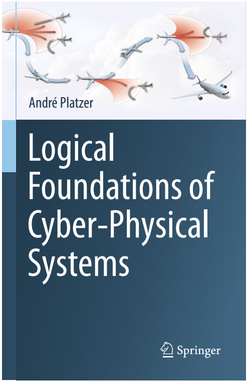
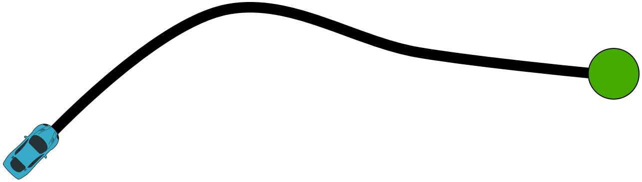
Logical Foundations of Autonomous Cyber-Physical Systems



André Platzer

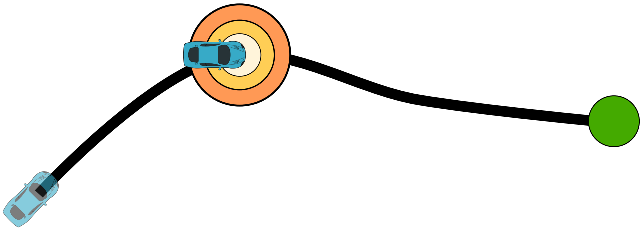
Carnegie Mellon University
Computer Science Department

Outline



Cyber-Physical Systems

CPSs combine cyber capabilities with physical capabilities
to solve problems that neither part could solve alone.



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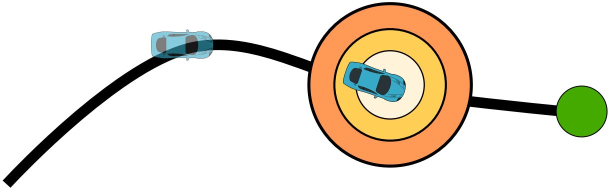

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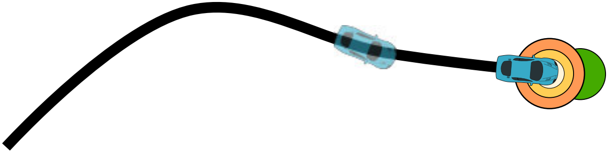

Cyber-Physical Systems

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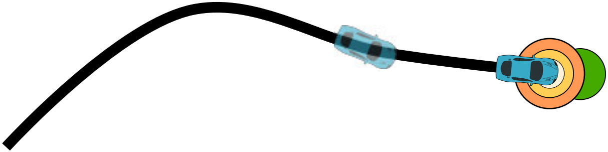
CPS Analysis

- Simple control
- ODE model
- Strong predictions
- Nondet decisions

AI Learning

- Flexible responses
- "No" model*
- Hard to predict
- Optimal decision $(t \to \infty)$



Cyber-Physical Systems

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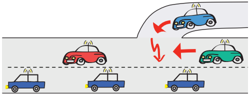
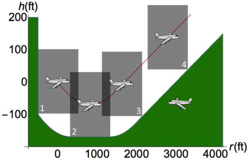
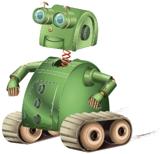
Autonomous CPSs Are on the Rise Everywhere

Prospects: Safety & Efficiency & Autonomy

Autonomous cars | Autonomous pilots | Robots near humans

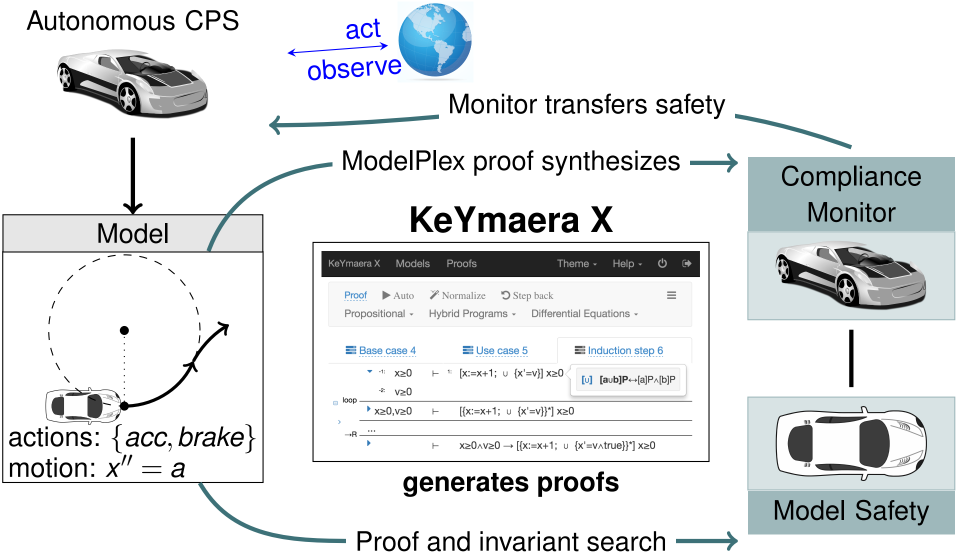






Objective

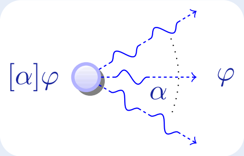
Best of both worlds: safety from CPS + flexibility from AI

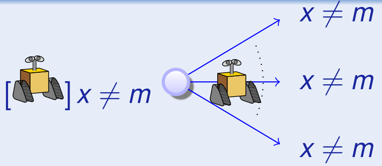

Autonomous CPS
act
observe
Monitor transfers safety
ModelPlex proof synthesizes
Compliance Monitor
Model
actions: $\{acc, brake\}$
motion: $x'' = a$
KeYmaera X
KeYmaera X Models Proofs Theme Help
Proof Auto Normalize Step back
Propositional Hybrid Programs Differential Equations
Base case 4 Use case 5 Induction step 6
x≥0 ⊢ [x:=x+1; ∪ {x'=v}] x≥0
v≥0
[∪] [a∪b]P↔[a]P∧[b]P
loop
x≥0,v≥0 ⊢ [{x:=x+1; ∪ {x'=v}}*] x≥0
→R
⊢ x≥0∧v≥0 → [{x:=x+1; ∪ {x'=v∧true}}*] x≥0
generates proofs
Model Safety
Proof and invariant search

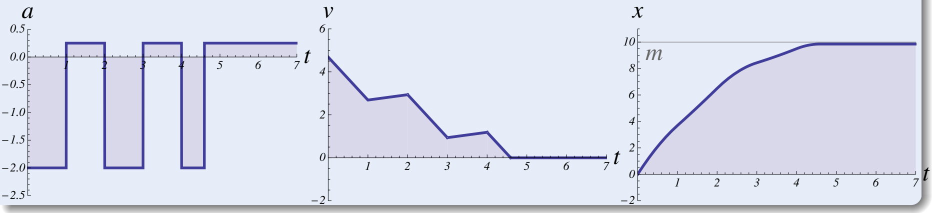
Outline

1. Autonomous Cyber-Physical Systems
2. Foundation: Differential Dynamic Logic
3. ModelPlex: Model Safety Transfer
4. VeriPhy: Executable Proof Transfer
5. Safe Learning in CPSs
6. Applications
   - Airborne Collision Avoidance System
   - Ground Robot Navigation
7. Summary

Concept (Differential Dynamic Logic) (JAR'08,LICS'12)







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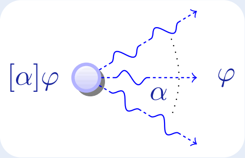
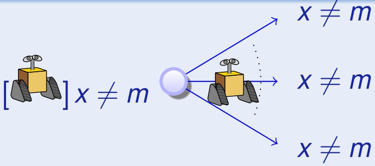
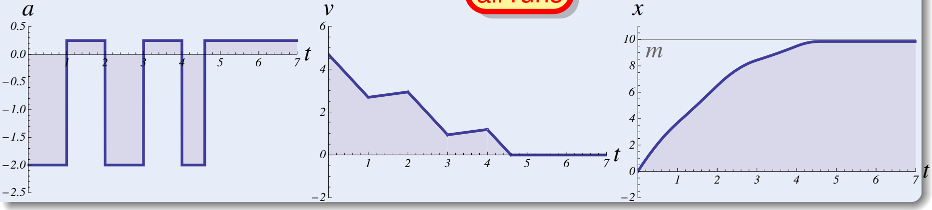




$$[\underbrace{((\text{if}(SB(x,m)) \quad a := -b) \; ; \; x' = v, v' = a)^*}_{\text{all runs}}]\underbrace{x \neq m}_{\text{post}}$$



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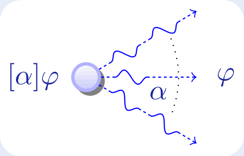
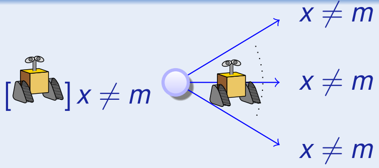
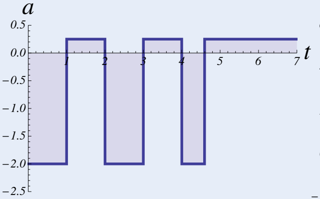
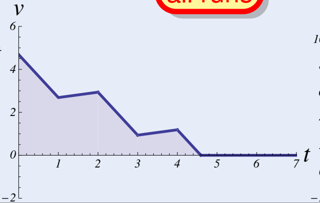


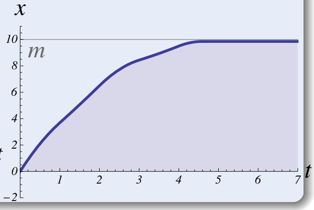


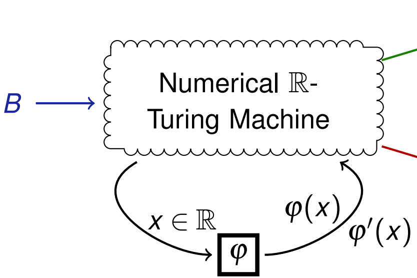
$$\underbrace{x \neq m \land b > 0}_{\text{init}} \to \Big[\Big(\big(\text{if}(SB(x,m))\quad a := -b\big)\ ;\ x' = v, v' = a\Big)^*\Big]\underbrace{x \neq m}_{\text{post}}$$

