



Expected Cost Analysis of Probabilistic Programs

Research Seminar WS21/22

Jonas Schöpf

November 24, 2021

Motivation

- model natural/physical processes \Rightarrow “real” coin flip

Motivation

- model natural/physical processes \Rightarrow “real” coin flip
- cryptography \Rightarrow primality tests

Motivation

- model natural/physical processes \Rightarrow “real” coin flip
- cryptography \Rightarrow primality tests
- robotics

Motivation

- model natural/physical processes \Rightarrow “real” coin flip
- cryptography \Rightarrow primality tests
- robotics
- machine learning

Motivation

- model natural/physical processes \Rightarrow “real” coin flip
- cryptography \Rightarrow primality tests
- robotics
- machine learning
- improvement of algorithms, e.g., quicksort

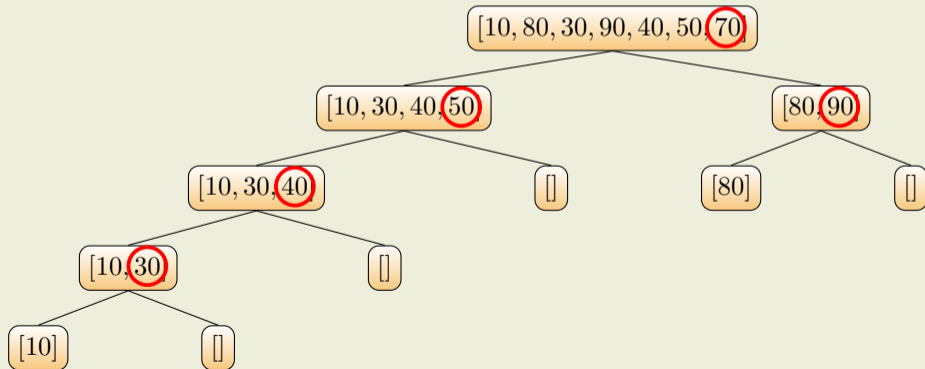
Motivation - Quicksort

- “standard” vs. randomized quicksort

Motivation - Quicksort

- “standard” vs. randomized quicksort

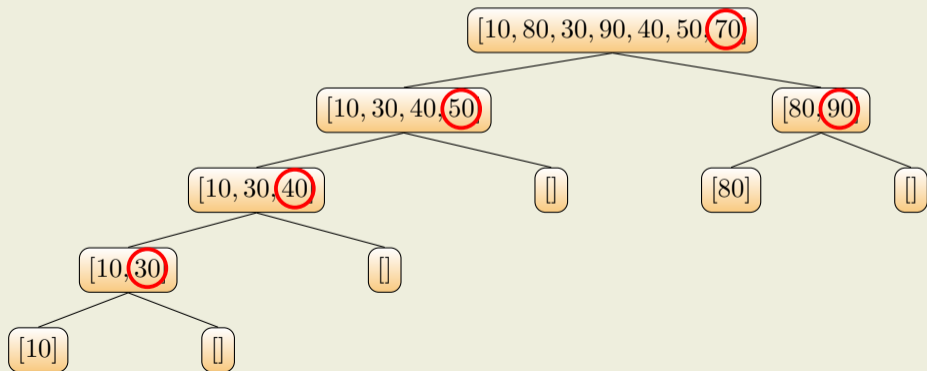
Example Quicksort



Motivation - Quicksort

- “standard” vs. randomized quicksort
- *first vs. last vs. random vs. median* pivot element

