

Research Review 2017

Certifiable Distributed Runtime Assurance

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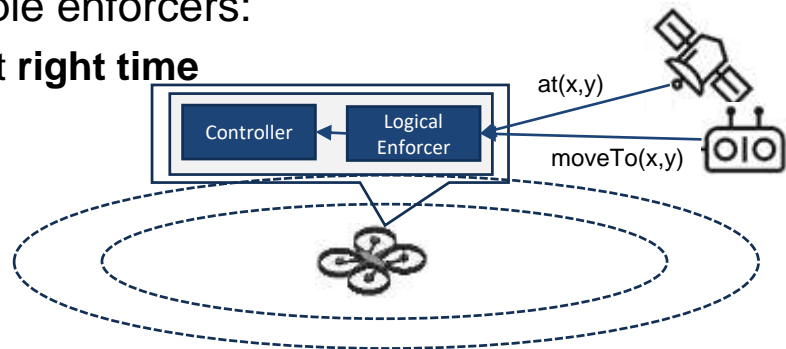
Certifiable Distributed Runtime Assurance

Challenge: Assure Safety of Distributed Cyber-Physical Systems

- Unpredictable Algorithms (Machine Learning)
- Multi-Vehicle (distributed) coordinating to achieve mission

Solution:

- Add **simpler (verifiable)** runtime enforcer to make algorithms predictable
- Formally: specify, verify, and compose multiple enforcers:
 - Enforcer **intercepts/replaces** unsafe action at **right time**



Formal Periodic Model: Representing Time-Aware Logic

State of the system: values of variables

State variables: V_S

Action variables: V_Σ

Variable values from **domain**: D

Location -- e.g., (x, y) position
Movement (move-to (x, y) position)
Domain specific variables

System state \equiv assignment of values to state variables: $s: V_S \mapsto D \in S$

Action \equiv assignment of values to action variables: $\alpha: V_\Sigma \mapsto D$

Behavior \equiv state transitions given actuation every period $P: R_P(\alpha) \subseteq S \times S$

Next state given action: $R_P(\alpha, s) = \{s' \mid (s, s') \in R_P(\alpha)\}$

Add **values to quantify**
position & move-to position

Account for **time &**
actuations

Property to verify subset of all possible states: $\phi \subseteq S$

Verify representative subset of ALL states
 (x, y) position within region

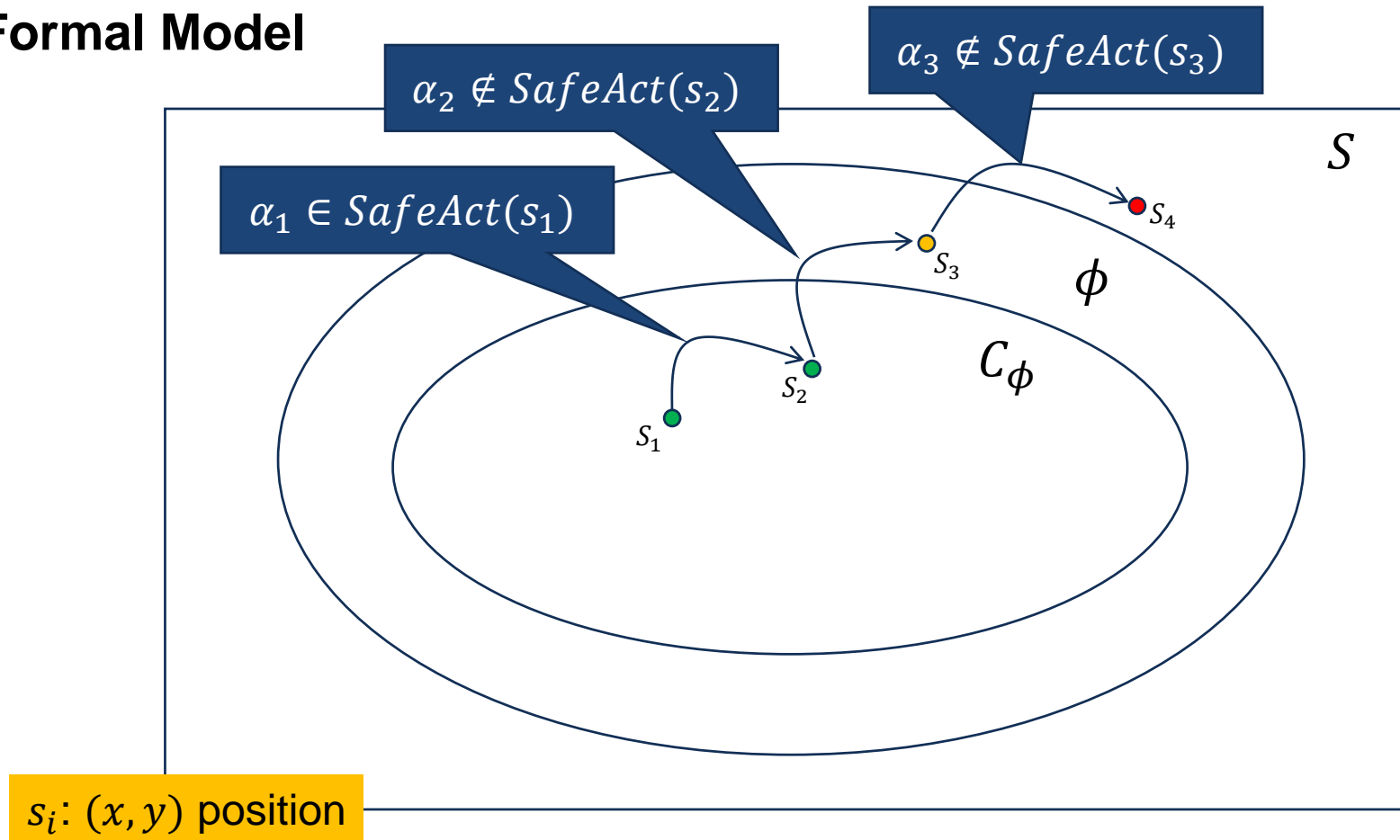
Enforceable state: $C_\phi \subseteq \phi \wedge C_\phi = \{s \mid \exists \alpha \in \Sigma: R_P(\alpha, s) \in C_\phi\}$

