Abstract

In fault diagnosis intermittent fault models are an important tool to adequately deal with realistic failure behavior. Current model-based diagnosis approaches account for the fact that a component \( c_j \) may fail intermittently by introducing a parameter \( g_j \) that expresses the probability the component exhibits correct behavior. This component parameter \( g_j \), in conjunction with a priori fault probability, is used in a Bayesian framework to compute the posterior fault candidate probabilities. Usually, information on \( g_j \) is not known a priori. While proper estimation of \( g_j \) can be critical to diagnostic accuracy, at present, only approximations have been proposed. We present a novel framework, coined BARINEL, that computes estimations of the \( g_j \) as integral part of the posterior candidate probability computation using a maximum likelihood estimation approach. BARINEL’s diagnostic performance is evaluated for both synthetic systems, the Siemens software diagnosis benchmark, as well as for real-world programs. Our results show that our approach is superior to reasoning approaches based on classical persistent fault models, as well as previously proposed intermittent fault models.

Key words: Fault Diagnosis, Bayesian Reasoning, Maximum likelihood estimation.
1. Introduction

In model-based fault diagnosis (MBD) faults are typically assumed to be persistent. In many practical situations, however, faults manifest themselves intermittently, such as in copiers where sometimes sheets may be blank, or where a worn roller sometimes slips and causes a paper jam [11]. Intermittent behavior is also relevant in software fault diagnosis, which is the primary context of this paper. Although software is supposed to be inherently deterministic, intermittent component models are often essential. This can be due to non-determinism (e.g., race conditions) caused by design faults related to properly dealing with concurrency. A more compelling reason is the modeling abstraction typically applied, where, for example, the software component’s input and output values are abstracted in the model, such that a component’s output may differ for the same input, manifesting as intermittent failures. Although a weak fault model (that does not stipulate particular fault behavior) admits any output behavior, modeling inconsistently failing (software) components merely in terms of weak models results in degraded diagnostic performance [4].

A model for intermittent behavior [9] was introduced as an extension of the GDE framework [10, 12]. Essentially, next to the prior probability $p_j$ that a component $c_j$ is at fault, a parameter $g_j$ is used to express the probability that a faulty component exhibits correct (good, hence $g$) behavior ($g_j = 0$ = for persistently faulty, $g_j = 1$ = effectively ok, $0 < g_j < 1$ = intermittently faulty). The model is incorporated into the standard, Bayesian framework that computes the posterior probability of diagnosis candidates based on observations [8, 12].

The intermittency framework has been shown to yield significantly better results (e.g., in the diagnosis and replanning of paper sheet paths in copiers with intermittent component failures [22], and in software fault diagnosis [4]), compared to an approach based on a classical, persistent fault model. An important problem in using the intermittency model, however, is the estimation of $g_j$, as calibration data on correct and incorrect component behavior is typically not available. Estimating $g_j$ for each component $c_j$ would be straightforward when (sufficient) system observations are available where only that single, intermittent component is involved [9]. However, in a multiple-fault context usually only system observations are available in which multiple faulty components are involved. Consequently, isolating to what extent each individual component contributes to the observed, inter-
mittent failure behavior is not trivial. However, as the influence of \( g_j \) in the computation of the posterior probability of each diagnostic candidate is significant, exact knowledge of each \( g_j \) can be critical to overall diagnostic accuracy.

In [11] as well as in [4, 5] strategies have been proposed to estimate the \( g_j \) in a multiple-fault context. However, the approaches are essentially based on an approximation. In this paper, we present a novel approach to compute the \( g_j \), in conjunction with a new approach towards the computation of the posterior candidate probabilities using an intermittent fault model that generalizes over classical, persistent MBD approaches. The approach represents a departure from the current Bayesian framework as used in current diagnosis approaches (e.g., [4] and [11]) in the sense that (1) the resulting \( g_j \) are maximum likelihood estimators instead of approximations, and (2) the computation of the posterior candidate probabilities is an integral product of the \( g_j \) estimation procedure.

Apart from diagnosis accuracy, in this paper we also address diagnosis efficiency. The weak (intermittent) modeling approach, in combination with the large systems we consider (\( \mathcal{O}(10,000) \) components) leads to a huge diagnostic candidate space. In this paper we present a minimal hitting set algorithm that features a novel, diagnosis-specific heuristic that directs the search to generate candidates in order of decreasing posterior probability, even within equal-cardinality groups. This feature allows the candidate generation process to be truncated to a very limited number of candidates (merely 100 in our experiments), yet effectively capturing all posterior probability mass. This tailored algorithm enables us to apply our diagnosis technique to very large systems.

This paper makes the following contributions

- We present our new approach for the candidate probability computation which features a maximum likelihood estimation algorithm to compute the \( g_j \) of all components involved in the diagnosis. The approach is coined BARINEL\(^1\), which is the name of the software implementation of our method;

- We present a new algorithm to compute the minimal hitting set from

\(^1\)BARINEL stands for Bayesian AppRoach to diagnose iNtErmittent faulLts. A barinel is a type of caravel used by the Portuguese sailors during their discoveries.
a set of conflicts, called Staccato\(^2\), and derive its time and space complexity;

- We compare the accuracy and complexity of Barinel (including Staccato) to the current approaches in [4] and [11] for synthetically generated observation series based on injected faults with known \(g_j\) setpoints;

- We describe the application of our approach to software multiple-fault diagnosis and evaluate its diagnostic performance using the well-known Siemens suite of benchmark programs (extended for multiple faults) as well as real-world programs (space, sed, gzip).

The results from the synthetic experiments, as well as from the application to real software systems, confirm that our new approach has superior diagnostic performance to all Bayesian approaches to intermittent systems known to date, at very limited computation cost.

The paper is organized as follows. In the next section we describe the current Bayesian approach to persistent and intermittent models. In Section 3 and 4 we describe our new approach to candidate generation, and posterior probability computation, respectively. Sections 5 and 6 present experimental results for synthetic observations, and real program codes, respectively. Section 7 describes related work, while Section 8 concludes the paper.

2. Preliminaries

In this section we describe the state-of-the-art in MBD involving intermittent faults.

2.1. Basic Definitions

**Definition** A diagnostic system \(DS\) is defined as the triple \(DS = \langle SD, COMPS, OBS \rangle\), where \(SD\) is a propositional theory describing the behavior of the system, \(COMPS = \{c_1, \ldots, c_M\}\) is a set of components in \(SD\), and \(OBS\) is a set of observable variables in \(SD\).

With each component \(c_j \in COMPS\) we associate a health variable \(h_j\) which denotes component health. The health states of a component are either healthy (\(h_j \text{ true}\)) or faulty (\(h_j \text{ false}\)).

\(^2\)Staccato is an acronym for STAtistiCs-direCted minimAl hiTing set algOrithm.
**Definition** An h-literal is $h_j$ or $\neg h_j$ for $c_j \in \text{COMPS}$.

