$ into $P_{Red4}$, and $R3$ is transformed into $R4$ (using the Requirements Interpretation part of the PPT) as follows:

R4.1 The DM shall decide which flare to select by observing a field in the cont message it receives.

R4.2 The DM shall decide to release a flare by observing a field in the cont message it receives.

R4.3 The selected flare shall only be released from the DU if the DM has received a flare release command when the input interlocks are satisfied.

R4.4 The three input interlocks are:

R4.4.1 $II$ observes input $st = \text{air}$.

R4.4.2 $II$ observes input $pin = \text{out}$.

R4.4.3 $II$ observes pilot input of $allow$.

RS The DC shall mitigate $H1 \& H2$ (Target: safety critical $10^{-7}$ fpfh).

The software problem is transformed to $P_{Red4}$:

$$
P_{Red4}: \quad DU(\text{flare\_select}, \text{flare\_fire})_{\text{fire\_sel}}, \; II(allow, pin, st)_{\text{int}},
\quad DM(\text{cont})_{\text{sel\_fire}}, \; SC_{\text{fire\_int\_fire}} \quad \leftarrow R4(\text{flare\_select}, \text{flare\_fire})_{\text{cont\_st\_pin\_allow}}$$

An equivalent PF representation is shown in Figure H.7.

CLAIM: The flare selection (DS.sel) and flare fire (DS.fire) commands are represented by the phenomena con.
ARGUMENT & EVIDENCE: This is covered by the *DS Domain Description*.

PHENOMENA: None

Figure H.7: Problem $P_{Red4}$ after *DS* Domain removal
H.3.5 PSA7 DU Domain Removal

The next domain to be removed is the Dispenser Unit domain DU, and the activities involved are captured in the PSA7 problem transformation step shown below.

\[ PSA7: \text{Application of the PPT for DU Domain Removal to problem P}_{\text{Red4}} \text{ to form P}_{\text{Red}} \]

**INCLUDES:** None

**JUSTIFICATION J:** The DU domain removal is based on the process given in section 5.1.2. The DU domain is adjacent to the requirement R4. The DU domain control phenomena are the \( sel \) flare selection input from the DM and the \( fire \) flare release command from the SC. These map directly to its output behaviour phenomena \( flare\_select \) and \( flare\_fire \) respectively. Therefore the effects \( flare\_select \) and \( flare\_fire \) will appear in the reference part of the requirement phenomena before the transformation, but will be replaced with their direct causes, \( sel \) and \( fire \), after the transformation. The requirement R4 is as detailed in step PSA6 on page 303. Inspection of R4 indicates that only R4.3 involves a reference to the DU.

Consider the transformation from R4.3 into R5.3 which involves the DU as noted above.

**R4.3:** The selected flare shall only be released from the DU if the DM has received a flare release command and the input interlocks are satisfied.

**R5.3:** The flare selected by the DM \( sel \) phenomena shall only be released by the SC issuing a fire command if the DM has received a flare release command and the input interlocks are satisfied.

**DU Domain Description:** The flare selected for release from the DU (\( flare\_sel \)) is determined by the \( sel \) phenomena input from the DM. The DU will release the selected flare (\( flare\_fire \)) when it receives a fire command input from the SC.

The justification for this problem progression is that:
R5.3 ∧ Assumption(flare_sel, flare_fire, sel, fire) ⇒ R4.3.

The $A_5 = Assumption(flare\_sel, flare\_fire, sel, fire)$ is given by the DU Domain Description. Inspection of R5.3 in conjunction with the DU Domain Description shows they imply R4.3 as required.

This requirement transformation does not require additional information not already in the interface nor does it refer to future events. However it does rely on the useful behaviour from the domain being removed being "saved" as part of the assumption that justifies the transformation – it is an example of an Environment Constraint non-feasible requirement which is discussed in a POSE context in [83]. As noted above, this useful behaviour contribution is contained in the DU Domain Description.

