This is the manual for the *RoboChart* tool. It describes the requirements, installation process and usage of the tool.
Chapter 1

Requirements

- Linux – Certain aspects of eclipse seems to work differently in Windows, Linux and macOS. While our plugins will work on any platform that has an Eclipse distribution, we will focus our efforts on fixing bugs that occur on Linux.

- Eclipse 2020-03 or greater – [https://www.eclipse.org/](https://www.eclipse.org/).

- Java Runtime Environment – Recommended to use Java 11 or above. If using the Eclipse Installer, a JRE can be installed if one is not already installed.


### Installation

1. Download Eclipse 2020-03 or greater (https://www.eclipse.org/) and install it. You can choose the Eclipse IDE for Java Developers package from https://www.eclipse.org/downloads/packages/. Recent versions of Eclipse can also be installed using the Eclipse Installer, that bundles a Java Runtime Environment. At the time of writing, Java 11 is recommended. Further instructions are available at https://wiki.eclipse.org/Eclipse/Installation regarding installation of Eclipse;

2. Select Help > Install New Software...;

3. Type https://robostar.cs.york.ac.uk/robotool/update in the Work with textbox and press Enter;

4. Select the plugins to suit your needs. If in doubt, you can install all available plugins. Currently, the following plugins are available, grouped by category as:

   - **RoboChart:**
     - RoboChart Assertions for writing properties over RoboChart models for analysis using FDR and PRISM;
     - RoboChart Graphical Editor is needed if you use the graphical notation of RoboChart;
     - RoboChart Metamodel and RoboChart Textual Editor are essential for working with RoboChart models;

   - **RoboChart Generator:**
     - RoboChart CSP Generator for verification of RoboChart models using FDR;
     - RoboChart PRISM Generator for verification of RoboChart models using PRISM. Please note that the PRISM Metamodel plug-in under the category PRISM must also be installed;

   - **RoboChart Extras:**
- **RoboChart CSP Semantics Comparison** essential for mutation testing with Wodel;
- **RoboChart Model Exporter** and **RoboChart Model Importer** are also required for interfacing with Wodel;

- **RoboSim**:
  - **RoboSim Assertions** for writing properties over RoboSim models for analysis using FDR;
  - **RoboSim Graphical Editor** is needed if you use the graphical notation of RoboSim;
  - **RoboSim Metamodel** and **RoboSim Textual Editor** are essential for working with RoboSim models;

- **RoboSim Generator**:
  - **RoboSim CSP Generator** is required for analysis of RoboSim models with FDR;

- **RoboSim Physical Modelling**:
  - **Physical Modelling Graphical Editor** is required if you use the graphical RoboSim language for modelling physical platforms;
  - **Physical Modelling Metamodel** and **Physical Modelling Textual Editor** are essential if using the physical modelling language of RoboSim;

- **RoboSim Physical Modelling Generator**:
  - **PhysMod CyPhyCircus Generator** allows generating CyPhyCircus models from RoboSim models;
  - **PhysMod SDF Generator** allows generating SDF models from physical RoboSim models;

5. Click **Next**;

6. Click **Next**;

7. Accept the license and click **Finish**;

8. A security warning will appear; click the **OK** button if you wish to continue with installation;

9. Once the plugins are installed, a popup box will appear requesting Eclipse to be restarted. Click **Yes**.
10. Verify your installation by:
   
a) Click the **Help** > **About Eclipse** menu item;

   b) Click the **Installation Details**;

   c) Look for **RoboChart Feature** in the list of Installed Software;

   d) Click the arrow to the left of **RoboChart Feature**;

   e) The **RoboChart Feature** should contain four sub-items: Sirius Core Runtime, Sirius Runtime IDE, Sirius Runtime Support AQL, and Sirius Specifier Environment.

11. For verification with PRISM, an additional plugin Epsilon is needed.
   
a) Select **Help > Install New Software...**;

   b) Type `https://download.eclipse.org/epsilon/updates` in the **Work with** textbox and press **Enter**;

   c) Select “Epsilon Core”, “Epsilon Core Development Tools”, and “Epsilon Development Tools for EMF” under “Epsilon EMF Integration”;

   d) Click **Next**;

   e) Click **Next**;

   f) Accept the license and click **Finish**;

   g) A security warning will appear; click the **OK** button if you wish to continue with installation;

   h) Once the plugins are installed, a popup box will appear requesting Eclipse to be restarted. Click **Yes**.

12. You are done. If you have any problems with the installation or usage, check for an associated issue or create a new issue on [https://github.com/UoY-RoboStar/robochart-textual](https://github.com/UoY-RoboStar/robochart-textual)
2.1 Updating the tool

In order to update the tool, there are a few alternative ways:

1. Click \texttt{Help} \texttt{Check for Updates}

2. If there are updates available, the installed features will be available; select them and click 
\texttt{Next} twice

3. Accept the license agreement, and click \texttt{Finish}

4. A security warning will appear; click the \texttt{OK} button if you wish to continue with
installation;

5. Once the plugins are installed, a popup box will appear requesting Eclipse to be restarted.
Click \texttt{Yes}.

While convenient, the \texttt{Check for Updates} features looks for all updates, not just RoboChart
updates, and it can take longer. Additionally, it may lead to accidental updates. If you want to
update only the RoboChart tool, follow these steps:

1. Click \texttt{Help} \texttt{About Eclipse}

2. Click the button \texttt{Installation Details}

3. In the \texttt{Installed Software} tab, find the installed features and select one of them;

4. Click the button \texttt{Update...}. This will search for updates specific to the selected feature;

5. If an update is found, a details page will be shown, click \texttt{Next};

6. Accept the license agreement, and click \texttt{Finish};

7. A security warning will appear; click the \texttt{OK} button if you wish to continue with
installation;

8. Once the plugins are installed, a popup box will appear requesting Eclipse to be restarted.
Click \texttt{Yes}. 
Chapter 3

RoboChart: usage


A RoboChart specification is a collection of named or anonymous packages (RCPackage in the abstract syntax). In the tool, we associate a RoboChart specification with a Modeling project, and a package with a file with the extension rct. An rct file records information about the elements defined in a package, but not how they are represented graphically. Packages recorded as rct files can be visualised and edited through a graphical editor. These diagrams are recorded in an aird file. For this reason, we first create a rct file, and then create a diagram to represent that file. Note that it is possible to have multiple graphical representations of the same package.