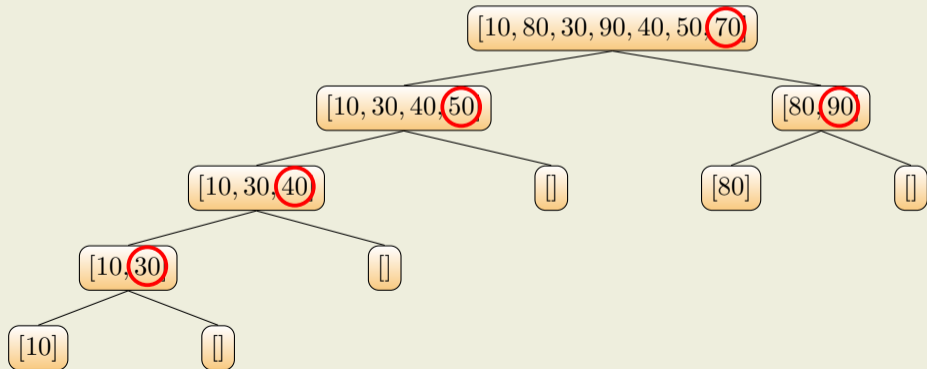
Example Quicksort



Motivation - Quicksort

- “standard” vs. randomized quicksort
- *first* vs. *last* vs. *random* vs. *median* pivot element
- worst case: $O(n^2)$ vs. $O(n^2)$ (BUT expected or average time complexity is $O(n \log n)$)

