Time(d) Petri Net

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Intuitively
A timed execution of a discrete event system (DES) is a finite or infinite sequence of events: \( e_1, e_2, \ldots \) interleaved with (possibly null) delays.

*generated by some operational model*

More formally
A timed execution of a DES is defined by two finite or infinite sequences:

- The sequence of states \( S_0, S_1, S_2, \ldots \) such that:
  1. \( S_0 \) is the initial state,
  2. \( S_i \) is the state of the system after the occurrence of \( e_i \).

- The sequence of delays \( T_0, T_1, T_2, \ldots \) such that:
  1. \( T_0 \) is the time elapsed before the occurrence of \( e_0 \),
  2. \( T_i \) is the time elapsed between the occurrences of \( e_i \) and \( e_{i+1} \).
A Timed Execution

Space

$S_{12}$

$S_7$

$S_6$

$S_4$

$S_3$

Time

$d_0$

$d_1$

$T_0 = d_0$

$T_1 = d_1$

$T_2 = 0$

$T_3 = 0$

$S_0 = S_4$

$S_1 = S_6$

$S_2 = S_3$

$S_3 = S_{12}$

$S_4 = S_7$
# Time in Petri Nets

## What are the events?

Atomicity versus non atomicity
- Beginning and end of transition firings
- Transition firings

## What are the delays?

Timing requirements for transition firing
- Duration of transition firings
  \((asap \ requirement)\)
- Appropriate age of tokens
  \((requirement \ on \ tokens)\)
- Delay before firing
  \((requirement \ on \ delay \ between \ enabling \ and \ firing)\)
A Duration-Based Semantic

Requires to specify durations.

Problem: most of the time, states are not reachable markings of the net.
A Token-Based Semantic

Requires to specify age constraints.
A Delay-Based Semantic

Requires to specify transition delays.
Outline

Time and Petri Nets

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Timed Petri Nets: Syntax and Semantics

Analysis of Timed Petri Nets
Time Petri Net (TPN): Syntax

Places: logical part of the state

Tokens: current value of the logical part of the state

Transitions: events, actions, etc.

Arcs: Pre and Post (logical) conditions of event occurrence

Time intervals: temporal conditions of event occurrence
TPN: Transition Occurrence

Logical part (as in Petri nets)

- The logical part of a state (or configuration) is a marking $m$, i.e. a number of tokens per place $m(p)$.
- A transition is enabled if the tokens required by the preconditions are present in the marking.

Timed part

- There is an implicit clock per enabled transition $t$ and its value $\nu(t)$ defines the timed part of the state.
- The clock valuation $\nu$ is the timed part of the configuration.
- An enabled transition $t$ is firable if its clock value lies in its interval $[e(t), l(t)]$.

Notation: $(m, \nu) \xrightarrow{t}$
The initial configuration is \((p_1 + 2p_2, (0, 0))\)

Both \(t_1\) and \(t_2\) are enabled.

None is firable.
Time elapsing $d$

- Time may elapse with updates of clocks if every clock value does not go beyond the corresponding interval.
- The marking is unchanged $(m, \nu) \xrightarrow{d} (m, \nu + d)$

\[ \begin{align*}
(p_1 + 2p_2, (0, 0)) & \xrightarrow{1.5} (p_1 + 2p_2, (1.5, 1.5)) \\
\text{Now } t_2 \text{ is firable.}
\end{align*} \]
Configuration Change by Transition Firing

**Transition firing \( t \)**

- Tokens required by the precondition are consumed and tokens specified by the postcondition are produced.
- Clocks values of *newly enabled* transitions are reset leading to valuation \( \nu' \).
- Thus \( (m, \nu) \xrightarrow{t} (m - Pre(t) + Post(t), \nu') \)

