

ABC Encapsulation

Fault tree generator

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Version 1.0

Abstract

ABC is a new generation fault-tree generator based on AltaRica DataFlow language. Developed as part of ISAAC project, it aims to overtake limits of historical generator of BPA DAS.

Firstly, *ABC* overtakes current fault tree generation limit by considering:

- instantaneous events
- different types of synchronizations (not only Common Cause Failures)
- models using flows in guards of transitions.

Eventually, it will manage systems with loops.

This chapter deals with the integration of this engine in BPA DAS.

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FaultTree generation with ABC

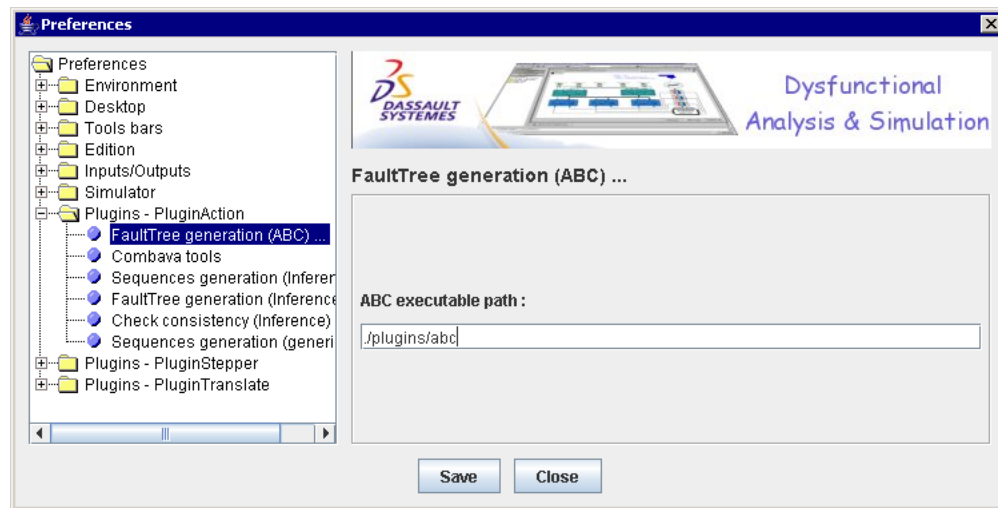
FaultTree generation consists in compiling AltaRica model into boolean formula. Compilation algorithm use a deductive approach from groups of "independant" components. Boolean formula generation is made with reachability graphs associated to each group.

Fault-trees are generated in *Aralia* format. This format contains equations (tree structure), laws, attributs associated with model events, and parameters of generated laws. Generated trees can be either used directly in *Aralia* with command scripts, or imported in BPA SSA or in another fault-tree-editor which supports *Aralia* native format.

Install/Parameter

FaultTree generation is based on *ABC* software. This software is available in plugin installation directory.

Users preferences allow to specify *ABC* location.



FaultTree generation requirements

It's important to notice that AltaRica model can be dynamic (reconfiguration, maintenance, ...) and that a fault-tree is an instantaneous view of a system, that's to say a static view. Therefore, an AltaRica model may not be compilable into boolean formula.

FaultTree generation implies some model restrictions. These restrictions are:

- Dynamic behavior of components

Because fault-tree is a static model, it's impossible to compile a model whose final state depends on faults order. The two following restrictions ensure a static behavior:

- For each fault-combination, if a fault-permutation is workable, every other permutation must be workable and must lead to the same state of the component.
- Transitions must be independant of component flows. In other words, component reachability graph must only depends on its initial state and its local failures.
- Uncomplete or unconsistant component(s)
- Too complex component(s)

A too complex component will generate a local combinative explosion during calcul of its reachability graph.

- Looped System

A looped system is a system with circular definition of its flow variables. That is to say, a X variable is define with a set of AltaRica assertions which depend on variable X.

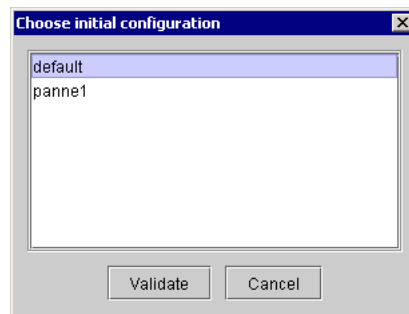
These restrictions ensure a good behavior of compilation algorithm. Check properties (when config is correct) enables to spot things that don't fit these restrictions.