**Definition** An h-clause is a disjunction of h-literals containing no complementary pair of h-literals.

**Definition** A conflict of $(SD, \text{COMPS}, OBS)$ is an h-clause of negative h-literals entailed by $SD \cup OBS$.

**Definition** Let $S_N$ and $S_P$ be two disjoint sets of components indices, faulty and healthy, respectively, such that $\text{COMPS} = \{c_j \mid j \in S_N \cup S_P\}$ and $S_N \cap S_P = \emptyset$. We define $d(S_N, S_P)$ to be the conjunction $(\bigwedge_{j \in S_N} \neg h_j) \land (\bigwedge_{j \in S_P} h_j)$

A diagnosis candidate is a sentence describing one possible state of the system, where this state is an assignment of the status healthy or not healthy to each system component.

**Definition** A diagnosis candidate $d(S_N, S_P)$ for $DS$ given an observation $obs$ over variables in $OBS$ is such that

$$SD \land obs \land d(S_N, S_P) \nvdash \bot$$

In the remainder we refer to $d(S_N, S_P)$ simply as $d$, which we identify with the set $S_N$ of indices of the negative literals. A minimal diagnosis is a diagnosis that is not subsumed by another of lower fault cardinality (i.e., number of negative h-literals $C = |d|$).

**Definition** A diagnostic report $D = < d_1, \ldots, d_k, \ldots, d_K >$ is an ordered set of all $K$ diagnosis candidates, for which $SD \land obs \land d_k \nvdash \bot$.

The diagnostic accuracy of a diagnosis $D$ depends on the ranking of the actual system’s fault state $d^*$. Assuming a diagnostician traverses $D$ top to bottom, a diagnostic approach that produces a $D$ where $d^*$ is ranked on top has higher accuracy (i.e., generates less testing effort) than an approach that ranks $d^*$ lower. Details are discussed in the experimental evaluation sections later on.

The Bayesian approach serves as the foundation for the derivation of diagnostic candidates, i.e., (1) deducing whether a candidate diagnosis $d_k$ is consistent with the observations, and (2) the posterior probability $\Pr(d_k)$.
of that candidate being the actual diagnosis. With respect to (1), rather than computing \( \text{Pr}(d_k) \) for all possible candidates, just to find that most of them have \( \text{Pr}(d_k) = 0 \), search algorithms are typically used instead, such as CDA* [31], SAFARI [14], or just a minimal hitting set (MHS) algorithm when conflict sets are available (e.g. [12]), but the Bayesian probability framework remains the basis. In this section we will briefly describe the contemporary approach to the derivation of candidates and their posterior probability.

2.2. Candidate Generation

Consider a particular process, involving a set of components, that either yields a nominal result or a failure. For instance, in a logic circuit a process is the sub-circuit (cone) activity that results in a particular primary output. In a copier a process is the propagation of a sheet of paper through the system. In software a process is the sequence of software component activity (e.g., statements) that results in a particular return value. The result of a process is either nominal (“pass”) or an error (“fail”). As explained earlier, in the sequel we assume weak component fault models \( (h \Rightarrow <\text{nominal behavior}> \), compatible with the notion of intermittency which allows a faulty component to (intermittently) exhibit correct behavior.

Definition Let \( S_f = \{ c_j | c_j \text{ involved in a failing process} \} \), and let \( S_p = \{ c_j | c_j \text{ involved in a passing process} \} \), denote the fail set and pass set, respectively.

Approaches for fault diagnosis that assume persistent, weak fault models often generate candidates based on fail sets (aka conflict sets), essentially using an MHS algorithm to derive minimal candidates. A well-known example is GDE [12] where fail sets are derived from detecting inconsistencies in the system given certain input and output observations. Recent approaches that allow intermittency also take into account pass sets (consistent behavior). Examples that use pass sets next to fail sets include intermittent logic, and the copier and software systems mentioned earlier. A fail set indicts components (i.e., increases their posterior fault probability), whereas a pass set exonerates components (i.e., decreases their posterior fault probability). The extent of indictment or exoneration is computed using Bayes’ rule. In the following we assume that a number of pass and fail sets have been collected, either by static modeling (e.g., logic circuits, where each circuit (cone)
involved in computing an output yields a pass or fail set) or by dynamic pro-
filng (e.g., software, where each run yields a pass or fail set, collectively
known as a hit spectrum [3, 19]).

**Definition** Let $N$ denote the number of passing and failing processes. Let
$N_f$ and $N_p$, $N_f + N_p = N$, denote the number of fail and pass sets (spectra),
respectively. Let $A$ denote the $N \times M$ activity matrix of the system, where
$a_{ij}$ denotes whether component $j$ was involved in process $i$ ($a_{ij} = 1$) or not
($a_{ij} = 0$). Let $e$ denote the error vector, where $e_i$ signifies whether process $i$
has passed ($e_i = 0$) or failed ($e_i = 1$, i.e., a conflict).

The observations $(A, e)$ are the only input to the diagnosis process (see Fig-
ure 1).

$$\begin{bmatrix}
    a_{11} & a_{12} & \cdots & a_{1M} \\
    a_{21} & a_{22} & \cdots & a_{2M} \\
    \vdots & \vdots & \ddots & \vdots \\
    a_{N1} & a_{M2} & \cdots & a_{NM}
\end{bmatrix}
\begin{bmatrix}
e_1 \\
e_2 \\
\vdots \\
e_N
\end{bmatrix}$$

Figure 1: Input to the diagnostic process

In our Barinel approach we compute the candidates from the fail sets
using our Staccato MHS algorithm (Section 3).

2.3. Candidate Probability Computation

Given the multitude of candidates that are typically generated the rank-
ing induced by posterior probability computation is critical to diagnostic
accuracy. Let $\Pr(j) = p_j$ denote the prior probability that a component $c_j$
is at fault. Assuming components fail independently the prior probability of
a candidate $d_k$ is given by

$$\Pr(d_k) = \prod_{j \in S_N} \Pr(\{j\}) \cdot \prod_{j \in S_P} (1 - \Pr(\{j\}))$$

For each observation $obs_i = (A_i, e_i)$ the posterior probabilities are updated
according to Bayes rule (naive Bayes classifying)

$$\Pr(d_k | obs_i) = \frac{\Pr(obs_i | d_k)}{\Pr(obs_i)} \cdot \Pr(d_k) \quad (1)$$
The denominator \( \Pr(\text{obs}_i) \) is a normalizing term that is identical for all \( d_k \) and thus needs not be computed directly. \( \Pr(\text{obs}_i\mid d_k) \) is defined as

\[
\Pr(\text{obs}_i\mid d_k) = \begin{cases} 
0 & \text{if } \text{obs}_i \land d_k \text{ are inconsistent}; \\
1 & \text{if } \text{obs}_i \text{ is unique to } d_k; \\
\varepsilon & \text{otherwise.}
\end{cases}
\]  

(2)

As mentioned earlier, rather than updating each candidate only candidates derived from the diagnostic search algorithm are updated, implying that the 0-clause need not be considered.

For the large majority of cases, the \( \varepsilon \)-clause applies. Many policies exist for \( \varepsilon \) [8]. Three policies can be distinguished. The first policy, denoted \( \varepsilon^{(0)} \) equals the classical MBD policy for persistent, weak faults, and is defined as follows

\[
\varepsilon^{(0)} = \begin{cases} 
\frac{E_P}{E_P + E_F} & \text{if } e_i = 0 \\
1 - \frac{E_P}{E_P + E_F} & \text{if } e_i = 1
\end{cases}
\]  

(3)

where \( E_P = 2^M \) and \( E_F = (2^{|d_k|} - 1) \cdot 2^{M-|d_k|} \) are the number of passed and failed observations that can be explained by diagnosis \( d_k \), respectively. A disadvantage of this classical policy is that pass sets, apart from making single faults more probable than multiple faults, do not help in pinpointing the faults, in particular for weak fault models which do not rule out any candidates (the \( 2^M \) term in Eq. 3). In addition, there is no way to distinguish between diagnoses with the same cardinality, because the terms are merely a function of the cardinality of the diagnosis candidate.