The PPT application transforms the problem from $P_{Red4}$ into $P_{Red}$, and R4 is transformed into R5 (using the Requirements Interpretation part of the PPT) as follows:

R5.1 The DM shall decide which flare to select by observing a field in the cont message it receives.

R5.2 The DM shall decide to release a flare by observing a field in the cont message it receives.

R5.3 The flare selected by the DM sel phenomena shall only be released by the SC issuing a fire command if the DM has received a flare release command when the input interlocks are satisfied.

R5.4 The three input interlocks are:

R5.4.1 II observes input $st = air$.

R5.4.2 II observes input $pin = out$.

R5.4.3 II observes pilot input of allow.

RS The DC shall mitigate H1 & H2 (Target: safety critical $10^{-7}$ fpfh).

The domain DU is no longer referenced in the model and can be removed.
The software problem is transformed to $P_{Red}$:

$$P_{Red} : II(allow, pin, st)^{int},$$

$$DM(cont, sel)^{fire}, SC(fire)^{int, fire} \vdash R5_{cont, st, pin, allow}$$

An equivalent PF representation is shown in Figure H.8.

**PHENOMENA:** None

Figure H.8: Problem $P_{Red}$ after $DU$ Domain removal
H.3.6 The PrePSA Step for the Revised DC Case Study

To derive an Alloy model from $P_{Red}$ requires reconciliation of the requirements and domain phenomena, i.e., the relationship between them needs to be established. This could be achieved by applying the PPT to remove the DM and II domains to allow the specification to be derived, but as in the FA case study the preferred way forward (as the model is useful for the PSA) is to just apply the REQUIREMENTS INTERPRETATION transformation to extract the relationship between the phenomena. This can be captured as the PrePSA problem transformation step below, which forms the last part of the Pattern Problem Simplification task.

The PrePSA Step manages the transformation of $P_{Red}$ into $P_{Equiv}$, which can be used to directly derive the specification of the SC and forms the basis of the PSA work.

| PrePSA8: Application of REQUIREMENT INTERPRETATION to problem $P_{Red}$ to form $P_{Equiv}$ |

**CONCERNS:** Reconciliation of the requirements and domain phenomena. The requirement $R5$ (associated with $P_{Red}$) refers to $cont$, $sel$, $fire$, $st$, $pin$, and $allow$, whilst the $SC$ relates to $fire?$, $fire$ and $int$. Therefore there is a need to apply REQUIREMENTS INTERPRETATION to identify the relationship between these phenomena, as in section 5.5.3.

**JUSTIFICATION J:** Inspection of the useful behaviour relation for the DM, II and SC domains indicate the logical equivalence of: $int$ to $allow$, $pin$ and $st$; $fire?$ to $cont$; $fire$ to $fire$. Further, the functionality of the SC does not involve flare selection, so the phenomena $sel$ is not part of its specification.

This is justified by identifying the useful behaviour relations (domain contributions) of the DM, II and SC domains. The DM domain effects are concerned with decoding $cont$ to extract the flare selection, $sel$, and whether a flare is to be released, $fire?$.
DM sends the status of the fire request, fire?, to the SC which uses this information (in conjunction with int) to determine whether to output the flare release phenomena, fire. The II domain effect is to combine the input information it obtains from the phenomena allow, pin and st, and output this as the phenomena int sent to the SC.

The requirements R5 can be updated to R6 (the SC specification) as follows:

R6.1 Null

R6.2 The SC shall evaluate whether to release a flare by observing the fire? message it receives.

R6.3 A flare shall only be commanded to be released by the SC issuing a fire command if it has received a fire? message when the input interlocks are satisfied.

R6.4 The input interlocks are determined by int.

RS The DC shall mitigate H1 & H2 (Target: safety critical 10^-7 fpfh).