Enforcement Mechanism
 (x, y) still prevent getting out

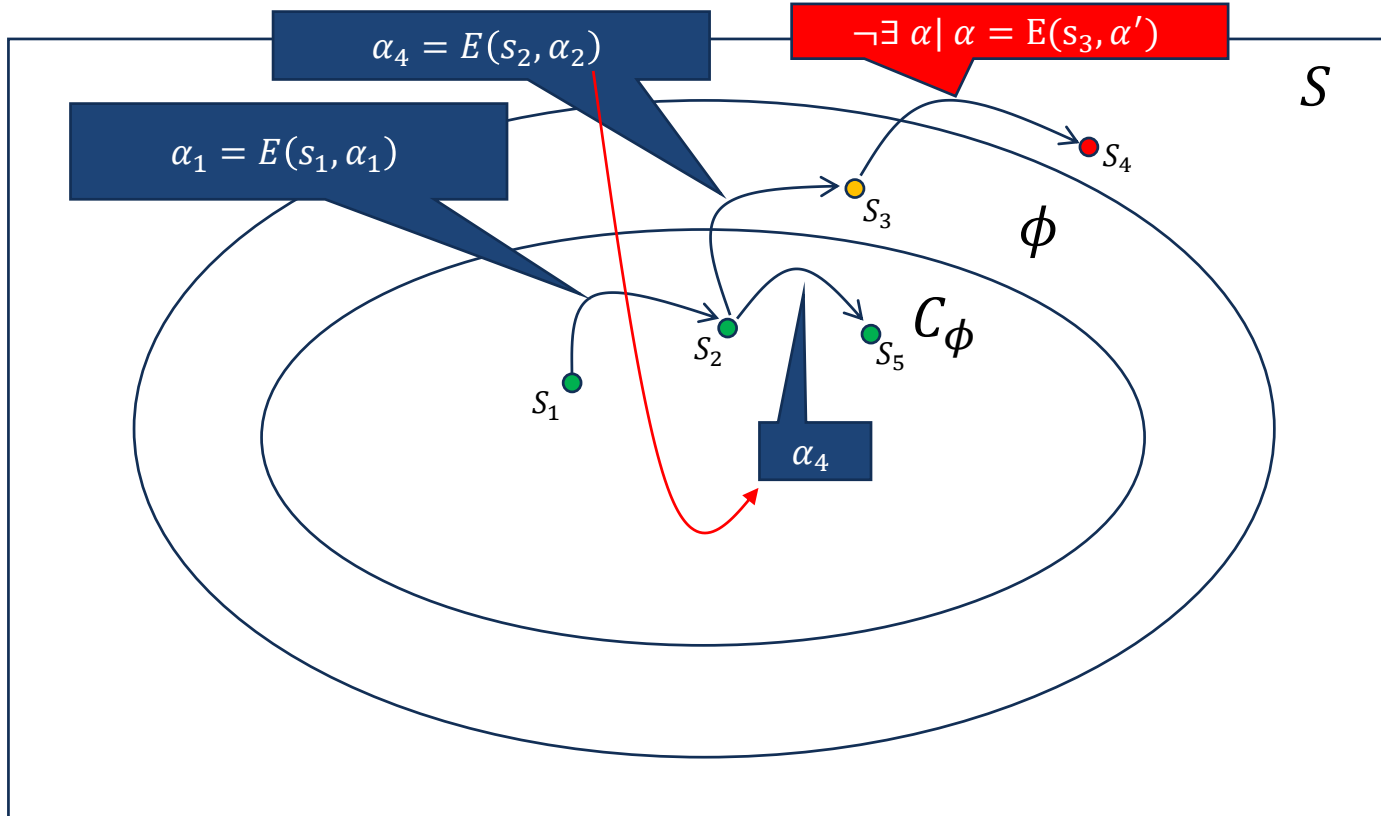
Safe actuation : $SafeAct(s) = \{\alpha \mid R_P(\alpha, s) \in C_\phi\}$

Safe actuation *AHEAD* of enforcement

Formal Model



Enforcer $E(s, \alpha): \alpha \in \text{SafeAct}(s) ? \alpha : \alpha' \in \text{SafeAct}(s)$