**A transition \( t' \) is newly enabled if**

1. \( t' \) is enabled in \( m - Pre(t) + Post(t) \)
2. and \( t' \) is disabled in \( m - Pre(t) \) or \( t' = t \)
An Execution

\[
p_1 \quad t_1, [2, 2] \quad 0 \quad p_2 \quad 1.5 \quad t_2, [1, 4]
\]

\[
t_1, [2, 2] \quad 1.5 \quad t_2 \quad p_2
\]

\[
p_1 \quad t_2, [1, 4] \quad 0.5 \quad t_1, [2, 2] \quad 2 \quad p_2 \quad 0.5 \quad t_1, [2, 2] \quad 1.5 \quad p_2
\]

\[
t_1 \quad p_2 \quad t_1 \quad t_2
\]

\[
p_1 \quad t_2, [1, 4] \quad 0 \quad t_1, [2, 2] \quad 0 \quad p_2 \quad 1.5 \quad t_2, [1, 4]
\]
An Equivalent Semantic

The timed part is defined by a *dynamic firing interval* \([\bar{e}(t), \bar{l}(t)]\) associated with every enabled transition \(t\).

### Firing of \(t\)

- A transition may fire if it is enabled and \(\bar{e}(t) = 0\).
- Intervals of newly enabled transition are reinitialized: \([\bar{e}(t), \bar{l}(t)] := [e(t), l(t)]\).

### Time elapsing \(d\)

- Time \(d\) may elapse if for every enabled transition \(t\), \(d \leq \bar{l}(t)\).
- Time intervals are accordingly updated \([\max(0, \bar{e}(t) - d), \bar{l}(t) - d]\).
Revisiting the Execution
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Properties

Generic properties

- **Reachability** Given some state $m$ can the system reach $m$?
- **Non Termination** Does there exist an infinite firing sequence?
- **Deadlock** Does there exist a state from which no transition will fire?

Specific properties

- **Temporal Logic** CTL, LTL, CTL*, etc.
  
  Is $e$ eventually followed by $e'$ in every maximal sequence?

- **Timed Temporal Logic** TCTL, MTL, MITL, etc.
  
  Is $e$ eventually followed by $e'$ within at most 10 t.u. in every maximal sequence?
Overview

In TPNs,

all relevant properties are undecidable.

In bounded TPNs,

▶ many generic properties are decidable,
▶ some temporal model checking is decidable.

Boundedness problem

▶ Undecidable for TPNs
▶ A decidable sufficient condition: boundedness of the underlying PN

Key algorithms: class graph constructions
What is a Class?

A class is a finite representation of an infinite set of reachable configurations.

A class is defined by:

- A marking \( m \) (with \( T_m \) the set of enabled transitions);
- A set of variables \( \{x_0 = 0\} \cup \{x_t\}_{t \in T_m} \) with \( x_t \) the possible firing delay for \( t \);
- A matrix \( C \) (called a DBM) representing a set of constraints:
  \[
  C(x_1, \ldots, x_n) \equiv \bigwedge_{i,j} x_j - x_i \leq c_{ij}
  \]

The initial class

Let \( T_0 = \{t_1, \ldots, t_k\} \) be the set of transitions enabled at \( m_0 \).

Then:

\[
C(x_{t_1}, \ldots, x_{t_k}) \equiv \bigwedge_{t \in T_0} e(t) \leq x_t \leq l(t)
\]
Firing a Transition from a Class

Firability of \( t^* \) from class \((m, C)\)

In order to fire some \( t^* \in T_m \), the following system must have a solution:

\[
C_{t^*} \equiv C \land \bigwedge_{t \in T_m \setminus \{t^*\}} x_{t^*} \leq x_t
\]

Firing \( t^* \) from class \((m, C)\)

Let \( m \xrightarrow{t^*} m' \) and \( T_{m'} \) be the transitions enabled at \( m' \) with delays \( x'_t \) then:

- If \( t \) is newly enabled, the constraint is \( C_t \equiv (e(t) \leq x'_t \leq l(t)) \)
- Otherwise the constraints are inherited by \( C_t \equiv (x'_t = x_t - x_{t^*}) \)

Consequently, the constraints for firing delays after firing of \( t^* \) is

\[
C' \equiv \exists x_{t_1} \ldots \exists x_{t_k} C_{t^*} \land \bigwedge_{t \in T_{m'}} C_t
\]

Problem: this is no more a DBM-based representation of a class!
Recovering the Class Representation

The initial class: \( C \equiv 0 \leq x_1 \leq 4 \land 5 \leq x_2 \leq 6 \land 3 \leq x_3 \leq 6 \)

The firability condition: \( C_{t_1} \equiv C \land x_1 \leq x_2 \land x_1 \leq x_3 \)