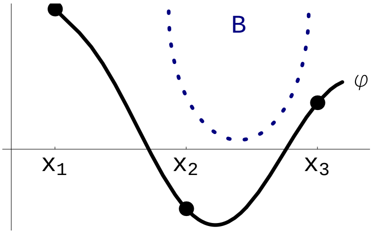
all runs





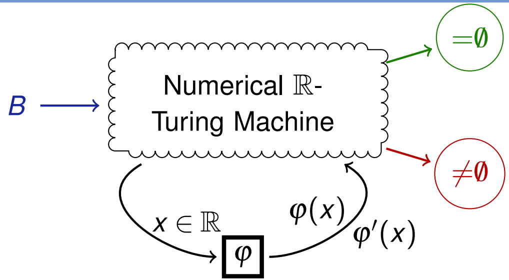


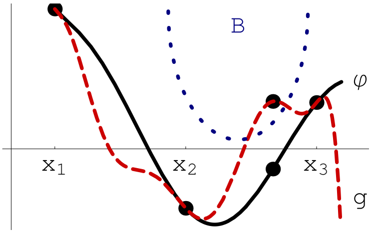




HSCC'07

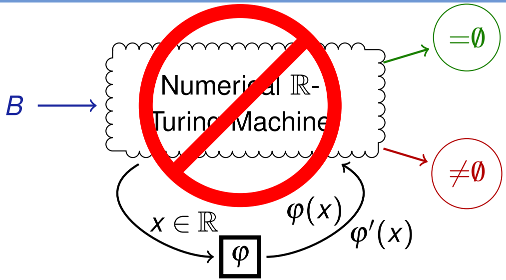
Model Requirements

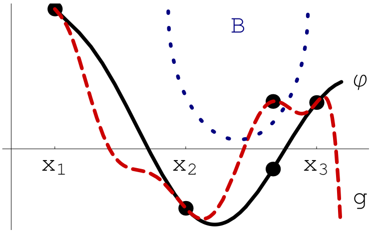




HSCC'07

Model Requirements: Symbolic/Intensional!





Proposition (Continuous image computation undecidable)

$\varphi(D) \cap B \overset{?}{=} \emptyset$ is undecidable by evaluating $\varphi(x)$ for

- *arbitrarily effective flow $\varphi \in C^k(D \subseteq \mathbb{R}^n, \mathbb{R}^m)$ with effective D, B*
- *even if tolerating error $\varepsilon > 0$ in decisions*

HSCC'07

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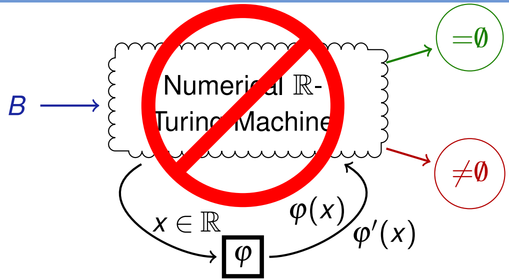

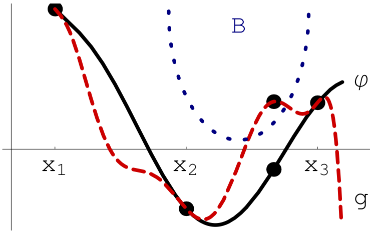

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- *even if tolerating error $\varepsilon > 0$ in decisions*
- *even φ smooth polynomial function with $\mathbb{Q}$-coefficients*
- *even in Blum-Shub-Smale "real Turing machines"*

HSCC'07

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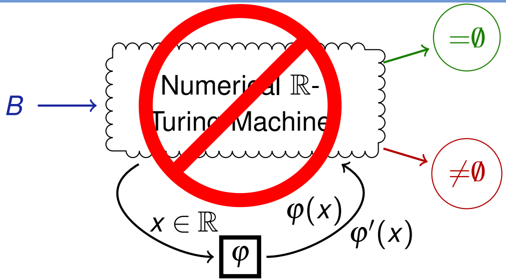

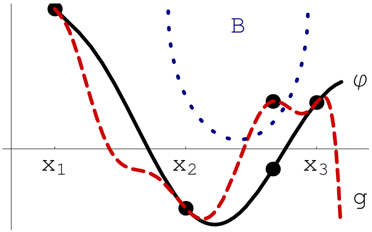

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- *even if tolerating error* $\varepsilon > 0$ *in decisions*
- *even* φ *smooth polynomial function with* $\mathbb{Q}$*-coefficients*
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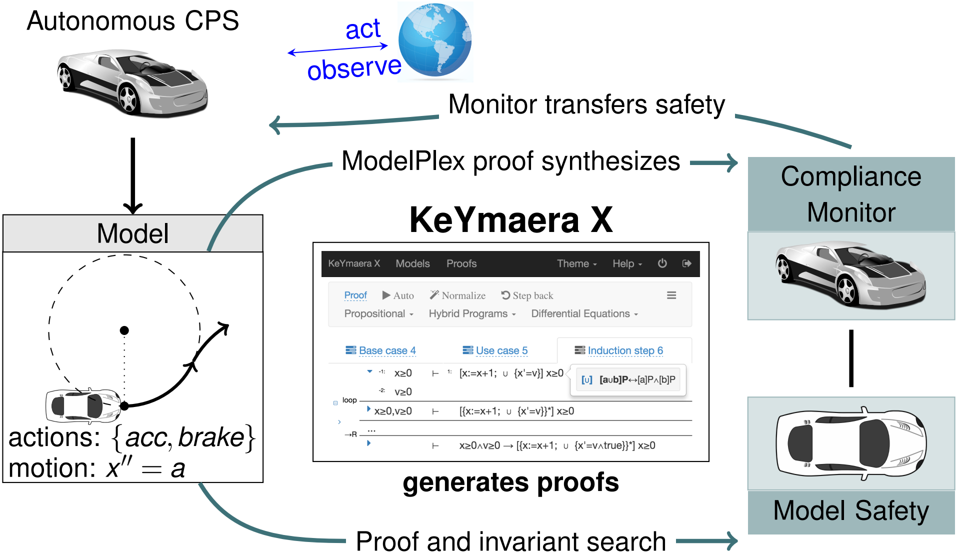
The promise of "no model" is a myth

HSCC'07

Outline

Approach: Safety Proofs for Autonomous CPS

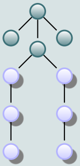


Formal Verification in CPS Development

Real CPS

safe

Proof

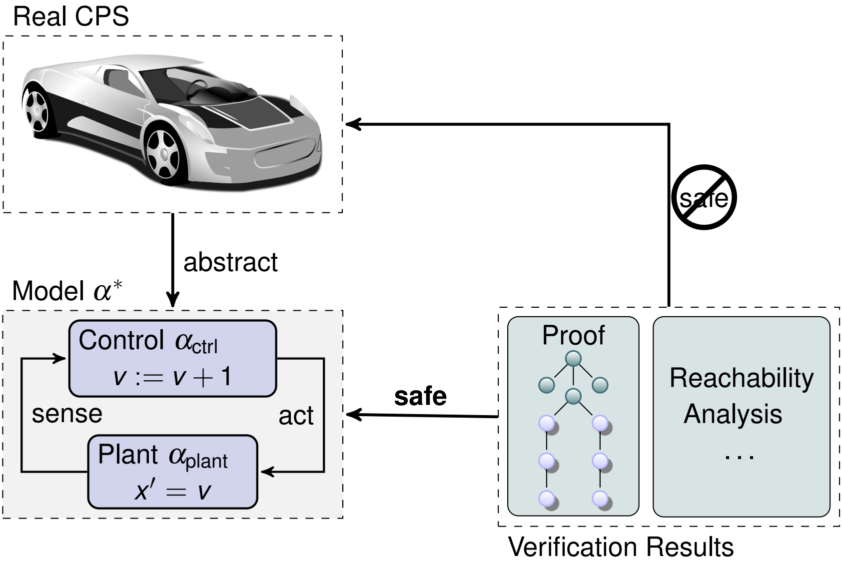


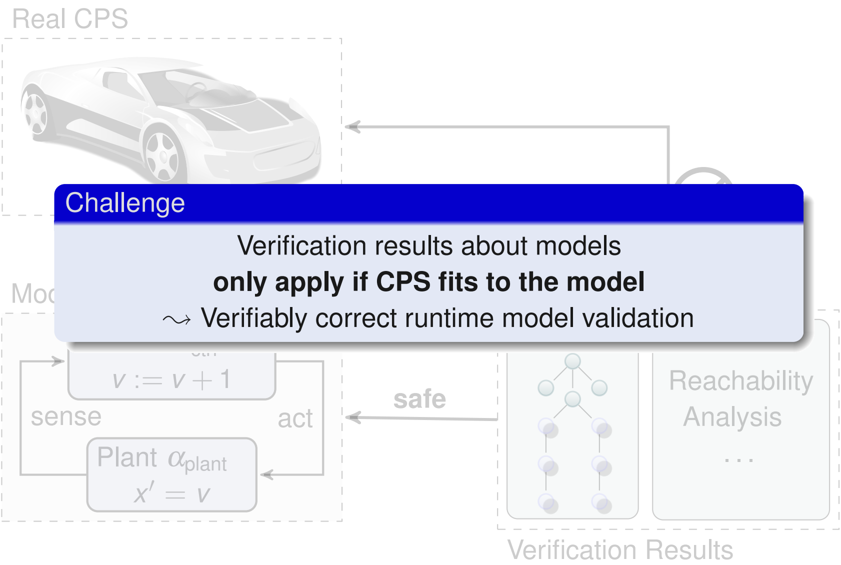
Reachability Analysis

. . .