Composing Enforcers

Enforcer Details: $E: (P, C_\phi, \mu, U)$

- $\forall s \in C_\phi: \mu(s) \subseteq SafeAct(s)$
- U : utility

Composition without conflict

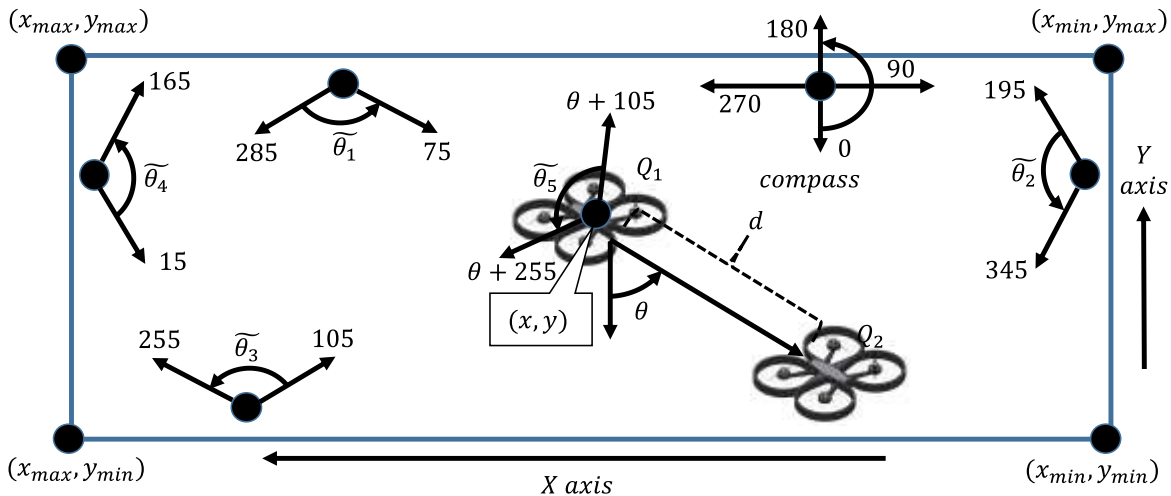
- $E_1: (P_1, C_{\phi_1}, \mu_1, U_1)$
- $E_2: (P_2, C_{\phi_2}, \mu_2, U_2)$
- $\mu_{1,2}: \mu_1 \cap \mu_2$

Conflicting: Priority:

- $\mu_{1,2}: \mu_1 \cap \mu_2 \neq \emptyset ? \mu_1 \cap \mu_2 : \mu_1$

Conflicting: Utility

- $\mu_{1,2}: \mu_1 \cap \mu_2 \neq \emptyset ? argmax_{\alpha \in \mu_1 \cap \mu_2} \sum U_i(s, \alpha') : argmax_{\alpha \in \mu_1} \sum U_i(s, \alpha')$



Are We Done Yet?

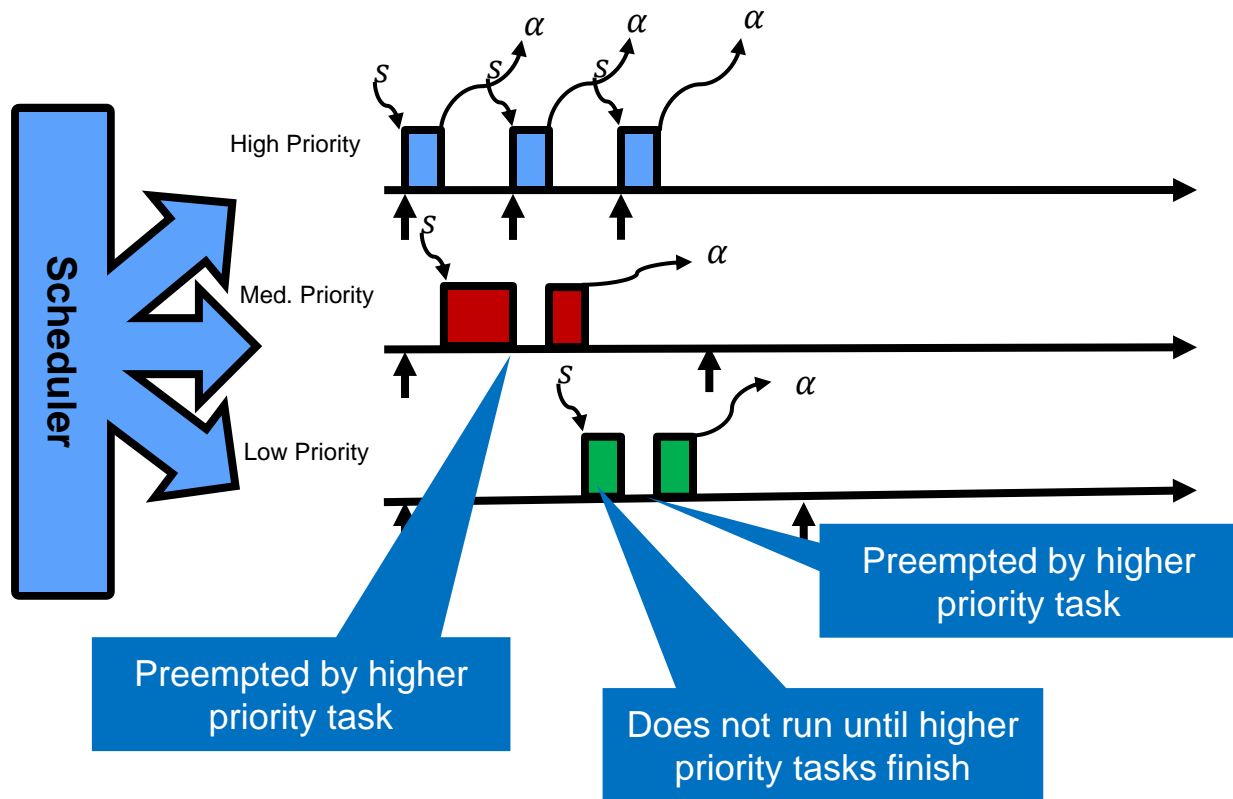
Timing Assumption:

- Unverified software finishes execution and enforcer evaluates output every P period.
- Software is guaranteed to finish executing by the next period (schedulable)
 - Unverified software executes for less than its Worst-Case Execution Time (WCET)
 - Other software running also executes for less than its WCET
 - Schedulability analysis successful

What can go wrong?