These updates allow the problem to be transformed from P_{Red} into P_{Equiv} as follows.

\[ P_{Equiv} : II(int), DM(fire?), SC(fire)_{int, fire?} \vdash R6_{fire}^{int, fire?} \]

CLAIM: The software problem P_{Equiv} allows the specification of SC to be derived.

ARGUMENT & EVIDENCE: The requirement R6 uses the same phenomena as the domains, i.e., R6 is the specification.

CLAIM: The requirements model is a valid representation of the system

ARGUMENT & EVIDENCE: Informally, the SC receiving a valid fire? command when the II contribution, int, indicates the interlocks are satisfied combine to satisfy R6.3. Note that R6.2 is part of R6.3. The II contribution covers R6.4. The PSA considers RS. Therefore, (informally) the POSE requirements model (P_{Equiv}) satisfies the requirement ( specification) R6. This will be formally checked as part of the Alloy simulation and proof work.
H.4 POSE Safety Pattern Activity 4

The fourth activity in the POSE safety pattern is to perform the safety analysis tasks required by the PSA.

The validation and safety analysis (PSA) of the case study makes use of formal modelling using Alloy and is based on the four part process summarised in section 6.4:

1. Derive the Alloy model directly from the POSE software problem description – using a template.

2. Use the following four-part process for applying the formal modelling:

   (a) use simulation to develop the model and gain confidence it has the required behaviour;

   (b) perform formal proof to validate the model;

   (c) use the model to prove safety properties (if necessary)

   (d) investigate any specific problem areas using simulation. (This process is efficient because the more expensive proof work is only undertaken once simulation has provided confidence in the efficacy of the model.)

3. Use the FFA/FTA and modified HAZOPS form for domains not formally modelled.

The formal analysis was conducted using a variety of Alloy files to cover simulation, proof of requirements and investigation of the model’s properties. The simulation and proof results were used to develop an in-depth understanding of the model and guided its development as follows.
H.4.1 DC Model Simulation

The initial model of the DC system used a simple version of the SC which is shown below

```plaintext
### Define Behaviour

pred SCBehava [t, t': Time]( //R6.3
  (II.int1.t = val \&\& DM.fireq.t = rel) \rightarrow SC.fire.t' = rel
  else SC.fire.t' = noac )
```

When doing the simulation with the above simple model for the SC, the results showed that SC.fire was set to rel in the next time instant as long as the interlocks were valid (II.int1 = val) and DM.fireq was rel in the current time instant. This allowed DM.fireq to be rel at the same time instant as II.int1 = val. However, the intention was to improve integrity by requiring that DM.fireq should be the initiating event for flare release – that is, the interlocks should become (and remain) valid prior to DM.fireq being set to rel, other combinations should inhibit flare release. The specification R6 and the requirement R do not specify this explicitly and a derived requirement RD was introduced to cover this desired behaviour:

```
RD:
The SC shall only send the fire message if it has received an active fireq with the interlocks being valid. The interlocks must be valid prior to the arrival of fireq and continue to be valid through the flare release process.
```

The specification was modified to become R6+ (R6+ = R6 + RD).

H.4.2 DC Model Formal Proof

The formal proof of requirements to validate the model used the Alloy model shown below. The assert statements R63full, R51, R52, R53full and R54 validate that the specification R6.3, and the requirements R5.1, R5.2, R5.3 and R5.4 respectively, are satisfied by the model.
//### Problem:: Decoy Controller: DC
// Model based on R5/FRed/Figure 2.7 -- Reduced model including sel behaviour.

open util/ordering[Time] as Ti

sig Time{}

### Define Phenomena

sig FIR {}

one sig noac, rel extends FIR {} // Fire command has two states: no action or fire.

sig INL {}

one sig val, nov extends INL {} // Status of II.intl.t is either valid or not valid.

sig CONT {}

one sig c0, c1, c2, c3 extends CONT {} // c0 is default and selects s0; c1 and c3 select s1 and s3; c2 is a fire command, leaves flare selection unchanged.