Verification Results

Formal Verification in CPS Development





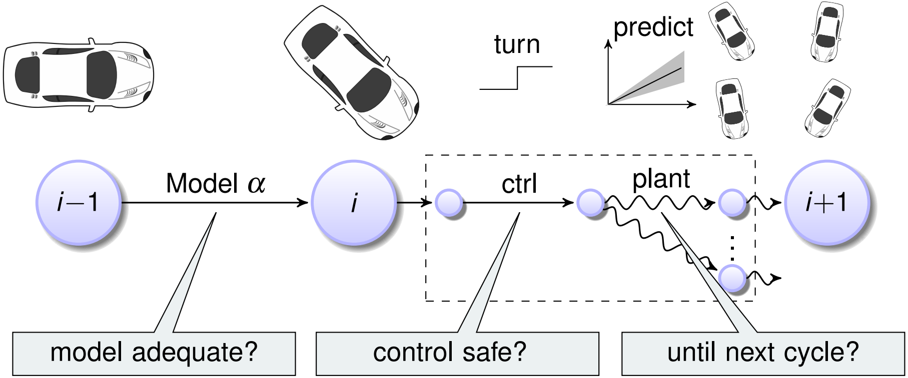
Challenge

Verification results about models

only apply if CPS fits to the model

$\rightsquigarrow$ Verifiably correct runtime model validation

ModelPlex **ensures that verification results** about models **apply to CPS** implementations



FMSD'16

ModelPlex **ensures that verification results** about models **apply to CPS** implementations

Insights

- Verification results about models transfer to the CPS when validating model compliance.
- Compliance with model is characterizable in logic dL.
- Compliance formula transformed by dL proof to monitor.
- Correct-by-construction provably correct model validation at runtime.

model adequate?

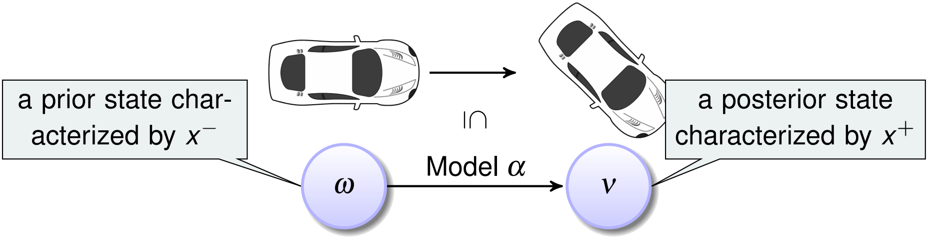
control safe?

until next cycle?

FMSD'16

Characterizing State Relations in Logic

When are two states linked through a run of model α?



Semantical: $(\omega, \nu) \in [\![\alpha]\!]$ — reachability relation of α

FMSD'16

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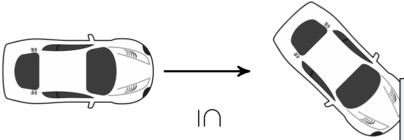

a prior state characterized by x^-

$\mathrel{|\!\cap}$

$$\omega \xrightarrow{\text{Model } \alpha} \nu$$

a posterior state characterized by x^+

Offline

Semantical: $(\omega, \nu) \in [\![\alpha]\!]$

$\Updownarrow$ Lemma

Logical dL: $(\omega, \nu) \models \langle \alpha \rangle (x = x^+)$

exists a run of α to a state where $x = x^+$

FMSD'16

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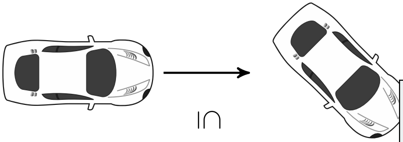

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$\subseteq$

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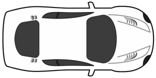
$\Updownarrow$ dL proof

Arithmetical: $(\omega, \nu) \models F(x^-, x^+)$

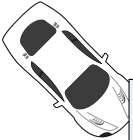
check at runtime (efficient)

FMSD'16

When are two states linked through a run of model α?



$\longrightarrow$



$\subseteq$

a prior state characterized by x^-

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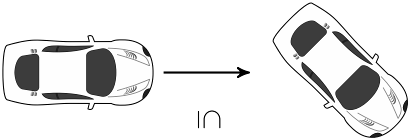
FMSD'16

Logic reduces CPS safety to runtime monitor with offline proof



$\cap|$

dL proof $A \to [\alpha]S$ $\quad \omega \xrightarrow{\text{Model } \alpha} \nu$

Init $\omega \in [\![A]\!]$ Safe $\nu \in [\![S]\!]$

Offline

Semantical: $(\omega, \nu) \in [\![\alpha]\!]$

$\Updownarrow$ Lemma

Logical dL: $(\omega, \nu) \models \langle\alpha\rangle(x = x^+)$

$\Uparrow$ dL proof

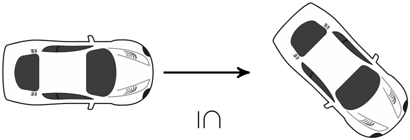
Arithmetical: $(\omega, \nu) \models F(x^-, x^+)$

check at runtime (efficient)

FMSD'16

Logical Reductions for Model Safety Transfer

Logic reduces CPS safety to runtime monitor with offline proof



dL proof $A \to [\alpha]S$ $\qquad \omega \xrightarrow{\text{Model } \alpha} \nu$

Init $\omega \in [\![A]\!]$ $\qquad$ Safe $\nu \in [\![S]\!]$

Offline

Semantical: $(\omega,\nu) \in [\![\alpha]\!]$

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Logical dL: $(\omega,\nu) \models \langle\alpha\rangle(x = x^+)$

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Arithmetical: $(\omega,\nu) \models F(x^-, x^+)$

check at runtime (efficient)

FMSD'16

Outline

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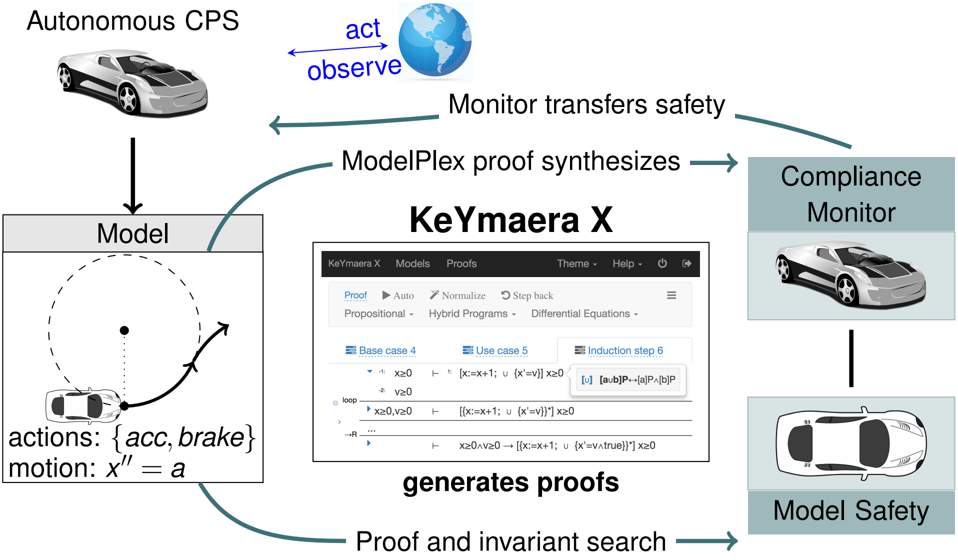
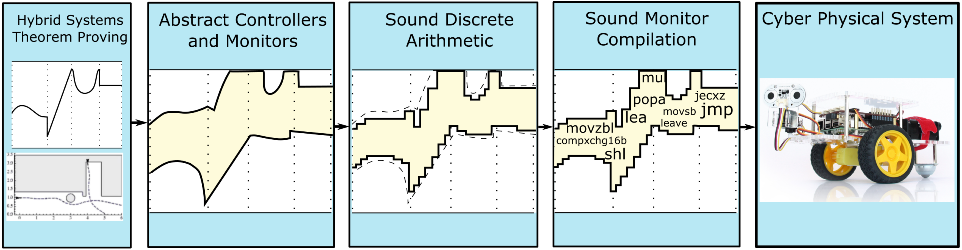
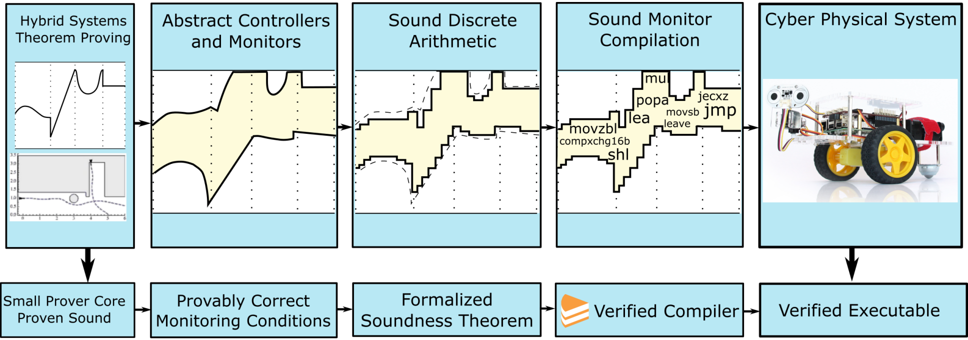



Hybrid Systems Theorem Proving
Abstract Controllers and Monitors
Sound Discrete Arithmetic
Sound Monitor Compilation
mul
popa
jecxz
lea
movsb
jmp
leave
movzbl
compxchg16b
shl
Cyber Physical System

PLDI'18

VeriPhy: Automatic, Verified EXEs from Controllers



PLDI'18

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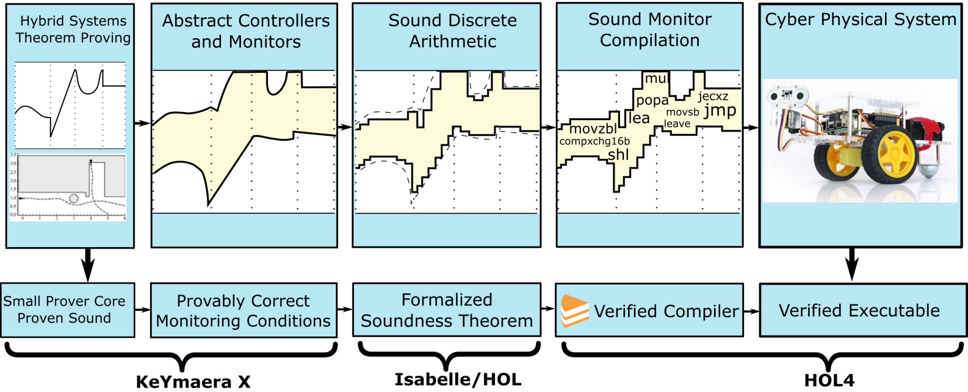
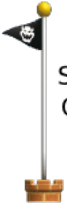