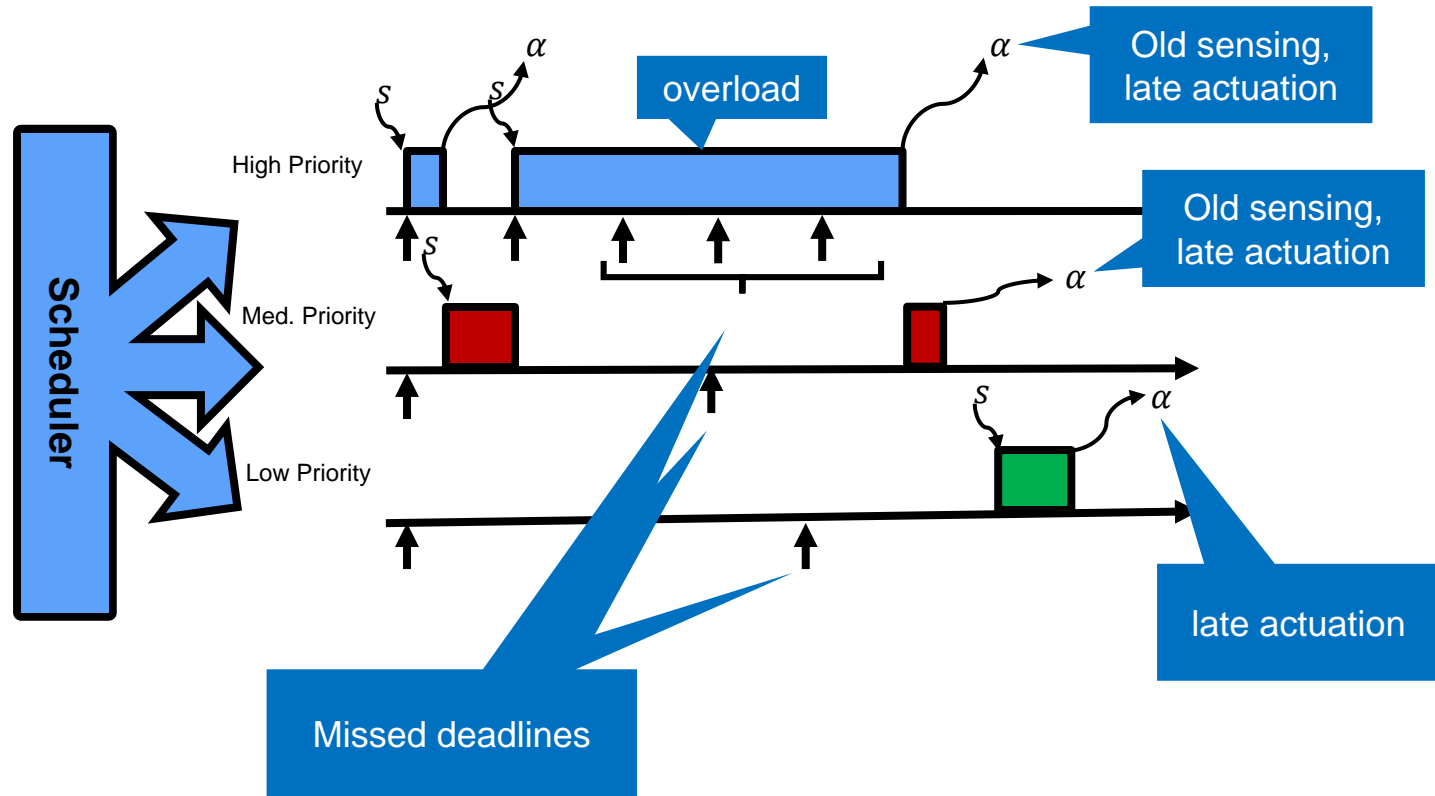
- Unverified software executes **A BIT** longer than WCET
 - Can make other software miss deadlines: late actions with old sensing
- Unverified software executes **A LOT** longer than WCET
 - Makes other miss deadline
 - Does **NOT** produce an output that can be evaluate by enforcer: late action + old sensing
 - **Inertia** takes it to **unsafe state**

