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Search-Based Synthesis of Probabilistic Models for Quality-of-Service Software Engineering

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ABSTRACT
The formal verification of finite-state probabilistic models supports the engineering of software with strict quality-of-service (QoS) requirements. However, its use in software design is currently a tedious process of manual multiobjective optimisation. Software designers must build and verify probabilistic models for numerous alternative architectures and instantiations of the system parameters. When successful, they end up with feasible but often suboptimal models. The EvoChecker search-based software engineering approach and tool introduced in our paper employ multiobjective optimisation genetic algorithms to automate this process and considerably improve its outcome. We evaluate EvoChecker for six variants of two software systems from the domains of dynamic power management and foreign exchange trading. These systems are characterised by different types of design parameters and QoS requirements, and their design spaces comprise between $2E+14$ and $7.22E+86$ relevant alternative designs. Our results provide strong evidence that EvoChecker significantly outperforms the current practice and yields actionable insights for software designers.

1. INTRODUCTION
The design of modern software systems requires tools capable of assessing the quality and dependability of the solution under design as early as possible in the engineering process. The late discovery of defects leads to suboptimal operation of the delivered systems, high maintenance costs, and negative impact on their users [14, 25]. This is particularly relevant for business-critical and safety-critical applications, where failures may cause financial loss or loss of human life.

Model Checking (MC) [8, 24] is among the most effective means for developing software for critical applications [59]. Given a finite-state transition model of a concurrent system, MC automatically verifies if the model satisfies requirements formally expressed in propositional temporal logic. MC can verify if software systems meet their reliability, performance and other quality-of-service (QoS) requirements [44]. Probabilistic MC verifies models with state transitions annotated by probabilities or transition rates (e.g., discrete and continuous-time Markov chains, and Markov decision processes), and operates with QoS requirements specified in probabilistic variants of temporal logics.

This paper is concerned with the use of probabilistic MC at design time to identify models that satisfy the QoS requirements of a software system. Currently, this is a tedious trial-and-error process in which software designers must build and verify probabilistic models for numerous alternative architectures and instantiations of the system parameters. Even when this manual attempt at multiobjective optimisation is successful, the models produced are often suboptimal in terms of their tradeoffs between reliability, performance, cost and other QoS requirements. The EvoChecker search-based software engineering approach introduced in our paper automates this process and considerably improves its outcome.

To this end, EvoChecker synthesises (a) a set of probabilistic models that closely approximates the Pareto-optimal model set associated with the QoS requirements of a software system; and (b) the corresponding approximate QoS Pareto front. This provides insight into the tradeoffs between multiple QoS requirements, enabling software designers to make informed decisions about the architecture and parameters of their systems. To achieve this, EvoChecker employs established multiobjective optimisation genetic algorithms (MO-GAs) and a fitness function that captures the satisfaction of the QoS requirements. EvoChecker uses as input:

- a probabilistic model template that encodes alternative architectures and parameter ranges for the system;
- a set of QoS requirements specifying both constraints (e.g., “At least 95% of the requests must be processed within 200ms”) and optimisation objectives (e.g., “The system should operate with minimal energy consumption”).

EvoChecker uses the probabilistic model checker PRISM [45] for its verification steps. Accordingly, the probabilistic model template is expressed in an extension of the PRISM high-level modelling language, and EvoChecker handles all types of probabilistic models and probabilistic temporal logics supported by PRISM and shown in Table 1.
The main contributions of our paper include:

1. The EvoChecker extension of the PRISM modelling language, and the EvoChecker search-based model synthesis approach, which we describe in Section 3, and we illustrate using a running example introduced in Section 2.
2. The definition of the probabilistic model synthesis problem (Section 3.3).
3. The open-source EvoChecker tool presented in Section 4, which we make freely available on our project webpage.
4. An extensive evaluation of the EvoChecker approach and prototype tool in two case studies drawn from different application domains, which we summarise in Section 5.

Our evaluation is based on established Pareto-front quality indicators (i.e., unary epsilon [66], hypervolume [65] and inverted generational distance [58]) shows that EvoChecker significantly outperforms the current “trial and error” practice, makes effective use of state-of-the-art MOGAs such as NSGA-II [26], SPEA2 [49] and MOCell [64], and provides actionable insights for software designers.

To the best of our knowledge, EvoChecker is the first approach that uses search-based software engineering to synthesise approximate Pareto-optimal sets of probabilistic models for the QoS requirements of software systems. The only related work we are aware of is discussed in Section 6, and belongs to the area of model repair [10, 16]. However, model repair for probabilistic systems focuses on modifying an existing probabilistic model, only at transition probability level, and only to satisfy a single temporal logic property that is violated by the original model. In contrast, EvoChecker handles multiple QoS requirements and uses multiobjective optimisation to derive an approximate Pareto-optimal set of probabilistic models and its associated Pareto front starting from a probabilistic model template.

2. RUNNING EXAMPLE

We will illustrate the EvoChecker components and operation using a software-controlled dynamic power management (DPM) system adapted from [53, 56]. As shown in Fig. 1, the system consists of a service provider that handles requests generated by a service requester and stored in two request queues of different priorities. The service provider has four states associated with different power usage, i.e., busy, idle, standby and sleep. Fig. 1 depicts the power usage of each state (in watts), the possible transitions between states, and the energy consumed by each transition (in joules). These values are taken from [53], and correspond to a Fujitsu disk drive.

Table 1: Types of models supported by EvoChecker

<table>
<thead>
<tr>
<th>Type of probabilistic model</th>
<th>QoS requirement specification logic</th>
</tr>
</thead>
<tbody>
<tr>
<td>Discrete-time Markov chains</td>
<td>PCTL⁷, LTL⁵, PCTL*⁶</td>
</tr>
<tr>
<td>Continuous-time Markov chains</td>
<td>CSL⁴</td>
</tr>
<tr>
<td>Markov decision processes</td>
<td>PCTL⁷, LTL⁵, PCTL*⁶</td>
</tr>
<tr>
<td>Probabilistic automata</td>
<td>PCTL⁷, LTL⁵, PCTL*⁶</td>
</tr>
<tr>
<td>Probabilistic timed automata</td>
<td>PCTL⁷</td>
</tr>
</tbody>
</table>

⁴ Probabilistic Computation Tree Logic [13, 34]
⁵ Linear Temporal Logic [51]
⁶ PCTL* is a superset of PCTL and LTL
⁷ Continuous Stochastic Logic [7, 9]

When the service provider is in the busy state, it processes requests as follows. If the high-priority queue contains \( q_H > 0 \) requests, then a high-priority request is processed. Otherwise, if the low-priority queue contains requests (i.e., if \( q_L > 0 \)), a low-priority request is handled. After handling the last request (i.e., when both queues become empty), the service provider automatically transitions to the idle state. The transitions from idle to busy are also automatic, and occur whenever the empty-queue DPM system receives a new request. In contrast, all the other transitions are controlled by a software power manager that aims to reduce power usage while maintaining an acceptable service level for the system. We use the real values from [53] for the state transition times (Table 2) and the request service rate (i.e., 125s⁻¹), and we assume average arrival rates of 0.05s⁻¹ and 0.15s⁻¹ for the high-priority and low-priority requests, respectively.

