



Safety evaluation of in-car real-time applications distributed on TDMA-based networks

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Nancy, 13-14 October 2005

Safety evaluation of in-car real-time applications distributed on TDMA-based networks



Cédric Wilwert



Françoise Simonot-Lion, Ye-Qiong Song



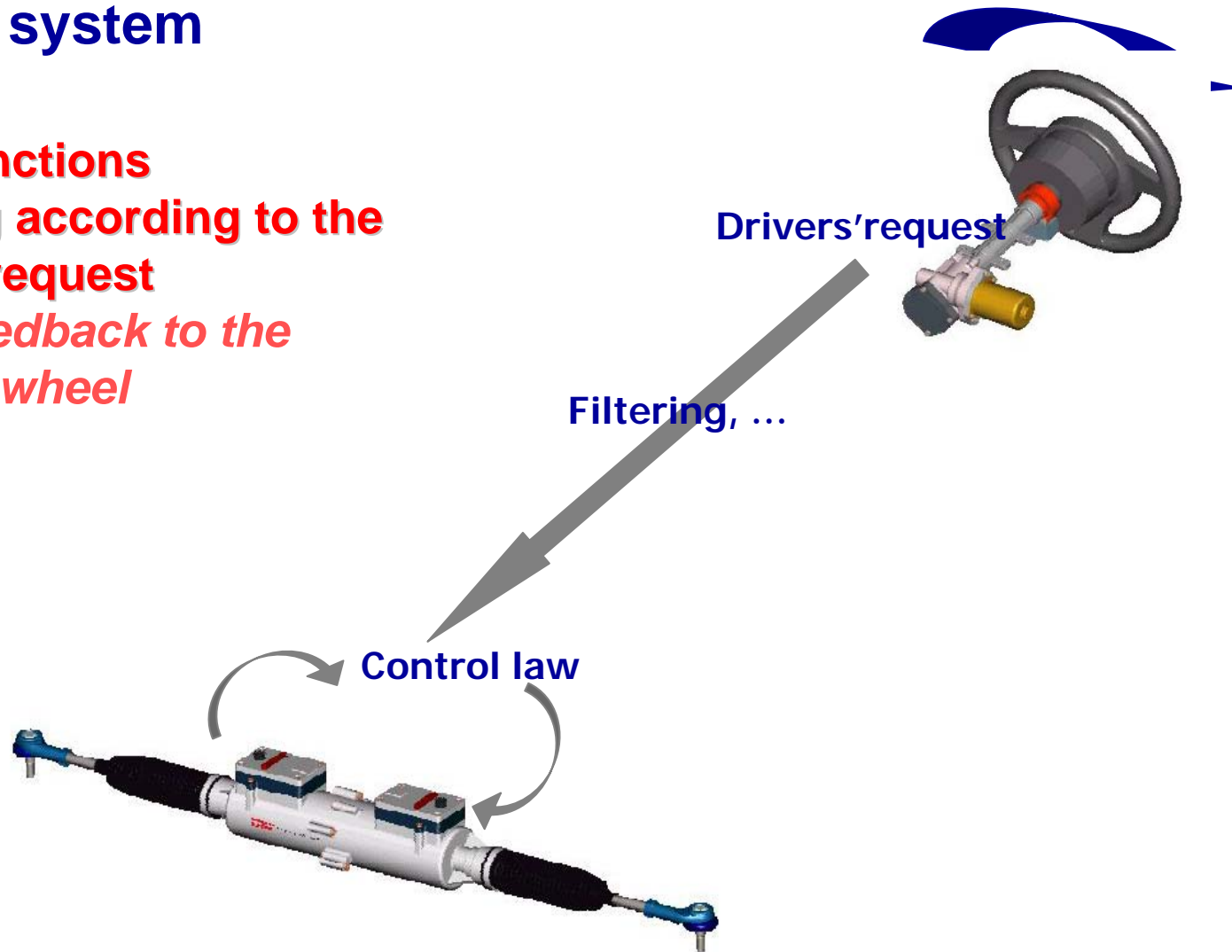
François Simonot

X-by-Wire and Safety assessment: which issue?