Primer: Fixed-Priority Scheduling + Rate Monotonic

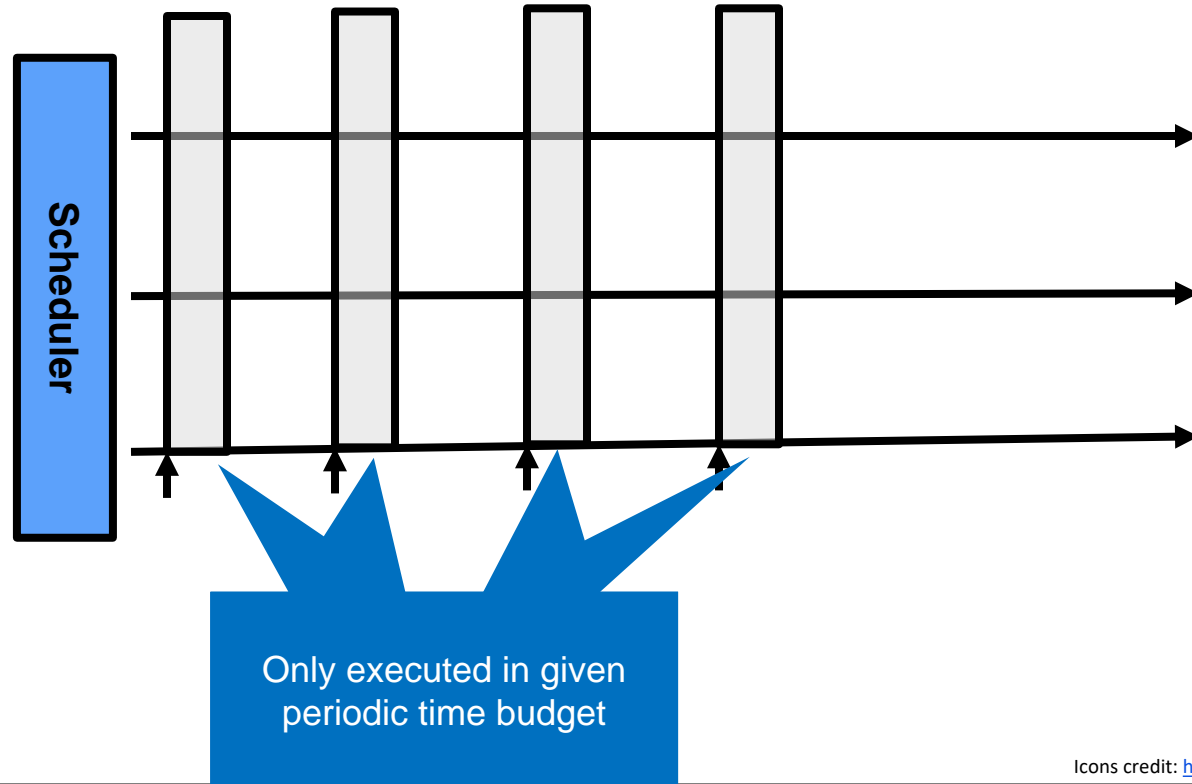


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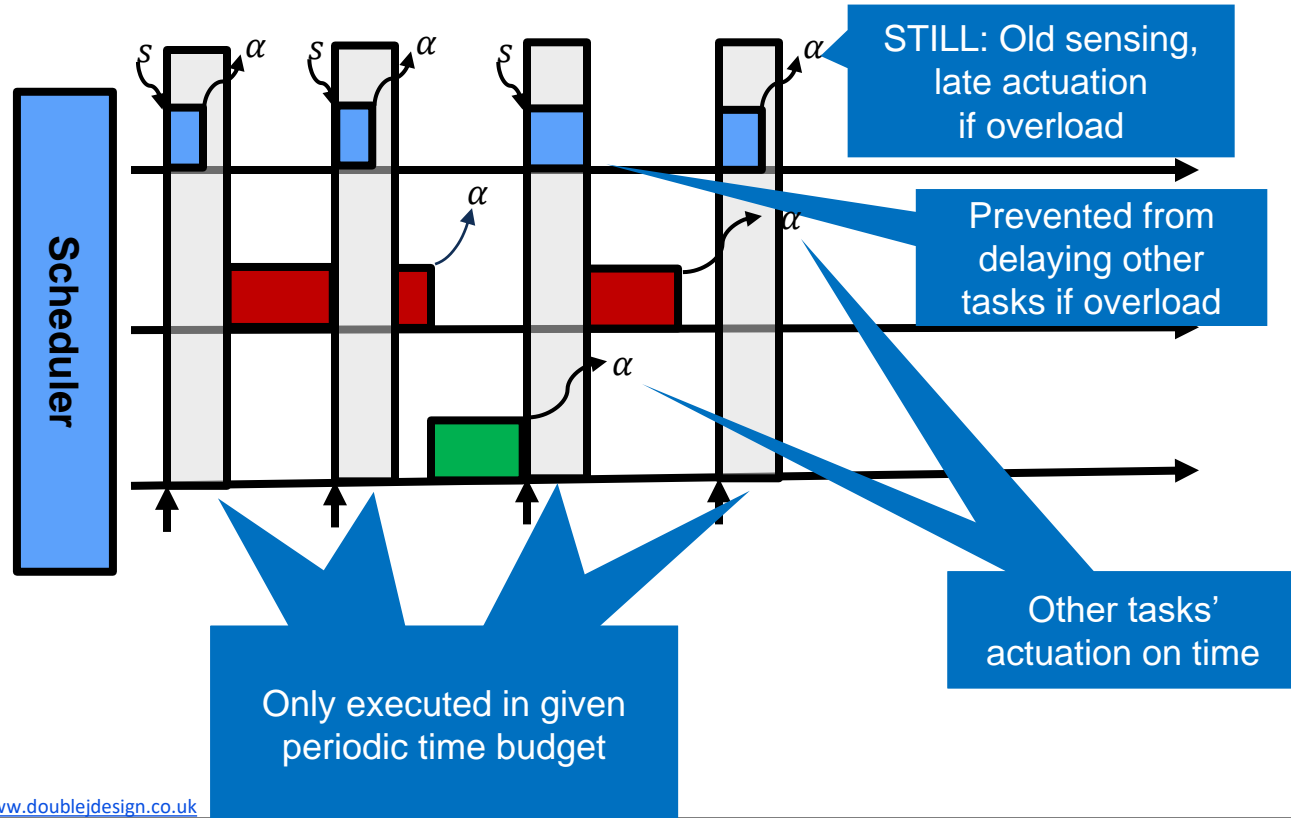
Overload -> Old Sensed Data + Late Actuation



Solution: Enforce Timing Budgets (Timing Enforcement)