sig SEL {}

one sig s0, s1, s3 extends SEL {} // Flare selection: s0 is default, s1 and s3 are other flare types

sig AIR {}

one sig air, gnd extends AIR {} // Aircraft status, either in the air or on the ground.

sig PIN {}

one sig out, inn extends PIN {} // Safety pin is either in or out.

sig OK {}

one sig yes, noo extends OK {}

### Define Domains

one sig SC { fire : FIR -> Time} {}

one sig DM { sel : SEL->Time, fireq: FIR -> Time) {}}

one sig II { intl : INL -> Time} {}

// EXT represents the external interface of the model

one sig EXT { cont : CONT -> Time, allow : OK->Time, pin : PIN->Time, at : AIR->Time} {}

pred SCBehave [t,t':Time]{ let tp = prev[t] | //R5.3 + RD
  (II.intl.tp = val && II.intl.t = val && DM.fireq.t = rel) => SC.fire.t' = rel
  else SC.fire.t' = noac }

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pred DMBehave \[t,t':\text{Time}\] 
// R5.1 
(\text{EXT. cont.} t = c0 \Rightarrow \text{DM. sel.} t' = s0 \\
\text{else EXT. cont.} t = c1 \Rightarrow \text{DM. sel.} t' = s1 \\
\text{else EXT. cont.} t = c2 \Rightarrow \text{DM. sel.} t' = \text{DM. sel.} t \\
\text{else EXT. cont.} t = c3 \Rightarrow \text{DM. sel.} t' = s3) \\
) 
// R5.2 
(\text{EXT. cont.} t = c0 \Rightarrow \text{DM. fireq.} t' = \text{noac} \\
\text{else EXT. cont.} t = c1 \Rightarrow \text{DM. fireq.} t' = \text{noac} \\
\text{else EXT. cont.} t = c2 \Rightarrow \text{DM. fireq.} t' = \text{rel} \\
\text{else EXT. cont.} t = c3 \Rightarrow \text{DM. fireq.} t' = \text{noac}) \\
) 
pred IIBehave \[t,t':\text{Time}\] 
// A5,4 
((\text{EXT. allow.} t \Rightarrow \text{yes} \&\& \text{EXT. pin.} t \Rightarrow \text{out} \&\& \text{EXT. st.} t \Rightarrow \text{air} \Rightarrow \text{II. inti.} t' \Rightarrow \text{val} \\
\text{else II. inti.} t' \Rightarrow \text{nov}) \\
) 
// EXT version set to support proof work 
pred EXTBehave \[t,t':\text{Time}\] 
(\text{EXT. cont.} t' = c0 \text{ or EXT. cont.} t' = c1 \text{ or EXT. cont.} t' = c2 \text{ or EXT. cont.} t' = c3 ) \&\& 
(\text{EXT. allow.} t' = \text{noo} \text{ or EXT. allow.} t' = \text{yes} ) \&\& 
(\text{EXT. pin.} t' = \text{out} \text{ or EXT. pin.} t' = \text{inn} ) \&\& 
(\text{EXT. st.} t' = \text{gnd} \text{ or EXT. st.} t' = \text{air} ) \\
) 
// Predicate trange returns true if t is in the range from ts to tf. 
pred trange \[t : \text{Time}, ts, tf : \text{Int}\] \{ \#prevs\[t\] > is \&\& \#prevs\[t\] < tf\} 
// Predicate change returns true if the phenomena a has changed state. 
fun change \[a : \text{FIR} \Rightarrow \text{Time}, t1 : \text{Time}\] : \text{OK} \{ a.t1 \Rightarrow a.(\text{prev}[t1]) \Rightarrow \text{yes} \text{ else noo} \} 
// Predicate timeorder returns true if the times t1,t2, and t3 are in an ascending sequence. 
fun timeorder \[t1, t2, t3 : \text{Time}\] : \text{OK} \{ 
(t1 = \text{prev}[t2] \&\& t2 = \text{prev}[t3] \&\& t1 = \text{prev}[\text{prev}[t3]]) \Rightarrow \text{yes} \text{ else noo} \} 
// Define the Trace Model 
pred init \[t : \text{Time}\] \{\text{SC. fire.} t = \text{noac} \&\& \text{DM. sel.} t = s0 \&\& \text{DM. fireq.} t = \text{noac} \&\& \text{II. inti.} t = \text{nov} \&\& 
\text{EXT. cont.} t = c0 \&\& \text{EXT. allow.} t = \text{noo} \&\& \text{EXT. pin.} t = \text{out} \&\& \text{EXT. st.} t = \text{gnd}\} 