Steering system

Critical functions

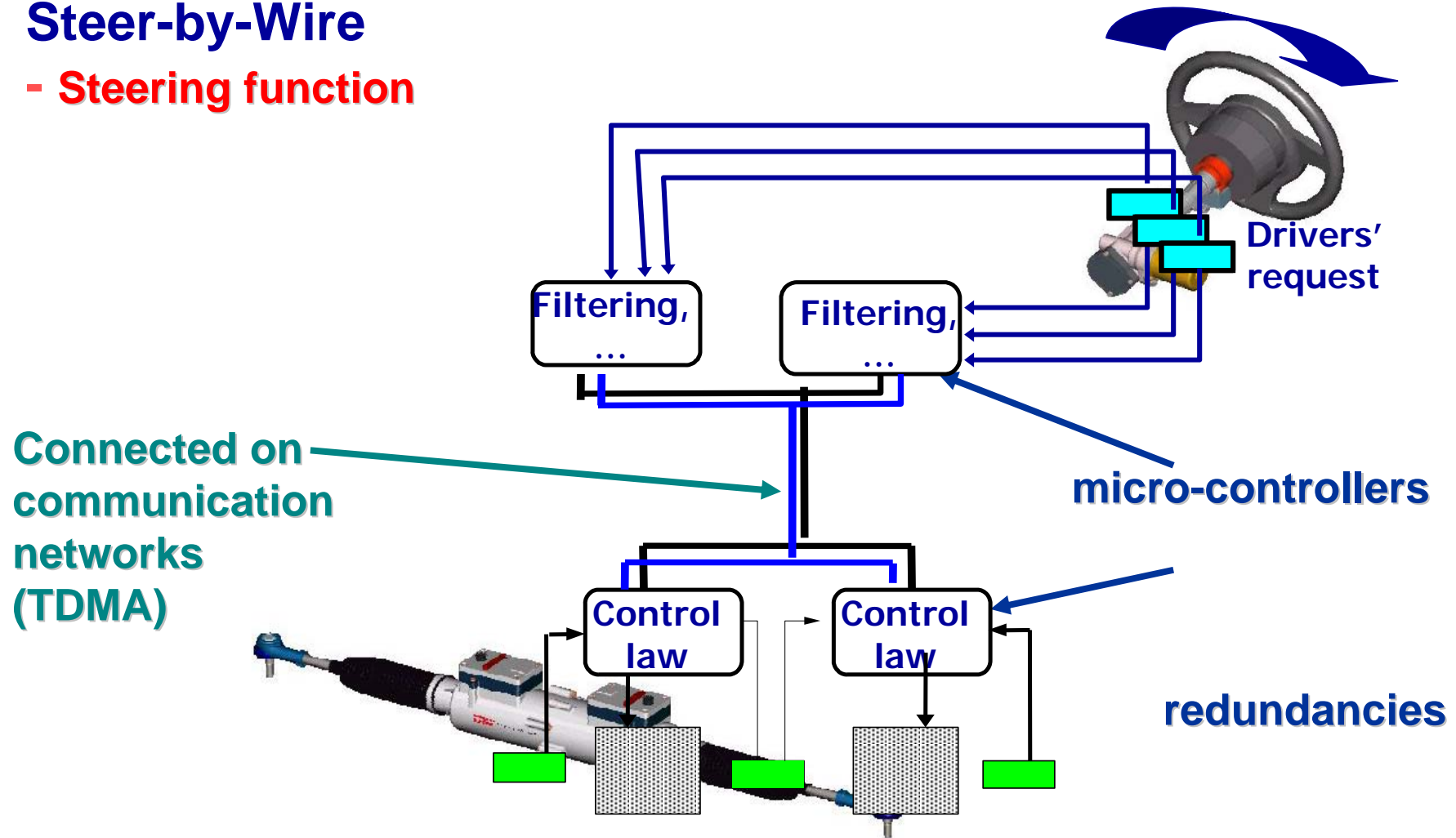
- **Steering according to the drivers' request**
- *Force feedback to the steering wheel*



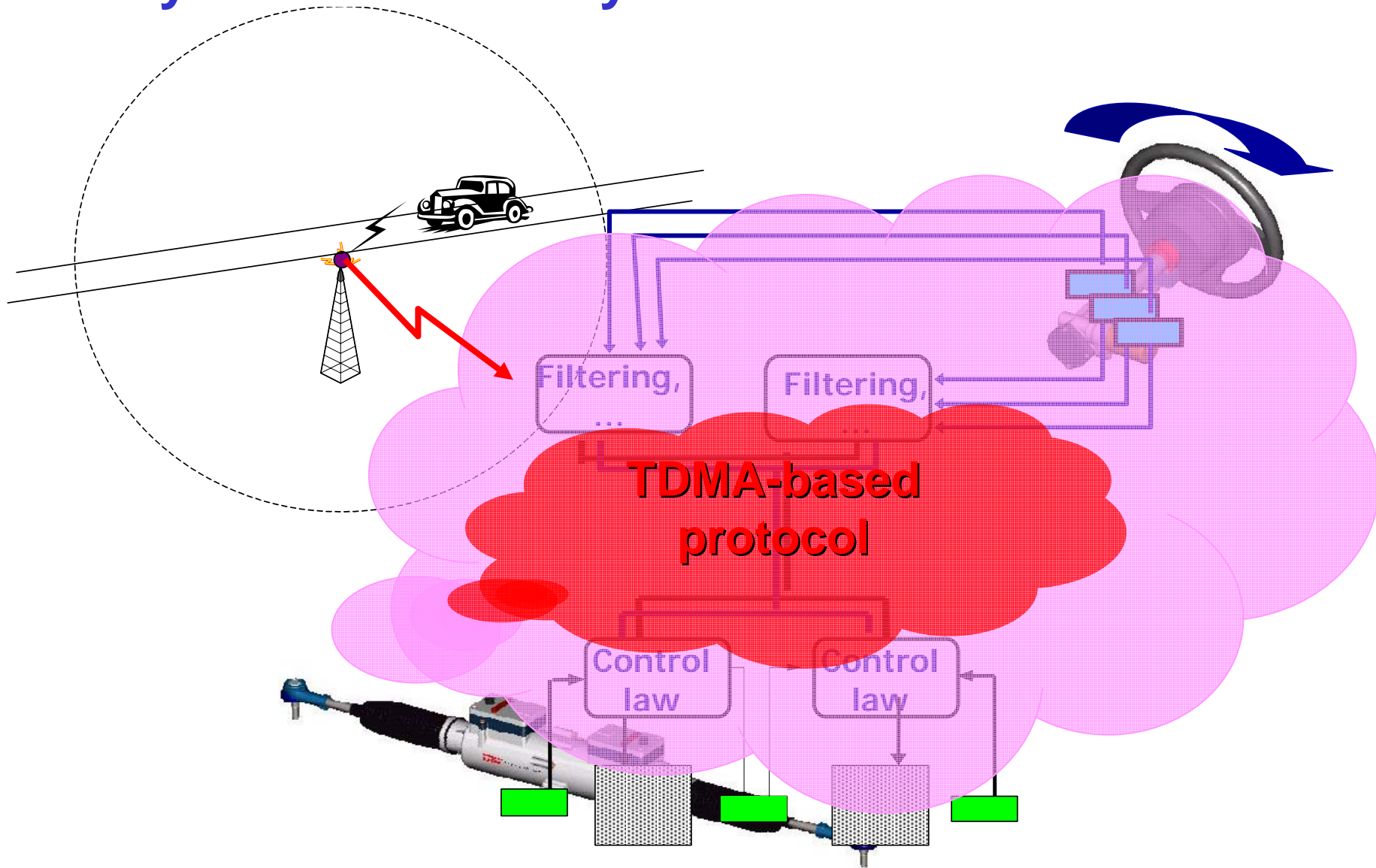
X-by-Wire and Safety assessment: which issue?