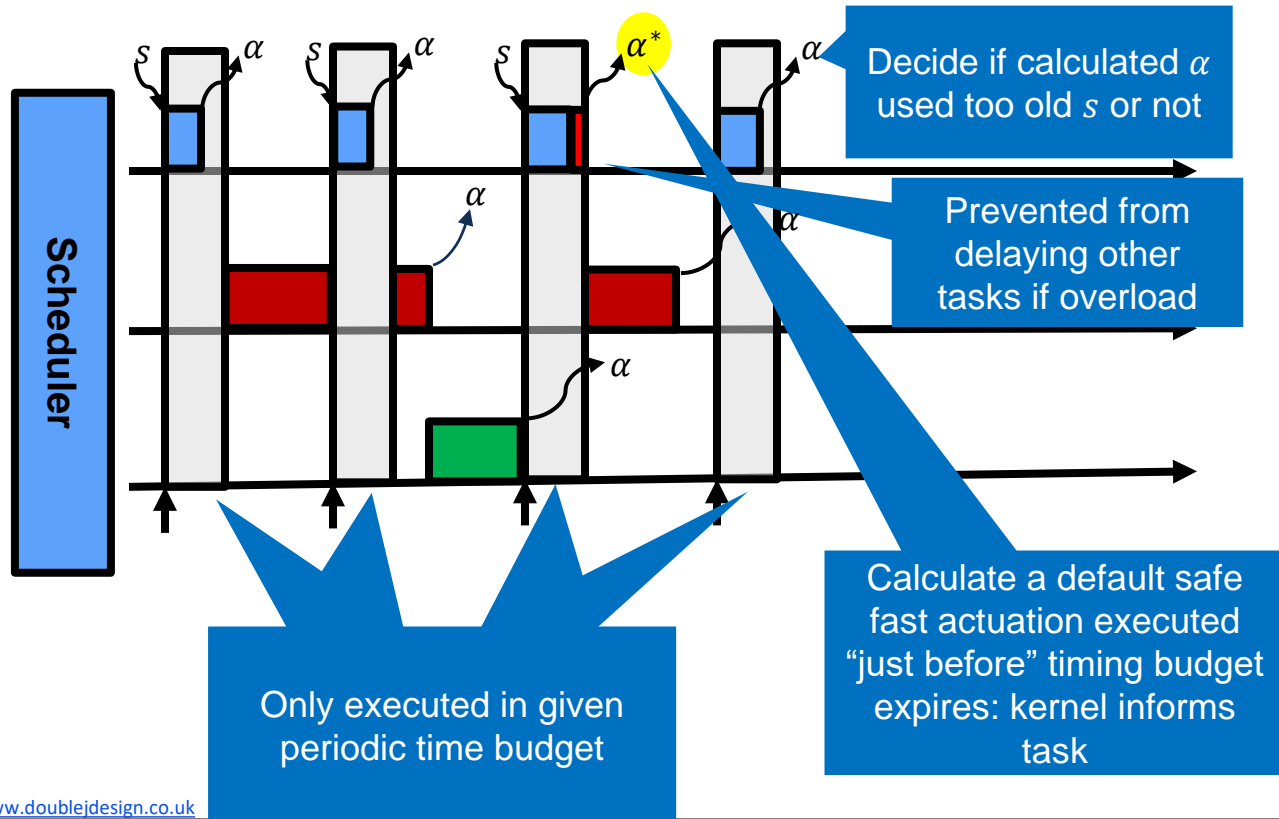


Solution Step 1: Enforce Timing Budgets (Timing Enforcement)



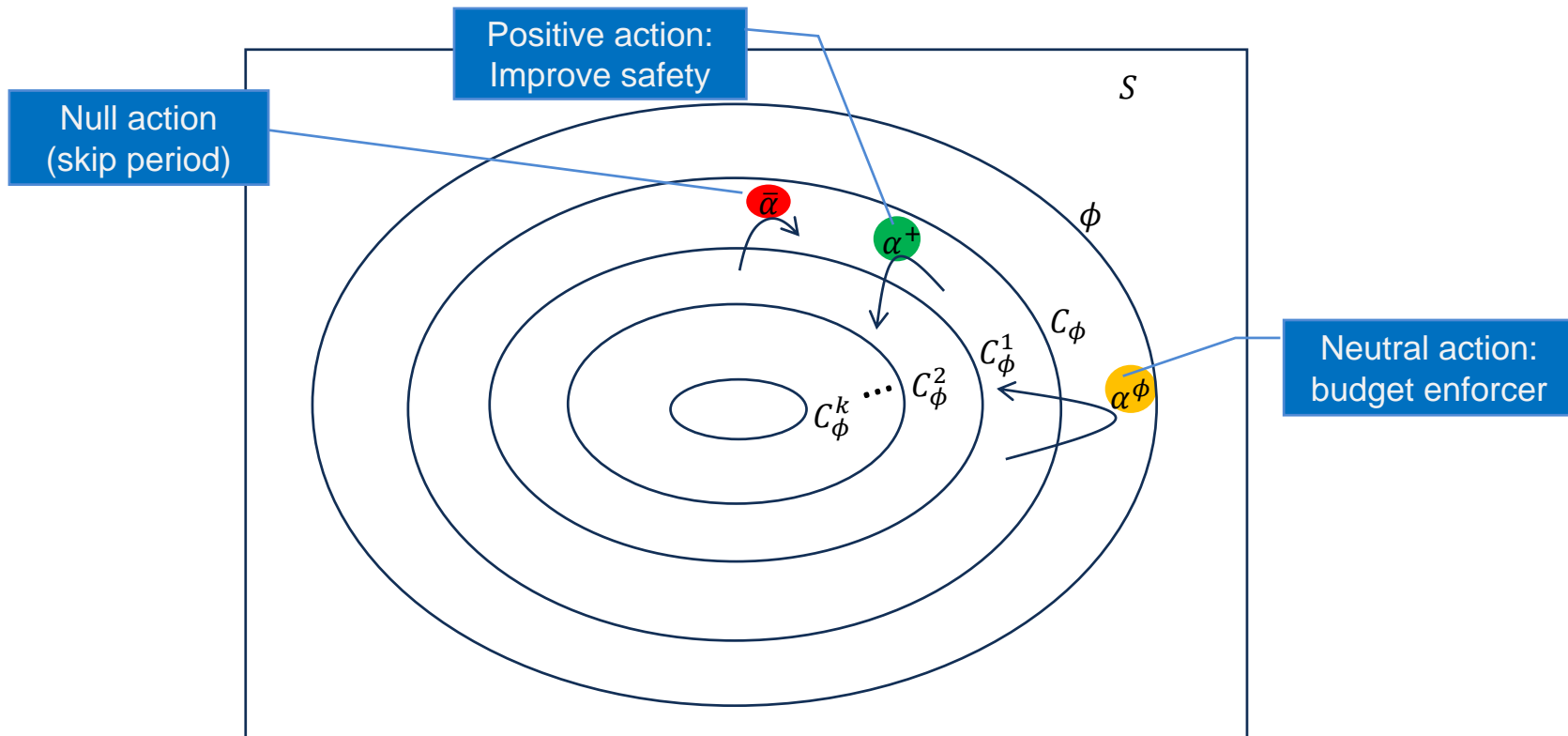
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Solution Step 2: Safe Actuation on Timing Enforcement