FaultTree generation launching



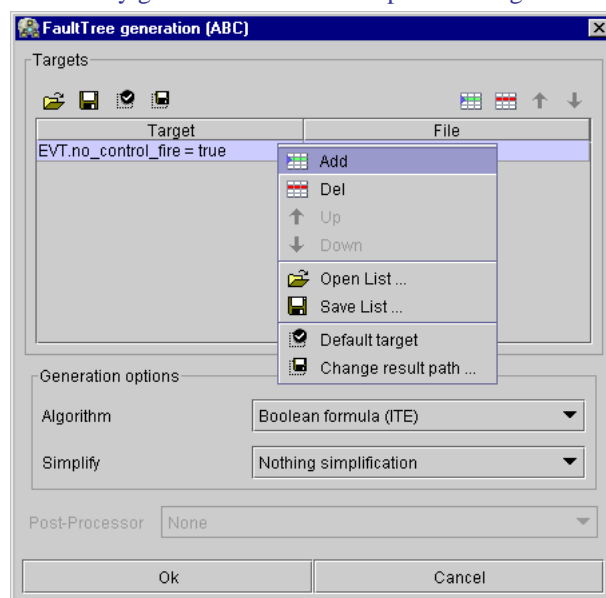
In order to launch FaultTree generation, use the **FaultTree generation (ABC)...** command.

A window is displayed when model has many initial configurations (**System** menu, **Initial states ...** command), in order to select initial configuration to take into account.



Feared event is defined thanks to a calculation-target. The target corresponds to a specific value of a model variable (If the variable is equal to the selected target the feared event happens). Calculation parameters are usually associated with a calculation-target (for exemple, the result file name).









The following dialog window enables to define one (or several) target(s) which must be taken into account during FaultTree generation. A fault-tree will by generated for each computation target.



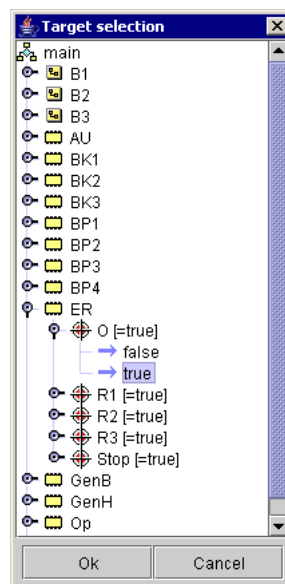
This window manage a list of computation-targets. When this window is validate, every typed information are validate to ensure that there is no incomplete line, no wrong line, targets correspond to a variable of processed model, file can be written

Moreover, if result-files already exist, a dialog window will ask for old file deletion.

Some icons/actions enables to modify the list of calculation targets.

	Add a calculation-target (a line in the list). The target is duplicated from a default calculation target.
	Remove selected computation target.
	Climb selected target up.
	Go selected target down.
	Define default computation-target from selected target. Every new target will be created using this default one.
	Save target-list in a XML file in order to re-use it.
	Load a list of computation targets.
	It enables to define result files associated to targets thanks to a pattern which take into account informations linked to calculation targets. The result file name will be define replacing generation tag %xxx% by their contents : %num% => order number in the list, %var% => variable name, %val% => value to use, ...

Double-click on an element of the list enables to edit it with an appropriate editor



Target editor opens a window and shows every model variable in a tree view. Select the value corresponding to the feared event to take into account.

File editor displays a standard file chooser window.

Two **Algorithm** are available in order to generate boolean formula :

1. **Boolean Formula (SOP)** : compile sum of product into simple boolean formule.
2. **Boolean Formula (ITE)** : compile sum of product into a tree structure 'If ... then ... else ...' (more powerful in case of weighty systems).

Three **Simplify** levels are available :

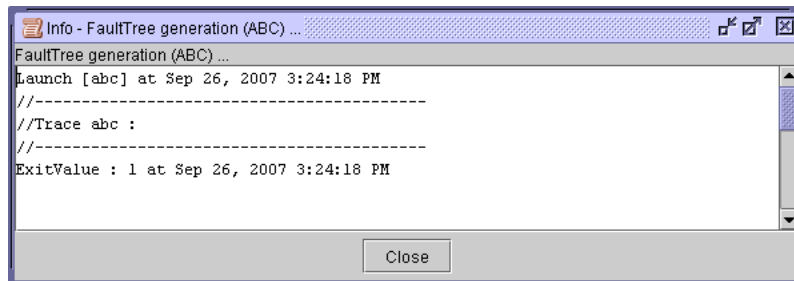
- **Nothing simplification**
- **Constant propagation** : In generated fault tree, boolean connectors having true or false arguments are simplified.
- **Unreferenciation** : simplifies the tree by deleting unuseful intermediate variables.

When this window is correctly filled and validated, **ABCTree** task is added to the task manager of BPA DAS

Result of FaultTree generation

At the end of fault tree generation, a window is displayed. It shows *ABC* execution trace.

If everything is alright, this trace should be empty.



In the contrary (looped system, ...), *ABC* displays an error message.