Example Quicksort



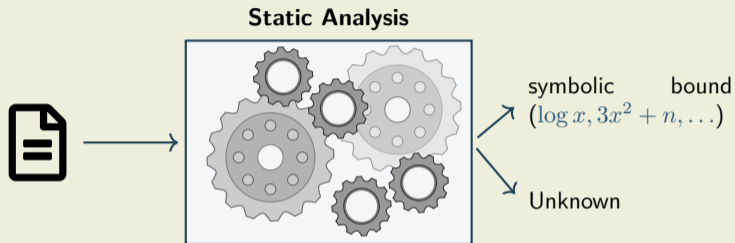
Overview

- Primer
- ERT
- ECT – Syntax & Semantic
- Automation
- Summary

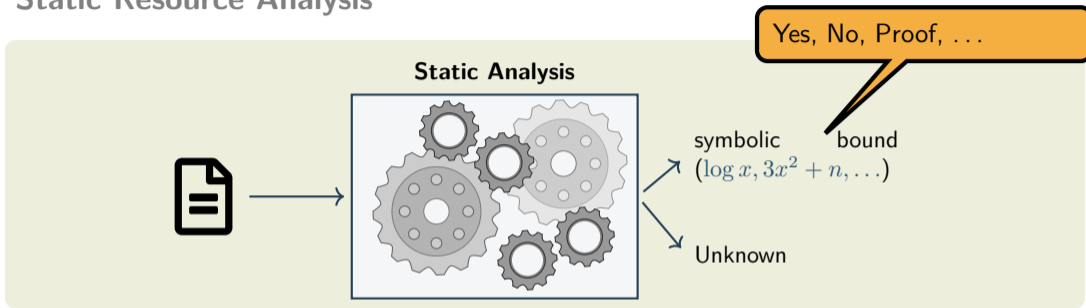
Overview

- Primer
- ERT
- ECT – Syntax & Semantic
- Automation
- Summary

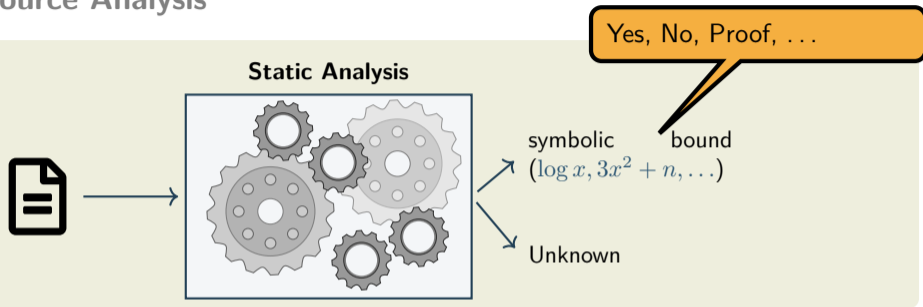
Static Resource Analysis



Static Resource Analysis

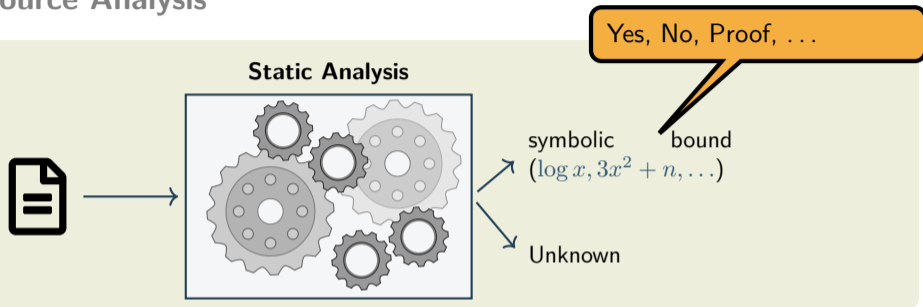


Static Resource Analysis



- integral part of formal verification
- improving the quality of complex software
- medical software, aviation software, nuclear software, ...

Static Resource Analysis



- integral part of formal verification
- improving the quality of complex software
- medical software, aviation software, nuclear software, ...

- recurrence relations
- type systems
- term rewriting
- ...

Non-/Deterministic vs. Probabilistic

Non-/Determi.

Probabilistic

Dynamics

Semantics

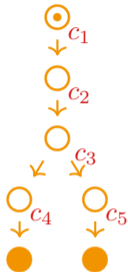


Non-/Deterministic vs. Probabilistic

Non-/Determi.

Probabilistic

Dynamics



Semantics

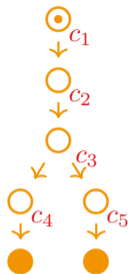


Non-/Deterministic vs. Probabilistic

Non-/Determi.

Probabilistic

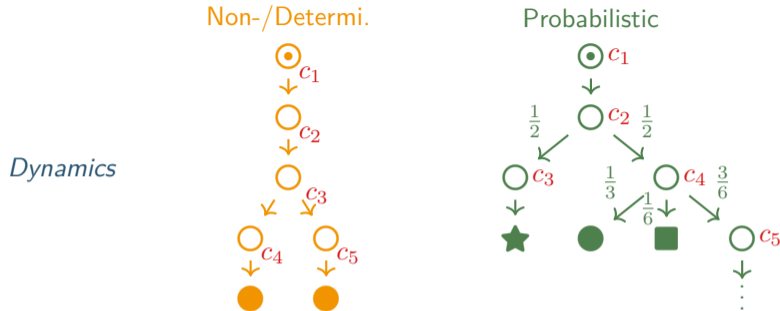
Dynamics



Semantics

- assign cost c_i to each operation
- overall cost is the sum of all operation costs

Non-/Deterministic vs. Probabilistic



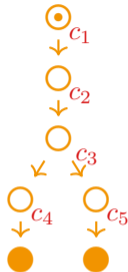
Semantics

- assign cost c_i to each operation
- overall cost is the sum of all operation costs
- deal with probabilities

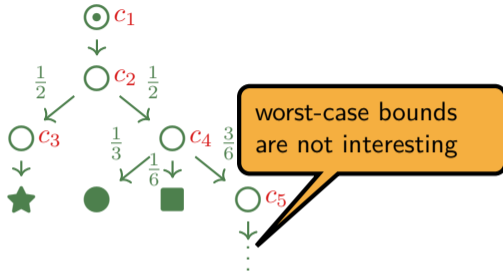
Non-/Deterministic vs. Probabilistic

Dynamics

Non-/Determi.



Probabilistic



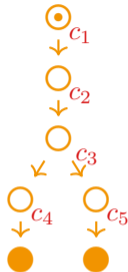
Semantics

- assign cost c_i to each operation
- overall cost is the sum of all operation costs
- deal with probabilities

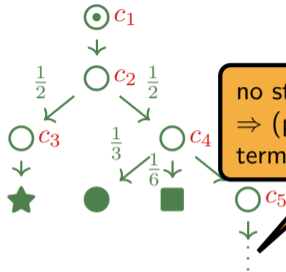
Non-/Deterministic vs. Probabilistic

Dynamics

Non-/Determi.