The next section describes how to create a project (i.e., RoboChart specification), and the following section describes how to create new rct files (i.e., RoboChart packages).

3.1 Creating a new project

1. Select Modeling perspective, if it is not yet selected:
   
a) Click the `Window > Perspective > Open Perspective > Other...` menu item;

b) Select the item `Modeling` from the list; and

   c) Click `OK`. The `Modeling` perspective is divided in four main parts:

   i. `Model Explorer` – top left corner

   ii. `Outline` – bottom left corner


2. Create a new Modeling project
   
a) Right click the Model Explorer window and select New Project; alternatively, in
the menu click File > New > Project.

b) Either type Modeling in the wizard text box, or open the Sirius folder;

c) Select the item Modeling Project and click Next;

d) Type the project name and click Finish.

3. In order to browse the contents of the project click the arrow to the left of the project
name in the Model Explorer; the new project will contain two initial components:

   a) Project Dependencies – This can be used to add references to external packages,
but I have not used it;

   b) representations.aird – This file stores the graphical representation of all the dia-
grams.

3.2 Creating a new RoboChart package

A project can have several packages (.rct files). Here, we describe how to create a package
inside a project.

1. Select the project in which you wish to create a new package;

2. Press Ctrl+N and select General File; or right click the project and select New > File;
or in the menu click File > New > File;

3. Type the name of the file with extension .rct and press Finish;

4. The first time you create a package in a new project, a popup will appear asking to
convert the project into an Xtext project. This is necessary, so click Yes;
5. The first time you create a package in a new project, right click the project and select **Viewpoint Selection**. A popup window will appear with an item *RoboChart*; tick this item and click **OK**.

6. In order to open a diagram follow the following steps:

   a) Click the arrow to the left of the name of the *rcf* file; there should be a subitem **ROCPackage** under the file name.

      i. If there is no arrow to the left of **ROCPackage**, or no subitem of type diagram (marked by the icon), right click **ROCPackage** and click **New Representation**. Finally, click **OK** (this creates a new diagram associated with the *rcf* file);

      ii. If there is already a diagram under **ROCPackage**, do nothing.

   b) Finally, double click a diagram (identified by the icon ) to open it.

An alternative, more automated way of creating a RoboChart involves the use of the RoboChart Wizard. Notice that this is a newer feature and more prone to errors, so if it fails, try the steps above.

1. Select the project in which you wish to create a new package;

2. Press Ctrl+N, or right click the project and select **New Other...**; or in the menu click **File** > **New** > **Other...**;

3. Type *RoboChart* in the wizard text box, or find the RoboChart folder and open it;

4. Select the item **New RoboChart Package** and click **Next**;

5. Change the file name (it must end in .rct) and click **Finish**;

6. The first time you create a package in a new project, a popup will appear asking to convert the project into an Xtext project. This is necessary, so click **Yes**;

7. The wizard will create the *rcf* file, select the appropriate viewpoint, create the diagram and open it automatically.

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1Sirius does not seem to behave consistently when creating a new file, sometimes it creates the diagram automatically, other times it does not.

2If you wish, you can change the name.
3.3 Deleting a RoboChart package

Since a RoboChart package is associated with an rct file and a diagram (in the aird file), we need to delete both the rct file and the diagram:

1. In order to delete a RoboChart package, that is, the rct file and the associated diagrams:
   a) Select the file, press [Delete] (or select delete on the context menu) and click [OK];
   b) Click the left arrows on the file representations.aird, the subitem RoboChart and the subitem Package. The names of the diagrams associated with the deleted file will be in a lighter font. Select them, press delete (or right-click and click [Delete]) and confirm the deletion by clicking [OK].

3.4 Editing a RoboChart diagram

1. Use the palette to the right to select objects to add to the diagram. For most objects (except connection) you can either drag and drop the object to the diagram, or select and click (if you keep [Ctrl] pressed, it is possible to click multiple times on the diagram to create multiple instances of the object). After creating a new component (e.g., type), make sure to save the diagram (press [Ctrl]+[S] or click [File] > [Save]) to guarantee the newly created element can be used.

Notice that the palette may not show all tools depending on the size of the screen. It is divided into category boxes that group similar tools. In order to explore the available tools you can click a category box to close it, and click once more to fully expand it. It is also possible to use the arrows at the bottom and top of the category box (or the scroll wheel on your mouse) to scroll through the available tools. If you are familiar with the icons, it is possible to reduce the space taken by the tools by removing the text and showing only the icons. To do this, right click the palette and select [Layout] > [Icons Only].

3 We must delete the diagram associated with the RoboChart package, not the whole aird file.
2. To use connections, select the appropriate connection tool (e.g., transition), click the source node and then the target node

3. To change labels (e.g., interface names, transition labels) there are a few options:
   a) Select the item and start typing. This option will delete the original text; to avoid this use one of the next two options; or
   b) Press F2 and the text will become editable; or
   c) Click once over the text and it will become editable.

<table>
<thead>
<tr>
<th>Label editing has some limitations that are worth mentioning:</th>
</tr>
</thead>
<tbody>
<tr>
<td>a) Not all labels editors are implemented yet (if you think label editing for a specific feature is missing, create an issue in the bitbucket issue tracker);</td>
</tr>
<tr>
<td>b) If you type a label with syntax errors, the edit will fail and the previous text will show (potentially empty text). transitions, the failure text will be stored internally and shown again if you press F2 or click the label (you can then fix the error directly instead of retyping the whole text again).</td>
</tr>
</tbody>
</table>

4. Most textual elements (variable declarations, operations, actions etc) are input through a pop-up window that provides a hint of the syntax and parses the input before creating the element. For example, when creating a new action in a state:
   a) a pop-up windows will appear requesting the text of the action in the format [(entry|exit|during) Action], that is, one of the keyword entry, exit or during followed by an action:
      i. if you only type entry, for instance, the box will show Cannot parse below the text box and keep the button OK disabled
      ii. if, on the other hand, you type entry skip, the tool parses the action correctly and enables the OK button. If you click OK the action will be added to the state.

5. To save a diagram, press Ctrl+S or click File > Save.

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While you can use Ctrl+Z to undo changes to the diagram, it can create inconsistencies, so use it carefully.

See the language reference manual for the concrete syntax of actions and other elements.
3.5 Deleting element from diagrams

To delete an object from the diagram, select it and press \texttt{delete}; avoid using the option \texttt{Right-click} as it can make the diagram inconsistent.