PLDI'18

VeriPhy: Takeaway Metaphor

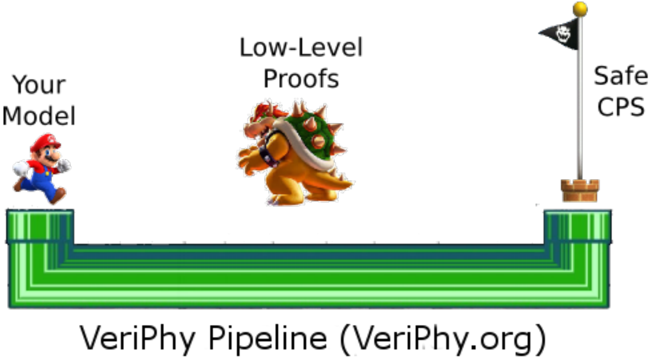
Your Model

Low-Level Proofs



Safe CPS

VeriPhy: Takeaway Metaphor



Outline

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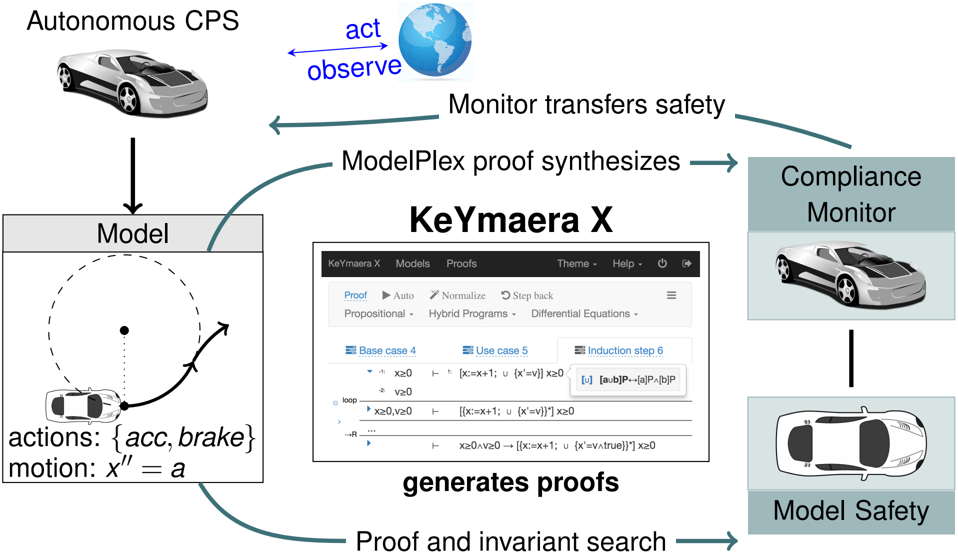
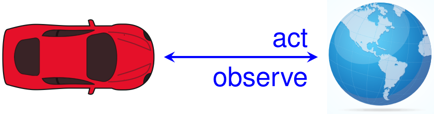
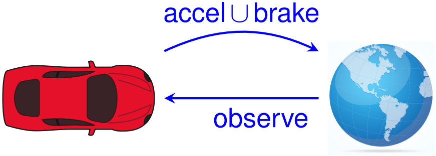




Reinforcement Learning learns from experience of trying actions

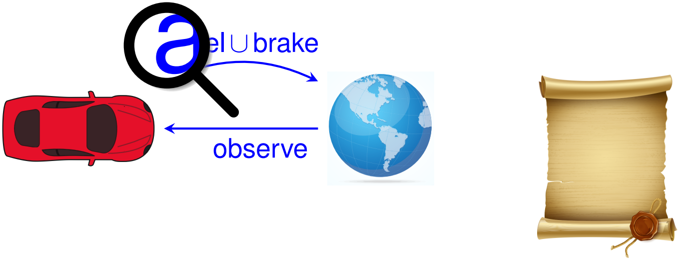
AAAI'18,ITC'18,TACAS'19,QEST'19



RL chooses an action, observes outcome, reinforces in policy if successful

AAAI'18,ITC'18,TACAS'19,QEST'19

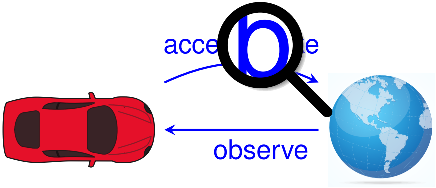
Learning to Act Safely in a CPS



ModelPlex monitor inspects each decision, vetoes if unsafe

AAAI'18,ITC'18,TACAS'19,QEST'19

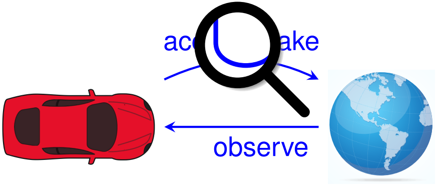
Learning to Act Safely in a CPS



ModelPlex monitor gives early feedback about possible future problems.
No need to wait till disaster strikes and propagate back.

AAAI'18,ITC'18,TACAS'19,QEST'19

Learning to Act Safely in a CPS

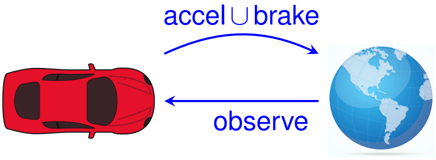


dL benefits from RL optimization.

RL benefits from dL safety signal.

AAAI'18,ITC'18,TACAS'19,QEST'19

Learning to Act Safely in a CPS



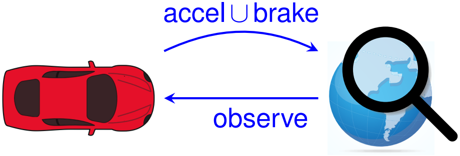
Theorem Safe policy if ODE accurate

Experiment Graceful recovery outside ODE $\leftsquigarrow$ quantitative ModelPlex

Detect modeled versus unmodeled state space $\leftsquigarrow$ ModelPlex

AAAI'18,ITC'18,TACAS'19,QEST'19

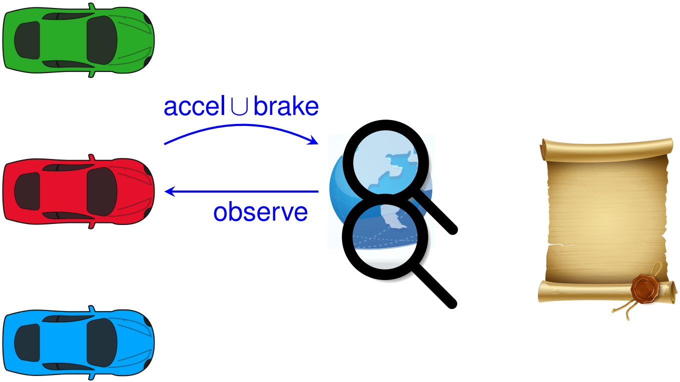
Learning to Act Safely in a CPS



What's safe when off model?

AAAI'18,ITC'18,TACAS'19,QEST'19

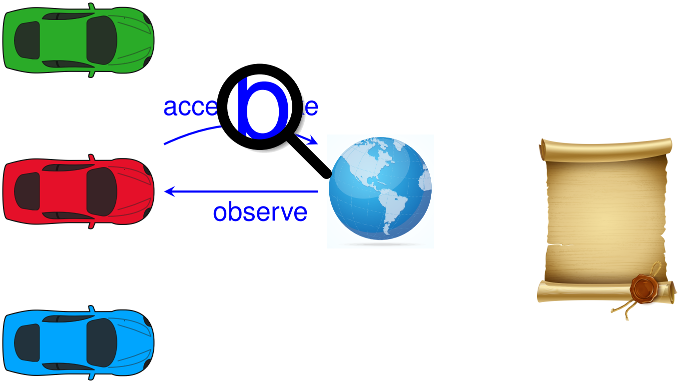
Learning to Act Safely in a CPS with Multiple Models



What's safe with multiple possible models?

AAAI'18,ITC'18,TACAS'19,QEST'19

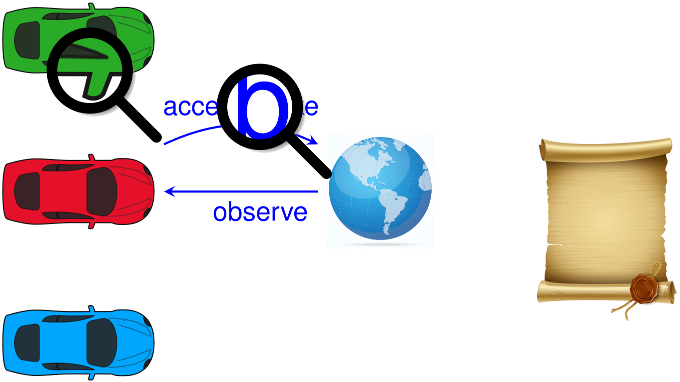
Learning to Act Safely in a CPS with Multiple Models



ModelPlex monitors conjunction of all plausible models

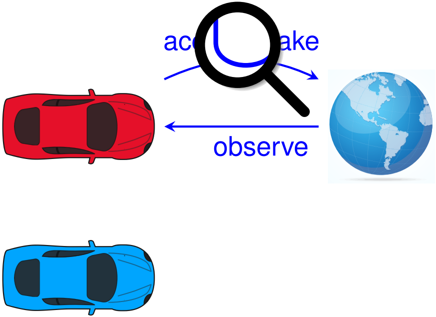
AAAI'18,ITC'18,TACAS'19,QEST'19

Learning to Act Safely in a CPS with Multiple Models



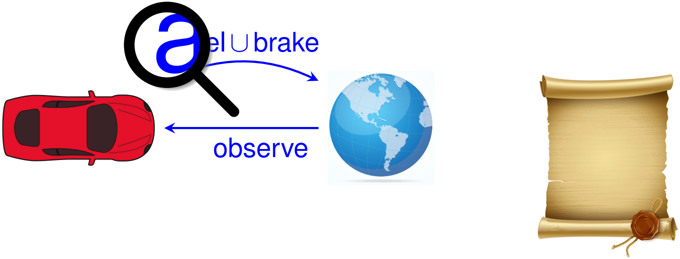
Remove incompatible models after contradictory observation