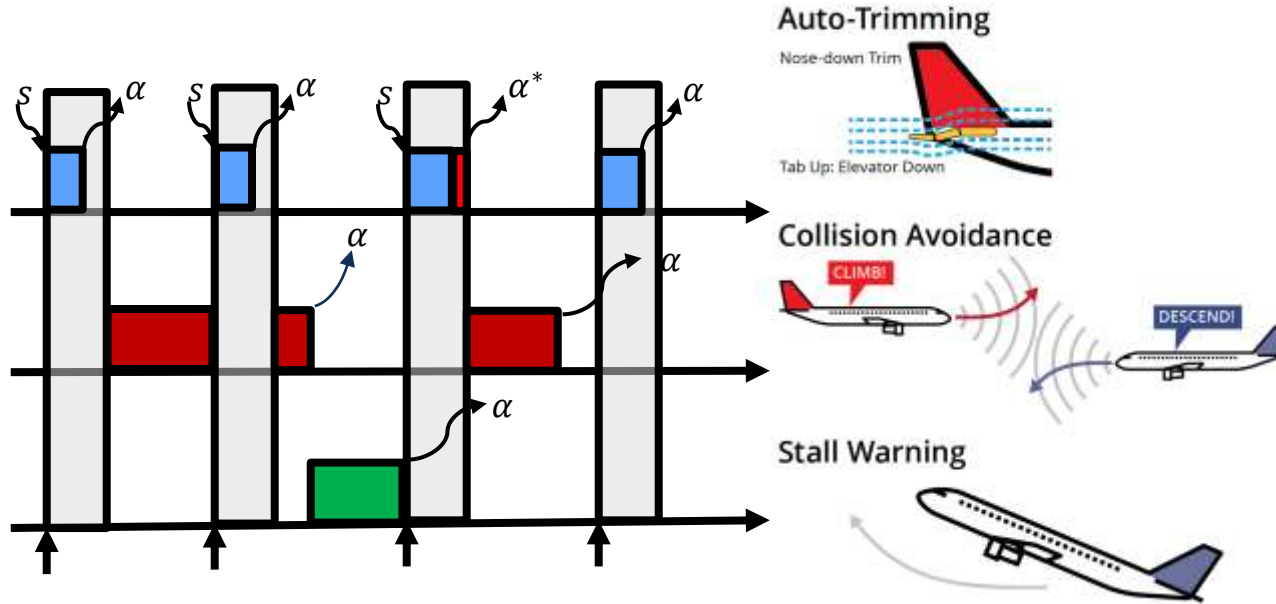


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Scheduling Resilience: Tolerance To Miss Deadlines