Steer-by-Wire

- Steering function



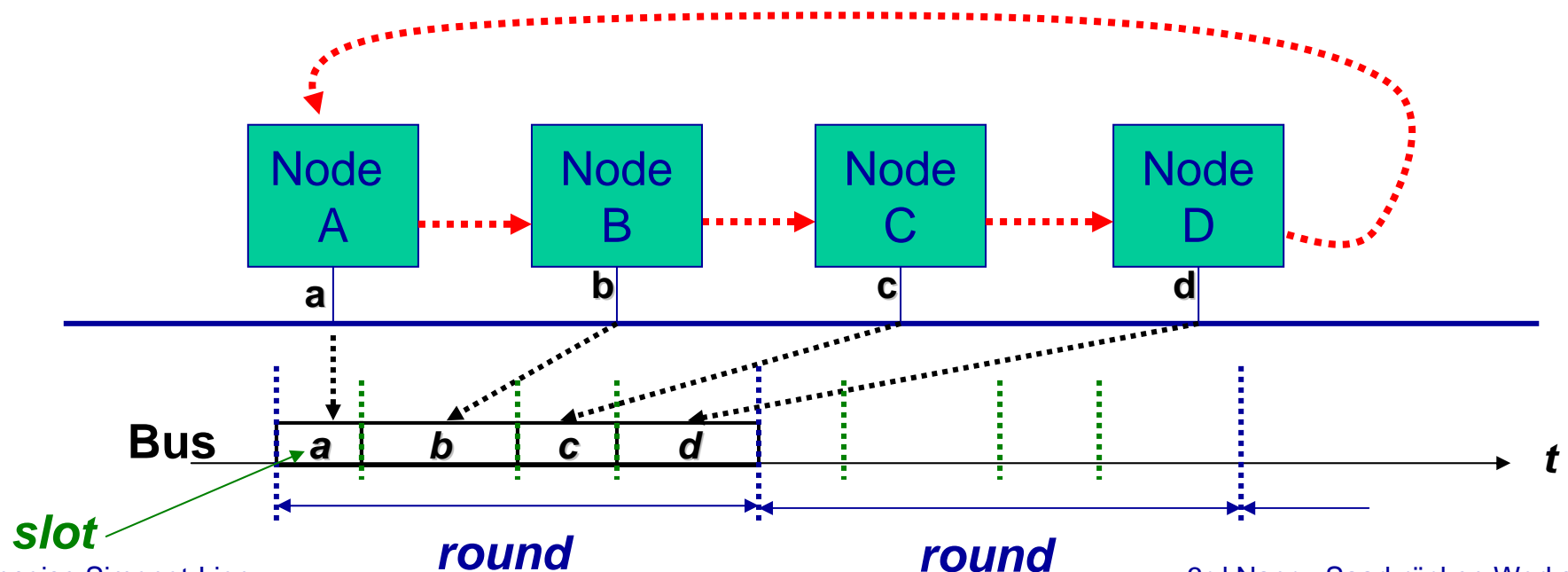
X-by-Wire and Safety assessment: which issue?



TDMA protocol (*Time Division Multiplexed Access*)

TTP/C

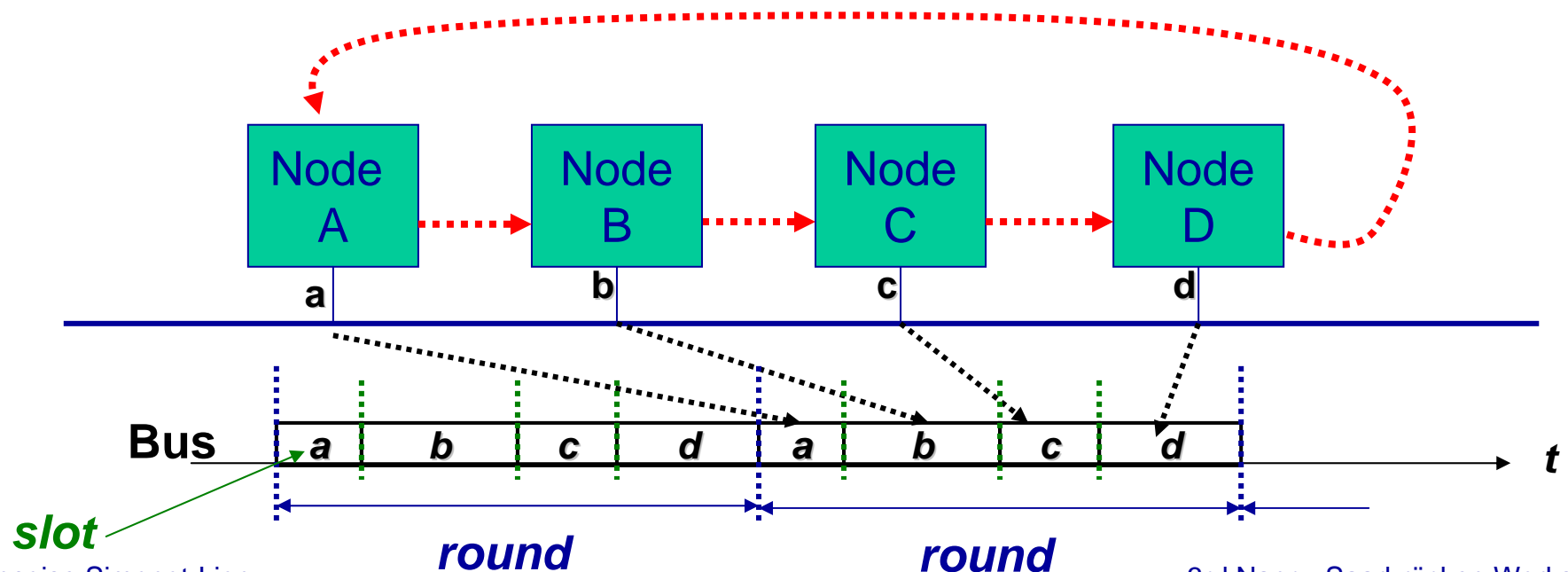
- **Slot:** time interval for a node to send a message (frame)
- **Round (cycle):** a sequence of slots such as each node sends one and only one time (TTP/C)