Finally, suppose that the DPM system designer must select:
1. the capacity of the request queues, \( Q_{max} \); 2. one of two alternative power managers (described later); 3. the parameters of the selected power manager such that the QoS requirements in Table 3 are satisfied.

Table 2: Average service-provider transition times

<table>
<thead>
<tr>
<th>State transition</th>
<th>Average time (s)</th>
<th>State transition</th>
<th>Average time (s)</th>
</tr>
</thead>
<tbody>
<tr>
<td>idle → standby</td>
<td>0.4</td>
<td>standby → idle</td>
<td>1.2</td>
</tr>
<tr>
<td>idle → sleep</td>
<td>0.67</td>
<td>sleep → idle</td>
<td>1.6</td>
</tr>
<tr>
<td>standby → sleep</td>
<td>0.3</td>
<td>sleep → standby</td>
<td>0.6</td>
</tr>
</tbody>
</table>

Table 3: QoS requirements for the DPM system

<table>
<thead>
<tr>
<th>ID</th>
<th>Description</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>R1</td>
<td>The steady-state utilisation of the high-priority queue should be less than 90%</td>
<td>constraint</td>
</tr>
<tr>
<td>R2</td>
<td>The steady-state utilisation of the low-priority queue should be less than 90%</td>
<td>constraint</td>
</tr>
<tr>
<td>R3</td>
<td>The system should operate with minimum steady-state power utilisation</td>
<td>objective</td>
</tr>
<tr>
<td>R4</td>
<td>The number of requests lost at the steady state should be minimised</td>
<td>objective</td>
</tr>
<tr>
<td>R5</td>
<td>The capacity of both queues should be minimised</td>
<td>objective</td>
</tr>
</tbody>
</table>
3. EvoChecker

3.1 Modelling Language

EvoChecker probabilistic model templates are specified in an extended version of the PRISM high-level modelling language [45]. This language is based on the Reactive Modules formalism [3], which describes a system as the parallel composition of a set of modules. The state of a module is encoded by a set of finite-range local variables, and its state transitions are defined by probabilistic guarded commands that change these variables, and have the general form:

\[ \text{[action]} \text{guard} \rightarrow e_1 : \text{update}_1 + \ldots + e_n : \text{update}_n; \]

In this command, guard is a boolean expression over all the variables in the model. If guard evaluates to true, the arithmetic expression \( e_i \), \( 1 \leq i \leq n \), gives the probability (for discrete-time models) or rate (for continuous-time models) with which the update \( e_i \) change of the module variables occurs. The action is optional; when present, it forces all modules comprising commands with this action to perform one of these commands simultaneously (i.e., to synchronise). For a detailed description of the PRISM modelling language, we refer the reader to the PRISM manual, available at http://www.prismmodelchecker.org/manual.

Example 1. Fig. 2 shows the continuous-time Markov chain (CTMC) model of the dynamic power management system from our running example. The model comprises a module for each request queue, a ServiceProvider module, and a module for one of the two power managers considered during the design of the system. The local variables from the high-priority and low-priority request queue modules record the number of requests from the two queues, \( q_H \) and \( q_L \), and the ServiceProvider local variable \( sp \) encodes the state of the service provider. The queue modules and ServiceProvider synchronise through the actions requestH,L and serveH,L, which reflect requests arriving into the queues and being served, respectively. The service provider switches between its busy and idle states automatically (lines 20, 22, 24 and 26), and can also perform the state transitions from Table 2, aiming to switch to lower-power states when both request queues are empty (i.e., \( q_H + q_L = 0 \)) and back towards the busy state otherwise (lines 28–34). However, these transitions are controlled by the power manager through the synchronisation of all ServiceProvider and PowerManager commands with common actions. For example, lines 43–44 have false guards and thus disable the transitions between idle and sleep, the transition between idle and standby is always enabled due to the true guard in line 46, and constraints are placed on all other transitions.

Software designers use probabilistic models to manually explore an often very large design space comprising alternative module implementations, parameter values and transition probabilities. EvoChecker extends the PRISM modelling language with three constructs that support the specification of all these design alternatives within a probabilistic model template whose instantiations correspond to possible system designs. The three constructs are defined below.

1. **Evolvable parameters.** EvoChecker uses the syntax

   \[ \text{evolve int param \([\text{min}..\text{max}]\);} \]

   \[ \text{evolve double param \([\text{min}..\text{max}]\);} \]

   to declare model parameters of type `int` and `double`, respectively, and acceptable ranges for them. These parameters can be used in any field of command (1) other than action, just like constant model parameters declared using `const int` and `const double` from the original language.

\[ \begin{align*}
\text{ctmc} & = \ldots \\
\text{module HighPriorityRequestQueue} & \text{[QmaxH]} \text{[3..15];}
\text{module LowPriorityRequestQueue} & \text{[QmaxL]} \text{[5..30];}
\text{module ServiceProvider} & \text{[sp: \{0..3\}]} \text{init} 0; \text{[// 0=busy, 1=idle, 2=standby, 3=sleep]} \\
\text{module PowerManager} & \text{[p: \{0..1\}]} \text{init} 0.7; \text{[// 0=loop, 1=sleep to standby]} \\
\text{const} & \text{double x1 = 0.2;}
\text{const} & \text{double x2 = 0.8;}
\text{const} & \text{double y1 = 0.35;
\text{const} & \text{double y2 = 0.65;]
\end{align*} \]

Figure 2: CTMC model of the DPM system; Δ–Greek symbols represent EvoChecker extensions of the PRISM modelling language.
2. Evolvable probability distributions. The syntax
   \[
   \text{evolve distribution } dist \{ [min_1, max_1], \ldots, [min_n, max_n] \}; \tag{3}
   \]
   where \([min_i, max_i] \subseteq [0,1]\) for all \(1 \leq i \leq n\), is used to declare
   an \(n\)-element discrete probability distribution, and ranges for the \(n\) probabilities of the distribution.
   The name of the distribution can then be used instead of expressions \(e_1, e_2, \ldots, e_n\) from an \(n\)-element command (1).