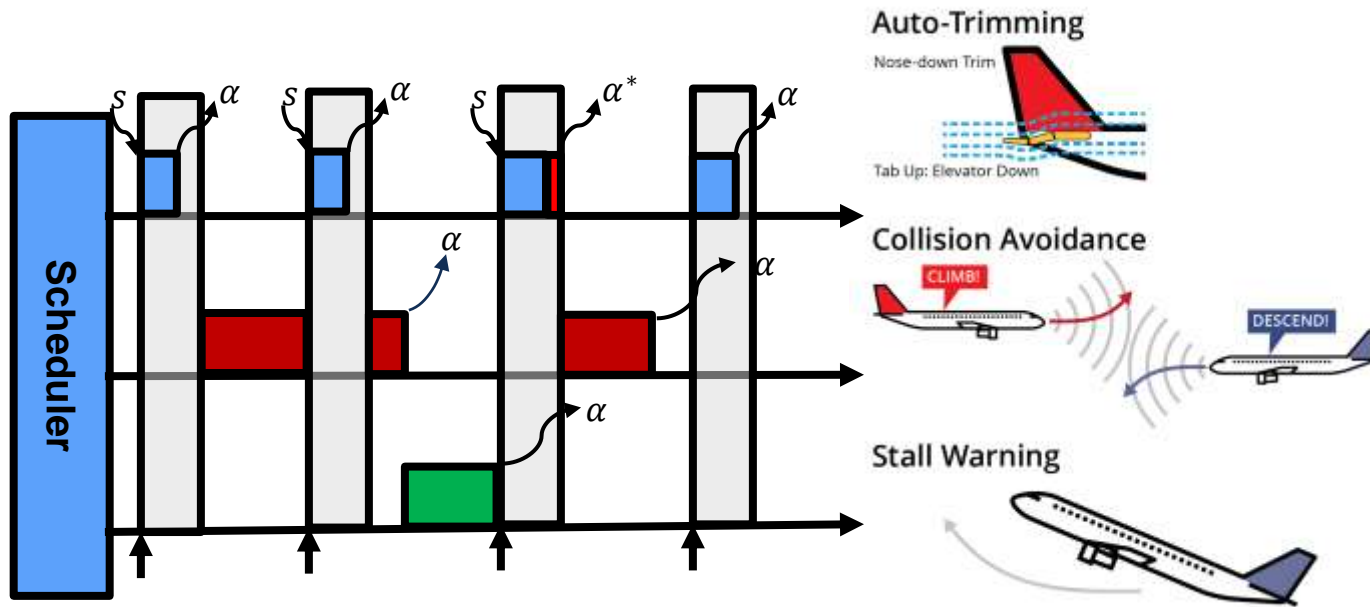


Many Physical Processes – Many Threads



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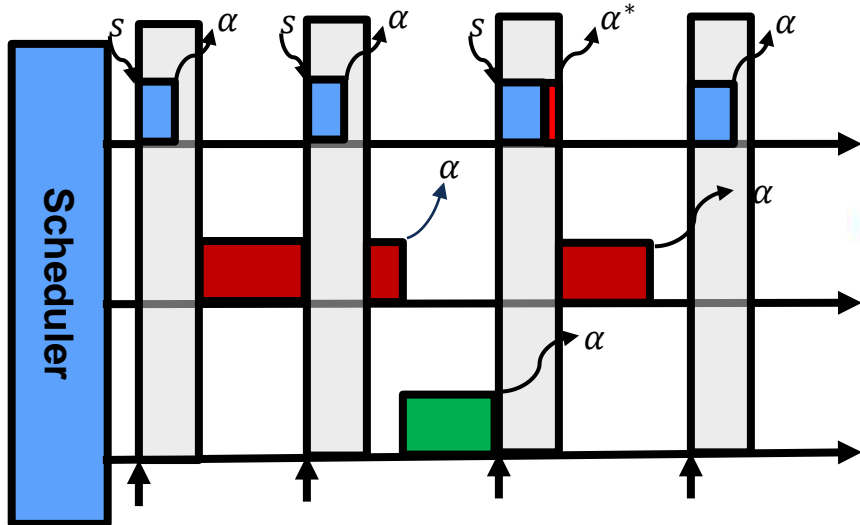
Threads Share Single Processor



Analyze Resilience to Skip Actuations

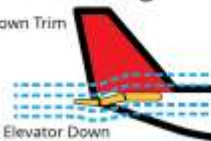
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Threads Share Single Processor



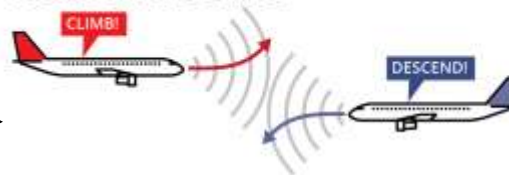
Auto-Trimming

Nose-down Trim

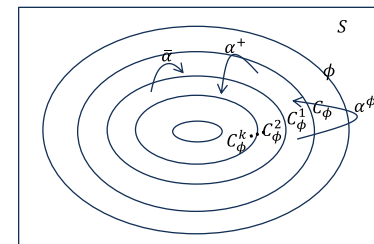
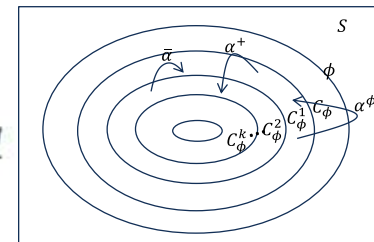
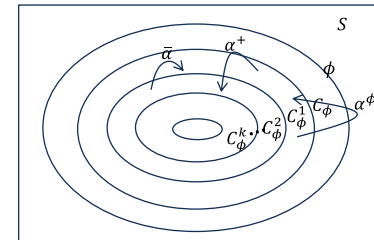


Tab Up: Elevator Down

Collision Avoidance



Stall Warning



Analyze Resilience to Skip Actuations

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Hypervisor Porting

Porting of XMHF Hypervisor for Drone Demos

- Raspberry Pi 3
- New Timing Infrastructure to support integration with temporal enforcer

To Support Tamper-Proof Protection

Results so Far (1)

Paper accepted on 17th International Conference on Runtime Verification 2017

- “Combining Symbolic Runtime Enforcers for Cyber-Physical Systems”
Bjorn Andersson, Sagar Chaki, and Dionisio de Niz

Paper under submission

- “Analyzing Real-Time Scheduling of Cyber-Physical Resilience”
Bjorn Andersson, Dionisio de Niz, and Sagar Chaki.

Results So Far (2)

Software Artifacts

- Temporal Enforcer Scheduler with default actuation
- SMT-Based Logical Enforcer Combination
- Porting of XMHF Hypervisor to Raspberry Pi 3 (to support drone demo)

Demos

- SMT-Based Parrot Mini-Drone demos
 - Logical + Temporal Enforcer

AFRL Summer of Innovation Transition

- Temporal (ZSRM) + Logical Enforcer into Drone Development Platform (UxAS)

ONR : Reuse of some core modeling ideas

Future

Second Year

- Integration of Hypervisor for Tamper-Proof Protection
 - Protect against compromised Virtual Machine
 - Coordinate temporal enforcer between hyper-visor and ZSRM
 - Logical Verification of Hypervisor Integration
- Logical Verification of Logical Enforcer and Default Actuation

Long Term

- Minimize enforcement actions: allow riskier high reward actions BUT safely
 - Require deeper understanding of risky actions and application:
 - e.g., Autonomy and Machine Learning

Contact Information

Presenter / Point(s) of Contact

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