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\[ \text{fact traces } \{ \text{init[Ti/first[]]} \]
\[ \quad \text{all } t : \text{Time} - Ti/last[] \quad \text{let } t' = Ti/next[t] \quad \text{SCBehave}(t, t') \land \text{DMBehave}(t, t') \land \text{IIBehave}(t, t') \land \text{EXTBehave}(t, t') \} \]

//## Investigate Properties

assert R63full {all t1, t2, t3 : Time |}
\[ \text{timeorder}[t1, t2, t3]=\text{yes} \land \text{II.int1.t1=val} \land \text{II.int1.t2=val} \land \text{DM.fireq.t2=rel} \rightarrow \text{SC.fire.t3=rel} \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3]=\text{yes} \land \text{not(II.int1.t1=val} \land \text{II.int1.t2=val} \land \text{DM.fireq.t2=rel}) \rightarrow \text{SC.fire.t3=noac}) \]

assert R51 {all t1, t2, t3 : Time |}
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.cont.t1 = c0} \rightarrow \text{DM.sel.t2 = s0} \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.cont.t1 = c1} \rightarrow \text{DM.sel.t2 = s1} \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.cont.t1 = c2} \rightarrow \text{DM.sel.t2 = s2} \}

assert R52 {all t1, t2, t3 : Time |}
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.cont.t1 = c0} \rightarrow \text{DM.fireq.t2 = noac} \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.cont.t1 = c1} \rightarrow \text{DM.fireq.t2 = noac} \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.cont.t1 = c2} \rightarrow \text{DM.fireq.t2 = rel} \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.cont.t1 = c3} \rightarrow \text{DM.fireq.t2 = noac} \}

assert R53full {all t1, t2, t3 : Time |}
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{DM.sel.t2=s0} \land \text{II.int1.t1=val} \land \text{II.int1.t2=val} \land \text{DM.fireq.t2=rel} \land \text{EXT.cont.t1 = c2} \rightarrow (\text{SC.fire.t3 = rel } ) \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{DM.sel.t2=s1} \land \text{II.int1.t1=val} \land \text{II.int1.t2=val} \land \text{DM.fireq.t2=rel} \land \text{EXT.cont.t1 = c2} \rightarrow (\text{SC.fire.t3 = rel } ) \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{DM.sel.t2=s3} \land \text{II.int1.t1=val} \land \text{II.int1.t2=val} \land \text{DM.fireq.t2=rel} \land \text{EXT.cont.t1 = c2} \rightarrow (\text{SC.fire.t3 = rel } ) \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{not(II.int1.t1=val} \land \text{II.int1.t2=val} \land \text{DM.fireq.t2=rel}) \rightarrow \text{SC.fire.t3=noac}) \]

assert R54 {all t1, t2, t3 : Time |}
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{EXT.allow.t1=yes} \land \text{EXT.pin.t1=out} \land \text{EXT.st.t1=air} \rightarrow \text{II.int1.t2=val} \]
\[ \land \]
\[ \text{timeorder}[t1, t2, t3] = \text{yes} \land \text{not(EXT.allow.t1=yes} \land \text{EXT.pin.t1=out} \land \text{EXT.st.t1=air}) \rightarrow \text{II.int1.t2=mov}) \]
H.4.3 DC Model Safety Analysis

The validation proof for the Alloy model assert R53full (refer to the Alloy model above) demonstrates that the system represented by the specification R6+ (including derived requirement RD) provides mitigation for H1 & H2.