Probabilistic

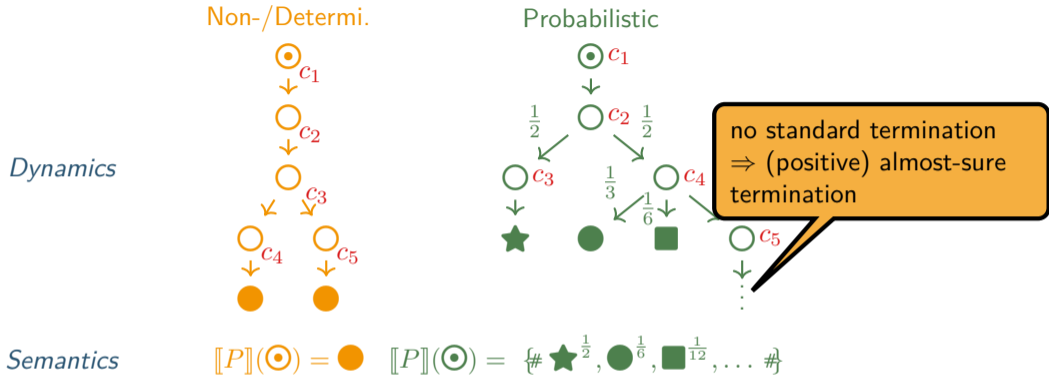


no standard termination
 \Rightarrow (positive) almost-sure
termination

Semantics

- assign cost c_i to each operation
- overall cost is the sum of all operation costs
- deal with probabilities

Non-/Deterministic vs. Probabilistic



- assign cost c_i to each operation
- overall cost is the sum of all operation costs
- deal with probabilities

Overview

- Primer
- **ERT**
- ECT – Syntax & Semantic
- Automation
- Summary

Expected Runtime Transformer

- wp-style calculus
- obtains bounds for the expected runtime of randomized algorithms and proves positive almost-sure termination
- can deal with basic constructs, loops and recursion

Expected Runtime Transformer

- wp-style calculus
- obtains bounds for the expected runtime of randomized algorithms and proves positive almost-sure termination
- can deal with basic constructs, loops and recursion

“Assertions about programs” are predicates that are supposed to be “true at this point of the program”.

Expected Runtime Transformer

- wp-style calculus
- obtains bounds for the expected runtime of randomized algorithms and proves positive almost-sure termination
- can deal with basic constructs, loops and recursion

“Assertions about programs” are predicates that are supposed to be “true at this point of the program”.

Formalized — into logic — it looks as:

	$\{pre\} prog \{post\}$	Hoare-style
or	$pre \Rightarrow wp.prog.post$	Dijkstra-style

Expected Runtime Transformer

- wp-style calculus
- obtains bounds for the expected runtime of randomized algorithms and proves positive almost-sure termination
- can deal with basic constructs, loops and recursion

“Assertions about programs” are predicates that are supposed to be “true at this point of the program”.

Formalized — into logic — it looks as:

or $\{pre\} prog \{post\}$ Hoare-style
 $pre \Rightarrow wp.prog.post$ Dijkstra-style

Example

$$\mathbb{C}^\Sigma \triangleq \{t \mid t : \Sigma \rightarrow \mathbb{R}_{\geq 0}\}$$

Expected Runtime Transformer

- wp-style calculus
- obtains bounds for the expected runtime of randomized algorithms and proves positive almost-sure termination
- can deal with basic constructs, loops and recursion

“Assertions about programs” are predicates that are supposed to be “true at this point of the program”.

Formalized — into logic — it looks as:

or $\{pre\} prog \{post\}$ Hoare-style
 $pre \Rightarrow wp.prog.post$ Dijkstra-style

Example

$$\mathbb{C}^\Sigma \triangleq \{t \mid t : \Sigma \rightarrow \mathbb{R}_{\geq 0}\}$$

$$ert[\bullet] : \mathbb{C} \rightarrow (\mathbb{C}^\Sigma \rightarrow \mathbb{C}^\Sigma)$$

$$ert[\mathbb{C}](f)$$

Overview

- Primer
- ERT
- ECT – Syntax & Semantic
- Automation
- Summary

What Do We Want to Achieve?