TDMA protocol (*Time Division Multiplexed Access*)

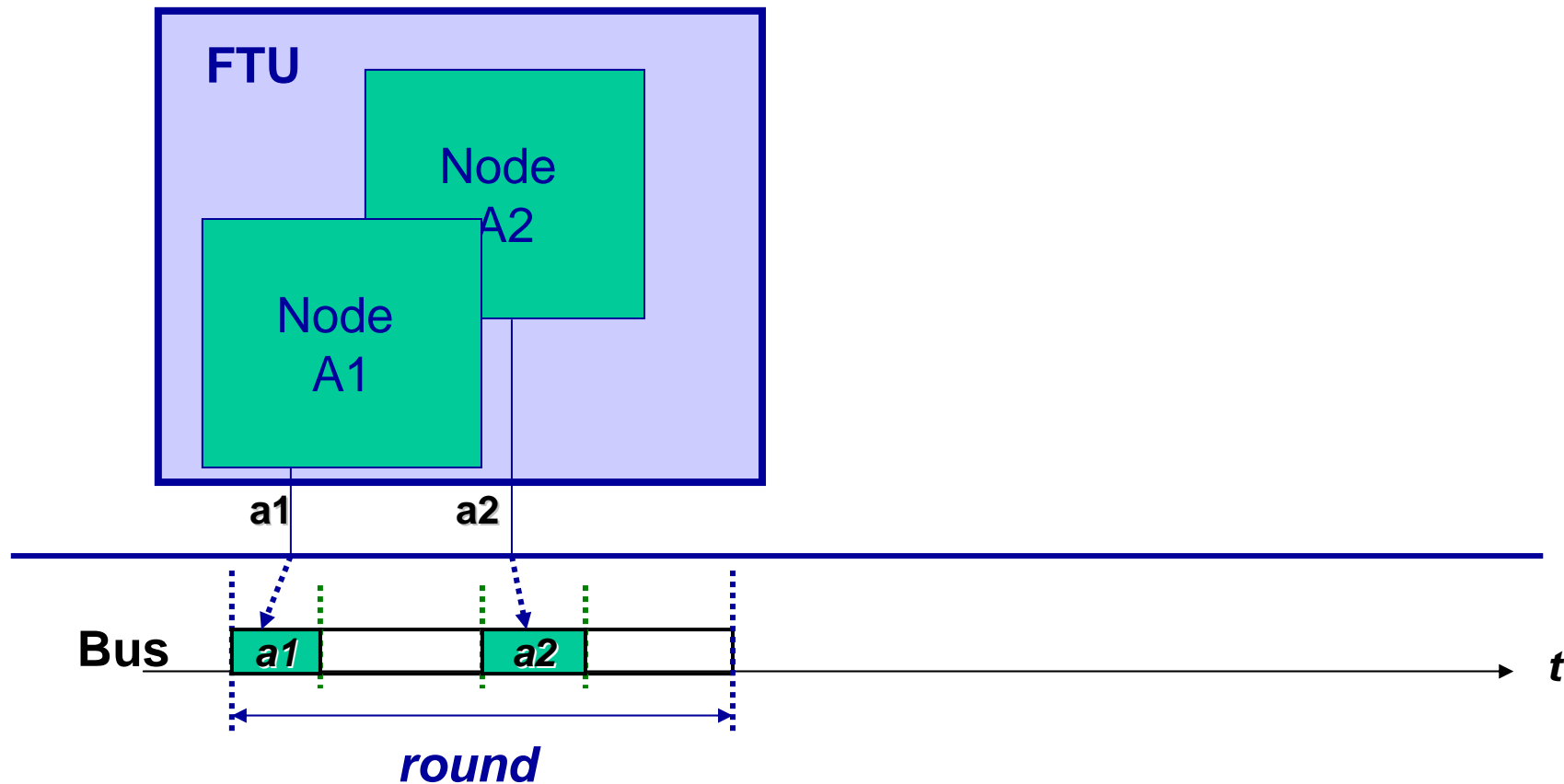
TTP/C

- **Slot:** time interval for a node to emit a message (frame)
- **Round:** a sequence of slots such as each node emit one and only one time (TTP/C)