The safety analysis was based on the FFA/HAZOPS/FTA approach and followed the work presented in section 5.2.2. Table 5.3 contains the summary for the HAZOPS and the entries in this table were investigated further using the simulation model, the results of this work are presented in the next section.

H.4.4 DC Model Investigate Problem Areas

The simulation of the entries in Table 5.3 was performed using the timing model introduced in section 5.5.4. The external inputs for the safety model (based on R5) were modelled using the domain EXT and the input timing was varied using the structure shown below.

```plaintext
// EXT version not to support simulation work
pred EXTBehave [t,t':Time]{
  (trange[t,0,2] => EXT.cont.t' = c0
   else trange[t,3,5] => EXT.cont.t' = c2
   else trange[t,6,8] => EXT.cont.t' = c3
   else trange[t,9,10] => EXT.cont.t' = c1
```
The simulation work validated the outcomes defined in Table 5.3, but also found some problematic behaviour. The simulation for the cases where continuous \( fireq \) (\( fire ? \) in Table 5.3) was received, H4 and H5, indicated that a flare release could occur whenever consecutive periods of \( II.int1 = val \) were encountered – which is the outcome outlined in section 4.4. The current specification \( (R6+) \) assumes that \( fireq \) is a single initiating entity of relatively short duration, but this is not the case when a failure such as H4 occurs. The integrity of the model needs to be further improved to mitigate the case where \( fireq \) has failed active by adding an additional derived requirement as follows:

**RDD:**

The \( SC \) shall only send the \( fire \) message if it detects a transition of \( fireq \) going from inactive \( (noac) \) to active \( (rel) \) with the interlocks being
valid prior to the arrival of fireq going active and continuing to be valid through the flare release process.

The behaviour of SC in the model (SCBehave) was modified as follows to incorporate the derived requirement RDD:

```plaintext
pred SCBehave [t,t':Time]{ let tp = prev[t] } //R5.3 + RDD
   (II.inti.tp = val && II.inti.t = val && DM.fireq.tp = noac && DM.fireq.t = rel)
   -> SC.fire.t' = rel else SC.fire.t' = noac }
```

The simulation was repeated and the model behaved correctly with respect to dealing with fireq failing active. Therefore the derived requirement RDD was added to replace RD, and this formed the specification R6++ = R6+RDD. The validation proofs of R5.1, R5.2 and R5.4 were repeated successfully on the revised model. The assert statements for R6.3 and R5.3 were amended to reflect RDD and successfully proved for the model – the revised assert for R6.3 is shown below.

```plaintext
assert R63full (all t1,t2,t3 : Time |
   (timeorder[t1,t2,t3]=yes && II.inti.t1=val && II.inti.t2=val && DM.fireq.t1=noac && DM.fireq.t2=rel)
   -> SC.fire.t3 = rel )
   
   (timeorder[t1,t2,t3]=yes && not(II.inti.t1=val && II.inti.t2=val && DM.fireq.t1=noac && DM.fireq.t2=rel)
   -> SC.fire.t3 = noac )
```

**H.5 Revised DC Case Study Discussion**

The revised DC case study has demonstrated another successful application of the POSE safety pattern using the “good” practice requirements form based on [118] introduced in section 4.1.1).

The case study provided further support for the properties Simplification, [NecessaryP] and mitigation of the issue [LateI3]. Support for the property Simplification was demonstrated through the problem progression steps in section H.3.1 through H.3.5, whilst support for [NecessaryP] was demonstrated through
the derivation of the specification in section H.3.6. Mitigation of the issue [LateI3] was provided by the safety analysis work covered in section H.4.