Be careful when deleting elements:

1. In general, make sure they are not used elsewhere. For example, when deleting an event used as the trigger of a transition, the transition will point to a non-existent event; make sure to remove the reference first;

2. We have implemented controlled deletions for Interfaces and Types, but not for other elements:\footnote{If and when I implement more cases, I’ll add them to this manual.}

   a) When deleting an interface, the tool will delete all required and provided references and try to replace call to the operations in the interface by other operations of the same name in scope; if this is not possible, operation calls are converted into \texttt{skip}

   b) When deleting a type, the tool will look for uses of that type, if none are found, the type is deleted. Otherwise, a list of types is offered to the user to replace the deleted type.

3.6 Exporting diagrams as figures

It is possible to export the diagrams as figure:\footnote{The available formats are JPG, PNG, SVG, BMP and GIF. Exporting SVG will also generate a PDF equivalent.}

To export all the diagrams at the same time:

1. Click the arrow to the left of the file \texttt{representations.aird} to expand it.

2. Expand the items \texttt{RoboChart} and \texttt{Package}.

3. Use \texttt{Ctrl + left click} to select multiple diagrams

4. Right click the selection and click \texttt{Export representations as images}
5. A popup window will appear allowing you to select the target directory and the image format; after selecting the directory and the format, click [OK].

To export a specific diagram, follow these steps:

1. Open the diagram (if it not already open)
2. If any diagram elements are selected, deselect them by pressing [Esc] or clicking in the background of the diagram
3. The toolbar at the top of the diagram contains a camera icon [ affluent ]; click it
4. A popup window will appear allowing you to select the target file and the image format; after selecting the file and the format, click [OK].

If you right click representation.aird, an option [ Export representations as images ] is available. While this option works and generates images for all diagrams, it may have a side effect of closing all open diagrams, and making the project tree inconsistent. In this case, collapse the project by clicking the arrow to the left of the project name, and expand it again. This should refresh the project and offer to reopen the diagrams.

### 3.7 Exporting projects

Since the tool is under development, it is advisable to not only frequently save your specifications, but also export them as compressed files. To do that follow these steps:

1. Right-click the project in the Model Explorer and click [ Export ]
3. Give a name to the compressed file (or select an existing file using the [ Browse ] button) and click [ Finish ]
3.8 Importing projects

To import a RoboChart specification into eclipse:

1. Right-click the Model Explorer and click **[Import]** (alternatively, click **[File]** > **[Import]**)
2. Select **[General]** > **Existing Projects into Workspace** and press **Next**
3. Choose the option **[Select archive file]** and press the button **[Browse]**
4. Find the compressed file (zip or tar file) that contains the specification and press **[OK]**
5. The project should be selected in the window below. In this case, click **[Finish]**. If the project is not selected in the window, it is because a project with the same name already exists in the workspace; either delete the project or rename it before trying to import again.

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*This should have been exported as described in the previous section*
Chapter 4

RoboSim: usage

Similarly to RoboChart, the RoboSim plugins are also based on the Sirius framework. This chapter discusses specifics of working with RoboSim models.

A RoboSim specification is a collection of named or anonymous packages (also RCPackages in the abstract syntax). Importantly, RoboSim packages are contained in files with the extension .rst. Such files record information about the elements defined in the package, but not how they are represented graphically. Diagrams are recorded in a unique .aird file per project. A project may contain both RoboChart and RoboSim packages and diagrams. This is crucial, for example, to verify that a RoboSim simulation is correct with respect to a RoboChart model, as explained later in Section 5.4.

The following sections discuss how to use RoboSim packages. They are similar in nature to RoboChart packages, so their usage is similar to that described in Chapter 3. Here, we focus on aspects that are specific to RoboSim packages.

4.1 Creating a new RoboSim package

A project can have several packages (.rst files). Here, we describe how to create a RoboSim package inside a project.

1. Select the project in which you wish to create a new package;

2. Press Ctrl+N and select [General] File; or right click the project and select [New] File; or in the menu click [File] New File;

Sirius has an experimental mode that allows each diagram to be saved in separate files within a folder named .representations. This can be enabled by setting the system property createLocalRepresentationInSeparateResource to true, for example, by passing it as a parameter to the Java VM as -DcreateLocalRepresentationInSeparateResource=true. For further details see https://www.eclipse.org/sirius/doc/6.0.x/developer/representations_lazy_loading.html
3. Type the name of the file with extension .rst and press Finish;

4. The first time you create a package in a new project, a popup will appear asking to convert the project into an Xtext project. This is necessary, so click Yes;

5. The first time you create a package in a new project, right click the project and select Viewpoint Selection. A popup window will appear with an item RoboSim; tick this item and click OK;

6. In order to open a diagram follow the following steps:
   a) Click the arrow to the left of the name of the rst file; there should be a subitem RCPackage under the file name;
      i. If there is no arrow to the left of RCPackage, or no subitem of type diagram (marked by the icon ), right click RCPackage and click New Representation\{name}\, where \{name\} is the name of the file without the extension. Finally, click OK (this creates a new diagram associated with the rst file);
      ii. If there is already a diagram under RCPackage, do nothing.
   b) Finally, double click a diagram (identified by the icon ) to open it.

4.2 Deleting a RoboSim package

Since a RoboSim package is associated with an rst file and a diagram (in the aird file), we need to delete both the rst file and the diagram.

1. In order to delete a RoboChart package, that is, the rst file and the associated diagrams:
   a) Select the file, press Delete (or select delete on the context menu) and click OK;
   b) Click the left arrows on the file representation.aird, the subitem RoboSim and the subitem RCPackage. The names of the diagrams associated with the deleted file will be in a lighter font. Select them, press delete (or right-click and click Delete) and confirm the deletion by clicking OK.

\footnote{If you wish, you can change the name.}
\footnote{We must delete the diagram associated with the RoboSim package, not the whole aird file.}
RoboTool provides facilities for running the CSP model checker – FDR – on user specified assertions directly via the tool. Currently, both RoboChart and RoboSim models can be analysed using FDR. Provided there are no errors, RoboTool automatically calculates and stores under the csp-gen folder the definition of the semantics using CSP_m, the machine-readable version of CSP accepted by FDR. This consists of files with the extension csp organised according to the tree structure outlined in Figure 5.1a.