The next two, intermittent policies account for the fact that components involved in pass sets should to some extent be exonerated. In the following we distinguish between two policies, \( \varepsilon^{(1)} \) [9] and \( \varepsilon^{(2)} \) [4] which are defined as

\[
\varepsilon^{(1)} = \begin{cases} 
g(d_k) & \text{if } e_i = 0 \\
1 - g(d_k) & \text{if } e_i = 1
\end{cases}
\]

and

\[
\varepsilon^{(2)} = \begin{cases} 
g(d_k)^m & \text{if } e_i = 0 \\
1 - g(d_k)^m & \text{if } e_i = 1
\end{cases}
\]

where \( m = \sum_{j \in d_k} [a_{ij} = 1] \) is the number of faulty components according to \( d_k \) involved in process \( i \). Note that a term \( g(d_k) \) is used rather than

\(^3 [\cdot] \) is Iverson’s operator (\([\text{true}] = 1, [\text{false}] = 0\) ).
the real individual component intermittency parameters \( g_j \). As mentioned earlier, this is due to the fact that obtaining \( g_j \) from pass and fail sets where multiple intermittent failures are involved has been far from trivial. Instead, an “effective” intermittency parameter \( g(d_k) \) is estimated for the multiple-fault candidate \( d_k \) by counting how many times components of \( d_k \) are involved in pass and fail sets. In both policies \( g(d_k) \) is approximated by

\[
g(d_k) = \frac{n_{10}(d_k)}{n_{10}(d_k) + n_{11}(d_k)}
\]

where

\[
n_{10}(d_k) = \sum_{i=1..N} \left[ (\bigvee_{j\in d_k} a_{ij} = 1) \wedge e_i = 0 \right]
\]

\[
n_{11}(d_k) = \sum_{i=1..N} \left[ (\bigvee_{j\in d_k} a_{ij} = 1) \wedge e_i = 1 \right]
\]

Policy \( \varepsilon^{(2)} \) is a variant of \( \varepsilon^{(1)} \), which approximates the probability \( \prod_{j\in d_k} g_j \) that all \( m \) components in \( d_k \) exhibit good behavior by \( g(d_k)^m \) assuming that all components of \( d_k \) have equal \( g \) values. This takes into account the fact that the failure probability should increase with the number intermittent faults involved.

2.4. Example

To illustrate how current Bayesian approaches work, consider the diagnosis candidates \( d_k \) in Table 1 obtained from a 2-faulty gzip software program (components 2553 and 2763 are faulty, \( M = 5,680 \) components, \( N = 210 \) test cases, of which \( N_F = 12 \) failed). For simplicity, we refrain from reporting the activity matrix, summarizing it in terms of \( n_{11}(d_k) \), \( n_{10}(d_k) \), \( n_{01}(d_k) \), \( n_{00}(d_k) \) instead\(^4\). The terms \( n_{01}(d_k) \) and \( n_{00}(d_k) \) are defined as follows

\[
n_{01}(d_k) = \sum_{i=1..N} \left[ (\bigvee_{j\in d_k} a_{ij} = 0) \wedge e_i = 1 \right]
\]

\[
n_{00}(d_k) = \sum_{i=1..N} \left[ (\bigvee_{j\in d_k} a_{ij} = 0) \wedge e_i = 0 \right]
\]

\(^4\)For interested readers, the activity matrix can be downloaded from http://www.st.ewi.tudelft.nl/~abreu/aij.
\[
\begin{array}{|c|cccc|}
\hline
\epsilon(0) & \epsilon(1) & \epsilon(2) \\
\hline
\{1347\} & 0.11 \times 10^{-1} & : & : & : \\
\vdots & \vdots & \vdots & \vdots & \vdots \\
\{2682, 2745\} & 0.11 \times 10^{-3} & \{2553, 2763\} & 0.17 \times 10^{-9} & \{1347\} \\
\{2110, 2745\} & 0.11 \times 10^{-3} & \{2553, 2763\} & 0.17 \times 10^{-9} & \{1347\} \\
\{2553, 2763\} & 0.11 \times 10^{-3} & : & : & : \\
\hline
\end{array}
\]

<table>
<thead>
<tr>
<th>(d_k)</th>
<th>(n_{11})</th>
<th>(n_{10})</th>
<th>(n_{01})</th>
<th>(n_{00})</th>
<th>(g(d_k))</th>
</tr>
</thead>
<tbody>
<tr>
<td>{1347}</td>
<td>12</td>
<td>189</td>
<td>0</td>
<td>9</td>
<td>0.94</td>
</tr>
<tr>
<td>{2553, 2763}</td>
<td>12</td>
<td>16</td>
<td>0</td>
<td>182</td>
<td>0.57</td>
</tr>
<tr>
<td>{2682, 2745}</td>
<td>12</td>
<td>2</td>
<td>0</td>
<td>196</td>
<td>0.14</td>
</tr>
<tr>
<td>{2110, 2745}</td>
<td>12</td>
<td>2</td>
<td>0</td>
<td>196</td>
<td>0.14</td>
</tr>
</tbody>
</table>

Table 1: Candidates obtained from gzip

Table 2: Diagnostic Reports

A snippet of the diagnostic reports obtained for the different policies is given in Table 2. Common to traditional policies, \(\epsilon(0)\) does not distinguish between candidates with the same cardinality, ranking them in order of diagnosis candidate’s cardinality. The diagnostic report yielded by \(\epsilon(2)\) differs from \(\epsilon(1)\) because \(\epsilon(2)\) takes into account the number of (faulty) components involved in a process (the rationale being that the more faulty components are involved, the more likely it is that the run will fail). Essentially, due to the ranking position of the true fault \(\epsilon(2)\) requires the developer to inspect less code than the other policies.

In Section 4 we will show that knowledge of the individual \(g_j\) yields far better results than the above \(g(d_k)\) estimations.
3. Candidate Generation: Staccato

As mentioned earlier, we derive the diagnosis candidates from the activity matrix $A$ comprising the pass and fail sets. As the fail sets represent conflicts, we apply a minimal hitting set algorithm to compute the diagnosis candidates. Due to the typically large number of hitting sets a search heuristic that focuses the search towards solutions that are potentially a minimal hitting set will yield significant efficiency gains. However, many of the computed minimal hitting sets may potentially be of little value (i.e., have very low posterior probability). Therefore, the solutions need to be ordered in terms of relevance, possibly aborting the search once a particular number of minimal hitting sets have been found, again boosting efficiency. MHS algorithms typically generate candidates in terms of increasing cardinality, implying that cardinalities of highest posterior probability are generated first. However, changes in the order within the same cardinality class (aka ambiguity group) can greatly affect diagnostic accuracy. In this section we present our approximate, statistics-directed minimal hitting set algorithm, coined Staccato, aimed to increase search efficiency.