3. Evolvable modules. EvoChecker uses the syntax
   \[
   \text{evolve module mod implementation}_1 \text{ endmodule} \\
   \ldots \\
   \text{evolve module mod implementation}_n \text{ endmodule} \tag{4}
   \]
to define \(n \geq 2\) alternative implementations of a module.

The role of the three EvoChecker constructs is described by the following definitions.

**Definition 1.** A valid PRISM probabilistic model augmented with a set of EvoChecker constructs (2)–(4) is called a probabilistic module template.

**Definition 2.** A probabilistic model is an instance of a probabilistic module template \(T\) if and only if it can be obtained from \(T\) using the following transformations:
   - Each evolvable parameter (2) is replaced by a ‘\text{const int param } \text{ val}’ or ‘\text{const double param } \text{ val}’ declaration (depending on the type of the parameter), where \(\text{val} \in \{\text{\text{min}}, \ldots, \text{\text{max}}\}\), respectively.
   - Each evolvable probability distribution (3) is removed, and the \(n\) occurrences of its name instead of expressions \(e_1, \ldots, e_n\) of a command (1) are replaced with values from the ranges \([\text{\text{min}}, \text{\text{max}}], \ldots, [\text{\text{min}}, \text{\text{max}}]\), respectively, such that the sum of the \(n\) values is 1.0.
   - Each set of evolvable modules with the same name is replaced with a single element from the set, from which the keyword ‘\text{evolve}’ was removed.

**Definition 3.** The set of all probabilistic models that are instances of a probabilistic module template \(T\) is called the design space of \(T\), and is denoted \(DS^T\).

**Example 2.** Fig. 2 illustrates the three EvoChecker constructs used to transform the CTMC model from our running example into a probabilistic module template. The replacement of the elements from the dashed rectangles with those from the continuous rectangles shows how: ① two evolvable parameters are used to specify the sizes of the two request queues; ② two evolvable distributions are used to specify the transition probabilities from lines 53 and 55 of the power manager; and ③ the module PowerManager is declared one of several possible implementations of the power manager. Note that at least one additional implementation of this module needs to be provided in a valid probabilistic module template; due to space constraints, the second implementation is not included here, but we make it available at http://www-users.cs.york.ac.uk/~simos/EvoChecker.

### 3.2 Quality-of-Service Requirements

EvoChecker supports two types of QoS requirements: constraints and optimisation objectives. Both types refer to QoS attributes of the system under design, such as response time, throughput, reliability or cost. Constraints define bounds for the acceptable values of these attributes, while optimisation objectives specify QoS attributes that should be minimised or maximised (subject to all constraints being satisfied). Without loss of generality, we will assume that the latter QoS attributes are to be minimised in the remainder of the paper. Formally, a software system considered by EvoChecker needs to satisfy \(n_1 \geq 0\) constraints of the form
   \[
   RC_1 : \text{attr}_i \preceq \text{bound}_i, \ 1 \leq i \leq n_1, \tag{5}
   \]
   and \(n_2 \geq 1\) optimisation objectives of the form
   \[
   RC_2 : \text{minimise } \text{attr}_i, \ 1 \leq i \leq n_1 + n_2, \tag{6}
   \]
   where \(\preceq \in \{<, =, \geq, >\}\) and \(\text{bound}_i \in \mathbb{R}\) for all \(1 \leq i \leq n_1\), and \(\text{attr}_1, \text{attr}_2, \ldots, \text{attr}_{n_1+n_2} \in \mathbb{R}\) represent \(n_1 + n_2\) QoS attributes of the system. These QoS attributes are formally expressed in the probabilistic temporal logics shown earlier in Table 1. Given a probabilistic model \(M\) of a possible system design, and the probabilistic temporal logic formulæ \(\Phi_1, \Phi_2, \ldots, \Phi_{n_1+n_2}\) of the QoS attributes, the probabilistic model checker PRISM [45, 46] automatically establishes the value of the QoS attributes corresponding to this design, i.e.,
   \[
   \text{attr}_i(M) = \text{PMC}(M, \Phi_i), \ 1 \leq i \leq n_1 + n_2. \tag{7}
   \]
   Due to space constraints, we do not present the probabilistic temporal logics supported by EvoChecker; references to detailed descriptions of each logic are provided in Table 1.

**Example 3.** The QoS requirements from our running example (Table 3) comprise two constraints (R1 and R2), and three optimisation objectives (R3–R5). The QoS attributes for all requirements are specified using rewards probabilistic temporal logic formulæ [4, 40, 44]. To this end, positive values are associated with specific states and transitions of the CTMC in Fig. 2 by using rewards..endrewards structures. For example, the structure below enables the computation of the total number of lost requests for requirement R4:

\[
\text{rewards } "\text{TotalLost}" \\
\text{[dropH] true : 1; } \\
\text{[dropl] true : 1; } \\
\text{endrewards}
\]

by associating a value of 1 with each transition that corresponds to a request being dropped because of a full queue. The corresponding temporal logic formula is \(\Phi_4 = R_{\text{TotalLost}}[S]\), and represents the “steady-state reward” for the above rewards structure, i.e., the long-run average number of dropped requests for the system.

### 3.3 Probabilistic Model Synthesis Problem

Consider a probabilistic model template \(T\) with design space \(DS^T\), and a set of QoS requirements comprising \(n_1\) constraints (5) and \(n_2\) optimisation objectives (6). The probabilistic model synthesis problem involves finding the Pareto- optimal design set \(PS\) of models from \(DS^T\) that satisfy the \(n_1\) constraints and are non-dominated with respect to the \(n_2\) optimisation objectives:

\[
PS = \{ M \in DS^T \mid \forall 1 \leq i \leq n_1 \bullet \text{attr}_i(M) \preceq \text{bound}_i \land \left( \exists M' \in DS^T \bullet M' < M \right) \}, \tag{8}
\]
with the dominance relation $\prec$ : $D^S \times D^S \rightarrow \mathbb{B}$ defined by
\[
\forall M_1, M_2 \in D^S \cdot M_1 \prec M_2 \equiv \\
\forall n_1 + 1 \leq i \leq n_1 + n_2 \cdot \text{attr}_i(M_1) \leq \text{attr}_i(M_2) \land \\
\exists M \in P S . \forall n_1 + 1 \leq i \leq n_1 + n_2 \cdot a_i = \text{attr}_i(M), (9)
\]
Finally, given the Pareto-optimal design set $PS$, we are also interested in the Pareto front defined by
\[
PF = \{ (a_{n_1+1}, a_{n_1+2}, \ldots, a_{n_1+n_2}) \in \mathbb{R}_n^2 \mid \\
\exists M \in PS \cdot \forall n_1 + 1 \leq i \leq n_1 + n_2 \cdot a_i = \text{attr}_i(M) \},
\]
since designers need this information alongside their domain knowledge when choosing between the models in $PS$.