RoboChart and RoboSim models can span one or more packages, defined in model files with extensions rct and rst, respectively. For each such file, a corresponding .csp file is generated by RoboTool under the directory csp-gen: if a file defines a package named P, then the generated file is named P.csp, and otherwise it takes the name of the .rct, or .rst, file concatenated after a prefix file_. At the root of csp-gen we have an untimed CSP semantics for RoboChart models, with auxiliary .csp files contained within the subfolder defs. A timed semantics for RoboChart models, defined using tock-CSP is contained within the subfolder csp-gen\timed, that is structured similarly to csp-gen. Likewise, the tock-CSP semantics of RoboSim models is contained within the subfolder csp-gen\sim.

Within RoboTool, the actual filesystem structure can be seen, for example, using the Project Explorer view. In Figure 5.1b we reproduce this view for an example, where a subset of the generated .csp files is visible.

The remaining sections of this chapter are structured as follows. Section 5.1 discusses how to use and adapt the generated semantics for verification. Section 5.2 discusses how to open FDR from within Eclipse. Section 5.3 describes the language used to specify assertions, and Section 5.5 describes the steps to run FDR from inside RoboTool.
RoboTool automatically generates the CSP\textsubscript{M} semantics of each construct of a model, provided there are no errors concerning that construct, namely that all relevant well-formedness conditions are satisfied. The well-formedness conditions for RoboChart models are listed in \cite[Chapter 3]{2}, while those for RoboSim models are listed in \cite[Chapter 3]{1}. Additionally, it generates an `instantiations.csp` file and `coreassertions.csp` files for each model file.

These files use a special annotation to indicate which parts of the file can be re-generated. They have annotations of the form `-- generate ID`, where ID is any identifier, followed by excerpts of CSP. The specification under the comment will be regenerated every time the model is saved. If you do not want the specification under the comment to be re-generated, add a `not` after the identifier (`-- generate ID not`). This will cause the generator to ignore that part of the specification.

The instantiations file provides default values for constants, functions and bounds, and the assertions file provide default assertion checks where relevant. Use these files and the annotations above to add your own assertions and values without losing them on re-generation.
5.1.1 RoboChart semantics: CSPₘ conventions

The CSPₘ semantics of RoboChart components is structured using modules named after model elements, and nested according to the hierarchy of a RoboChart model. For example, the semantics of a Module M is defined by a parametrised process $D__(id, c₁, \ldots, cᵢ)$ in a CSPₘ module named $M$, that can be referred to using the syntax $M::D__(id, c₁, \ldots, cᵢ)$, where :: is a delimiter and:

- $id$ is an identifier (used in a semantics for collections []). It can be set to a default of $\emptyset$ when instantiating the process for analysis;
- $c₁$ to $cᵢ$ are constants used by $M$.

Effectively, in CSPₘ $D__(id, c₁, \ldots, cᵢ)$ is a function that yields a complete CSP process. Within the CSPₘ module $M$, there are declarations for all channels used in the semantics of that module. For example, the RoboChart event obstacle in a module $M$ is modelled as a channel $obstacle$ within $M$ and can be referred using the notation $M::obstacle$. Events may be typed, so a corresponding CSPₘ channel is typed accordingly as $event.InOut.type$, where the possible values of $InOut$ are $in$ to refer to an input event, or $out$ for output events, and $type$ is the actual event type modelled in CSPₘ.

Similarly, a Controller $C$ defined in a module $M$ is defined in a nested CSPₘ module of $M$. Its full name is $M::C$, and its semantics is given by a $M::C::D__(\ldots)$ process. Likewise, the same convention applies for state machines within Controllers.

In addition, for each $D__$ process there is a similar $O__$ process with the same parameters, that employs compression functions to reduce the state space for model-checking with FDR. A special process $AS_O__$ also exists in the semantics of Modules that allows writes to platform variables to be observed for the purpose of specialised analysis. We observe that these conventions are subject to change, and that specialised processes may be withdrawn in the future.

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1 See [https://cocotec.io/fdr/manual/cspm/definitions.html#modules]
5.2 Opening FDR directly from Eclipse

The semantics of the RoboChart and RoboSim models is generated automatically in the csp-gen folder as a collection of .csp files, as previously described. Each file at the root folder csp-gen (or csp-gen\timed in the case of the tock-CSP semantics, and csp-gen\sim for the semantics of RoboSim) is self-contained and can be opened in FDR to perform analysis and simulation. The actual definitions of the elements of the model can be found in the files in the folder defs.

It is possible to open the .csp files directly from the Model Explorer.

If you installed FDR on Ubuntu, it is possible that FDR is the default program for .csp files. In this case, it may be possible to open the file in FDR by double clicking the file. If, instead of FDR, the file is open in Eclipse, right-click the .csp file, select Open with System Editor.

If FDR is not the default program for .csp files, you can add it to the list of editors in Eclipse as follows:

1. Right-click a .csp file and select Open with Other
2. Click Browse..., find the fdr4 executable and click OK
3. Select External programs, and check both boxes below the Browse... button
4. Click OK

Once you follow these steps, every time you double click a .csp file in Eclipse, FDR should open. If you want to open the .csp file in a text editor, right-click the file, and select Open with Text Editor. To open the file in FDR again, right-click the file, and select Open with fdr4.

5.3 RoboChart assertions language

RoboTool provides a textual editor to support the specification of assertions, regarding RoboChart models, in files with extension .assertions.

5.3.1 Assertions

An assertion is specified as follows:
assertion = (untimed | timed)? assertion NAME : specification (in the CSP Model)? (with parameters)? (.)?

specification =
   ELEMENT is (not)?
      (deadlock-free | divergence-free | deterministic | timelock-free) |
   ELEMENT (does not terminate | terminates) |
   STATE is (not)? reachable in ELEMENT |
   ELEMENT (refines | equals | does not refine | is not equal to) ELEMENT |
   clock CLOCK is (not)? initialised

CSP Model = failures divergences model | traces model | failures model | tick-tock model

parameters = AssertionParameter (, AssertionParameter)° (, and AssertionParameter)?