Similar to contemporary MHS algorithms [12, 21, 15], the algorithm combines components, starting with cardinality $C = 1$, until a combination is found that covers all conflicts. In principle, the algorithm executes in depth-first order until all minimal hitting sets are found. Initially, the components $c_j$ are ordered using a heuristic function $H: j \rightarrow R$. Then during the search the algorithm selects the components in that order.

A generally accepted heuristic [12] is to assume that components that are members of more fail sets than other components, are more likely to be part of a minimal hitting set. The trivial case are those components that are involved in all sets, which constitute minimal hitting sets of cardinality 1. This heuristic is given by

$$H(j) = \sum_{i=1}^{N} a_{ij} \quad (4)$$

Despite its generally good performance, the above heuristic is not particularly tailored to the diagnostic domain. Given a set of conflicts, the MHS solutions should ideally be ordered in terms of Eq. 1. However, due to the circular dependency, we would first need an MHS algorithm to be able to solve Eq. 1, which would defeat any cost-effective approach. Hence, a low-
cost heuristic that still provides a good prediction of Eq. (1) is a critical success factor.

A low-cost, statistics-based technique that is known to be a good predictor for ranking (software) components in order of likelihood to be at fault is spectrum-based fault localization (SFL) [3]. SFL takes the same (spectral) input \((A, e)\) and produces a ranking of the components in order of fault likelihood. The component ranking is computed using a similarity coefficient that measures the statistical correlation between component involvement and erroneous/nominal system behavior. Many similarity coefficients exist for SFL, the best one currently being the Ochiai coefficient, known from molecular biology and introduced to SFL in [3]. It is defined as follows

\[
s(j) = \frac{n_{11}(\{j\})}{\sqrt{(n_{11}(\{j\}) + n_{01}(\{j\})) * (n_{11}(\{j\}) + n_{10}(\{j\}))}}
\]  

(5)

The similarity coefficient indicts components using \(n_{11}(\{j\})\), and exonerates components using \(n_{10}(\{j\})\) and \(n_{01}(\{j\})\). In [3] it has been shown that similarity coefficients provide an ordering of components that yields good diagnostic accuracy, i.e., components that rank highest are usually faulty. This diagnostic performance, combined with the very low complexity of \(s(j)\) is the key motivation to use the Ochiai coefficient \(s(j)\) for \(H\). If \((A, e)\) only contains conflicts (i.e., \(\exists e_i = 0\)), the ranking returned by this heuristic function reduces to the more simple Eq. 4 and, therefore, classic MHS problems are also adequately handled by our MBD-specific heuristic.

**Staccato** uses the SFL heuristic Eq. 5 to focus the search of the minimal hitting set computation (see Algorithm 1). To illustrate how **Staccato** works, consider the following \((A, e)\), comprising two fail sets and one pass set.

<table>
<thead>
<tr>
<th>(c_1)</th>
<th>(c_2)</th>
<th>(c_3)</th>
<th>(e_i)</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>0</td>
<td>1</td>
<td>1</td>
<td>1</td>
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<tr>
<td>1</td>
<td>0</td>
<td>1</td>
<td>0</td>
</tr>
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</table>

From \((A, e)\) it follows \(H(1) = 0.5\), \(H(2) = 0.7\), and \(H(3) = 1\), yielding the following ranking \(< 3, 2, 1 >\). As component \(c_3\) is involved in all failed sets, it is added to the minimal hitting set and removed from \(A\) using function **Strip_Component**, avoiding solutions subsumed by \(\{3\}\) to be considered (lines 5–12). After this phase \((A, e)\) is as follows.
Algorithm 1 Staccato

Inputs: Matrix \((A, e)\), number of components \(M\), stop criteria \(\lambda, L\)

Output: Minimal Hitting set \(D\)

1. \(T_F \leftarrow \{A_i \mid e_i = 1\}\) \quad \triangleright \text{Collection of conflict sets}
2. \(R \leftarrow \text{RANK}(\mathcal{H}, A, e)\) \quad \triangleright \text{Rank according to heuristic } \mathcal{H}
3. \(D \leftarrow \emptyset\)
4. \(seen \leftarrow 0\)
5. for all \(j \in \{1..M\}\) do
   6. \(\text{if } n_{11}(\{j\}) = |T_F| \text{ then}\)
      7. \(\text{push}(D, \{j\})\)
      8. \(A \leftarrow \text{STRIP\_COMPONENT}(A, j)\)
      9. \(R \leftarrow R \setminus \{j\}\)
     10. \(seen \leftarrow seen + \frac{1}{M}\)
   end if
7. end for
8. while \(R \neq \emptyset \land seen \leq \lambda \land |D| \leq L\) do
   9. \(j \leftarrow \text{POP}(R)\)
   10. \(seen \leftarrow seen + \frac{1}{M}\)
   11. \((A', e') \leftarrow \text{STRIP}(A, e, j)\)
   12. \(D' \leftarrow \text{STACCATO } (A', e', \lambda)\)
   13. while \(D' \neq \emptyset\) do
      14. \(j' \leftarrow \text{POP}(D')\)
      15. \(j' \leftarrow \{c\} \cup j'\)
      16. \(\text{if } \text{IS\_NOT\_SUBSUMED}(D, j')\text{ then}\)
         17. \(\text{push}(D, j')\)
   end if
   18. end while
   19. end while
20. return \(D\)

<table>
<thead>
<tr>
<th>(c_1)</th>
<th>(c_2)</th>
<th>(e_i)</th>
</tr>
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<tbody>
<tr>
<td>1</td>
<td>0</td>
<td>1</td>
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<tr>
<td>0</td>
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<td>1</td>
</tr>
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<td>1</td>
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</table>

Next component to be checked is \(c_2\), which is not involved in one failed set.
Thus, the column for that component as well as all conflict sets in which it is involved are removed from \((A, e)\), using the \texttt{Strip} function, yielding the following

<table>
<thead>
<tr>
<th>(i)</th>
<th>(e_i)</th>
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<tbody>
<tr>
<td>1</td>
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<tr>
<td>1</td>
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</tbody>
</table>

Running \texttt{Staccato} with the newly generated \((A, e)\) yields a ranking with component 1 only (line 15–18), which is a MHS for the current \((A, e)\). For each MHS \(d\) returned by this invocation of \texttt{Staccato}, the union of \(d\) and \(c_2\) is checked \(\{1, 2\}\), and because this set is involved in all failed sets, and is minimal, it is also added to the list of solutions \(D\) (lines 18–24). The same would be done for \(c_1\), the last in the ranking, but no minimal set would be found. Thus, \texttt{Staccato} would return the following minimal hitting sets \(\{\{3\}, \{1, 2\}\}\). Note that this heuristic ranks component 2 on top of component 1, whereas the previous heuristic ranked component 1 and 2 at the same place (because they both explained the same number of conflicts).

In the above example the two parameters were set at \(\lambda = 1\) (relative search depth), and \(L = \infty\) (maximum number of solutions returned) which results in a full search (i.e., \texttt{Staccato} is complete). In practice, however, we exploit \texttt{Staccato}’s focusing property by (1) decreasing \(\lambda\) such that only the top fraction \(\lambda\) of components in the ranking are actually selected in each recursion, and (2) aborting the search after \(L\) solutions have been returned. Experiments for synthetic problems have shown that \(\lambda = 0.1\) hardly sacrifices completeness where none of the more important MHS solutions are missed, and that virtually the entire probability mass is returned in less than the first \(L = 100\) solutions [1]. As a result, \texttt{Staccato} allows our diagnostic approach to be applied to very large systems.