The case study again demonstrated the successful use of the four part formal POSE/Alloy modelling process summarised in section 6.4. The modelling identified a shortfall in the safety integrity which was rectified by augmenting the requirements with a derived requirement and then validated using the process. The problem was that the requirement \( R6.3 \) was not specific enough to exclude unwanted behaviours and it allowed a flare release even when the interlock became valid at the same time as the fire command had been received – this was corrected by defining the derived requirement \( RD \). The approach also identified the problem with \( \text{fireq} \) failing active and this was resolved by adding the derived requirement \( RDD \) to replace \( RD \) to form the specification \( R6 + + \).

The modelling process allows the behaviour of the proposed development to be investigated in detail, and any shortcomings highlighted and resolved. In this case study the requirement \( R \) (see section H.1) and specification \( R6 \) were improved by the definition of the derived requirement \( RDD \) to clarify the desired behaviour.
Appendix I

Analysis of Research Contribution

The goal of this appendix is to present a more detailed analysis of my research contribution on using POSE in the early stages of a safety critical system development, as an extension of the work presented in section 7.5. As noted in section 7.5 my contribution has three main parts:

- developing and extending the theory of Problem Orientation;
- applying the extended theory in a safety critical engineering setting;
- providing partial validation for the extended theory within that setting.

These three elements of my contribution are depicted in Figure I.1 and each is expanded further in the sections that follow.

![Figure I.1: Contribution Summary](image-url)
I.1 Detailed Discussion of Develop the Theory

I.1.1 Develop the Theory Detailed 1 - Problem Progression

The problem progression transformations were raw and relatively undeveloped, and I developed – in parallel with other work in this by Jon Hall, Lucia Rapanotti and Zhi Li – a process for applying them (as published in the FASE07 [87] paper). This culminated in the POSE problem progression for safety systems discussed in section 5.1.2 – the basic elements of this development are depicted in Figure I.2.

A contribution to knowledge is the resulting engineering form of the PPT and a method to support its application (IWAAPF08 [83] paper, and section 5.1.2). Also, this research allowed me to comment further on the relationship between the notion of a domain’s useful behaviour and the work on non-implementable requirements from Zave and Jackson’s Four Dark Corners paper [133] - as discussed in the IWAAPF08 [83] paper, and presented in section 5.1.1.1 and section 5.1.1.2.

As noted, another contribution is a collection of useful heuristics for engineers for its application (IWAAPF08 [83] paper, and section 5.1.2) that substantiate the practical nature of Jackson’s original idea sketch. These were used extensively in the case studies that followed section 5.1.2.
I.1.2 Develop the Theory Detailed 2 – How to Sequence

Another contribution to knowledge is the ability to sequence the transformations through the abstraction provided by the POSE safety pattern (FASE07 [87], SSS08 [88], and in section 6.1) and the use of problem transformation steps (refer to section 4.1.4.2) which collect basic POSE transformations into meaningful engineering steps in the development process - and allows appropriate validation at that level. The resulting hierarchy is shown in Figure I.3.

This abstraction hierarchy is useful for managing development tasks. Further, this work was extended by my supervisors to be the POE Process Pattern (Assurance-Driven Development in POE [37]).

I.2 Detailed Discussion of Application

I.2.1 Application 1

Develop the applicability aspects of POSE using the case studies as exemplars. The case studies contribute to knowledge in a number of ways, e.g. they provided evidence to demonstrate that an extended POSE is a capable SSSD (Safe Software System Development) approach. This contribution is phrased in terms of 10 identified properties (Table 2.3), which showed that, from a practical engineering perspective,
extended POSE was a suitable SSSD approach.

The applicability aspect was also explored with respect to the Research Objectives (refer to section 1.2), the results being that:

1. a suitable specification can be derived using the PPT (FASE07, IWAAPF08, and sections 5.1.3, 5.5.3 and 6.3.3 etc.);

2. the PrePSA step (e.g. page 168 and page 180) was developed to support deriving the specification;

3. the safety analysis involving HAZOPS could be enhanced using the structure and information provided by POSE (refer to section 5.2);

4. the traceability and iteration capabilities under POSE assist backtracking (extension of HASE07 first presented in IET07, and developed in section 5.3);

5. analysis under POSE is efficient because the model used for the safety analysis was the same as that used in the development (e.g. SSS08 and section 7.2.8).