### 3.4 EvoChecker Model Synthesis

Computing the Pareto-optimal design set (8) is in most cases unfeasible, as the design space $DS^T$ is typically extremely large and may be infinite (i.e., when the probabilistic model template $T$ contains evolvable parameters of type double and/or evolvable distributions). Therefore, EvoChecker uses elitist genetic algorithms for multiobjective optimisation (e.g., [26, 49, 64]) to synthesise a set of probabilistic models that closely approximates this Pareto-optimal set.

A genetic algorithm (GA) [43] encodes possible solutions of a search problem as a sequence of genes (i.e., binary representations of the problem variables). For EvoChecker, each instance of an ‘evolvable’ construct from Section 3.1 contributes to this sequence with the gene(s) given by the encoding rules in Table 4. These rules are used by the Template parser from the high-level EvoChecker architecture in Fig. 3 to extract the value ranges $V_1, V_2, \ldots, V_n$ for the $n \geq 1$ genes associated with the model template $T$.

Given the solution encoding described above, GAs start with a randomly generated set (population) of feasible solutions (individuals). This population is then iteratively evolved into populations containing “fitter” individuals by means of GA selection, crossover and mutation. Selection uses a real-valued fitness function to evaluate each individual created during the GA execution, in order to select the population for the next iteration and the mating pool of individuals for the current iteration. Crossover randomly selects two individuals from the mating pool, and generates a new individual by combining their genes. Finally, mutation produces a new individual by randomly modifying some of the genes of an individual from the pool. GAs terminate after a fixed number of (individual) evaluations or when a predetermined number of successive iterations generate populations with no significantly fitter individuals.

As shown in Fig. 3, the GA used by EvoChecker is elitist, i.e., it preserves the best individuals across iterations. This involves maintaining a finite “archive” of the fittest individuals (e.g., by elitist GAs like MOCell [49] and SPEA2 [64]) or by retaining the fittest individuals from one iteration to the next (e.g., by NSGA-II [26]). The algorithms used by EvoChecker are also multiobjective optimisation GAs (MOGAs), i.e., they generate Pareto-optimal set approximations spread as uniformly as possible across the search space. Therefore, they use fitness functions that encode in ways specific to each MOGA both the nondomination level of each evaluated individual and the population density in its area of the search space. For example, NSGA-II [26] associates a nondominance level of 1 to all nondominated individuals of a population, a level of 2 to the individuals that are not dominated when level-1 individuals are ignored, etc.; and SPEA2 [64] evaluates population density as the inverse of the distance to the $k$-th nearest neighbour of the individual. Providing full technical details about the MOGAs that EvoChecker can use is beyond the scope of this paper. The reader can find their descriptions in [26, 49, 64], and a comparison of their relative merits in [28].

In EvoChecker the MOGA evaluation of the fitness of individuals is supported by an Individual QoS analyser (Fig. 3). This component takes as input the gene sequence $(g_1, \ldots, g_n)$ for an individual, and returns to the MOGA the QoS attributes $\text{attr}_{1}, \text{attr}_{2}, \ldots, \text{attr}_{n_1+n_2}$ of the model $M$ associated with this individual. To this end, the analyser uses an internal representation $T'$ of the model template produced by the Template parser and the gene sequence $(g_1, \ldots, g_n)$ to obtain the model $M$, and then invokes a Probabilistic model checker to establish the $n_1 + n_2$ QoS attributes from (7) one at a time. This setup enables the MOGA to generate approximations of the Pareto-optimal model set $PS$ and of the associated Pareto front $PF$ as illustrated in Fig. 3.

**Example 4.** Consider again the DPM system from our running example. Using the rules in Table 4, EvoChecker encodes each instance $M$ of the probabilistic model template from Fig. 2 as the sequence of genes

\[
(\text{Qmax}_H, \text{Qmax}_L, x_1, x_2, y_1, y_2, \text{pm}), (10)
\]

Individuals not satisfying problem constraints are assigned a default level of 0.

---

**Table 4: EvoChecker gene encoding rules**

<table>
<thead>
<tr>
<th>Evolvable feature of the probabilistic model template</th>
<th>EvoChecker gene(s)</th>
</tr>
</thead>
<tbody>
<tr>
<td>(\text{int param}[\text{min., max.}];)</td>
<td>(1 \text{ (min., max.)})</td>
</tr>
<tr>
<td>(\text{double param}[\text{min., max.}];)</td>
<td>(1 \text{ (min., max.)})</td>
</tr>
<tr>
<td>(\text{distribution dist}[\text{min., max.}];)</td>
<td>(n \text{ (min., max.)})</td>
</tr>
<tr>
<td>(\text{module mod implementation}_n \text{ endmodule})</td>
<td>(1 \text{ (1, 2, \ldots, m)})</td>
</tr>
</tbody>
</table>

**Figure 3: High-level EvoChecker architecture**

As shown in Fig. 3, the GA used by EvoChecker is elitist, i.e., it preserves the best individuals across iterations. This involves maintaining a finite “archive” of the fittest individuals (e.g., by elitist GAs like MOCell [49] and SPEA2 [64]) or by retaining the fittest individuals from one iteration to the next (e.g., by NSGA-II [26]). The algorithms used by EvoChecker are also multiobjective optimisation GAs (MOGAs), i.e., they generate Pareto-optimal set approximations spread as uniformly as possible across the search space. Therefore, they use fitness functions that encode in ways specific to each MOGA both the nondomination level of each evaluated individual and the population density in its area of the search space. For example, NSGA-II [26] associates a nondominance level of 1 to all nondominated individuals of a population, a level of 2 to the individuals that are not dominated when level-1 individuals are ignored, etc.; and SPEA2 [64] evaluates population density as the inverse of the distance to the $k$-th nearest neighbour of the individual. Providing full technical details about the MOGAs that EvoChecker can use is beyond the scope of this paper. The reader can find their descriptions in [26, 49, 64], and a comparison of their relative merits in [28].