In terms of the algorithm, \texttt{Staccato} comprises the following steps:

- Initialization phase, where a ranking of components using the heuristic function borrowed from SFL is computed (lines 1–4 in Algorithm 1);
- Components that are involved in all failed sets are added to \(D\) (lines 5–12);
- While \(|D| < L\), for the first top \(\lambda\) components in the ranking (including also the ones added to \(D\), lines 13–25) do the following: (1) remove the component \(j\) and all \(A_i e\) for which \(e_i = 1 \land a_{ij} = 1\) holds from \((A, e)\)
(line 17), (2) run \textsc{Staccato} with the new \((A, e)\), and (3) combine the solutions returned with the component and verify whether it is a minimal hitting set (lines 17–24).

We conclude this section with a complexity analysis of \textsc{Staccato}. To find a minimal hitting set of cardinality \(C\) \textsc{Staccato} has to be (recursively) invoked \(C\) times. Each time \textsc{Staccato} (1) updates the four counters per component \(O(N \cdot M)\), (2) ranks components in fault likelihood \(O(M \cdot \log M)\), (3) traverses \(\lambda\) components in the ranking \(O(M)\), and (4) checks whether it is a minimal hitting set \((O(N))\). Hence, the overall time complexity of \textsc{Staccato} is \(O((M \cdot (N + \log M))^C)\). In practice, however, due to the search focusing heuristic the time complexity is merely \(O(C \cdot M \cdot (N + \log M))\). With respect to space complexity, for each invocation of \textsc{Staccato} the algorithm has to store four counters per component to create the SFL-based ranking \((n_{11}, n_{10}, n_{01}, n_{00})\). As the recursion depth is \(C\) to find a solution of the same cardinality, \textsc{Staccato} has a space complexity of \(O(C \cdot M)\). In [1] it has been verified that \textsc{Staccato} generates solutions with high search efficiency, ordered such that all posterior probability mass is concentrated in the first \(L\) solutions. Experiments involving activity matrices of size \(30 \times 300\) show that diagnostic accuracy is optimal for as low as \(L \geq 100\). The performance benefits of our approach is exemplified by the fact that matrices with \(M = 1,000,000\), \(N = 1,000\), and \(C = 1,000\) are processed with an average solution rate of 88.6 ms (2.3 GHz Intel Pentium-6 PC with 4 GB memory).

4. Candidate Probability Computation: Barinel

In this section we present our approach to compute the \(g_j\) and the associated, posterior candidate probabilities \(\Pr(d_k)\) given the observations \((A, e)\). In our approach we (1) determine the real \(g_j\) instead of \(g(d_k)\), and (2) apply the \(g_j\) in an improved epsilon policy to compute \(\Pr(\text{obs}|d_k)\). The key idea underlying our approach is that for each candidate \(d_k\) we compute the \(g_j\) for the candidate’s faulty components that \textit{maximizes the probability} \(\Pr(e|d_k)\) \textit{of the observations} \(e\) \textit{occurring, conditioned on that candidate} \(d_k\) \textit{(maximum likelihood estimation for naive Bayes classifier} \(d_k)\). For a given process \(i\), in terms of \(g_j\) the epsilon policy for (possibly) intermittent components is given
by

$$\varepsilon = \begin{cases} \prod_{j \in d_k \land a_{ij} = 1} g_j & \text{if } e_i = 0 \\ 1 - \prod_{j \in d_k \land a_{ij} = 1} g_j & \text{if } e_i = 1 \end{cases}$$ \quad (6)$$

Eq. 6 reflects the fact that the probability of a process failure is one minus the probability that none of the candidate components induce a failure ($g_j$ per component, the product comes from the failure independence assumption, a common assumption in the diagnosis community).

In our approach $g_j$ is solved by maximizing $Pr(e|d_k)$ under the above epsilon policy, according to

$$G = \arg \max_G Pr(e|d_k)$$

where $G = \{g_j | j \in d_k\}$. Note that for a particular candidate $d_k$ the optimum $g_j$ values may differ with those for another candidate $d'_k$ for the same components.

Our approach, of which the implementation is coined BARINEL, is described in Algorithm 2 and comprises three main phases. In the first phase (line 2) a list of candidates $D$ is computed from $(A, e)$ using STACCATO that returns a list of most probable diagnosis candidates (in our experiments $L = 100$ candidates).

In the second phase $Pr(d_k|(A, e))$ is computed for each $d_k \in D$ (lines 3 to 15). First, GENERATEPR derives for every candidate $d_k$ the probability $Pr(e|d_k)$ for the current set of observations $e$. As an example, suppose the following measurements when $c_1, c_2$ are at fault (ignoring the healthy components):

| $c_1$ | $c_2$ | ... | $e$ | $Pr(e_i|\{1,2\})$ |
|------|------|-----|-----|------------------|
| 1    | 0    | ... | 1   | $1 - g_1$       |
| 1    | 1    | ... | 1   | $1 - g_1 \cdot g_2$ |
| 0    | 1    | ... | 0   | $g_2$           |
| 1    | 0    | ... | 0   | $g_1$           |

As the four observations are independent, the probability of obtaining $e$ given $d_k = \{1, 2\}$ equals (Eq. 6).

$$Pr(e|d_k) = g_1 \cdot g_2 \cdot (1 - g_1) \cdot (1 - g_1 \cdot g_2)$$

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Subsequently, all $g_j$ are computed such that they maximize $\Pr(e|d_k)$. To solve the maximization problem we apply a simple gradient ascent procedure [6] (bounded within the domain $0 < g_j < 1$). The motivation behind the choice for a simple, linearly converging, optimization procedure over, e.g., a quadratically convergent, but much more complex procedure, is our focus on demonstrating the added diagnostic accuracy due to our maximum likelihood estimation approach, rather than to minimize computation cost. Moreover, even with the simple optimization scheme, all the test programs are already processed by BARINEL in the order of seconds.

In the third and final phase, the diagnoses are ranked according to $\Pr(d_k|(A, e))$, which is computed by EVALUATE according to the usual, posterior update (Eq. 1).

For single-fault candidates, the maximum likelihood estimator for $g_1$ equals the intermittency rate $\sum_i e_i/N$, which is the intuitive way to determine $g_1$ for single faults. Consider the following $(A, e)$ (only showing the $c_1$ column and the rows where $c_1$ is hit), $e$, and the probability of that occurring ($\Pr$):

| $c_1$ | $e$ | $\Pr(e_i|d_k)$ |
|-------|-----|----------------|
| 1     | 0   | $g_1$          |
| 1     | 0   | $g_1$          |
| 1     | 1   | $1 - g_1$      |
| 1     | 0   | $g_1$          |

As $\Pr(e|\{1\})$ is given by $\Pr(e|\{1\}) = g_j^3 \cdot (1 - g_1)$, the value of $g_1$ that maximizes $\Pr(e|\{1\})$ is $\frac{3}{4}$, which is easily found by differentiating the expression and determining the zero root. From $e$ we find the same intermittency rate $g_1 = \frac{3}{4}$. While averaging over $e$ offers a low-cost, analytic solution to computing $g_j$, this approach only works for single faults, motivating our numeric (gradient ascent) alternative in the multiple-fault case, in contrast to the approximate, averaging techniques ($\varepsilon^{(1,2)}$) published thusfar.