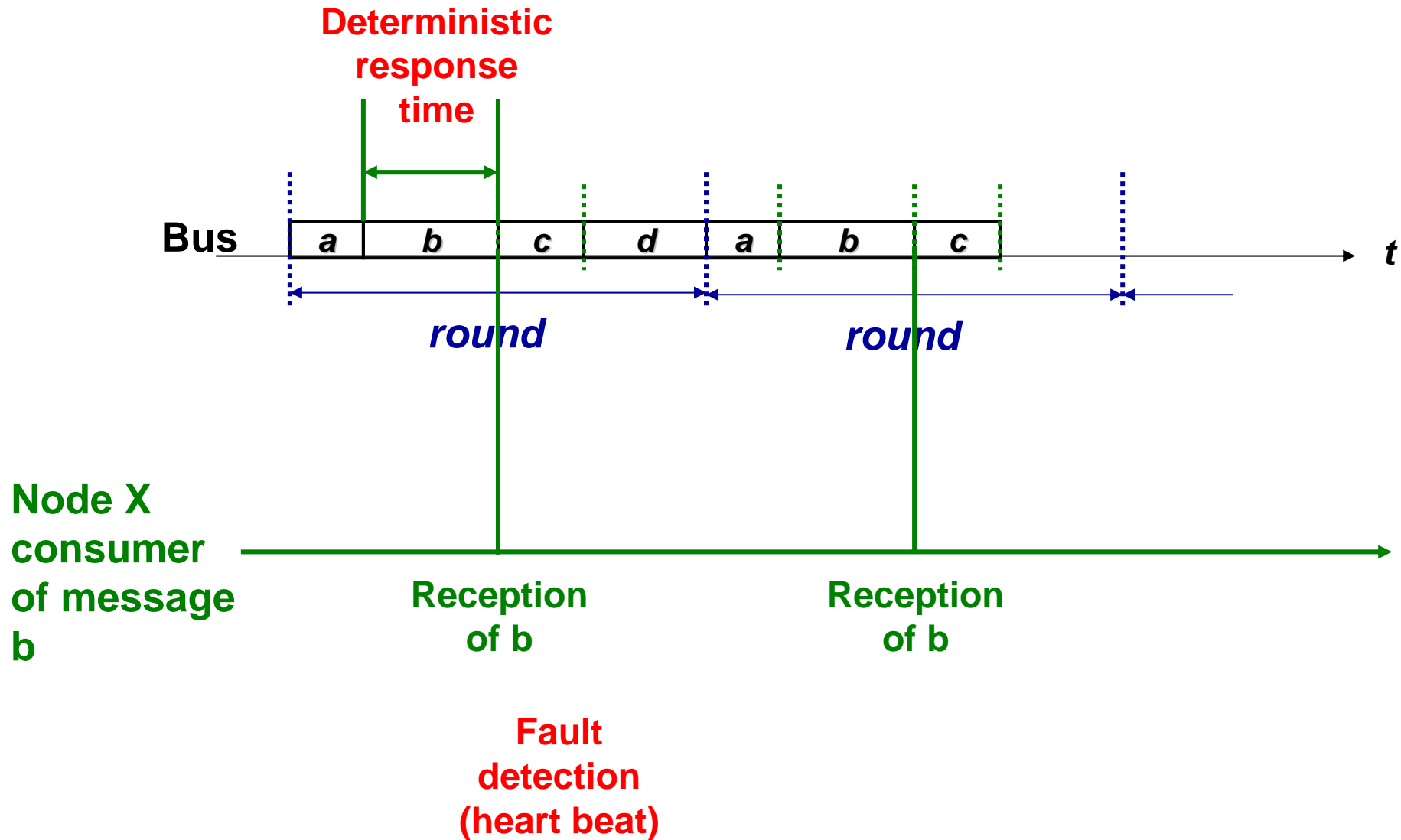


TDMA protocol - Fault Tolerant Unit (FTU)

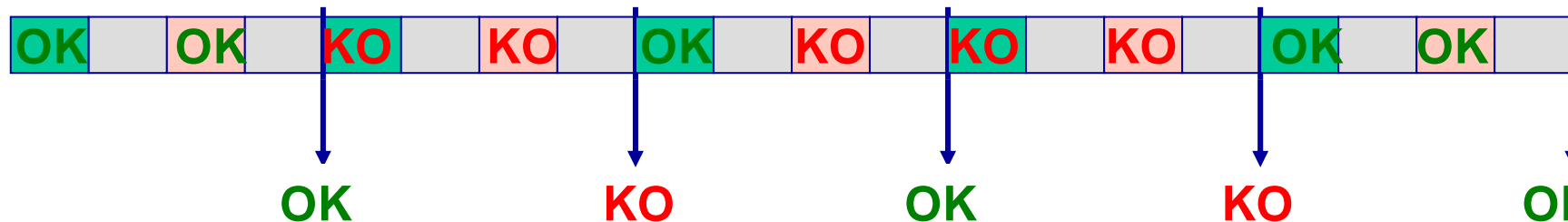
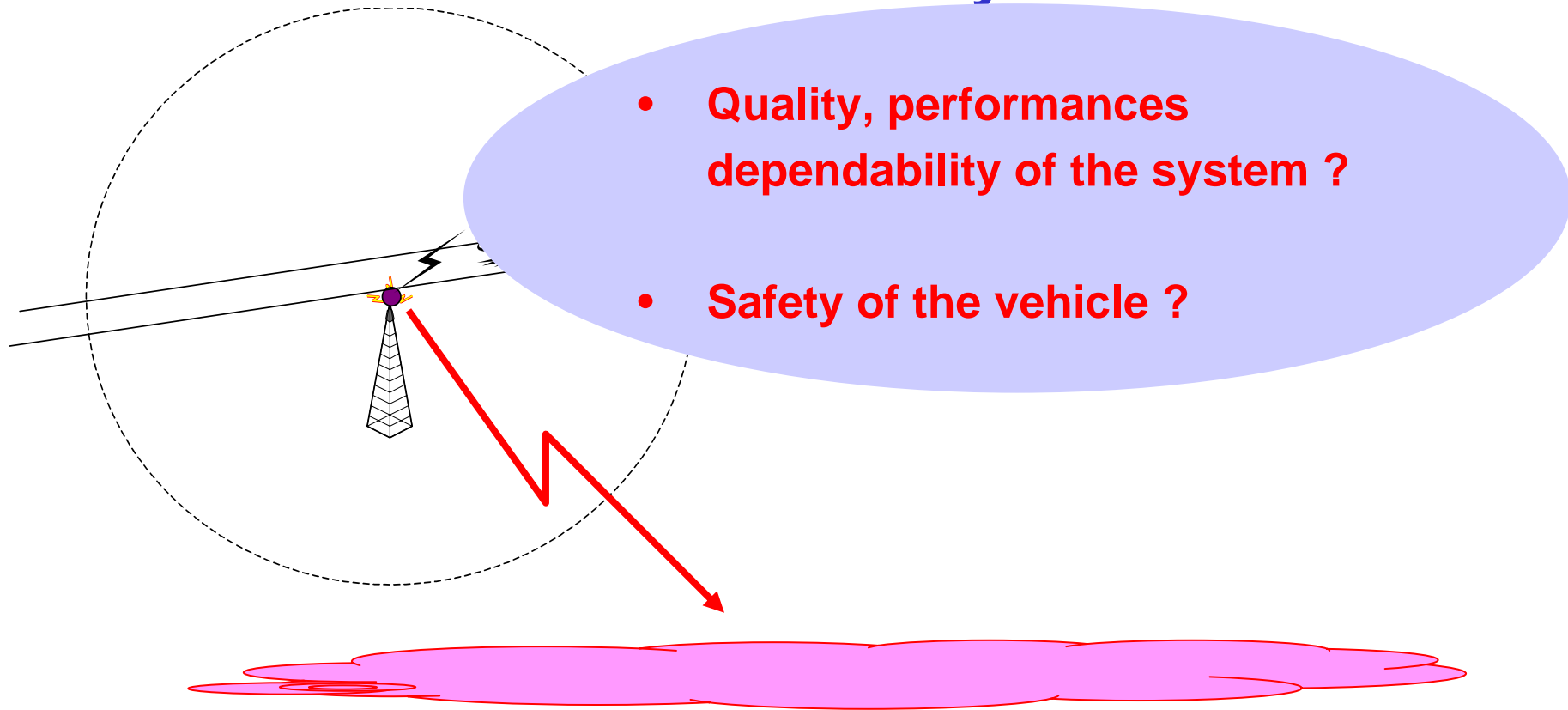
- FTU: redundant nodes
 - perform identical computations
 - message redundancy in each TDMA round