After firing: \( C' \equiv \exists x_1 \exists x_2 \exists x_3 \ C_{t_1} \land x'_2 = x_2 - x_1 \land x'_3 = x_3 - x_1 \)

Recovery process

- Elimination of \( x_2 \) and \( x_3 \) by substitution
  \[ C'' \equiv \exists x_1 \ 0 \leq x_1 \leq 4 \land 5 \leq x'_2 + x_1 \leq 6 \land 3 \leq x'_3 + x_1 \leq 6 \]

- Elimination of \( x_1 \) by upper and lower bounds
  \[ C'' \equiv \exists x_1 \ \max(0, 5 - x'_2, 3 - x'_3) \leq x_1 \leq \min(4, 6 - x'_2, 6 - x'_3) \]
  \[ \equiv 1 \leq x'_2 \leq 6 \land 3 \leq x'_3 \leq 6 \land -3 \leq x'_3 - x'_2 \leq 1 \]
The Class Graph Algorithm

Add the initial class $C$ to $G$ (*the class graph*)

$\text{Insert}(\text{Heap}, C)$

**While** $\text{Heap}$ is not empty **do**

$C \leftarrow \text{Pick}(\text{Heap})$

**For all** $t$ **firable from** $C$ **do**

$C' \leftarrow \text{Fire}(C, t)$

**If** $C'$ **does not belong the graph** **then**

Add $C'$ to $G$

$\text{Insert}(\text{Heap}, C')$

Add $C \xrightarrow{t} C'$ to $G$

Open issues

- How to check the emptiness of a DBM?
- How to check whether two DBMs admit the same set of solutions?
## Properties of the Class Graph

### Finiteness for bounded nets
- The number of reachable markings is finite.
- The absolute value of integers occurring in the DBMs are bounded by:
  \[ \max(\max_{t \in T}(l(t) \mid l(t) \text{ finite}), \max_{t \in T}(e(t) \mid l(t) \text{ infinite})) \]

### Trace and marking representation
- The untiming of every firing sequence of the TPN is a path of the graph.
- For every path of the graph there is a corresponding firing sequence.
- Thus the reachable markings are exactly those occurring in the graph.
- The reachable configurations are those of the classes occurring in the graph.
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Properties of DBM

There exists a canonical representation for non empty DBM.

Canonization and emptyness checking can be done in polynomial time.

DBM are effectively closed under:

1. Projection $\exists x_1 \ C(x_1, x_2, \ldots, x_n)$
2. Relativization $\exists x_1 \ C(x_1, x_2 + x_1, \ldots, x_n + x_1)$
3. Past $\exists d \ C(x_1 + d, x_2 + d, \ldots, x_n + d)$
4. Future $\exists d \ C(x_1 - d, x_2 - d, \ldots, x_n - d)$
5. Reset $\exists x \ C(x, x_2, \ldots, x_n) \land x_1 = 0$
Canonization

Canonization is done by a shortest path computation.

Let the constraint be:

\[ x_1 - x_0 \leq 3 \land -2 \leq x_2 - x_1 \leq 1 \land x_0 - x_2 \leq -2 \]

Then the canonized constraint is:

\[ 1 \leq x_1 - x_0 \leq 3 \land -1 \leq x_2 - x_1 \leq 1 \land -4 \leq x_0 - x_2 \leq -2 \]
Floyd-Warshall Algorithm

For all $k$ do
  For all $j$ do
    For all $i$ do
      $c_{ij} \leftarrow \min(c_{ij}, c_{ik} + c_{kj})$
    For all $i$ do
      If $c_{ii} < 0$ Then Return(Empty DBM)
### Correctness of the Algorithm

**Correctness of the shortest path algorithm . . .**

- The algorithm returns **Empty DBM** iff there is a negative cycle in the graph.
- Otherwise, $c_{ij}$ is the length of a shortest path from $x_i$ to $x_j$ and consequently $c_{ik} \leq c_{ij} + c_{jk}$ for all $k$.