AssertionParameter = constant | parameter

constant = constant NAME of NAME (assigned | set to | with value) Expression

parameter = parameter NAME of NAME (assigned | set to | with value) Expression

In the description above, NAME is any valid identifier, ELEMENT is the name of any state machine, controller, module or collection, STATE is any state in a state machine, and CLOCK is any clock name. Below is an example of an assertion:

```
assertion A1: LMachine is deadlock-free with constant
   SET_SPACE_TIME of LMachine set to 1,
   SET_SPACE_BOUND of LMachine set to 1,
   CHANGE_LANE_TIME of LMachine set to 1,
   CHANGE_LANE_BOUND of LMachine set to 1,
   JOIN_DISTANCE_TIME of LMachine set to 1,
   JOIN_DISTANCE_BOUNDS of LMachine set to 1,
   and maxPL of LMachine with value 3
```

While it is not necessary to specify all required or defined constants in an assertion, the tool will give a warning indicating which constants are missing.

The value of unspecified constants is either a default value for the type of the constant (for example, 0 is the default value of the type nat), the value stored in the instantiations.csp file, or the initial value specified in the model.
Values specified in a assertion override the usual definition.

While the assertion language supports comparison of constructs (refinement and equality), this may not be enough for the verification of more general properties. In order to address this limitation, we allow the specification of general CSP processes in an assertions file, which can then be used in an assertion as a member of the class ELEMENT. The syntax that allows the specification of CSP processes in an assertions file is as follows:

CSP specification =
   (untimed | timed) csp PROCESS_NAME (associated to ELEMENT)?
   csp-begin CSP.M csp-end

A CSP specification declares an ELEMENT with name n (PROCESS_NAME), that can be declared to be associated to a RoboChart ELEMENT. This information should be provided when the specification uses the semantics of a RoboChart component, so that the CSPM generator can automatically bring into context the semantics of ELEMENT and the definition of data types used. The content CSP.M is a CSP specification in the syntax accepted by FDR. This specification must include one process called n.

Assertions involving custom CSP specifications using the tick-tock model require the declaration of a CSPM constant named PROCESS_NAME__sem__events, where PROCESS_NAME is the name of the specification, within CSP.M that records the alphabet of the process. An example of its use is reproduced below, where SpecStm0__sem__events is defined on line 6 as a channel set, that includes the channels stm1::in1, stm1::in2, stm1::in3 and stm1::terminate.

1 timed csp SpecStm0 associated to stm0 csp-begin
2 SpecStm0 = stm0::0__(0)[[ stm0::in1 <- stm1::in1,
3   stm0::in2 <- stm1::in2,
4   stm0::in3 <- stm1::in3,
5   stm0::terminate <- stm1::terminate ]]
6 SpecStm0__sem__events = {|stm1::in1,stm1::i2,stm1::in3,stm1::terminate|}
7 csp-end
8
9 timed assertion TT0 : SpecStm0 refines stm1 in the tick-tock model

As of a recent version of the RoboChart CSP Generator, it is now possible to write refinement assertions between two RoboChart components, whereby events in the semantics are renamed automatically so that the comparison is meaningful. This mechanism does not support data refinement. Such cases should be handled via custom CSP specifications.
5.3.2 Optimisations

When checking models using FDR, performance may vary depending on the complexity of RoboChart models and the instantiation of data types. By default, the CSP\(_{\pi}\) generator attempts to generate an efficient representation for model-checking, including the use of compression functions offered by FDR. Some of these options can be toggled within RoboTool if analysis performs poorly by clicking on Window\П References and selecting RoboChart\П Analysis. The current list of options, as shown in Figure 5.2, is described below:

- **Disable iterated compression** (default: off): this option controls how the semantics of the behaviour of state machines is composed in parallel with that of their memory. The default option generates a sequence of parallel compositions that are subsequently compressed using FDR’s \textit{dbisim} and \textit{sbisim} functions. This works well when assignments to local variables constrain behaviours of a state machine or when some variables are not actually used in the model.

- **Enable default assertions compression** (default: off): this option controls whether the verification of assertions written using the RoboChart assertions language uses opt-
timised semantics, that is, $O_{\text{}}$ processes, instead of $D_{\text{}}$ processes. Because refinements are usually checked against much less complex specifications, compressing the semantics of a RoboChart component may not be efficient overall for property verification. On the other hand, if the RoboChart component is used as a specification in a refinement assertion, then this compression may be useful.

5.4 RoboSim assertions language

Similarly to the case with RoboChart assertions, RoboTool provides a textual editor to support the specification of assertions with respect to RoboSim models, in files with extension .rsa.

5.4.1 Assertions

Here, we focus on the syntax of RoboSim assertions. Syntax rules common to RoboChart, specified in Section 5.3.1, are generally omitted.

$\text{assertion} = \text{assertion NAME : specification (in the CSP Model)? (with parameters)? (.)?}$

The specification of assertions is similar to that for RoboChart, but includes the possibility to check whether a RoboSim component, namely a specification of all valid simulations defined over a RoboChart component, is schedulable, as discussed in [ ].

$\text{specification} =$

$\\text{ELEMENT is (not)? (deadlock-free | divergence-free | deterministic |}$
$\\text{ELEMENT (does not terminate | terminates) |}$
$\text{STATE is (not)? reachable in ELEMENT |}$
$\text{ELEMENT (refines | equals | does not refine | is not equal to) ELEMENT |}$
$\text{ELEMENT is (not)? schedulable}$

In addition to setting the value of constants and parameters, RoboSim assertions allow setting the cycle of SimModules, SimControllers and SimMachineDefs using the syntax below.

$\text{AssertionParameter} = \text{constant | parameter | cycle}$

$\text{cycle} =$

$\text{cycleDef of ELEMENT (assigned | set to | with value) Expression}$
Similarly to RoboChart assertions, arbitrary CSP processes may also be written, as specified by the syntax rule \texttt{CSPProcess}. In addition, RoboSim extends this mechanism to allow the specification of \textit{SimulationInstantiations}, that define all valid (RoboSim) simulations of a RoboChart component, suitable for verification.

\textit{CSP specification} = \texttt{CSPProcess} $|$ \textit{SimulationInstantiation}

\textit{SimulationInstantiation} =

\begin{verbatim}
  simulation NAME of ELEMENT { cycleDef Expression } |
  simulation NAME of ELEMENT { cycleDef Expression InputContext OutputContext }
\end{verbatim}

A simulation instantiation must be \textit{NAMEd} and defines an \textit{ELEMENT} of the same name, so that it can be used in an assertion. After the \texttt{of} keyword a RoboChart \textit{ELEMENT} must be provided. A \textit{cycleDef} must also be defined, and optionally an \textit{input context} or \textit{output context} can be defined like in RoboSim, as specified by the following syntax rules.