Finally, to illustrate the benefits of our approach, consider the example presented in Section 2.4. As mentioned in the previous section, $\varepsilon^{(0)}$ does not distinguish between candidates with the same cardinality. As (i) candidates rank with the same probability and (ii) the true fault has cardinality 2, all candidates with cardinality 1 and 2 would have to be inspected. $\varepsilon^{(1,2)}$ distinguishes between candidates with the same cardinality, but $\{2110, 2745\}$ and $\{2682, 2748\}$ outrank the true fault $\{2553, 2763\}$. BARINEL yields better results due to a better estimation of estimation of the individual $g_j$, ranking the
Algorithm 2 Diagnostic Algorithm: BARINEL

**Inputs:** Activity matrix $A$, error vector $e$,

**Output:** Diagnostic Report $D$

1. $\gamma \leftarrow \epsilon$
2. $D \leftarrow \text{STACCATO}((A,e),1,100)$ \triangleright Compute MHS
3. for all $d_k \in D$ do
4.     $\text{expr} \leftarrow \text{GENERATEPR}((A,e),d_k)$
5.     $i \leftarrow 0$
6.     $\text{Pr}[d_k]^i \leftarrow 0$
7.     $\forall j \in d_k \ g_j \leftarrow 0.5$
8.     repeat
9.         $i \leftarrow i + 1$
10.        for all $j \in d_k$ do
11.            $g_j \leftarrow g_j + \gamma \cdot \nabla \text{expr}(g_j)$
12.        end for
13.        $\text{Pr}[d_k]^i \leftarrow \text{EVALUATE}(\text{expr}, \forall j \in d_k \ g_j)$
14.     until $|\text{Pr}[d_k]^{i-1} - \text{Pr}[d_k]^i| \leq \xi$
15. end for
16. return $\text{sort}(D, \text{Pr})$

true fault $\{2553,2763\}$ before all the other diagnosis candidates considered:

<table>
<thead>
<tr>
<th>$d_k$</th>
<th>$g_j$</th>
<th>$\text{Pr}(d_k)$</th>
</tr>
</thead>
<tbody>
<tr>
<td>${2553,2763}$</td>
<td>$g_{2553} = 0.94 \quad g_{2746} = 0.001$</td>
<td>$7.8 \times 10^{-4}$</td>
</tr>
<tr>
<td>${2110,2745}$</td>
<td>$g_{2110} = 0.26 \quad g_{2745} = 0.95$</td>
<td>$3.6 \times 10^{-5}$</td>
</tr>
<tr>
<td>${2682,2745}$</td>
<td>$g_{2682} = 0.26 \quad g_{2745} = 0.15$</td>
<td>$9.0 \times 10^{-5}$</td>
</tr>
<tr>
<td>${1347}$</td>
<td>$g_{1347} = 0.94$</td>
<td>$5.8 \times 10^{-20}$</td>
</tr>
</tbody>
</table>

As the $g_j$ expressions that need to be maximized are simple and bounded in the $[0,1]$ domain, the time/space complexity of our approach is identical to the other reasoning policies presented in Section 2 modulo a small, near-constant factor on account of the gradient ascent procedure, which exhibits rapid convergence for all $M$ and $C$ (see Section 6).

5. Theoretical Evaluation

In order to assess the performance improvement of our framework we generate synthetic observations based on sample $(A, e)$ generated for various
values of $N$, $M$, and number of injected faults $C$ (cardinality). The motivation for using synthetic data next to real-world data is the ability to study the effect of the various parameters in a controlled setting whereas real programs only represent a few parameter settings in the multi-dimensional parameter space.

Component activity $a_{ij}$ is sampled from a Bernoulli distribution with parameter $r$, i.e., the probability a component is involved in a row of $A$ equals $r$. For the $C$ faulty components $c_j$ (without loss of generality we select the first $C$ components) we also set $g_j$. Thus the probability of a component being involved and generating a failure equals $r \cdot (1 - g)$. A row $i$ in $A$ generates an error ($e_i = 1$) if at least 1 of the $C$ components generates a failure. Measurements for a specific $(N, M, C, r, g)$ scenario are averaged over 1,000 sample matrices, yielding a coefficient of variance of approximately 0.02.

We compare the accuracy of our approach with previous work in terms of a diagnostic performance metric $W$, that denotes the excess diagnostic work spent in finding the actual components at fault. The metric is an improvement on metrics typically found in the software debugging domain which measure the debugging effort associated with a particular diagnostic method [3, 29]. For instance, consider a $M = 5$ component program with the following diagnostic report $D = \langle \{4, 5\}; \{4, 3\}; \{1, 2\} \rangle$ while $c_1$ and $c_2$ are actually faulty. The first diagnosis candidate leads the developer to inspect $c_4$ and $c_5$. As both components are healthy, $W$ is increased with 2.5. Using the new information that $g_4 = g_5 = 1.0$ the probabilities of the remaining candidates are updated, leading to $Pr(\{4, 3\}) = 0$ ($c_4$ can no longer be part of a multiple fault). Consequently, candidate $\{4, 3\}$ is also discarded, avoiding wasting additional debugging effort. The next components to be inspected are $c_1$ and $c_2$. As they are both faulty, no more effort is wasted. Consequently, $W = \frac{2.5}{3}$.

The graphs in Figure 2 plot $W$ versus $N$ for $M = 20$, $r = 0.6$ (the trends for other $M$ and $r$ values are essentially the same, $r = 0.6$ is typical for real software as found in the Siemens suite), and different values for $C$ and $g$. The plots show that $W$ for $N = 1$ is similar to $r$, which corresponds to the fact that there are on average $(M - C) \cdot r$ components which would have to be inspected in vain. For sufficiently large $N$ all policies produce an optimal diagnosis, as the probability that healthy diagnosis candidates are still within the hitting set approaches zero.

For small $g_j$ $W$ converges more quickly than for large $g_j$ as computa-
Figure 2: Wasted effort $W$ vs. $N$ for several settings of $C$ and $g$

Sections involving the faulty components are much more prone to failure, while for large $g_j$ the faulty components behave almost nominally, requiring more observations (larger $N$) to rank them higher. For increasing $C$ more obser-
vations are required \((N)\) before the faulty components are isolated. This is due to the fact that failure behavior can be caused by much more components, reducing the correlation between failure and particular component involvement.

The plots confirm that \(\varepsilon^{(0)}\) is the worst performing policy, mainly due to the fact that it does not distinguish between diagnosis with the same fault cardinality. Only for \(C = 1\) the \(\varepsilon^{(2)}\) and \(\varepsilon^{(1)}\) policies have equal performance to BARINEL, as for this trivial case the approximations for \(g_j\) are equal. For \(C = 5\) the plots confirm that BARINEL has superior performance, demonstrating that a correct computation of \(g_j\) is quite relevant. In particular, the other approaches deteriorate for increasing \(C\).

6. Empirical Evaluation

In this section, we evaluate the diagnostic capabilities and efficiency of the diagnosis techniques for real programs.