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**Example 4.** Consider again the DPM system from our running example. Using the rules in Table 4, EvoChecker encodes each instance $M$ of the probabilistic model template from Fig. 2 as the sequence of genes

\[
(\text{Qmax}_H, \text{Qmax}_L, x_1, x_2, y_1, y_2, \text{pm}), (10)
\]

Individuals not satisfying problem constraints are assigned a default level of 0.
where $Q_{max_H} \in V_1 = \{3, 4, \ldots, 15\}$ and $Q_{max_L} \in V_2 = \{5, 6, \ldots, 30\}$ represent the capacities of the two queues; $x_1 \in V_3 = [0.1, 0.3]$ and $x_2 \in V_4 = [0.7, 0.9]$ such that $x_1 + x_2 = 1$, and $y_1 \in V_5 = [0.3, 0.6]$ and $y_2 \in V_6 = [0.4, 0.7]$ such that $y_1 + y_2 = 1$ represent the two probability distributions; and $pm \in V_7 = \{1, 2\}$ is a gene that encodes which of the $m = 2$ implementations of the PowerManager module in Fig. 2 is used by $M$. The gene value ranges $V_1$ to $V_7$ are extracted by the EvoChecker Template parser and passed to the MOGA, which uses the Individual QoS analyser to iteratively generate model populations of increasing fitness and eventually outputs the Pareto front and Pareto-optimal set approximations achieved after a pre-established number of evaluations. As an example, Fig. 4 depicts a Pareto front approximation obtained using NSGA-II [26] as the EvoChecker MOGA, with an initial population of 150 individuals and after 5000 evaluations. Remember that the dimensionality of Pareto front for a probabilistic model synthesis problem is given by the number of optimisation objectives $n_2$. Our DPM system has $n_2 = 3$ optimisation objectives, as shown in Table 3.

4. EvoChecker TOOL
To automate the EvoChecker synthesis of probabilistic models, we implemented a tool with the architecture in Fig. 3. Our EvoChecker tool uses the established MOGA implementations provided by the Java-based framework for multi-objective optimization with metaheuristics JMetal [27], and the probabilistic model checker PRISM [45]. We developed the other components of the architecture from Fig. 3 in Java, using the Antlr\(^2\) parser generator to build the Template parser, and implementing an Individual QoS analyser specifically for the EvoChecker tool. The open-source code of EvoChecker, the full experimental results summarised in the following section, additional information about EvoChecker and the case studies used for its evaluation are available at http://www-users.cs.york.ac.uk/~simos/EvoChecker.

5. EVALUATION
5.1 Research Questions
We evaluated the effectiveness of EvoChecker by performing extensive experiments to answer the next research questions.

RQ1 (Validation): How does EvoChecker perform compared to random search? We used this research question to establish if EvoChecker “comfortably outperforms a random search” [38], as expected of effective search-based software engineering solutions.

RQ2 (Comparison): How do EvoChecker instances using different MOGAs perform compared to each other? Since we devised EvoChecker to work with any MOGA, we examined the results produced by EvoChecker instances using three established such algorithms (i.e., NSGA-II [26], SPEA2 [64] and MOCell [49]).

RQ3 (Insights): Can EvoChecker provide insights into the trade-offs between the QoS attributes of alternative software architectures and configurations? To support software designers in their decision making, EvoChecker must provide insights into the trade-offs between multiple QoS objectives. To address this question, we identified a range of design decisions suggested by the EvoChecker results for the software systems considered in our evaluation.

5.2 Analysed Software Systems
Our experiments used EvoChecker in multiple scenarios associated with two software systems from different application domains—the dynamic power management (DPM) system from our running example, and a real-world service-based system from the area of foreign exchange trading. The second system, which we anonymise as FX for confidentiality reasons, is used by an European foreign exchange brokerage company, and implements the workflow in Fig. 5.

An FX customer (called a trader) can use the system in two operation modes. In the expert mode, FX executes a loop that analyses market activity, identifies patterns that satisfy the trader’s objectives, and automatically carries out trades. Thus, the Market watch service extracts real-time exchange rates (bid/ask price) of selected currency pairs. This data is used by a Technical analysis service that evaluates the current trading conditions, predicts future price movement, and decides if the trader’s objectives are: (i) “satisfied” (causing the invocation of an Order service to carry out a trade); (ii) “unsatisfied” (resulting in a new Market watch invocation); or (iii) “unsatisfied with high variance” (triggering an Alarm service invocation to notify the trader about discrepancies/opportunities not covered by the trading objectives). In the normal mode, FX assesses the economic outlook of

Figure 4: Pareto front approximation for the DPM system

![Figure 4: Pareto front approximation for the DPM system](http://www-users.cs.york.ac.uk/~simos/EvoChecker)

Figure 5: The FX workflow

![Figure 5: The FX workflow](http://www-users.cs.york.ac.uk/~simos/EvoChecker)
a country using a Fundamental analysis service that collects, analyses and evaluates information such as news reports, economic data and political events, and provides an assessment on the country’s currency. If satisfied with this assessment, the trader can use the Order service to sell or buy currency, in which case a Notification service confirms the completion of the trade.

We assume that the FX designer has to select third-party implementations for each of the $n \leq 1$ services from Fig. 5 for which in-house implementations are not available, in order to meet the QoS requirements from Table 5. The designer can use any subset of the $n_i \geq 1$ third-party implementations of the $i$-th service unavailable in-house, and either a probabilistic or a sequential selection strategy. The probabilistic strategy involves using a randomly selected third-party service from the subset for each invocation of service $i$, where the random selection is made according to a discrete probability distribution decided by the designer. The sequential strategy involves invoking the services from the subset in a designer-specified order, until one of the invocations is successful or all the invocations failed. We used an EvoChecker probabilistic model template to capture these alternative FX designs. This template uses all EvoChecker “evolvable” constructs, and is parameterised by the number of services $n$, the number of third-party service implementations $n_1, n_2, \ldots$, and by the costs, success probabilities and response times of these implementations.

To evaluate EvoChecker for multiple design space sizes, we applied it to each of the system variants from Table 6. The entries in this table list the int-valued probabilistic model template parameters from (10) for the DPM system, and described above for the FX system. The ‘Size’ column reports the size of the design space that an exhaustive search would need to explore, assuming two-decimal precision for the double-valued parameters of the probabilistic model templates (cf. Table 4). This is a valid assumption, as the nonlinearity of most probabilistic models means that a 0.01 change in a state transition probability often translates into significant changes in the values of model properties. Finally, note that the $n = 8$ services used by FX_large correspond to using two-part composite services for the Technical analysis and Fundamental analysis operations from Fig. 5.