\textit{InputContext} = \texttt{input context} \{(\texttt{uses} Interface | \texttt{requires} Interface | Event)* \}

\textit{OutputContext} = \texttt{output context} \{(\texttt{uses} Interface | \texttt{requires} Interface | Event)* \}

Although RoboChart Modules and Controllers contain sufficient information to automatically determine its inputs and outputs from a RoboSim point-of-view, state machines may require further input from the user. For example, a required operation of a RoboChart state machine may be defined as a software operation, or required as robotic platform operation, and so this needs to be explicitly captured in an \textit{output context} when defining a simulation. An example showing its use is reproduced below.

```
1 simulation SimSTM of M::STM {
2   cycleDef cycle==2
3   input context { event In:nat }
4   output context { event Out:nat }
5 }
6
7 assertion RS2 : STM equals SimSTM in the failures divergences model
8   with cycleDef of STM set to 1,
9   and cycleDef of SimSTM set to 1
```

Here, we have the definition of a \textit{simulation} named \texttt{SimSTM}, obtained as all valid simulations of a RoboChart state machine \texttt{M::STM}, where: the \texttt{cycle} is set by default to 2, and the \texttt{input context} considers the event \texttt{In}, and the \texttt{output context} considers the event \texttt{Out}. Then, we have the definition of an \textit{assertion} \texttt{RS2}, that checks whether all valid simulations of \texttt{M::STM},
defined as $\text{SimSTM}$ behave exactly as $\text{STM}$, a RoboSim state machine, where the cycle has been set to 1.

5.4.2 Optimisations

Similarly to the verification of RoboChart assertions, when model checking with FDR, performance varies depending on the complexity of RoboSim models and the instantiation of data types. By default, the CSPW generator attempts to generate an efficient representation for model-checking, including the use of compression functions offered by FDR. Some of these options can be toggled within RoboTool by clicking on Window Preferences and selecting RoboSim Analysis. The current list of options, as shown in Figure 5.3, is described below:

- **Disable iterated compression** (default: off): this option controls how the semantics of the behaviour of state machines is composed in parallel with that of their memory. The default option generates a sequence of parallel compositions that are subsequently compressed using FDR’s dbisim and sbisim functions. This works well when assignments to local variables constrain behaviours of a state machine, or, when certain variables are not actually used.
• **Enable default assertions compression** (default: off): this option controls whether the verification of assertions written using the RoboSim assertions language uses optimised semantics, that is, 0__ processes, instead of D__ processes. Because refinements are usually checked against much less complex specifications, compressing the semantics of a RoboSim component may not be efficient overall for verification.

• **Enable iterated state machine cycle compression** (default: off): this option controls how the semantics of the behaviour of a RoboSim state machine is composed with the semantics of its cycle. When enabled, the cycle is composed in parallel with the state machine, and then the semantics of inputs (modelling state) is composed in parallel, but iteratively using FDR’s dbisim and sbisim compression functions. This option can work well when the value of inputs constrains the behaviour of a state machine, or, when certain inputs are not actually used by a state machine.

5.5 Running FDR

In order to run an `.assertions` file in FDR via RoboTool, the user must select the file in the model explorer or project explorer window, and either:

1. Click the **Run...** button on the FDR tool bar; or

2. Right-click the file, and click **RoboTool > CSP > Run...**.

In both cases, FDR will verify the assertions in the background, providing some progress information in the Progress window, and upon completion a HTML report is generated and displayed in the tool. This facility is currently only available for RoboChart assertions.
Additionally, RoboChart is capable of modelling probabilistic behaviour through probabilistic junctions and concrete probability values on transitions. This probabilistic behaviour is not captured in the automatically generated CSP semantics. Instead, we provide another manually invoked probabilistic behaviour generator or translator called translate2prism. It allows us to generate the probabilistic behaviour of a RoboChart model in a PRISM specification. Then we could use PRISM, a probabilistic model checker, to analyse the generated PRISM model.

6.1 Invoking the translator

1. Open a RoboChart project;

2. In Model Explorer, select the rct file that contains the top level RoboChart module; and

3. Right click the selected rct file and click RoboTool \(\rightarrow\) PRISM Compile;

4. The first time you run the translator, a prism-gen folder will be created.

5. Upon a successful translation, a popup dialog with the “Translate to PRISM Successfully” message will appear and then click OK. There will be several files generated in the prism-gen folder.

   a) rc2prism.prefs: the configuration file for the translator;

   b) <rct-file-name>.prism: the generated PRISM specification that we would like to analyse;

   c) <rct-file-name>.pm and <rct-file-name>.psc: the intermediate files during the translation and could be deleted safely (but if the translation fails, they could provide additional information for debugging);
6. However, if an error occurs during the translation, a popup dialog with an error message (shown in Figure 6.1) will appear. This is mainly because of following reasons:

a) Ex01: this feature is not yet supported in current release of the translator and will be supported in the future.

b) Ex02: this feature cannot be supported in the translator.

c) Ex03: the well-formedness condition is violated.

d) Ex09: miscellaneous causes as indicated in the error messages.

**Note:** these errors occur in the translation from RoboChart to PRISM and prevent the RoboChart model from being analysed by PRISM for its probabilistic behaviour, but they will not prevent it from being analysed by FDR. Therefore, you still can use FDR to verify other aspects of properties of the model.

![Translation Error Dialog](image)

**Figure 6.1: Translation Error Dialog**

### 6.2 Configuration File

The translator has a configuration file (named `rc2prism.prefs`) that allows users to provide customised inputs to the translator. One example is illustrated below.

```
#Configuration file for the translator from RoboChart to PRISM
#Fri Mar 08 14:34:29 GMT 2019
NAT_MIN=0
INT_MIN=-10
```

32
NAT_MAX=10
USE_CONF_FROM_INSTANTIATION_CSP=true
PRISM_MODELTYPE=dtmc
DBG_OPTION=true
ERROR_LOG_FILE=rc2prism.log
OUTPUT_LOG_FILE=rc2prism.log
INT_MAX=10
TYPE_OVERRIDE=[STM]left_right.steps \: [0..MAX],
[STM]left_right.x \: [1..M]
MAX_SEQ_INS=30

Detailed description of each configuration item is given below.