TDMA protocol for X-by-Wire systems



Impact of EMI perturbation on a TDMA-based communication system



Standard and Certification

A Steer-by-Wire system is a Safety Critical System

Regulatory laws → Certification and standard

Quantitative evaluation of the safety

**Probability to have a *critical* failure in one hour $< 10^{-10}$
(IEC 61508 / SIL4)
Industrial requirement**

Verification on an Operational Architecture?

- Mechanical / hydraulic components - architectures
- Electronic devices
- **???? Behavior of software architecture (tasks, messages)**

A contribution to the safety assessment of X-by-Wire systems

- **Quantitative evaluation of a failure probability**
 - extreme situation for the vehicle (worst case)
 - focus on the communication and EMI perturbations
 - TDMA-based protocol
 - Granularity: one TDMA cycle
 - transient faults (EMI perturbations): from transient faults to vehicle failure
 - metric and means for safety evaluation

Outline

Introduction



Key points for the safety assessment of X-by-Wire system

Technical solutions

Case study

Conclusions

Leading angles of the method

- **Robustness of the control law**
- **System *possibly* perturbed**
 - **How?**
 - **How long?**

Robustness of the control law

➤ **Control law used as a black box**

➤ **Matlab / Simulink model**

- of the vehicle (SimulinkCar – PSA Peugeot-Citroën)
- of the control law

for an « extreme » situation of the vehicle (worst case)

Fault injection + Simulations → 2 results

- Acceptable length of the TDMA cycle
- Maximal number of consecutive lost TDMA cycles - η_{\max}

How is a TDMA cycle affected by a perturbation?

➤ Error model

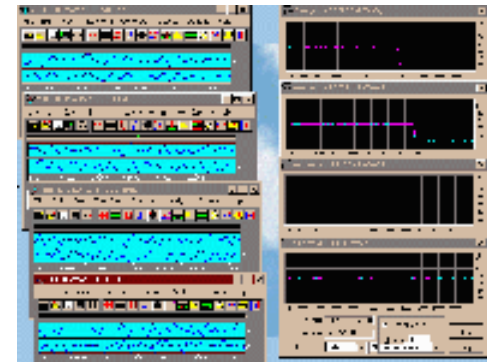
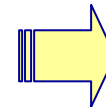
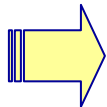
- Obtained by measurement
- Know-how of PSA Peugeot-Citroën

→ result

P_{err} , probability for a TDMA cycle to be *fully corrupted* when the network is submitted to a perturbation

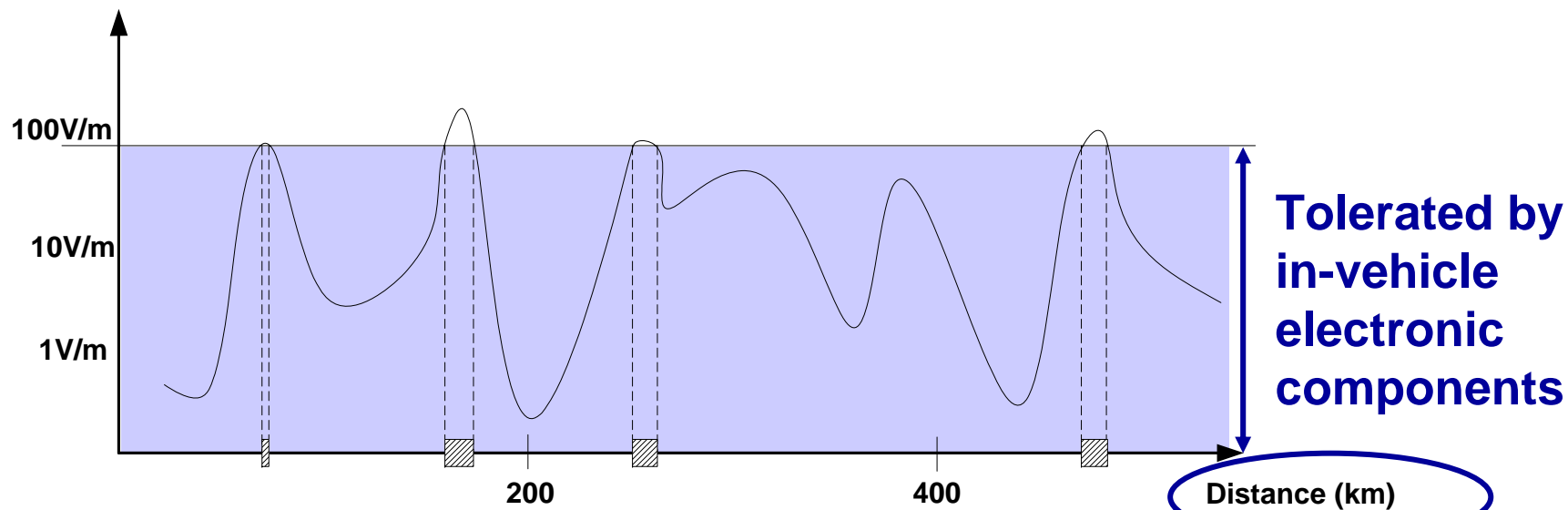
How long is a perturbation?