We would like to have a calculus which to determine the expected runtime of a probabilistic program or algorithm.

- compositional
- modular
- precise

Furthermore it would be beneficial if termination follows from this calculus.

Probabilistic While (`pWhile`)

- inspired by Dijkstra's Guarded Command Language (GCL)

Probabilistic While (`pWhile`)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Syntax of pWhile

$C, D ::=$

| skip

| abort

| $C;D$

| $\text{if}(\phi) \{C\} \{D\}$

| $\text{while}(\phi) \{C\}$

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Syntax of pWhile

```
C, D ::= x := d
      | skip
      | abort

      | C;D
      | if( $\phi$ ) {C} {D}
      | while( $\phi$ ) {C}
```

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Syntax of pWhile

```
C, D ::=  x := d
        | skip
        | abort

        | C;D
        | if( $\phi$ ) {C} {D}
        | while( $\phi$ ) {C}
        | {C} <> {D}
```

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Syntax of pWhile

```
C, D ::=  x := d
        | skip
        | abort
        | consume(e)
        | C;D
        | if( $\phi$ ) {C} {D}
        | while( $\phi$ ) {C}
        | {C} <> {D}
```

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Syntax of pWhile

```
C, D ::=  x := d
         | skip
         | abort
         | consume(e)
         | C;D
         | if( $\phi$ ) {C} {D}
         | while( $\phi$ ) {C}
         | {C} <> {D}
```


Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic constructs

`rand(e), unif(n, m), ber(n, m), ...`

Syntax of pWhile

```
C, D ::=  x := d
         | skip
         | abort
         | consume(e)
         | C;D
         | if( $\phi$ ) {C} {D}
         | while( $\phi$ ) {C}
         | {C} <> {D}
```

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Syntax of pWhile

```
C, D ::=  x := d
        | skip
        | prob(n, m) {C} {D}
        | consume(e)
        | C;D
        | if( $\phi$ ) {C} {D}
        | while( $\phi$ ) {C}
        | {C} <> {D}
```

Probabilistic While (pWhile)

- inspired by Dijkstra's Guarded Command Language (GCL)
- simple (\Rightarrow simplicity in reasoning helps)
- extended with probabilistic behavior

Syntax of pWhile

```
C, D ::=  x := d
        | skip
        | abort
        | consume(e)
        | C;D
        | if( $\phi$ ) {C} {D}
        | while( $\phi$ ) {C}
        | {C} <> {D}
```

Example – geo

```
b := 1;
x := 1;
while(b = 1) {
  consume(1);
  x := x * 2;
  b := ber(1, 1)}
```

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[C](f)$ can be seen as the cost of C w.r.t. a continuation cost f .

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	
skip	f	
abort	0	
$x := d$		
$\mathbf{C};\mathbf{D}$		
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$		
$\text{while}(\phi) \{\mathbf{C}\}$		
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$		

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	
skip	f	
abort	0	
$x := d$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$	
$\mathbf{C};\mathbf{D}$		
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$		
$\text{while}(\phi) \{\mathbf{C}\}$		
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$		

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	
skip	f	
abort	0	
$x := d$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$	
$\mathbf{C};\mathbf{D}$	$\text{ect}[\mathbf{C}](\text{ect}[\mathbf{D}](f))$	
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$		
$\text{while}(\phi) \{\mathbf{C}\}$		
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$		

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	
skip	f	
abort	0	
$x := d$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$	
$\mathbf{C};\mathbf{D}$	$\text{ect}[\mathbf{C}](\text{ect}[\mathbf{D}](f))$	
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$	$[\phi] \cdot \text{ect}[\mathbf{C}](f) + [\neg\phi] \cdot \text{ect}[\mathbf{D}](f)$	
$\text{while}(\phi) \{\mathbf{C}\}$		
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$		

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	
skip	f	
abort	0	
$x := d$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$	
$\mathbf{C};\mathbf{D}$	$\text{ect}[\mathbf{C}](\text{ect}[\mathbf{D}](f))$	
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$	$[\phi] \cdot \text{ect}[\mathbf{C}](f) + [\neg\phi] \cdot \text{ect}[\mathbf{D}](f)$	
$\text{while}(\phi) \{\mathbf{C}\}$	$\text{lfp}(\lambda F. [\phi] \cdot \text{ect}[\mathbf{C}](F) + [\neg\phi] \cdot f)$	
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$		