1. **INT_MIN** and **INT_MAX**: minimum and maximum integer numbers;

2. **NAT_MIN** and **NAT_MAX**: minimum and maximum natural numbers;

3. **USE_CONF_FROM_INSTANTIATION_CSP**: if it is set to true, minimum and maximum integer and natural numbers will come from the instantiations file (*instantiations.csp*) that is in the *csp-gen* folder. Otherwise, minimum and maximum integer and natural numbers will use above configuration items given in this configuration file;

4. **PRISM_MODELTYPE**: either **dtmc** or **mdp** for the discrete-time Markov chains or Markov decision processes respectively;

5. **ERROR_LOG_FILE** and **OUTPUT_LOG_FILE**: debug and error log file names. If their values are empty, by default debug and error messages will be displayed in standard output (stdout) and error (stderr).

6. **DBG_OPTION**: if it is set to true, debug information will be printed in the console or the specified log file for diagnostic purpose.

7. **TYPE_OVERRIDE**: this allows users to provide customised PRISM type for individual variables in the RoboChart model due to the fact that subtypes (such as [0..3]) are not supported in RoboChart now.
   - **[STM]left_right.steps:[0..MAX]**: for the variable steps in the state machine *left_right*, its type is set to the range from 0 to *MAX* in PRISM.
• Apart from [STM], the translator also supports additional two tags: [RP] and [CTRL] for robotic platforms and controllers respectively.

8. MAX_SEQ_INS: the maximum size of sequences when they are treated as fixed size arrays.

6.3 Opening PRISM directly from Eclipse

In order to load the generated PRISM specification <rct-file-name>.prism in PRISM, we can either open the executable PRISM model checker xprism then load the specification file, or open the PRISM model checker directly from Eclipse. Opening PRISM directly from Eclipse is very similar to opening FDR directly from Eclipse. Right-click the .prism file, select [Open with] System Editor. If xprism is not the default program for .prism files, you can add it to the list of editors in Eclipse as follows:

1. Right-click a .prism file and select [Open with] Other
2. Select [External programs], click [Browse...], find the xprism executable and click [OK]
3. Click [OK]

Once you follow these steps, every time you double click a .prism file in Eclipse, PRISM should open. If you want to open the .prism file in a text editor, right-click the file, and select [Open with] Text Editor. To open the file in PRISM again, right-click the file, and select [Open with] xprism.

6.4 Probabilistic assertion language

The syntax of the probabilistic assertion language is documented in RoboChart reference manual. In order to invoke verification with PRISM through the probabilistic assertion language, please follow the steps below:

1. Open a RoboChart project;
2. Create an assertion file and its extension is assertions;
3. Write the properties to be verified in the assertion file according to its syntax;
4. (Optional) If the RoboChart model has not generated its PRISM model manually, right-click one rct file, and select the RoboTool > PRISM > Compile item to generate the PRISM model.

5. Right click the selected assertions file and click RoboTool > PRISM > Run to verify the properties;

6. Provided there are no errors in the assertions or models, PRISM checks the assertions in the background, and RoboTool summarises the result in the form of a report, which is automatically opened upon completion of the checks.
Chapter 7

Mutation Testing with Wodel

The RoboTool plugins can be used to generate traces that a RoboChart model cannot perform; they can be used as the basis for defining tests. An overview of the workflow for generating these traces is shown in Figure 7.1. This approach has been developed using the mutation tool Wodel, which should be installed following the instructions on its website (http://gomezабajo.github.io/Wodel/). It may be possible to use this approach with other mutation testing tools. We refer to the paper Testing Robots Using CSP\(^1\) for more details of our approach.

![Figure 7.1: Overview of the mutation testing approach with Wodel](image)

The RoboTool features used in this procedure for generating traces are RoboChart Model Importer, RoboChart Model Exporter, RoboChart CSP Generator, and RoboChart CSP Semantics Comparison (along with their dependencies), which should be installed from the RoboTool update site (https://www.cs.york.ac.uk/robostar/robotool/update/). This procedure also requires FDR to be installed.

The steps in Figure 7.1 are numbered, and correspond to the sections below. The first three steps (Sections 7.1 to 7.3) are concerned with preparing the inputs required by Wodel, the fourth step (Section 7.4) is the generation of mutants with Wodel, the fifth and sixth steps (Sections 7.5 and 7.6) concern the import of mutants into RoboTool and generating CSP from

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them, and the seventh step (Section 7.7) is the comparison of the mutants with the original model to generate traces.

7.1 Exporting a RoboChart Model to XMI

Wodel takes the model to mutate as an Eclipse Modelling Framework (EMF) model in the XML Metadata Interchange (XMI) format. RoboChart models can be exported in this format by performing the following steps in Eclipse:

1. Select the File > Export... menu item, or right-click on the RoboChart file to export and select Export...;

2. Select RoboChart and then RoboChart Project as EMF Model;

3. Click Next;

4. Select the RoboChart (.rct) files to export in the upper panes;

5. Use the Browse... button to select the desired destination folder for the exported XMI files, or type the path of the destination folder into the text field;

6. If the model being exported is composed of multiple .rct files, select the Merge input files into a single file named option and enter the name of the desired output file (which should have the .model extension), since Wodel operates only on a single XMI file at a time;

7. Click Finish.

The exported .model files are then placed in the provided destination folder.

7.2 Obtaining the RoboChart Metamodel

Wodel requires an Ecore metamodel describing the layout of the model to be mutated. The current RoboChart metamodel used by RoboTool is included in the files of the RoboChart Metamodel RoboTool feature and can be downloaded directly from:
7.3 Writing Mutation Operators

A new Wodel project should be created as described at [https://github.com/gomezabajo/Wodel/wiki/Get-Started](https://github.com/gomezabajo/Wodel/wiki/Get-Started):

1. Select the **File** > **New** > **Other...** menu item;
2. Select **Wodel** then **New Wodel Project**;
3. Click **Next**;
4. Enter the desired project name and mutation file name;
5. Click **Next**;
6. Use the **Load file** button to select the RoboChart metamodel downloaded in Section 7.2;
7. Click **Finish**;
8. In the popup message, click **Yes**;
9. Copy the `.model` file exported in Section 7.1 to the `data/model/` folder of the newly created Wodel project.