6.1. Experimental Setup

For evaluating the performance of our approach we use the well-known Siemens benchmark set, as well as the larger programs space, gzip, and sed (obtained from SIR [13]). The Siemens suite is composed of seven programs. Every single program has a correct version and a set of faulty versions of the same program. Although the faulty may span through multiple statements and/or functions, each faulty version contains exactly one fault. For each program a set of inputs is also provided, which were created with the intention to test full coverage. The Space package provides 1,000 test suites that consist of a random selection of (on average) 150 test cases and guarantees that each branch of the program is exercised by at least 30 test cases. In our experiments, the test suite used is randomly chosen from the 1,000 suites provided.

Table 3 provides more information about the programs used in our experiments, where \(M\) corresponds to the number of lines of code (components in this context).

For our experiments, we have extended the subject programs with program versions where we can activate arbitrary combinations of multiple faults. For this purpose, we limit ourselves to a selection of 143 out of the 183 faults, based on criteria such as faults being attributable to a single line of code, to enable unambiguous evaluation.
As each program suite includes a correct version, we use the output of the correct version as reference. We characterize a run as failed if its output differs from the corresponding output of the correct version, and as passed otherwise.

### 6.2. Performance Results

In this section we evaluate the diagnostic capabilities of Barinel and compare it with other Bayesian policies. Similar to Section 5, we aimed at $C = 5$ for the multiple fault-cases, but for `print_tokens` insufficient faults are available. All measurements except for the four-fault version of `print_tokens` are averages over 100 versions, or over the maximum number of combinations available, where we verified that all faults are active in at least one failed run.

Table 4 presents a summary of the diagnostic quality of the different approaches, expressed in terms of wasted debugging effort $W$ (see Section 5). In agreement with the previous section, the results for software systems confirm that on average Barinel outperforms the other approaches, especially considering the fact that the variance of $W$ is considerably higher (coefficient of variance up to 0.5 for `schedule2`) than in the synthetic case (1,000 sample matrices versus at most 100 matrices in the experiments with real software programs). Only in 4 out of 30 cases, Barinel is not on top. Apart from the obvious sampling noise (variance), this is due to particular properties of the programs. Using the paired two-tailed Student’s t-test, we verified that the differences in the means of $W$ are not significant for those cases where

<table>
<thead>
<tr>
<th>Program</th>
<th>Faulty Versions</th>
<th>$M$</th>
<th>$N$</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>print_tokens</code></td>
<td>7</td>
<td>539</td>
<td>4,130</td>
<td>Lexical Analyzer</td>
</tr>
<tr>
<td><code>print_tokens2</code></td>
<td>10</td>
<td>489</td>
<td>4,115</td>
<td>Lexical Analyzer</td>
</tr>
<tr>
<td><code>replace</code></td>
<td>32</td>
<td>507</td>
<td>5,542</td>
<td>Pattern Recognition</td>
</tr>
<tr>
<td><code>schedule</code></td>
<td>9</td>
<td>397</td>
<td>2,650</td>
<td>Priority Scheduler</td>
</tr>
<tr>
<td><code>schedule2</code></td>
<td>10</td>
<td>299</td>
<td>2,710</td>
<td>Priority Scheduler</td>
</tr>
<tr>
<td><code>tcas</code></td>
<td>41</td>
<td>174</td>
<td>1,608</td>
<td>Altitude Separation</td>
</tr>
<tr>
<td><code>tot_info</code></td>
<td>23</td>
<td>398</td>
<td>1,052</td>
<td>Information Measure</td>
</tr>
<tr>
<td><code>space</code></td>
<td>38</td>
<td>9,564</td>
<td>13,585</td>
<td>ADL Interpreter</td>
</tr>
<tr>
<td><code>gzip-1.3</code></td>
<td>7</td>
<td>5,680</td>
<td>210</td>
<td>Data compression</td>
</tr>
<tr>
<td><code>sed-4.1.5</code></td>
<td>6</td>
<td>14,427</td>
<td>370</td>
<td>Textual manipulator</td>
</tr>
</tbody>
</table>

Table 3: The subject programs
Barinel does not clearly outperform the other approaches, and thus the noise is the cause for the small differences in terms of $W$. As an example, for print_tokens2 with $C = 2$ the differences in the means are significant, but it is not the case for schedule with $C = 1$. For tcas with $C = 2$ and $C = 5$, $\varepsilon^{(2)}$ marginally outperforms Barinel (by less than 0.5%), which is caused by the fact that (i) the program is almost branch-free and small ($M = 174$) combined with large sampling noise ($\sigma_W/\mu_W = 5\%$ for tcas), and (ii) almost all failing runs involve all faulty components (highly correlated occurrence). For schedule2 with $C = 2$ and $C = 5$, $\varepsilon^{(0)}$ is better due to the fact that almost all failing runs involve all faulty components (highly correlated occurrence). Hence, the program effectively has a single fault spreading over multiple lines, which favors $\varepsilon^{(0)}$ since it ranks candidates with cardinality one first.

6.3. Time/Space Complexity

In this section we report on the time/space complexity of Barinel. We measure the time efficiency by conducting our experiments on a 2.3 GHz Intel Pentium-6 PC with 4 GB of memory.

Table 5 summarizes the timing results. The columns show the programs, the average CPU time (in seconds) of Barinel, $\varepsilon^{(0)}$, $\varepsilon^{(1)}$, and $\varepsilon^{(2)}$, needed to compute the diagnostic report $D$ given $(A, e)$. In all cases, we use Staccato to generate the candidates. As expected, Barinel is more expensive than the previous, approximate Bayesian approaches. For example, Barinel requires about 42 seconds on average for space, whereas $\varepsilon^{(0,1,2)}$ needs less than 1 second. the reason is the numeric, gradient ascent procedure. The effect of the gradient ascent costs is clearly noticeable for the first three programs, as well as space, and is due to a somewhat lower convergence speed as a result of the fact that the $h_j$ are close to 1. Note, however, that the implementation has not been optimized. By using a procedure with quadratic convergence the performance penalty would largely disappear (e.g., 100 iterations instead of 10,000, gaining two orders of magnitude of speedup over linear convergence).

In the following we interpret the above cost measurements from a complexity point of view. All techniques update $|D|$ candidate probabilities, where $|D|$ is determined by Staccato. The complexity of Staccato is estimated to be $O(N \cdot M)$ (for a constant matrix density $r$) [1]. Although in all our measurements a constant $|D| = 100$ suffices, it is not unrealistic to assume that for very large systems $|D|$ would scale with $M$, again, yielding
Table 4: Wasted effort $W$ [%] on combinations of $C = 1 − 5$ faults for the subject programs
\(O(N \cdot M)\) for the probability updates. For \textsc{Barinel} the complexity of the maximization procedure appears to be rather independent of the size of the expression (i.e., \(M\) and \(C\)) reducing this term to a constant. As the report is ordered, the time complexity equals \(O(N \cdot M + M \cdot \log M)\). The results in Table 5 follow the trends predicted by this complexity analysis.