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	
skip	f	
abort	0	
$x := d$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$	
$\mathbf{C};\mathbf{D}$	$\text{ect}[\mathbf{C}](\text{ect}[\mathbf{D}](f))$	
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$	$[\phi] \cdot \text{ect}[\mathbf{C}](f) + [\neg\phi] \cdot \text{ect}[\mathbf{D}](f)$	
$\text{while}(\phi) \{\mathbf{C}\}$	$\text{lfp}(\lambda F. [\phi] \cdot \text{ect}[\mathbf{C}](F) + [\neg\phi] \cdot f)$	
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$	$\max(\text{ect}[\mathbf{C}](f), \text{ect}[\mathbf{D}](f))$	

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

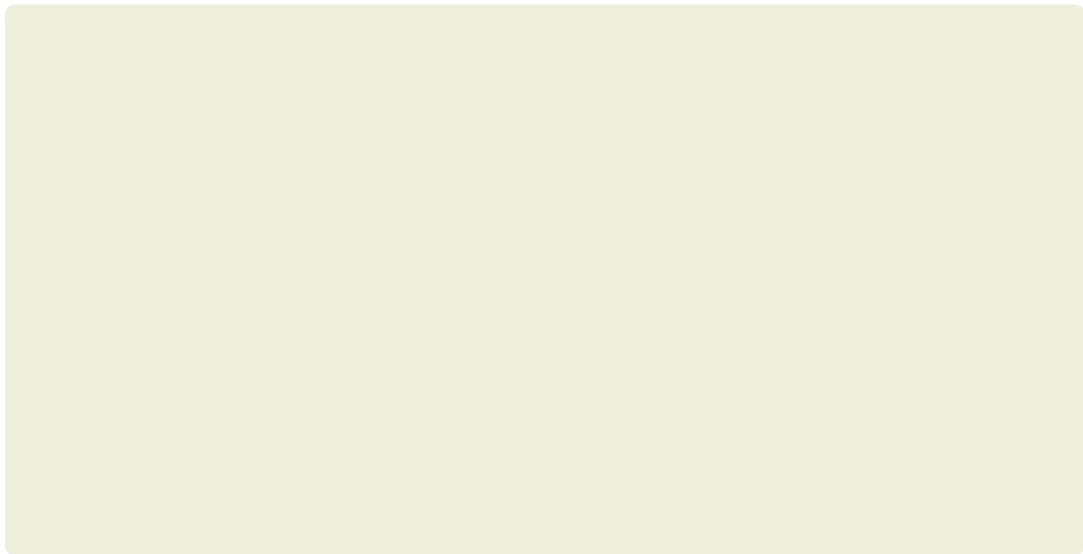
\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	f
skip	f	f
abort	0	0
$x := d$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$
$\mathbf{C};\mathbf{D}$	$\text{ect}[\mathbf{C}](\text{ect}[\mathbf{D}](f))$	
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$	$[\phi] \cdot \text{ect}[\mathbf{C}](f) + [\neg\phi] \cdot \text{ect}[\mathbf{D}](f)$	
$\text{while}(\phi) \{\mathbf{C}\}$	$\text{lfp}(\lambda F. [\phi] \cdot \text{ect}[\mathbf{C}](F) + [\neg\phi] \cdot f)$	
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$	$\max(\text{ect}[\mathbf{C}](f), \text{ect}[\mathbf{D}](f))$	

Expected Cost Transformer

We define the expected cost transformer (ECT) operating on cost functions over states. Thus $\text{ect}[\mathbf{C}](f)$ can be seen as the cost of \mathbf{C} w.r.t. a continuation cost f .