AAAI’18,ITC’18,TACAS’19,QEST’19



Plan differentiating experiment $\leadsto$ predictive monitor distinctions

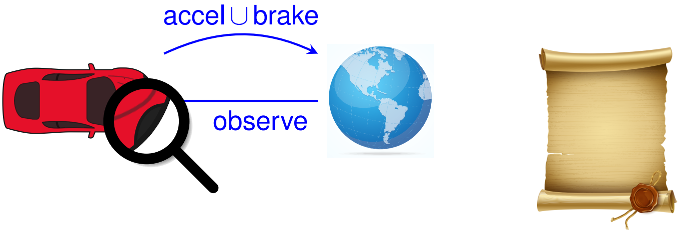
AAAI'18,ITC'18,TACAS'19,QEST'19



Convergence Plausible models converge to true model a.s., if possible

AAAI'18,ITC'18,TACAS'19,QEST'19

Learning to Act Safely in a CPS with Multiple Models

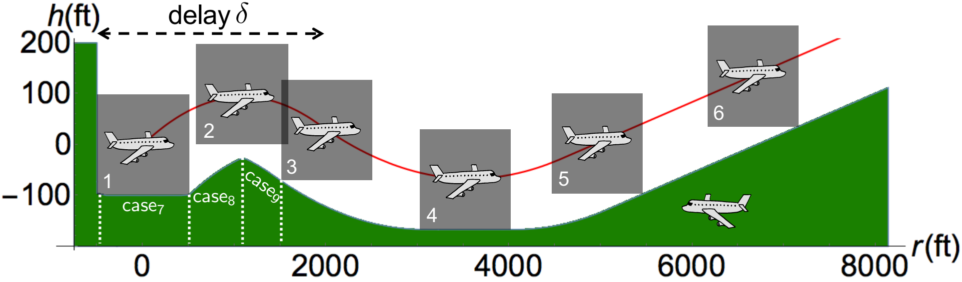


Modify model to fit observations by verification-preserving model update.
Safety proofs reified: modify model + proof tactic to preserve fit + safety

AAAI'18, ITC'18, TACAS'19, QEST'19

Outline

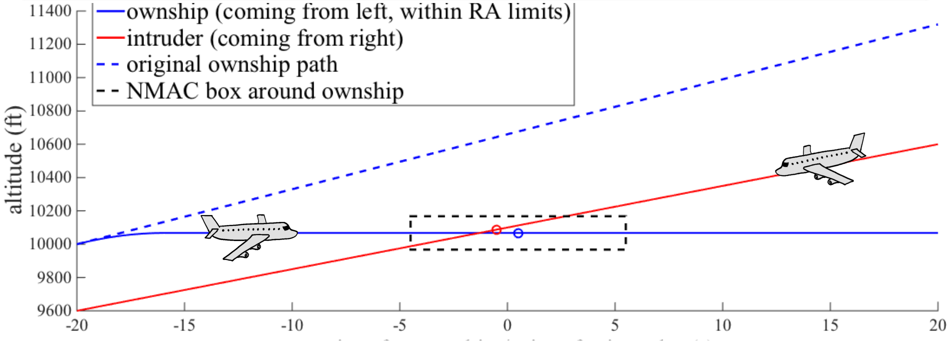
- Developed by the FAA to replace current TCAS in aircraft
- Approximately optimizes Markov Decision Process on a grid
- Advisory from lookup tables with numerous 5D interpolation regions



1. Identified safe region for each advisory symbolically
2. Proved safety for hybrid systems flight model in KeYmaera X

STTT'17

ACAS X table comparison shows safe advisory in 97.7% of the 648,591,384,375 states compared (15,160,434,734 counterexamples).

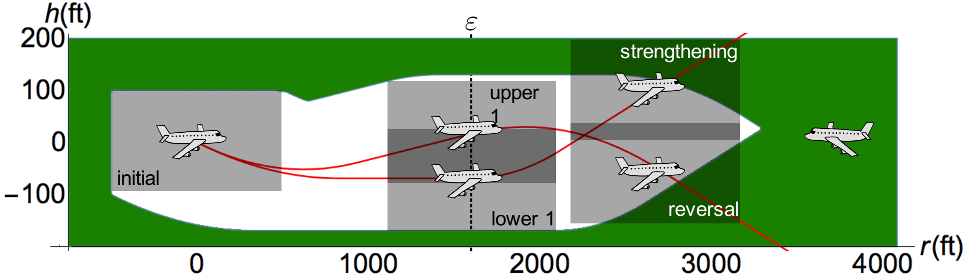


ACAS X issues DNC advisory, which induces collision unless corrected

STTT'17

Airborne Collision Avoidance System ACAS X: Refine

- Conservative, so too many counterexamples
- Settle for: safe for a little while, with safe future advisory possibility
- Safeable advisory: a subsequent advisory can safely avoid collision



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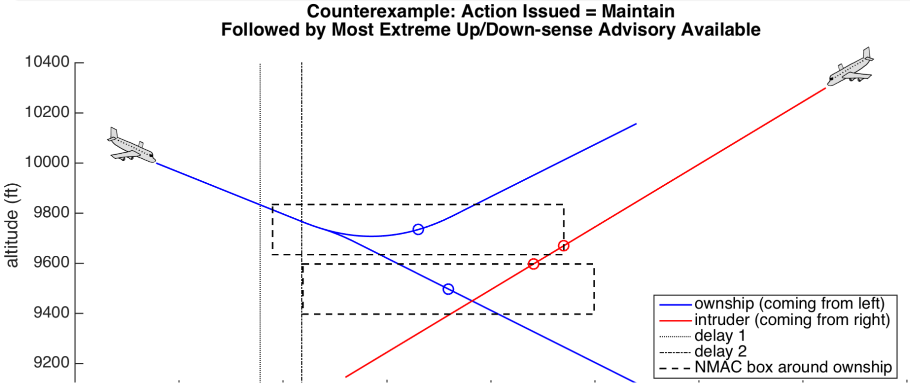
STTT'17

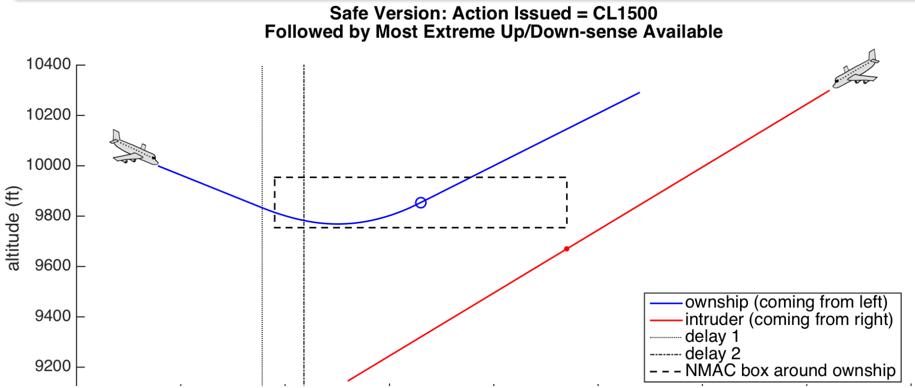
ACAS X table comparison shows safeable advisory in more of the 648,591,384,375 states compared ($\approx$899 10^6 counterexamples).



ACAS X issues Maintain advisory instead of CL1500

STTT'17

ACAS X table comparison shows safeable advisory in more of the 648,591,384,375 states compared ($\approx$899 10^6 counterexamples).

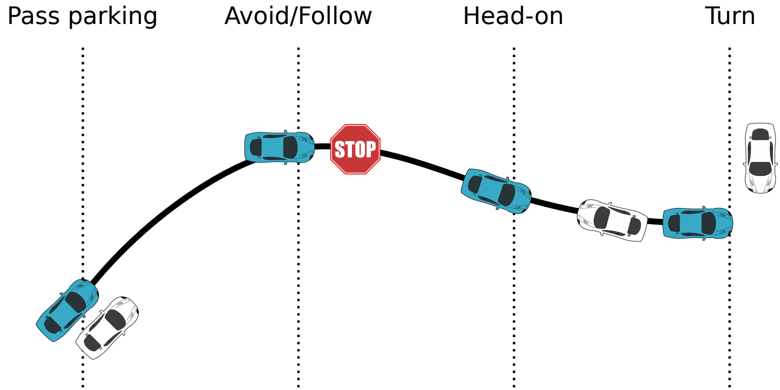


ACAS X issues Maintain advisory instead of CL1500

STTT'17

Ground Robot Obstacle Avoidance: Verify

- Fundamental safety question for ground robot navigation — IJRR'17
- When will which control decision avoid obstacles?
- Depends on safety objective, physical capabilities of robot + obstacle



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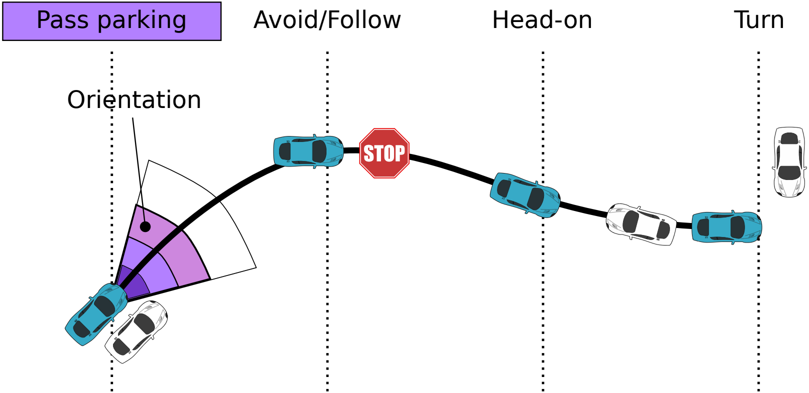