Further, the POSE safety pattern and the satisfaction of the property Context satisfies the research objective of capturing and separating contextual knowledge from the design of the system and its desirable properties.

I.2.2 Application 2

The assessment was conducted against six issues and four properties, which were identified by analysis and experience of using IPDP (refer to section 3.4.5) and evidenced from the (retrospective) case studies – DC (introduced in section 4.1.1), SMS (introduced in section 5.5.1) and FAS (introduced in section 6.3). As part of this contribution, we have argued that, as validation and verification (V&V) are an important aspect of the safety standards, the extended POSE caters for them at a number of levels: all transformations are justified, the problem transformation steps
include obligations that have to be discharged and the POSE safety pattern includes the PSA step (FASE07, SAFECOMP08 and section 6.1). The POSE safety pattern and the problem transformation steps (e.g. PS1 in section 4.2) provide structuring that supports the objective of keeping track of safety artefacts for validation and certification purposes.

As a final contribution in this section, this research provides evidence that POSE can be used with formal notations to provide formal proof and simulation capabilities (e.g. SSS08, section 6.3.4, section 6.3.6 and section 6.3.7) including the following developments:

1. Techniques for forming Alloy model directly from POSE model (e.g. section 5.5.4 and section 6.3.4.1)
2. Development of the Timing model (e.g. section 5.5.4)
3. Proposed means of performing formal analysis based on 4-step process (refer to section 6.4).

The work in section 5.2 and the subsequent case study results demonstrated that the extended POSE satisfies the research objective concerning the allowing for both formal and informal safety analysis techniques to take place.

I.3 Partial Validation

The three, varied case studies provide some evidence to support and validate the engineering application, as does the industrial use reported in the thesis (refer to section 7.3). They also show that extended POSE integrates well with the IPDP and satisfies the provisions of a number of important safety standards and guidelines (e.g. DS 00-56 [125], IEC61508 [51] and DO-178B [108]) providing support for the integrating with current safety engineering practice research objective.
The case studies were retrospective so it is always difficult to counter the argument that hindsight rather than the capabilities of the approach were responsible for finding the issues. To counter this hindsight issue, the case studies were organised to integrate with the IPDP and follow its standard course – care was taken to avoid performing analyses which were known to be capable of detecting the issues if they were not part of the standard approach or were not part of the extensions provided by using POSE. For example, the requirements were based closely on those used with the original development and were not (apart from the work reported in Appendix H on the revised DC case study) "improved" to a more idealised form. The ongoing industrial work is not retrospective and is proceeding with some success – providing good validation of the approach and demonstrating that extended POSE does improve the capabilities of the early phases of IPDP.

1.4 Thesis Contribution Summary

The POSE safety pattern and its associated case study work demonstrate that extended POSE does support the integration of safety analysis into the early phases of a system development, which satisfies the first research objective listed in section 1.2.

In summary POSE, as extended by the research work reported in this thesis, does satisfy the research objectives listed in section 1.2 of:

1. integrating safety analysis within the early phases of development, particularly requirement analysis and high level architectural design (this section)

2. allowing for both formal and informal safety analysis techniques to take place (section 1.2.2)

3. capturing and separating contextual knowledge from the design of the system and its desirable properties (section 1.2.1)
4. keeping track of safety artefacts for validation and certification purposes (section 1.2.2)

5. integrating with current safety engineering practice (section 1.3).

The work in this thesis has also demonstrated that extended POSE can be used within IPDP to improve the capabilities of IPDP – thus satisfying the second objective from section 1.2 of improving the early phases of an existing safety development process (section 1.3).
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