Wodel generates a `.mutator` file in the `src/` folder of the generated project. This should be modified to include suitable mutation operators for the desired mutations. We provide a standard set of mutation operators at [https://robostar.cs.york.ac.uk/robotool/testing/RoboChartMutationOperators.mutator](https://robostar.cs.york.ac.uk/robotool/testing/RoboChartMutationOperators.mutator), developed by Raluca Lefticaru for the Solar Panel Vacuum Cleaner case study, which cover a range of different RoboChart elements and should be applicable to most RoboChart models. Further details on how to write mutation operators can be found in [http://www.miso.es/pubs/Wodel.pdf](http://www.miso.es/pubs/Wodel.pdf). Mutation operators should not change the robotic platform, since that changes the interface of the module used for comparison. The mutation operators that are most likely to generate well-formed mutants are usually those that change transitions, states and actions within a state machine.
Examples of mutation operators on RoboChart models:

• Converting an entry action to a during action:

1. retype one EntryAction as DuringAction

• Moving the target of a transition to another state:

1. modify target ^target from one Transition to other State

• Replacing a transition trigger with another event selected from an interface:

1. interf = select one Interface where {events <> null}
2. ev = select one Event in interf->events
3. tg = create Trigger with {event = ev}
4. modify one Transition with {trigger = tg}

• Deleting a state and the transitions from and to it:

1. st = select one State
2. remove all Transition where ^source = st
3. remove all Transition where ^target = st
4. remove st

• Removing the action of a transition:

1. tr = select one Transition where {action <> null}
2. remove one Call from tr->action
3. remove one SendEvent from tr->action
4. remove one Action from tr

7.4 Running Wodel

Once a suitable set of mutation operators has been created, they can be run on the model to produce mutants, by right-clicking on the .mutator file and selecting Execute Mutations. This creates generated mutants in the mutant output folder (usually data/out/).
7.5 Importing Mutants into RoboTool

The mutants generated by Wodel can be imported back into RoboTool by performing the following steps in Eclipse:

1. Select the `File > Import...` menu item;

2. Select `RoboChart`, then `RoboChart models into project`;

3. Click `Next`;

4. Use the `Browse...` to select the folder in which Wodel output the mutants, or enter the path to the folder in the text field;

5. Select the mutants you would like to import in the panes below the text field; if they are not visible then adjust or deactivate the `Limit search depth below root to` option;

6. Use the `Browse...` button below the panes to select a project folder to import the mutants into (this is usually the project the original file was exported from);

7. Select the `Preserve directory structure below root` option if you wish to keep the mutants in separate folders below the folder selected in step 4 (this is usually advisable to keep the project organised);

8. Select the `Prefix model element names with directory structure` to ensure unique names and `Prefix filenames with directory structure` options (this is recommended in order to avoid conflicts in generating CSP code and comparing the mutants to the original model);

9. Click `Finish`.

The mutants (within their folders if the option in step 7 was selected) are then imported into the specified place in the project.

7.6 Generating RoboChart CSP Semantics

The CSP semantics for the original model should have been automatically constructed as the model was created. The CSP semantics for the mutants should have been automatically con-
structured when it was imported. If the CSP semantics has not been constructed, construction can be forced by selecting the [RoboTool CSP Compile] menu option.

If the RoboChart model has any constants, ensure that they have the correct values set for them in csp-gen/defs/instantiations.csp and csp-gen/timed/defs/instantiations.csp. Only the constants of the original model need to be set, as they are used for all mutants during the mutant comparison.

7.7 Generating Traces from Comparison with Mutants

The comparison can then be carried out by performing the following steps in Eclipse:

1. Right-click on the file containing the RoboChart module of the original model and select [RoboTool Compare to mutants...];

2. Select the mutants to compare to in the upper panes;

3. Select [Group test trace by directories in report] if you wish to have the mutants from different directories listed separately in the report of generated traces (which corresponds to separating different mutation operators in the directory structure generated by Wodel);

4. Select [Remove traces that are duplicates of existing traces] if you wish duplicate traces to be removed from the report of generated traces;

5. Select [List mutants that are refinements of the original in the report] if you wish a list of valid mutants that did not produce counterexample traces to be included in the report of generated traces;

6. Select [List files that are invalid in the report] if you wish a list of files that were not checked due to being invalid or blank to be included in the report of generated traces;

7. Click Ok.

Note that checking the mutants against the original model may take some time, especially if the model is large or there are many mutants. If the checking of the mutants completes successfully, an HTML report of the generated traces is produced and opened in Eclipse. Invalid mutants are skipped during the mutant comparison, so traces are not generated for such mutants.
If the checking of mutants does not complete successfully, ensure that FDR is properly licensed by first opening the FDR graphical interface. It should also be ensured that all constants are properly set and within range for their types (type ranges in instantiations.csp may need to be checked). The mutation operators in the file provided in Section 7.3 assume that the ranges of numerical types contain the integers 0, 1 and 2, so the ranges in instantiations.csp must be defined to contain those ranges. This is already the case for the default instantiations.csp file generated by the tool.

If manual execution or customisation of the comparison is desired, the FDR script to perform the comparison is generated as a file named after the file containing the original model (selected in step 3 above) followed by _compare.csp, within the csp-gen/ and _compare.csp csp-gen/timed/ directories. An FDR script to perform with the comparison for each individual mutant is also generated, named after the file containing the original model joined to the name of the mutant with an underscore and appended with _compare.csp. These separate scripts are used during checking to improve memory use and report more detailed results. Note that only the timed version is used during the generation of mutant traces.
Appendix A

Deviations from RoboChart reference manual
RoboTool is developed and maintained to be consistent with the RoboChart language definition. Nevertheless, certain aspects of the language definition have not yet been implemented, or have been implemented in a slightly different way, due to limitations in technologies. Here we discuss such deviations.

A.1 Well-formedness condition

Two well-formedness conditions have not been implemented in RoboTool as it requires the use of automated or semi-automated theorem provers. They are:

J2 The guards of the transitions out of a junction must form a cover; and

V1 If the initial value of a required variable or constant of a state machine or controller is defined, it must be consistent with the value of any (complementing) variable provided by the contexts (controllers or modules) where the state machine or controller is used.

A.2 Semantics

While the code generation faithfully implements the semantics of RoboChart, it targets the flavour of CSP called CSP-M, which is the input language for FDR. In particular, we make extensive used, in the implementation, of process declarations and FDR compression functions to improve the usability of our semantic models.

Other aspects, such as naming conventions, channel declarations, and so on, which are underspecified in the semantics, are made concrete in the implementation to support the use of FDR with our models. Finally, the concrete syntax of CSP-M varies slightly from the syntax standard CSP, which is used in the reference manual.
Bibliography