### 5.3 Evaluation Methodology

In line with the standard practice for evaluating the performance of stochastic optimisation algorithms [6], we performed multiple (i.e., 30) independent runs for each system variant from Table 6 and each multiobjective optimisation algorithm—NSGA-II, SPEA2, MOCell and random search. Each run comprised 10,000 evaluations, and the MOGAs used an initial population of 100 individuals, single-point crossover with probability $p_c = 0.9$, and single-point mutation with probability $p_m = 1/n_p$, where $n_p$ is the number of system variant parameters. All the experiments were run on a CentOS Linux 6.5 64bit server with two 2.6GHz Intel Xeon E5-2670 processors and 32GB of memory. The average run times for the six system variants are shown in Table 6.

Obtaining the actual Pareto front for our system variants is unfeasible because of their very large design spaces. Therefore, we adopted the established practice [63] of comparing the Pareto front approximations produced by each algorithm with the reference Pareto front comprising the non-dominated solutions from all the runs carried out for the analysed system variant. For this comparison, we employed the widely-used Pareto-front quality indicators below, and we will present their means and box plots as measures of central tendency and distribution, respectively:

1. **Unary additive epsilon ($I_1$)** [66], i.e., the minimum additive term by which the elements of the objective vectors from a Pareto front approximation must be adjusted in order to dominate the objective vectors from the reference front. This indicator presents convergence to the reference front and is Pareto compliant. Smaller $I_1$ values denote better Pareto front approximations.

2. **Hypervolume ($HV$)** [65], which measures the volume in the objective space covered by a Pareto front approximation with respect to the reference front (or a reference point). $HV$ measures both convergence and diversity, and is strictly Pareto compliant [62]. Larger $HV$ values denote better Pareto front approximations.

3. **Inverted Generational Distance ($IGD$)** [58], which provides an “error measure” as the Euclidean distance in the objective space between the reference front and the Pareto front approximation. $IGD$ shows both diversity and convergence to the reference front. Smaller $IGD$ values signify better Pareto front approximations.

We used inferential statistical tests to compare these quality indicators across the four algorithms [6, 38, 63]. As is typical of multiobjective optimisation [63], the Shapiro-Wilk test showed that the quality indicators were not normally distributed, so we used the Kruskal-Wallis non-parametric test with 95% confidence level ($\alpha = 0.05$) to analyse the results without making assumptions about the distribution of the data or the homogeneity of its variance. We also carried out a post-hoc analysis with pairwise comparisons between the four algorithms by means of Dunn’s pairwise test, controlling the family-wise error rate using the Bonferroni correction $p_{crit} = \alpha/k$, where $k$ is the number of comparisons.

---

**Table 5: QoS requirements for the FX system**

<table>
<thead>
<tr>
<th>ID</th>
<th>Description</th>
<th>Type</th>
</tr>
</thead>
<tbody>
<tr>
<td>R1</td>
<td>Workflow executions must complete successfully with probability at least 0.9</td>
<td>constraint</td>
</tr>
<tr>
<td>R2</td>
<td>The total service response time per workflow execution should be minimised</td>
<td>objective</td>
</tr>
<tr>
<td>R3</td>
<td>The probability of a service failure during a workflow execution should be minimised</td>
<td>objective</td>
</tr>
<tr>
<td>R4</td>
<td>The total cost of the third-party services used by a workflow execution should be minimised</td>
<td>objective</td>
</tr>
</tbody>
</table>

**Table 6: Analysed system variants; $T_{run}$ represents the EvoChecker running time averaged over 30 runs**

<table>
<thead>
<tr>
<th>Variant</th>
<th>Int-valued parameters</th>
<th>Size</th>
<th>$T_{run}$</th>
</tr>
</thead>
<tbody>
<tr>
<td>DPM_Small</td>
<td>$Q_{max}m \in {1,...,10}$</td>
<td>$m = 2$</td>
<td>2E+14</td>
</tr>
<tr>
<td>DPM_Medium</td>
<td>$Q_{max}m \in {1,...,15}$</td>
<td>$m = 2$</td>
<td>4.5E+14</td>
</tr>
<tr>
<td>DPM_Large</td>
<td>$Q_{max}m \in {1,...,20}$</td>
<td>$m = 2$</td>
<td>8E+14</td>
</tr>
<tr>
<td>FX_Small</td>
<td>$n = 4, n_1 = \cdots = n_4 = 3$</td>
<td></td>
<td>4.98E+31</td>
</tr>
<tr>
<td>FX_Medium</td>
<td>$n = 6, n_1 = \cdots = n_6 = 4$</td>
<td></td>
<td>1.39E+65</td>
</tr>
<tr>
<td>FX_Large</td>
<td>$n = 8, n_1 = \cdots = n_8 = 4$</td>
<td></td>
<td>7.22E+86</td>
</tr>
</tbody>
</table>

---

3Pareto compliant indicators do not “contradict” the order introduced by the Pareto dominance relation on Pareto front approximations [62].
Table 7: Mean quality indicator values for the system variants from Table 6

<table>
<thead>
<tr>
<th>Problem</th>
<th>NSGA-II</th>
<th>SPEA2</th>
<th>MOCell</th>
<th>Random</th>
</tr>
</thead>
<tbody>
<tr>
<td>DPM_Small</td>
<td>0.0209</td>
<td>0.0130</td>
<td>0.0242</td>
<td>0.1403</td>
</tr>
<tr>
<td>DPM_Medium</td>
<td>0.0225</td>
<td>0.0123</td>
<td>0.0489</td>
<td>0.1996</td>
</tr>
<tr>
<td>DPM_Large</td>
<td>0.0229</td>
<td>0.0147</td>
<td>0.0884</td>
<td>0.2497</td>
</tr>
</tbody>
</table>

\( I_\varepsilon \) (Epsilon)

<table>
<thead>
<tr>
<th>Problem</th>
<th>NSGA-II</th>
<th>SPEA2</th>
<th>MOCell</th>
<th>Random</th>
</tr>
</thead>
<tbody>
<tr>
<td>FX_Small</td>
<td>0.6258</td>
<td>0.5083</td>
<td>0.6745</td>
<td>2.2274</td>
</tr>
<tr>
<td>FX_Medium</td>
<td>1.6379</td>
<td>2.0105</td>
<td>2.0486</td>
<td>6.1529</td>
</tr>
<tr>
<td>FX_Large</td>
<td>3.6528</td>
<td>5.2777</td>
<td>4.6366</td>
<td>13.0234</td>
</tr>
</tbody>
</table>