- **Electric field level of a reference road**
 - Based on the results of a French project
 - Measured on board
 - *Assuming a tolerance level of embedded electronic components*



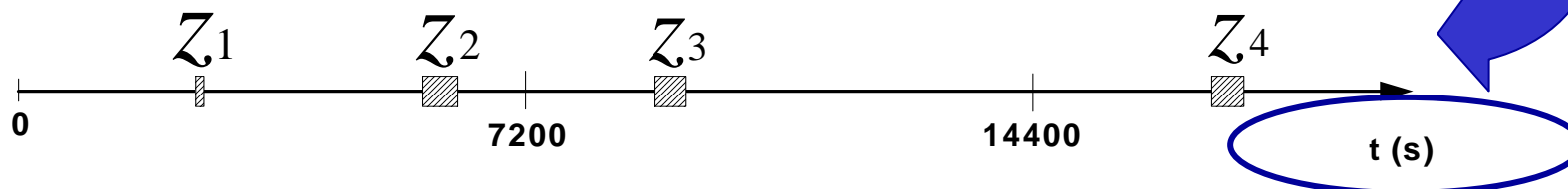
How long is a perturbation?

Electric field level (V/m)

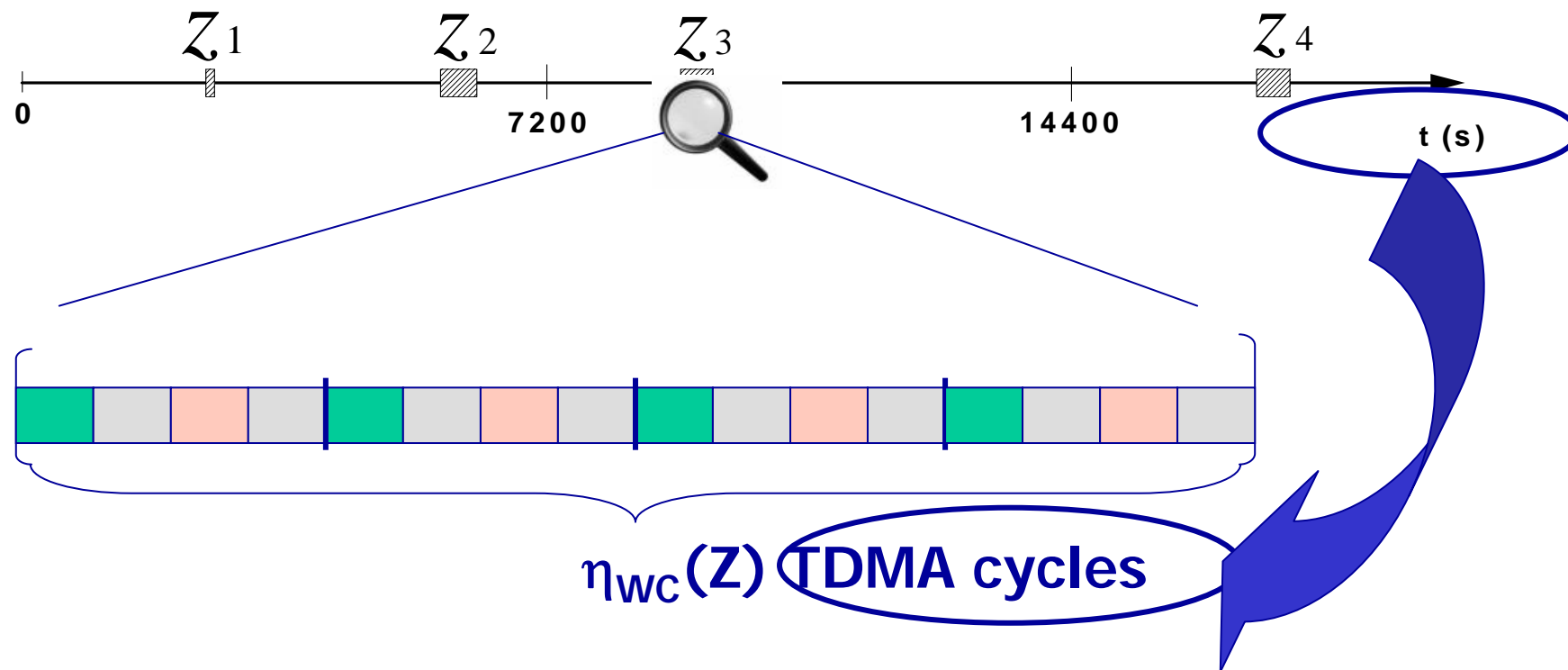


Distance (km)

driving situation



How long is a perturbation?



$$\eta_{WC} = \left\lceil \frac{\text{zone duration}}{\text{TDMA cycle}} \right\rceil + 2, \text{ (worst case)}$$

Outline

Problem

Key points for the safety assessment of X-by-Wire system



Technical solutions

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Technical solutions

➤ Given:

- η_{\max} : tolerance (consecutive corrupted TDMA cycles)
- η_{wc} : length of the perturbation (TDMA cycles) - extreme situation for the vehicle, worst case of perturbation cover
- P_{err} : probability for one TDMA cycle to be corrupted

➤ Problem:

determine the probability to have more than η_{\max} consecutive corrupted cycles in η_{wc} cycles (under P_{err}):

$$P_{\text{fail}}(\eta_{\max}, \eta_{\text{wc}}, P_{\text{err}})$$

Technical solutions

➤ **Similar to « consecutive-k-out-of-n:F » systems - C(k,n:F)**

- System = ordered sequence of n components
- The system fails if and only if more than k consecutive components fail
- L_n : number of consecutive failed components

$$P(L_n < k) = R(k, n; p)$$

[Burr, 1961], [Lambridis, 1985], [Hwang, 1986]

$$R(n, k; p) = \sum_{m=0}^{\lfloor (n+1)/(k+1) \rfloor} (-1)^m p^{mk} q^{m-1} \left(\binom{m-k}{m-1} + q \binom{n-mk}{m} \right)$$

with $q = 1 - p$

Technical solution

➤ Recurrent relation:

$$u_k(x+1) = u_k(x) - qp^k u_k(n-k) \text{ for } x \geq k$$

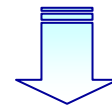
$$u_k(x) = 1 \text{ for } 0 \leq x \leq k-1$$

$$u_k(k) = 1 - p^k$$



$$n \geq 3 \text{ and } p \in]0, 1[$$

$$u_k(n) = R(k, n; p)$$



$$\begin{aligned} P_{fail}(\eta_{max}, \eta_{WC}, P_{err}) &= 1 - R(\eta_{max}, \eta_{WC}; P_{err}) \\ &= 1 - u_{\eta_{max}}(\eta_{WC}) \end{aligned}$$