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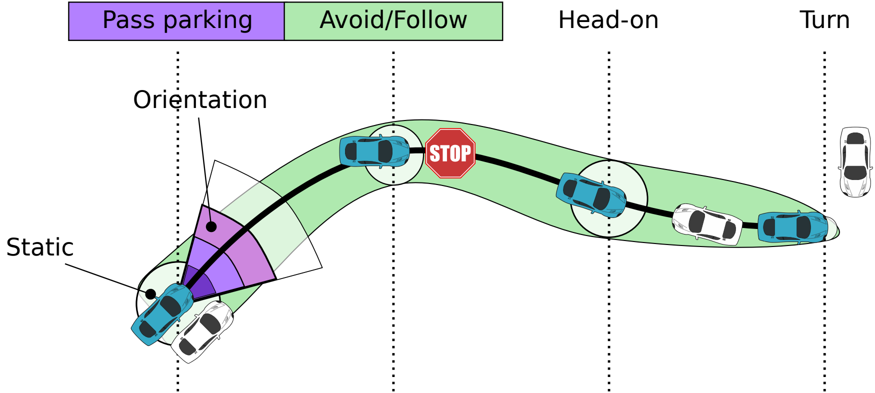

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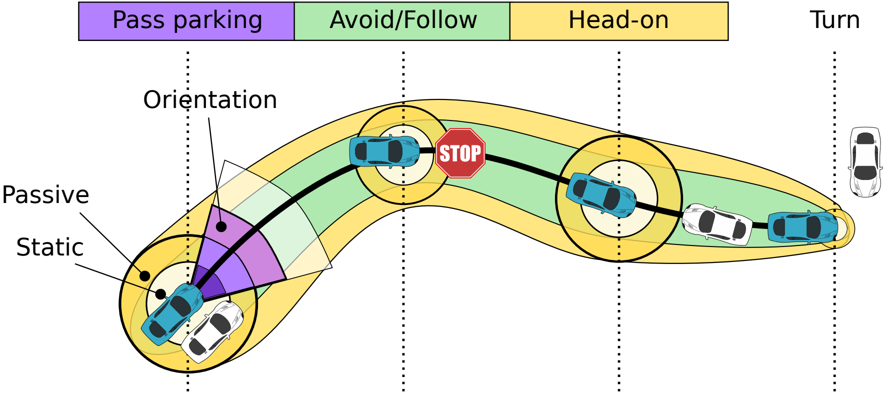

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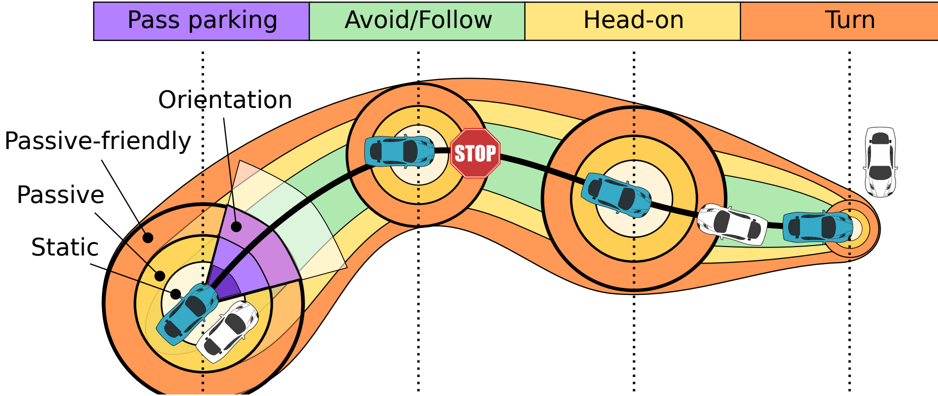

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Ground Robot Invariants and Safe Control Constraints

Safety	Invariant + Safe Control
static	$\|p-o\|_\infty > \frac{s^2}{2b} + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon s\right)$
passive	$s \neq 0 \rightarrow \|p-o\|_\infty > \frac{s^2}{2b} + V\frac{s}{b} + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon(s+V)\right)$
+ sensor	$\|\hat{p}-o\|_\infty > \frac{s^2}{2b} + V\frac{s}{b} + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon(s+V)\right) + \Delta_p$
+ disturb.	$\|p-o\|_\infty > \frac{s^2}{2b\Delta_a} + V\frac{s}{b\Delta_a} + \left(\frac{A}{b\Delta_a}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon(s+V)\right)$
+ failure	$\|\hat{p}-o\|_\infty > \frac{s^2}{2b} + V\frac{s}{b} + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon(v+V)\right) + \Delta_p + g\Delta$
friendly	$\|p-o\|_\infty > \frac{s^2}{2b} + \frac{V^2}{2b_o} + V\left(\frac{s}{b}+\tau\right) + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon(s+V)\right)$

$\vdots$

IJRR'17

Safety	Invariant + Safe Control
static	$\|p-o\|_\infty > \frac{s^2}{2b} + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon s\right)$
passive	$s \neq 0 \rightarrow \|p-o\|_\infty > \frac{s^2}{2b} + V\frac{s}{b} + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon(s+V)\right)$
+ sensor	[illegible] $V)\Big) + \Delta_p$
+ disturb.	$\|p-o\|_\infty >$ [illegible] $\frac{}{2b\Delta_a} + V$ [illegible] $\frac{}{b\Delta_a} + \Big($ [illegible] $\frac{}{b\Delta_a} + 1\Big)\Big($ [illegible] $\frac{}{2}\varepsilon^2 + \varepsilon(s+V)\Big)$
+ failure	$\|\hat{p}-o\|_\infty > \frac{s^2}{2b} + V\frac{s}{b} + \left(\frac{A}{b}+1\right)\left(\frac{A}{2}\varepsilon^2+\varepsilon(v+V)\right) + \Delta_p + g\Delta$
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⋮

Question

How to find and justify constraints? Proof!

IJRR'17

Outline

1. Autonomous Cyber-Physical Systems
2. Foundation: Differential Dynamic Logic
3. ModelPlex: Model Safety Transfer
4. VeriPhy: Executable Proof Transfer
5. Safe Learning in CPSs
6. Applications
   - Airborne Collision Avoidance System
   - Ground Robot Navigation
7. Summary

Logical Systems Lab at Carnegie Mellon University, Computer Science
Yong Kiam Tan, Brandon Bohrer, Nathan Fulton, Sarah Loos, Katherine Cordwell
Stefan Mitsch, Khalil Ghorbal, Jean-Baptiste Jeannin, Andrew Sogokon

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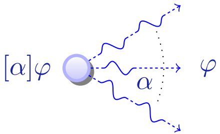
Stiftung / Foundation

differential dynamic logic

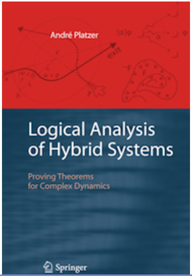
$$\mathrm{dL} = \mathrm{DL} + \mathrm{HP}$$



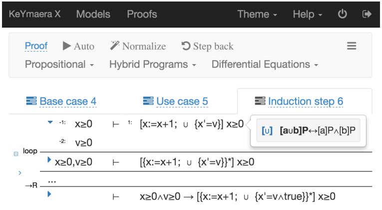
Logical Triumvirate of Technologies for Transitioning Trustworthiness

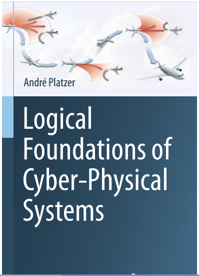
1. KeYmaera X: safe action in CPS model
2. ModelPlex: safe model $\rightsquigarrow$ safe impl
3. VeriPhy: sandbox $\rightsquigarrow$ safe executable

1. RL optimizes action choice
2. ModelPlex: safe reward for RL
3. VeriPhy: CPS sandbox for RL



KeYmaera X





A. Platzer. *Logical Foundations of Cyber-Physical Systems*. Springer 2018

I Part: Elementary Cyber-Physical Systems

2. Differential Equations & Domains
3. Choice & Control
4. Safety & Contracts
5. Dynamical Systems & Dynamic Axioms
6. Truth & Proof
7. Control Loops & Invariants
8. Events & Responses
9. Reactions & Delays

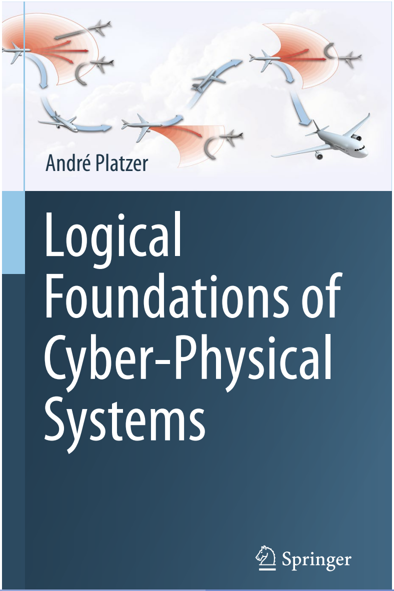
II Part: Differential Equations Analysis

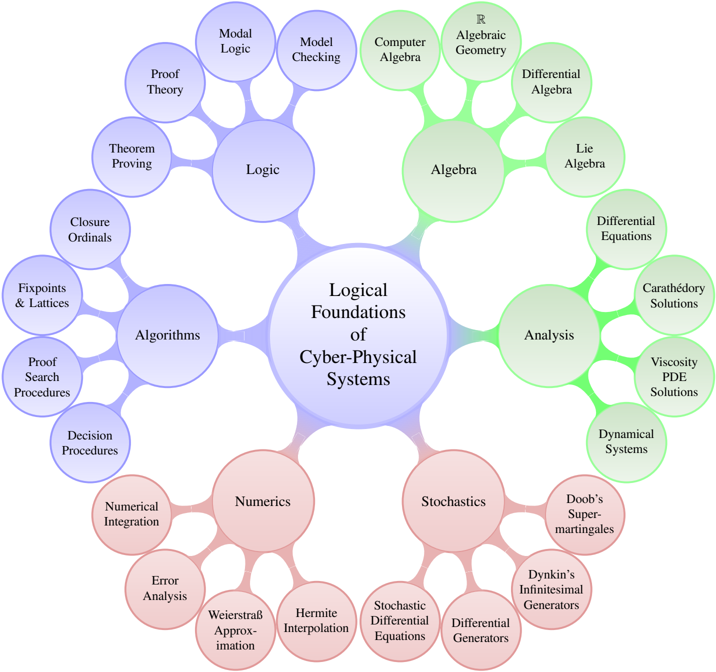
10. Differential Equations & Differential Invariants
11. Differential Equations & Proofs
12. Ghosts & Differential Ghosts
13. Differential Invariants & Proof Theory