\( I_{HV} \) (Hypervolume)

<table>
<thead>
<tr>
<th>Problem</th>
<th>NSGA-II</th>
<th>SPEA2</th>
<th>MOCell</th>
<th>Random</th>
</tr>
</thead>
<tbody>
<tr>
<td>DPM_Small</td>
<td>0.4455</td>
<td>0.4458</td>
<td>0.4396</td>
<td>0.4022</td>
</tr>
<tr>
<td>DPM_Medium</td>
<td>0.4487</td>
<td>0.4499</td>
<td>0.4386</td>
<td>0.3946</td>
</tr>
<tr>
<td>DPM_Large</td>
<td>0.4528</td>
<td>0.4549</td>
<td>0.4395</td>
<td>0.3947</td>
</tr>
</tbody>
</table>

\( I_{IGD} \) (Inverted Generational Distance)

<table>
<thead>
<tr>
<th>Problem</th>
<th>NSGA-II</th>
<th>SPEA2</th>
<th>MOCell</th>
<th>Random</th>
</tr>
</thead>
<tbody>
<tr>
<td>DPM_Small</td>
<td>0.00023</td>
<td>0.00018</td>
<td>0.00016</td>
<td>0.00062</td>
</tr>
<tr>
<td>DPM_Medium</td>
<td>0.00024</td>
<td>0.00019</td>
<td>0.00028</td>
<td>0.00091</td>
</tr>
<tr>
<td>DPM_Large</td>
<td>0.00024</td>
<td>0.00020</td>
<td>0.00038</td>
<td>0.00109</td>
</tr>
</tbody>
</table>

Figure 6: Boxplots for the six system variants from Table 6, evaluated using the quality indicators \( I_\varepsilon, I_{HV} \) and \( I_{IGD} \)

5.4 Results and Discussion

RQ1 (Validation). To answer the first research question, we carried out the experiments described in the previous section. The results are reported in Table 7 and Fig. 6. The ‘+’ from the last column of the table entries indicate that the Kruskal-Wallis test showed significant difference among the four algorithms (p-value < 0.05) for all six system variants and all Pareto-front quality indicators.

For both systems, EvoChecker with any MOGA achieved considerably better results than random search, for all quality indicators and system variants. The post hoc analysis of pairwise comparisons between random search and the MOGAs provided statistical evidence about the superiority of the MOGAs for all system variants and for all quality indicators. The best and, when obtained, the second best outcomes of this analysis per system variant and quality indicator are shaded and lightly shaded in the result tables, respectively. This superiority of the results obtained using EvoChecker with any of the MOGAs over those produced by random search can also be seen from the boxplots in Fig. 6.

We qualitatively support our findings by presenting in Fig. 7 the Pareto front approximations achieved by EvoChecker with each of the MOGAs and by random search, for a typical run of the experiment for the FX system variants. We observe that irrespective of the MOGA, EvoChecker achieves Pareto front approximations with more, better spread and higher quality non-dominated solutions than random search.

As explained in Section 2, the parameters we used for the DPM system variants (power usage, transition rates, etc.) correspond to the real-world system. In contrast, for the FX system variants we chose realistic values for the reliability, performance and cost of the third-party services. To mitigate the risk of accidentally choosing values that biased the EvoChecker evaluation, we performed additional experiments comprising 300 independent runs per FX system variant (900 runs in total) in which these parameters were randomly instantiated. The results of this further analysis (reported on our project webpage but not included here due to space constraints) confirm the findings presented above.

All these results provide strong empirical evidence that the EvoChecker significantly outperforms random search, for a range of system variants from two different domains, and across multiple widely-used MOGAs. This also confirms the challenging and well-formulated nature of the probabilistic model synthesis problem we introduced in Section 3.3.
**RQ2 (Comparison).** To compare EvoChecker instances based on different MOGAs, we first observe in Table 7 that NSGA-II and SPEA2 outperformed MOCell for all system variant–quality indicator combinations except DPM–Small–$I_{IGD}$. Between SPEA2 and NSGA-II, the former achieved slightly better results for the smaller design spaces of the DPM system variants (across all indicators) and for the $I_{HV}$ indicator (across all system variants), whereas NSGA-II yielded Pareto-front approximations with better $I_c$ and $I_{IGD}$ indicators for the larger design spaces of the FX system variants (except the combination FX–small–$I_c$).

Additionally, we carried out the post-hoc analysis described in Section 5.3, for 9 system variants (counting separately the FX system variants with chosen parameters and with randomly instantiated parameters) × 3 quality indicators = 27 tests. Out of these tests, 22 tests (i.e., a percentage of 81.4%) showed high statistical significance in the differences between the performance achieved by EvoChecker with different MOGAs (Table 8). The five system variant–quality indicator combinations for which the tests were unsuccessful are: FX–Medium–$I_c$, FX(random)–Small–$I_c$, FX(random)–Medium–$I_c$, FX–Small–$I_{IGD}$ and FX–Medium–$I_{IGD}$.

These results show that, like for any well-formulated optimisation problem, different algorithms are more suitable in dealing with specific problems. They also confirm the generality of EvoChecker, showing that its functionality can be realised using multiple established MOGAs.

**RQ3 (Insights).** We performed qualitative analyses of the Pareto front approximations produced by EvoChecker, with the purpose of identifying actionable insights. We illustrate this for the FX and DPM Pareto front approximations from Fig. 7 and Fig. 4, respectively. First, the EvoChecker results enable the identification of the “point of diminishing returns” for each system variant. The results from Fig. 7 show that design options with costs above approximately 52 for FX–Small, 61 for FX–Medium and 94 for FX–Large provide only marginal response time and reliability improvements over the best designs achievable for these costs. Likewise, the results in Fig. 4 show that DPM designs with power use above 1.7W yield insignificant reductions in the number of lost requests, whereas designs with even slightly lower power use lead to much higher request loss. This key information helps designers avoid unnecessarily expensive solutions.

Second, we note the high density of design solutions in the areas with low reliability (below 0.95) for the FX system in Fig. 7, and with high request loss (above 0.09) for the DPM system in Fig. 4. For the FX system, for instance, these correspond to the use of the probabilistic service selection strategy, for which numerous service combinations can achieve similar reliability and response time with relatively low, comparable costs. Opting for a design from this area will make the FX system susceptible to failures, as when the only service invoked for an FX operation fails, the entire workflow execution will fail. In contrast, reliability values above 0.995 correspond to high-cost designs that use the sequential service selection strategy, e.g., FX–small must use the sequential strategy for the Market watch and Fundamental analysis services in order to achieve 0.996 reliability.