With respect to space complexity, previous Bayesian approaches need two store the counters \((n_{11}, n_{10}, n_{01}, n_{00})\) used in the probability update per candidate. Assuming that \(|D|\) scales with \(M\), these approaches have \(O(M)\) space complexity. \textsc{Barinel} is slightly more expensive because for a given diagnosis \(d_k\) it stores the number of times a combination of faulty components in \(d_k\) is observed in passed runs \((2^{d_k} - 1)\) and in failed runs \((2^{d_k} - 1)\). Thus, \textsc{Barinel}'s space complexity is estimated to be \(O(2^C \cdot M)\) - being slightly more complex than previous, approximate Bayesian approaches. In practice, however, memory consumption is reasonable (e.g., around 5.3 MB for \texttt{sed}, the largest program used in our experiments).

<table>
<thead>
<tr>
<th>Program</th>
<th>\textsc{Barinel}</th>
<th>(e^{(0,1,2)})</th>
</tr>
</thead>
<tbody>
<tr>
<td>print_tokens</td>
<td>45.3</td>
<td>4.2</td>
</tr>
<tr>
<td>print_tokens2</td>
<td>24.7</td>
<td>4.7</td>
</tr>
<tr>
<td>replace</td>
<td>9.6</td>
<td>6.2</td>
</tr>
<tr>
<td>schedule</td>
<td>4.1</td>
<td>2.5</td>
</tr>
<tr>
<td>schedule2</td>
<td>2.9</td>
<td>2.5</td>
</tr>
<tr>
<td>tcass</td>
<td>1.5</td>
<td>1.4</td>
</tr>
<tr>
<td>t_tot_info</td>
<td>1.5</td>
<td>1.2</td>
</tr>
<tr>
<td>space</td>
<td>41.4</td>
<td>0.9</td>
</tr>
<tr>
<td>gzip</td>
<td>28.1</td>
<td>8.2</td>
</tr>
<tr>
<td>sed</td>
<td>92</td>
<td>6.7</td>
</tr>
</tbody>
</table>

Table 5: Diagnosis cost (time in seconds)

7. Related Work

As mentioned earlier, in many model-based diagnosis approaches (e.g., GDE [12] GDE+ [30], CDA* [31], SAFARI [14]) faults are assumed to be persistent. Consequently, they may not work optimally when components fail intermittently. Recently, a model for intermittent behavior was introduced as an extension of the GDE framework [9], later extended by [4, 5]. As shown by our results, our approach improves on the approximations within these works,
providing better results. This paper extends earlier work [2] by (i) including a full description of our MHS algorithm \textsc{Staccato}, and (ii) including the three, large, real-world programs into the experimental evaluation (\texttt{space}, \texttt{sed}, \texttt{gzip}).

Our approach to diagnosing multiple, intermittent faults has been developed and applied in a software fault diagnosis context. In model-based reasoning approaches to automatic software debugging, the model is typically generated from the source code - see [24] for an evaluation of several models. The model is generated by means of static analysis techniques, and is extremely complex. While at this detailed level intermittency is not an issue, the level of detail is such that the associated diagnostic complexity prohibits application to programs larger than a few hundred lines of code. As an indication, the largest program used in [24] is \texttt{tcas} (172 lines of code only). In contrast, our low-cost algorithm scales to hundreds of thousands of lines of code. Reasoning approaches based on model checkers include \texttt{explain} [18], and \texttt{Δ}-slicing [18], which compare execution traces of correct and failed runs. However, in contrast to our approach, these are not fully automatic as the system under analysis needs to be annotated with pre- and post-conditions to facilitate the generation of the model. In addition, they seem not to scale judging by the fact that the authors have only evaluated these approaches with small programs (only up to 174 lines of code).

Our dynamic approach towards determining component involvement and system failure (i.e., through \((A,e)\)) is inspired by statistical approaches to automatic software debugging, known as spectrum-based fault localization (each row in \(A\) is a spectrum). Well-known examples include the Tarantula tool [20], the Nearest Neighbor technique [29], and the Ochiai coefficient [3]. These approaches rank components in terms of the statistical similarity of component involvement and observed program failure behavior. While attractive from complexity-point of view, the approaches do not consider multiple faults. Furthermore, the similarity metric has little value other than for ranking, in contrast to our probability metric.

As for MHS computation, since Reiter [28] showed that diagnoses are MHSs of conflict sets, many (exhaustive) MHS algorithms have been presented in an MBD context. In [17, 12, 28, 32] the hitting set problem is solved using so-called hit-set trees. In [15] the MHS problem is mapped onto an 1/0-integer programming problem. Contrary to our work they do not consider any other information but the conflict sets. It is claimed that the integer programming approach has the potential to solve problems with thou-
sands of variables but no complexity results are presented. In contrast, our low-cost approach can easily handle much larger problems. In [33] a method using set-enumeration trees to derive all minimal conflict sets in the context of model-based diagnosis is presented. The authors merely conclude that this method has an exponential time complexity in the number of elements in the sets (components). The Quine-McCluskey algorithm [27, 25], originating from logic optimization, is a method for deriving the prime implicants of a monotone boolean function (a dual problem of the MHS problem). This algorithm is, however, of limited use due to its exponential complexity, which has prompted the development of heuristics such as Espresso (discussed later on).

Many heuristic approaches have been proposed to render MHS computation amenable to large systems. In [23] an approximate method to compute MHSs using genetic algorithms is described. The fitness function used aims at finding solutions of minimal cardinality, which is not always sufficient for MBD as even solutions with similar cardinality have different posterior probabilities. Their paper does not present a time complexity analysis, but we suspect the cost/completeness trade-off to be worse than for STACCATO.

Stochastic algorithms, as discussed in the framework of constraint satisfaction [16] and propositional satisfiability [26], are examples of domain independent approaches to compute MHS. Stochastic algorithms are more efficient than exhaustive methods. The Espresso algorithm [7], primarily used to minimize logic circuits, uses a heuristic to guide the circuit minimization that is inspired by this domain. Due to its efficiency, this algorithm still forms the basis of every logic synthesis tool. Dual to the MHS problem, no prime implicants cost/completeness data is available to allow comparison with STACCATO. To our knowledge the statistics-based heuristic to guide the search for computing MHS solutions has not been presented before. Compared to the above approaches, a unique feature is its heuristic which, given its SFL origin, is specifically tailored to model-based diagnosis.

8. Conclusions and Future Work

Intermittent fault models can be crucial when modeling complex systems. Estimating the probability that a faulty component exhibits correct behavior is an important step for logic reasoning approaches to properly handle intermittent failures. In contrast to previous work, which merely approximates such probabilities for particular diagnosis candidates, in this paper
we present a novel, maximum likelihood estimation approach (BARINEL) to compute the exact probabilities per component at a complexity that is only a constant factor greater than previous approaches due to the use of a heuristic minimal hitting set algorithm (STACCATO) underlying the candidate generation process.

We have compared the diagnostic performance of BARINEL with the classical (Bayesian) reasoning approach, as well as with three intermittent reasoning approaches. Synthetic experiments have confirmed that our approach consistently outperforms the previous approaches, demonstrating the significance of maximum likelihood estimation over approximation. Application to the Siemens benchmark, gzip, sed, and space also suggest BARINEL’s superiority (26 wins out of 30 trials), while the exceptions are caused by component clustering in combination with sampling noise.

Future work includes extending the activity matrix from binary to integer, to exploit component involvement frequency data (e.g., program loops), and reducing the cost of gradient ascent by introducing quadratic convergence techniques.

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References