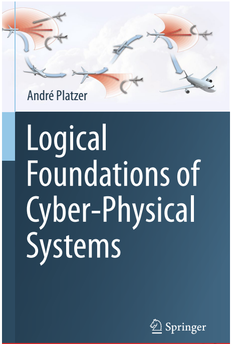
III Part: Adversarial Cyber-Physical Systems

14-17. Hybrid Systems & Hybrid Games

IV Part: Comprehensive CPS Correctness




Logical Foundations of Cyber-Physical Systems
Logic
Modal Logic
Model Checking
Proof Theory
Theorem Proving
Algebra
Computer Algebra
ℝ Algebraic Geometry
Differential Algebra
Lie Algebra
Algorithms
Closure Ordinals
Fixpoints & Lattices
Proof Search Procedures
Decision Procedures
Analysis
Differential Equations
Carathéodory Solutions
Viscosity PDE Solutions
Dynamical Systems
Numerics
Numerical Integration
Error Analysis
Weierstraß Approx-imation
Hermite Interpolation
Stochastics
Doob's Super-martingales
Dynkin's Infinitesimal Generators
Differential Generators
Stochastic Differential Equations


André Platzer
Logical Foundations of Cyber-Physical Systems
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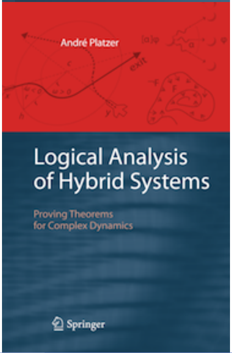

André Platzer
Logical Analysis of Hybrid Systems
Proving Theorems for Complex Dynamics
Springer

Differential Dynamic Logic dL: Syntax

Definition (Hybrid program α)

$$x := f(x) \mid ?Q \mid x' = f(x) \,\&\, Q \mid \alpha \cup \beta \mid \alpha ; \beta \mid \alpha^*$$

Definition (dL Formula P)

$$e \geq \tilde{e} \mid \neg P \mid P \wedge Q \mid \forall x\, P \mid \exists x\, P \mid [\alpha]P \mid \langle \alpha \rangle P$$

JAR'08,LICS'12,JAR'17

Differential Dynamic Logic dL: Syntax

Discrete Assign | Test Condition | Differential Equation | Nondet. Choice | Seq. Compose | Nondet. Repeat

Definition (Hybrid program α)

$$x := f(x) \mid ?Q \mid x' = f(x) \,\&\, Q \mid \alpha \cup \beta \mid \alpha;\beta \mid \alpha^*$$

Definition (dL Formula P)

$$e \geq \tilde{e} \mid \neg P \mid P \wedge Q \mid \forall x\, P \mid \exists x\, P \mid [\alpha]P \mid \langle\alpha\rangle P$$

All Reals | Some Reals | All Runs | Some Runs

JAR'08,LICS'12,JAR'17

Definition (Hybrid program semantics) $([\![\cdot]\!] : \mathrm{HP} \to \wp(\mathscr{S} \times \mathscr{S}))$

$$
\begin{aligned}
[\![x := e]\!] &= \{(\omega, \nu) : \nu = \omega \text{ except } \nu[\![x]\!] = \omega[\![e]\!]\} \\
[\![?Q]\!] &= \{(\omega, \omega) : \omega \in [\![Q]\!]\} \\
[\![x' = f(x)]\!] &= \{(\varphi(0), \varphi(r)) : \varphi \models x' = f(x) \text{ for some duration } r\} \\
[\![\alpha \cup \beta]\!] &= [\![\alpha]\!] \cup [\![\beta]\!] \\
[\![\alpha; \beta]\!] &= [\![\alpha]\!] \circ [\![\beta]\!] \\
[\![\alpha^*]\!] &= [\![\alpha]\!]^* = \bigcup_{n \in \mathbb{N}} [\![\alpha^n]\!]
\end{aligned}
$$

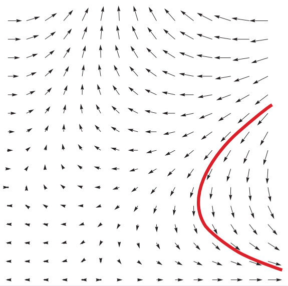
compositional semantics

Definition (dL semantics) $([\![\cdot]\!] : \mathrm{Fml} \to \wp(\mathscr{S}))$

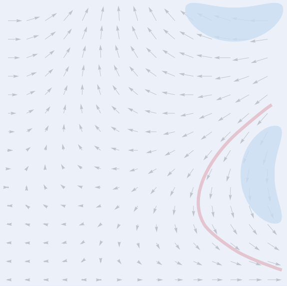
$$
\begin{aligned}
[\![e \geq \tilde{e}]\!] &= \{\omega : \omega[\![e]\!] \geq \omega[\![\tilde{e}]\!]\} \\
[\![\neg P]\!] &= [\![P]\!]^{\complement} \\
[\![P \land Q]\!] &= [\![P]\!] \cap [\![Q]\!] \\
[\![\langle\alpha\rangle P]\!] &= [\![\alpha]\!] \circ [\![P]\!] = \{\omega : \nu \in [\![P]\!] \text{ for some } \nu : (\omega, \nu) \in [\![\alpha]\!]\} \\
[\![[\alpha]P]\!] &= [\![\neg\langle\alpha\rangle\neg P]\!] = \{\omega : \nu \in [\![P]\!] \text{ for all } \nu : (\omega, \nu) \in [\![\alpha]\!]\} \\
[\![\exists x\, P]\!] &= \{\omega : \omega_x^r \in [\![P]\!] \text{ for some } r \in \mathbb{R}\}
\end{aligned}
$$

Differential Invariants for Differential Equations

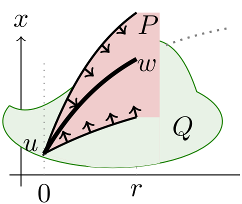
Differential Invariant



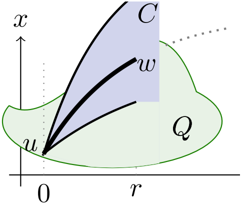
Differential Cut



Differential Ghost



$x' = f(x) \,\&\, Q$



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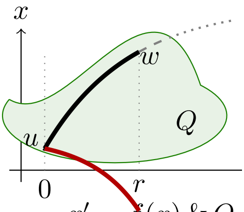
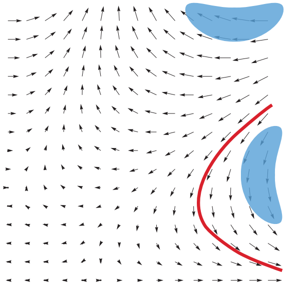
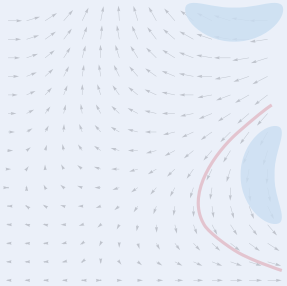


$x' = f(x) \,\&\, Q$

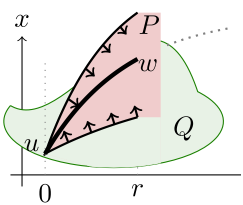
Differential Invariant



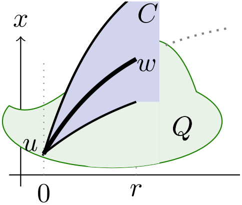
Differential Cut



Differential Ghost



$x' = f(x) \,\&\, Q$



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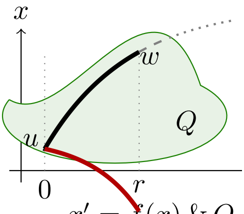
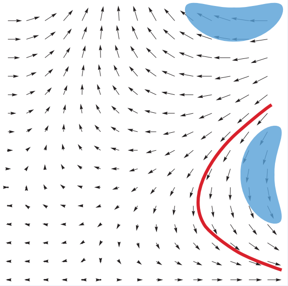