Third, the EvoChecker results reveal design parameters that QoS properties are particularly sensitive to. For the FX system, for example, we noticed a strong dependency of the workflow reliability on the service selection strategy and the number of services used for each operation. Designs from high-reliability areas of the Pareto front not only use the sequential selection strategy, but also require multiple services per FX operation (e.g., three FX service providers are needed for success rates above 0.99).

Finally, we note EvoChecker’s ability to produce solutions that: (a) cover a wide range of values for the QoS attributes from the optimisation objectives of the FX and DPM systems; and (b) include alternatives with different trade-offs for fixed values of one of these attributes. Thus, for 0.99 reliability, the experiment from Fig. 7 generated four alternative FX–Large designs, each with a different cost and execution time. Similar observations can be made for a specific value of either of the other two QoS attributes. These results support the system designers in their decision making.
5.5 Threats to Validity

Construct validity threats may be due to the simplifications and assumptions we made when modelling the DPM and FX systems. To mitigate this threat, the DPM system, model and requirements are based on a validated real-world case study taken from the literature [53, 56], which we were familiar with from our previous work [19]. For the FX system, the model and requirements were developed in close collaboration with a foreign exchange domain expert.

Internal validity threats can originate from the stochastic nature of the optimisation algorithms employed in our study. To mitigate these threats, we adopted the recommended practice for empirical studies in this research area [6, 38]. In particular, we reported results over 30 repeated runs of each experiment, and employed statistical tests to check for significance in the achieved results. Thus, we used the Shapiro-Wilk test to assess the normality of data, and the Kruskall-Wallis and Dunn pairwise non-parametric tests to check for statistical significance between the considered optimisation algorithms. Finally, we set the chance of committing a Type I error (a confidence limit) at 0.05, which is the standard value recommended for these studies.

External validity threats might be due to the difficulty of representing a software system and its QoS requirements as a probabilistic model synthesis problem (Section 3.3) using EvoChecker constructs (2)–(4), constraints (5) and optimisation objectives (6). We limit this threat by specifying EvoChecker probabilistic model templates in an extended version of the high-level modelling language of PRISM [45], a widely-used probabilistic model checker [50]. Moreover, given the generality of the EvoChecker constructs (2)–(4), other probabilistic modelling languages (e.g., those of the model checkers MRMC [40, 41] and Ymer [60]) can be naturally supported. Additionally, EvoChecker supports a wide range of probabilistic models and temporal logics (Table 1). Finally, to further reduce the risk that EvoChecker might be difficult to use in practice, we validated it through application to several variants of two realistic software systems with diverse characteristics in terms of application domain, size, complexity and requirements. Nevertheless, we are aware that our findings are by no means conclusive for all types of software systems, and more experiments are required to confirm the generality of the EvoChecker approach and tool.

6. RELATED WORK

Search-based software engineering (SBSE) [38] has been successfully used in areas ranging from project management [29, 54, 57] and testing [5, 32, 36] to effort estimation [48], software repair and evolution [20, 52] and software product lines [35, 55]. However, as reported in Harman et al.’s recent SBSE survey [37], this success does not yet extend to model checking. The only SBSE applications that we are aware of in this area are the approaches in [39, 42], which employ genetic evolution to synthesise model checking specifications, and the work in [1, 2], which uses ant colony optimisation to find counterexamples for large model checking problems.

To the best of our knowledge, EvoChecker is the first SBSE approach to synthesising Pareto-optimal sets of probabilistic models for QoS software engineering. As mentioned in Section 1, the only related work we are aware of belongs to the area of model repair [16, 61]. Unlike EvoChecker, most model repair research so far has focused on non-probabilistic models [15, 16, 21, 22, 47]. Also different from EvoChecker, these approaches support a single type of model, and target its “repair” with respect to a single temporal logic property.

In the probabilistic model checking domain, model repair involves automatically modifying the transition probabilities of a model that violates a formally-specified property in order to obtain a new model that satisfies the property and is “close” to the original model [10, 11, 23]. As probabilistic model repair modifies the original model only at transition probability level, and only to satisfy a single temporal logic property, its applicability is limited. In contrast, EvoChecker handles multiple QoS requirements and uses multiobjective optimisation to derive a set of probabilistic models that approximates the Pareto-optimal model set associated with these QoS requirements. To confirm that EvoChecker subsumes the capabilities of probabilistic model repair, we used our EvoChecker tool to successfully replicate the results of the IPv4 Zeroconf Protocol [10] and Network Virus Infection [23] case studies. We did not include these additional experiments in the paper due to space constraints, but we make the results available on our project webpage.

Finally, [31] synthesises Pareto front approximations over the policies of Markov decision processes (MDPs). However, its applicability is limited to fully specified MDPs, to a subset of probabilistic computation tree logic (i.e., reachability and expected total reward formulae), and to the finite search spaces that can be encoded as MDP policies. In contrast, EvoChecker fully supports all types of models and logics from Table 1, and solves a more general problem by starting from incompletely specified probabilistic model templates with potentially infinite search spaces (due to evolvable double parameters and distributions). Moreover, the implementation in [31] currently supports only up to 3 optimisation objectives, while EvoChecker does not have this limitation.

7. CONCLUSION

We defined the probabilistic model synthesis problem, and introduced EvoChecker, the first tool-supported search-based approach that tackles this problem with a focus on QoS software engineering. EvoChecker uses multiobjective optimisation genetic algorithms to automate the synthesis of approximate Pareto-optimal probabilistic model sets associated with the QoS requirements of a software system. We evaluated the EvoChecker approach and tool within two case studies from different domains, showing its effectiveness, potential applicability and flexibility. The limitations of our evaluation are discussed in Section 5.5.

The future research directions for our project include extending the applicability of EvoChecker to other modelling formalisms and verification logics by exploiting established quantitative model checkers such as UPAAL [12], exploring alternative multiobjective optimisation genetic algorithms to automate the synthesis of approximate Pareto-optimal probabilistic model sets associated with the QoS requirements of a software system. We evaluated the EvoChecker approach and tool within two case studies from different domains, showing its effectiveness, potential applicability and flexibility. The limitations of our evaluation are discussed in Section 5.5.

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Acknowledgements

This paper presents research sponsored by UK MOD. The information contained in it should not be interpreted as representing the views of the UK MOD, nor should it be assumed it reflects any current or future UK MOD policy.
8. REFERENCES