**implies correctness of the canonization.**

- If there is a negative cycle in the graph there is no solution of the DBM. *(by transitivity one gets $x_i - x_i < 0$)*
- Otherwise for all $i, j$ there is no solution with $x_j - x_i > c_{ij}$ and a solution with $x_j - x_i = c_{ij}$ *(define $x_i = 0$ and $x_k = c_{ik}$ for all $k \neq i$)*
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**Timed Petri Net (TdPN): Syntax**

**Places:** both logical and timed part of the state

**Tokens:** have an age

**Transitions:** events, actions, etc.

**Labels:** observable behaviour

**Arcs:** Pre (resp. Post) conditions of event occurrence

are multisets of timed intervals corresponding to

required (resp. possible) age of consumed (resp. produced) tokens
Marking and (simplified) precondition

- The marking of place \( p \), \( m(p) \) is a finite multiset of ages

\[
m(p) = \sum_{1 \leq i \leq r} a_i . \tau_i \text{ with } r \geq 0 \text{ and } a_i > 0
\]

- The precondition of a transition \( t \) with input place \( p \), \( Pre(p, t) \) is an interval.

A transition \( t \) is firable if for every input place \( p \) of \( t \)

There exists an appropriate token, i.e. some \( i \) such that \( \tau_i \in Pre(p, t) \)

Observation: the generalization to bags of intervals is intuitive but requires technical machinery.
Time elapsing $d$

- Time may elapse without any restriction.
- The age of tokens is accordingly updated $m \xrightarrow{d} m'$ such that $m'(p) = \sum_{1 \leq i \leq r} a_i \cdot (\tau_i + d)$ when $m(p) = \sum_{1 \leq i \leq r} a_i \cdot \tau_i$.

Transition firing $t$

- Tokens selected by the precondition are consumed.
- Tokens specified by the postcondition are produced with an initial age non deterministically chosen in the corresponding interval.
A time elapsing $2 \cdot (p_1, 0) + (p_2, 0) \xrightarrow{2} 2 \cdot (p_1, 2) + (p_2, 2)$
before a transition firing $2 \cdot (p_1, 2) + (p_2, 2) \xrightarrow{t_1} (p_1, 2) + (p_2, 0.5)$
(observe that the age of token in $p_2$ could be different)

followed by a time elapsing $(p_1, 2) + (p_2, 0.5) \xrightarrow{1.8} (p_1, 3.8) + (p_2, 2.3)$
(observe that the token in $p_1$ is dead)

before a transition firing $(p_1, 3.8) + (p_2, 2.3) \xrightarrow{t_2} (p_1, 3.8)$
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Reachability Analysis of Bounded TdPNs

The number of (reachable) configurations is infinite (and even uncountable). So one wants to partition configurations into regions such that:

1. The number of tokens of any place for two configurations in a region is the same.

2. Two configurations in a region allow the same transition firings and the new configurations belong to the same region.

3. If a configuration in a region letting time elapse reaches a new region every other configuration may reach the same region by time elapsing.

4. There is a finite representation of a region such that the discrete and time successors of the region are computable.

5. The number of regions is finite.
A First Partition
(two tokens and two markings)

Intervals check integer values.

\((x \text{ and } y \text{ are the ages of the two tokens})\)

Why this partition is not appropriate?
A Second Partition
(two tokens and two markings)

The exact value of a token age is irrelevant when it is beyond the maximal constant of the TdPN (here 2)

Why this partition is not appropriate?
A Third Partition
(two clocks and two locations)

Check that this partition is appropriate
The Region Graph: Illustration
Warning: when a region is “reachable”, it does not mean that every configuration of the region is reachable.

However it means that there is another reachable configuration of the region which differs only on the values of irrelevant ages of tokens.

Hence, in order to check the reachability of a configuration, it is enough to increase the maximal constant.

Example: reachability of \( ((p_0, 1.7), (p_1, 2.3)) \) requires to choose at least 3 as maximal constant.
Formalizing Regions

A region of a TdPN is:

- $n + 1$ different and ordered fractional parts of the token ages with the null fractional part.
- The distribution of tokens on places and their integer part (when less or equal than the maximal constant) for every fractional part.
- The distribution of tokens with age greater than the maximal constant on places.

In the unbounded case, the corresponding region graph is infinite but it is a well-structured transition system and thus (for instance) coverability can be decided by a symbolic backward exploration.
Main References

On definition and analysis of TPNs


On definition and analysis of TdPNs