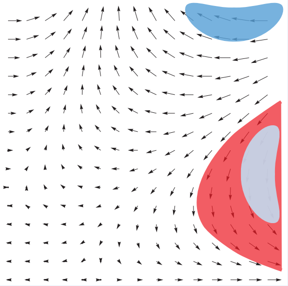
$x' = f(x) \,\&\, Q$

Differential Invariants for Differential Equations

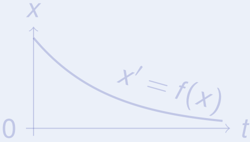
Differential Invariant

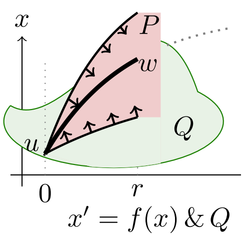


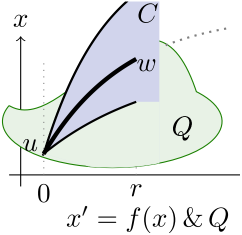
Differential Cut

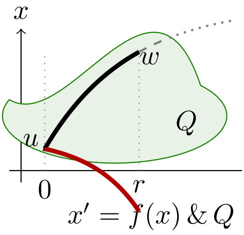


Differential Ghost



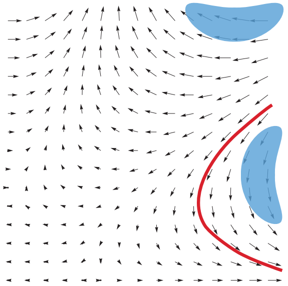




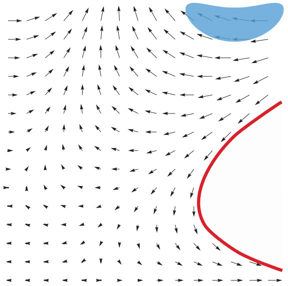


Differential Invariants for Differential Equations

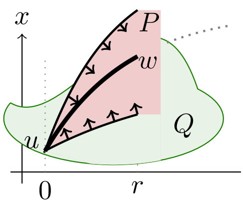
Differential Invariant



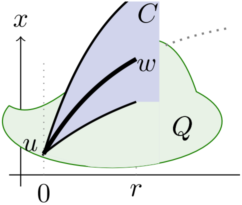
Differential Cut



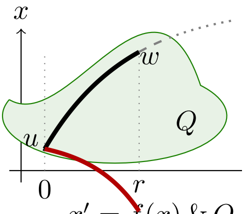
Differential Ghost



$$x' = f(x) \,\&\, Q$$



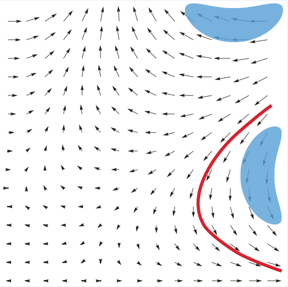
$$x' = f(x) \,\&\, Q$$



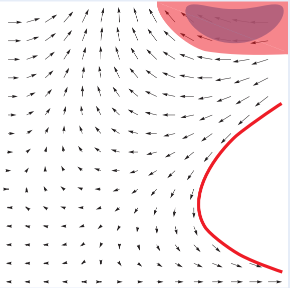
$$x' = f(x) \,\&\, Q$$

Differential Invariants for Differential Equations

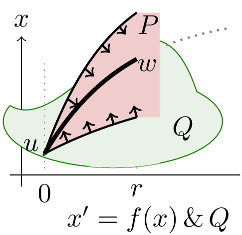
Differential Invariant

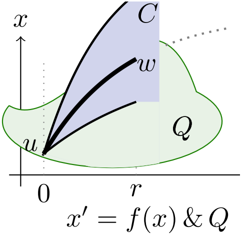


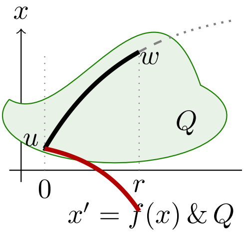
Differential Cut



Differential Ghost

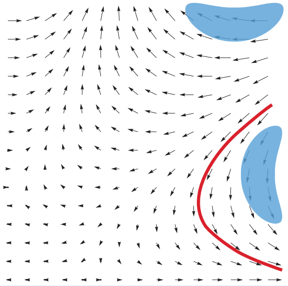




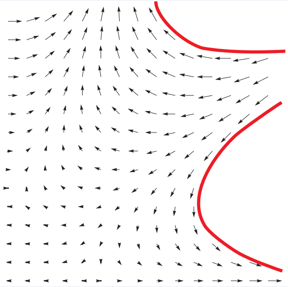


Differential Invariants for Differential Equations

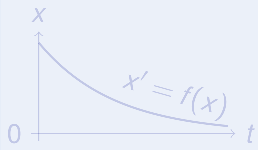
Differential Invariant

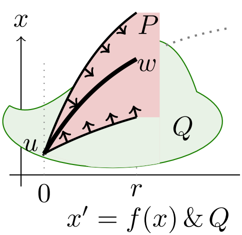


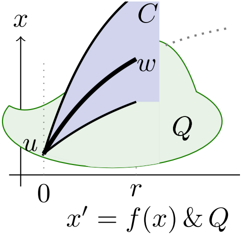
Differential Cut

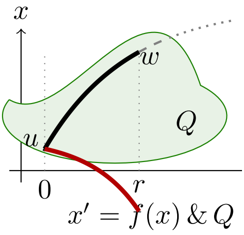


Differential Ghost

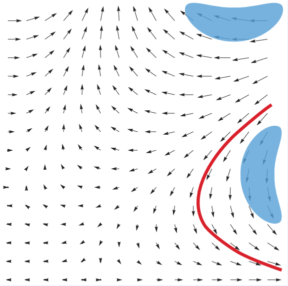




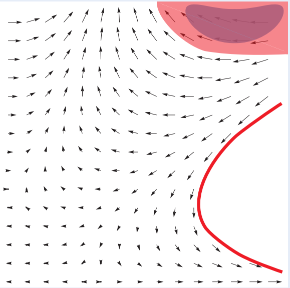




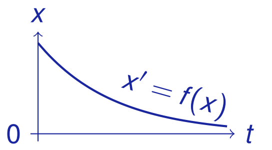
Differential Invariant

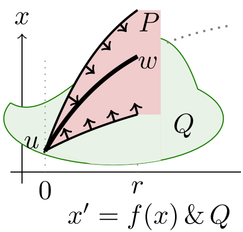


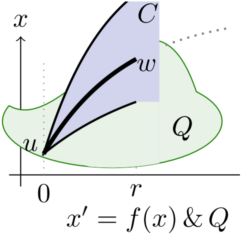
Differential Cut

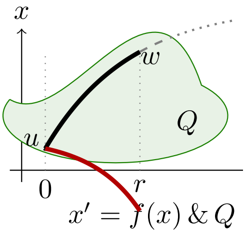


Differential Ghost



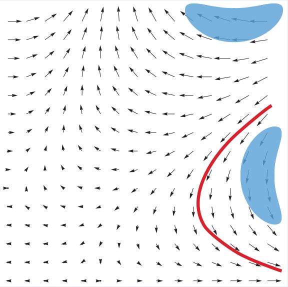




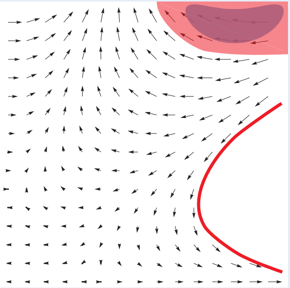


Differential Invariants for Differential Equations

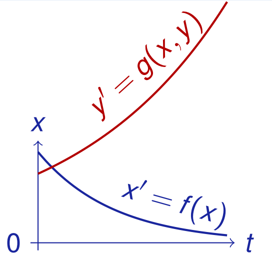
Differential Invariant

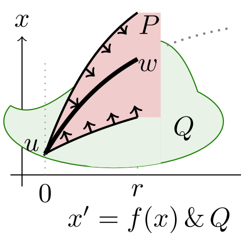


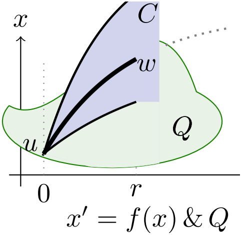
Differential Cut

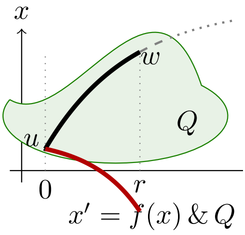


Differential Ghost



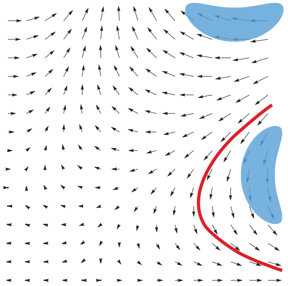




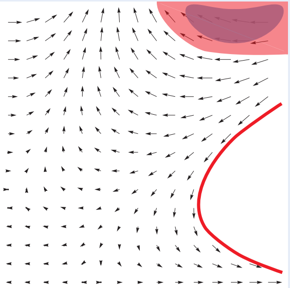


Differential Invariants for Differential Equations

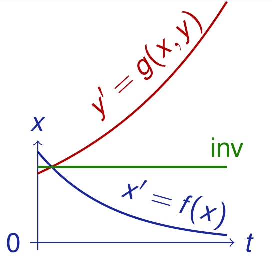
Differential Invariant

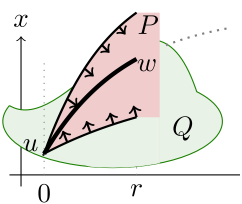


Differential Cut

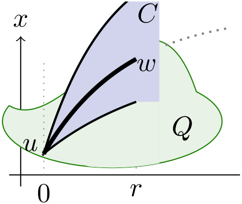


Differential Ghost

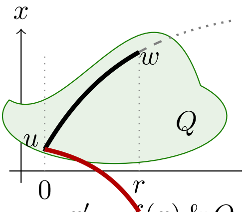




$x' = f(x) \,\&\, Q$



$x' = f(x) \,\&\, Q$



$x' = f(x) \,\&\, Q$

Differential Invariants for Differential Equations

Differential Invariant

$$\frac{Q \vdash [x' := f(x)](P)'}{P \vdash [x' = f(x) \,\&\, Q]P}$$

Differential Cut

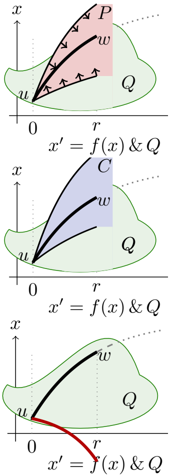
$$\frac{P \vdash [x' = f(x) \,\&\, Q]C \quad P \vdash [x' = f(x) \,\&\, Q \land C]P}{P \vdash [x' = f(x) \,\&\, Q]P}$$

Differential Ghost

$$\frac{P \leftrightarrow \exists y\, G \quad G \vdash [x' = f(x), y' = g(x,y) \,\&\, Q]G}{P \vdash [x' = f(x) \,\&\, Q]P}$$

deductive power added DI $\prec$ DI+DC $\prec$ DI+DC+DG

$$\omega[\![(e)']\!] = \sum_x \omega(x') \frac{\partial [\![e]\!]}{\partial x}(\omega)$$

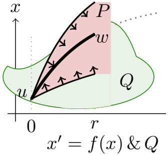


Springer'10, LMCS'12, LICS'12,JAR'17,LICS'18,JACM'20

Differential Invariants for Differential Equations

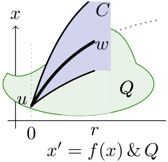
Differential Invariant

$$\frac{Q \vdash [x' := f(x)]\color{red}{(P)'}}{P \vdash [x' = f(x)\,\&\,Q]P}$$



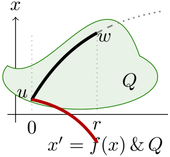
Differential Cut

$$\frac{P \vdash [x' = f(x)\,\&\,Q]\color{red}{C} \quad P \vdash [x' = f(x)\,\&\,Q \wedge \color{red}{C}]P}{P \vdash [x' = f(x)\,\&\,Q]P}$$



Differential Ghost

$$\frac{P \leftrightarrow \exists y\, \color{green}{G} \quad \color{green}{G} \vdash [x' = f(x), \color{red}{y' = g(x,y)}\,\&\,Q]\color{green}{G}}{P \vdash [x' = f(x)\,\&\,Q]P}$$



if $\color{red}{g(x,y) = a(x)y + b(x)}$, so has long solution!

Springer'10, LMCS'12, LICS'12, JAR'17, LICS'18, JACM'20

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