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Case study: a Steer-by-Wire system

-extreme situation

vehicle speed (90 km/h)

sharp turning

perturbated area = 2s

-robustness

$\eta_{max} = 7$ TDMA cycles

-impact of the EMI perturbation

$P_{err} = 5 \cdot 10^{-3}$

-duration of the possibly perturbed area

$\eta_{WC} = 336$ TDMA cycles



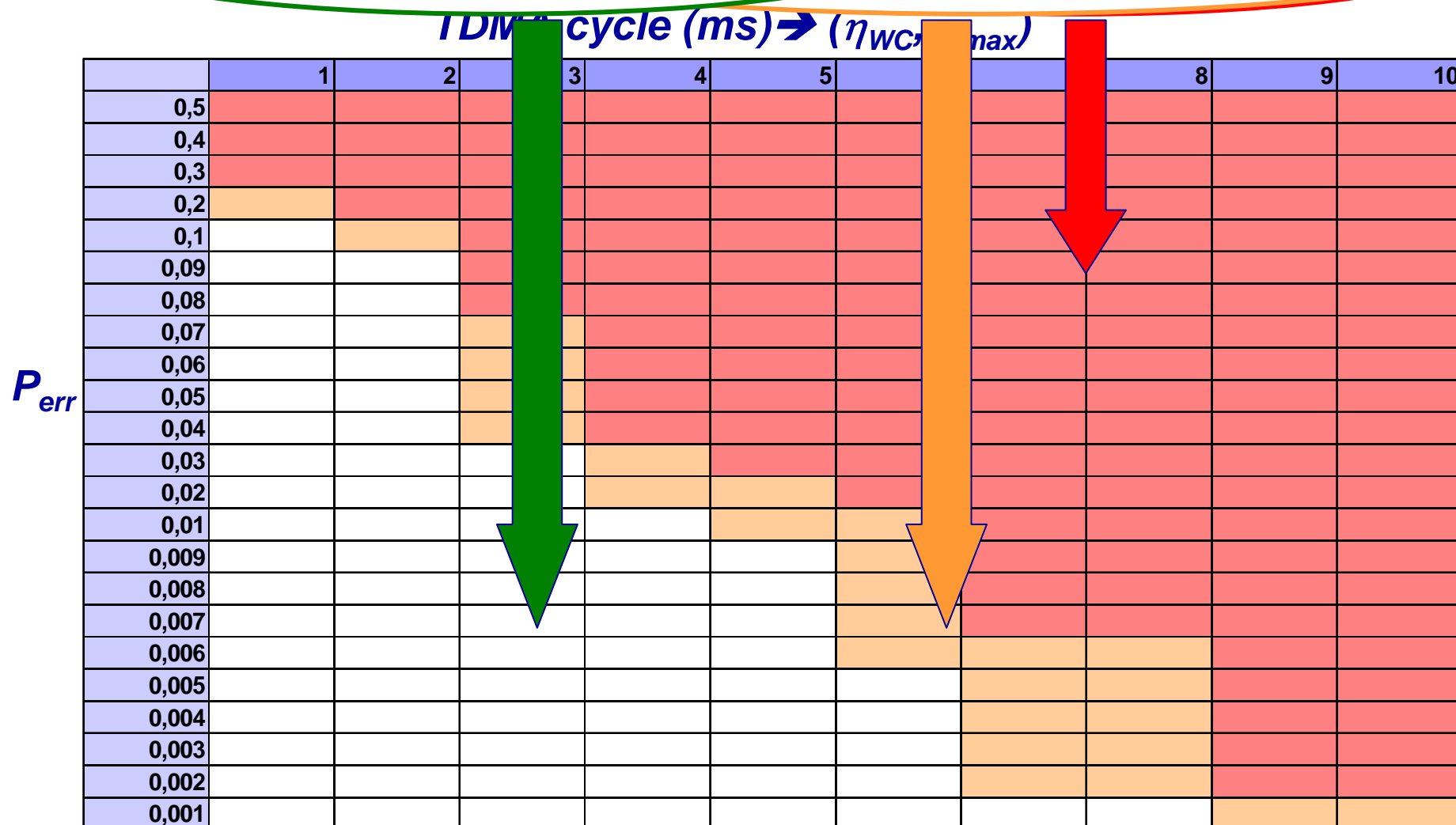
The diagram illustrates the control loop of a Steer-by-Wire system. It starts with a steering wheel labeled 'Drivers\' request'. A grey arrow labeled 'Filtering, ...' points from the steering wheel to a 'Control law' block. A green arrow points from the 'Control law' block to a car. A blue box at the bottom contains the failure probability equation.

$$P_{fail}(\eta_{max}, \eta_{WC}, P_{err}) = 2.87 \cdot 10^{-8}$$

Case study: configuration of a system

$$P_{fail}(\eta_{WC}, \eta_{WC}, P_{err}) < 10^{-10}$$

$$P_{fail}(\eta_{WC}, \eta_{WC}, P_{err}) < 10^{-7}$$



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Conclusions

Conclusions

- **A contribution to the dependability evaluation of an embedded system**
 - Transient fault at communication level to safety property at vehicle level
 - Mathematical evaluation / simulation

- **Generalisation**
 - P_{err} variable (error pattern, Markov process)
 - Other systems (e.g., dependability for application based on wireless networks)