\mathbf{C}	$\text{ect}[\mathbf{C}](f)$	$\text{evaluate}[\mathbf{C}](f)$
$\text{consume}(e)$	$\langle e \rangle + f$	f
skip	f	f
abort	0	0
$x := d$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$	$\lambda\sigma. \mathbb{E}_{d(\sigma)}(\lambda v. f[x/v](\sigma))$
$\mathbf{C};\mathbf{D}$	$\text{ect}[\mathbf{C}](\text{ect}[\mathbf{D}](f))$	$\text{evaluate}[\mathbf{D}](\text{evaluate}[\mathbf{C}](f))$
$\text{if}(\phi) \{\mathbf{C}\} \{\mathbf{D}\}$	$[\phi] \cdot \text{ect}[\mathbf{C}](f) + [\neg\phi] \cdot \text{ect}[\mathbf{D}](f)$	$[\phi] \cdot \text{evaluate}[\mathbf{C}](f) + [\neg\phi] \cdot \text{evaluate}[\mathbf{D}](f)$
$\text{while}(\phi) \{\mathbf{C}\}$	$\text{lfp}(\lambda F. [\phi] \cdot \text{ect}[\mathbf{C}](F) + [\neg\phi] \cdot f)$	$\text{lfp}(\lambda F. [\phi] \cdot \text{evaluate}[\mathbf{C}](F) + [\neg\phi] \cdot f)$
$\{\mathbf{C}\} \langle \rangle \{\mathbf{D}\}$	$\max(\text{ect}[\mathbf{C}](f), \text{ect}[\mathbf{D}](f))$	$\max(\text{evaluate}[\mathbf{C}](f), \text{evaluate}[\mathbf{D}](f))$

Probabilistic Abstract Reduction Systems (PARS)



Probabilistic Abstract Reduction Systems (PARS)

A PARS over A is given by the ternary relation $\bullet \dot{\rightarrow} \bullet \subseteq A \times \mathbb{R}_{\geq 0} \times \mathcal{D}(A)$ where a rule is written as $a \xrightarrow{w} \delta$.

Probabilistic Abstract Reduction Systems (PARS)

A PARS over A is given by the ternary relation $\bullet \xrightarrow{\cdot} \bullet \subseteq A \times \mathbb{R}_{\geq 0} \times \mathcal{D}(A)$ where a rule is written as $a \xrightarrow{w} \delta$. For example the program `geo` is modeled by the PARS

$$\text{geo}(x) \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2 \cdot x, \frac{1}{2} : \text{geo}(2 \cdot x) \# \} \quad \text{for all } x \in \mathbb{Z}$$

Probabilistic Abstract Reduction Systems (PARS)

A PARS over A is given by the ternary relation $\bullet \dot{\rightarrow} \bullet \subseteq A \times \mathbb{R}_{\geq 0} \times \mathcal{D}(A)$ where a rule is written as $a \xrightarrow{w} \delta$. For example the program `geo` is modeled by the PARS

$$\text{geo}(x) \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2 \cdot x, \frac{1}{2} : \text{geo}(2 \cdot x) \# \} \quad \text{for all } x \in \mathbb{Z}$$

. The reduction relation $\bullet \dot{\rightarrow} \bullet \subseteq \mathcal{M}(A) \times \mathbb{R}_{\geq 0} \times \mathcal{M}(A)$ is defined as

$$\frac{}{\mu \xrightarrow{0} \mu} \quad \frac{a \xrightarrow{w} \delta}{\{ \# 1 : a \# \} \xrightarrow{w} \delta} \quad \frac{\mu_i \xrightarrow{w_i} v_i}{\biguplus_{i \in I} p_i \cdot \mu_i \xrightarrow{w} \biguplus_{i \in I} p_i \cdot v_i}$$

.

Probabilistic Abstract Reduction Systems (PARS)

A PARS over A is given by the ternary relation $\bullet \dot{\rightarrow} \bullet \subseteq A \times \mathbb{R}_{\geq 0} \times \mathcal{D}(A)$ where a rule is written as $a \xrightarrow{w} \delta$. For example the program `geo` is modeled by the PARS

$$\text{geo}(x) \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2 \cdot x, \frac{1}{2} : \text{geo}(2 \cdot x) \# \} \quad \text{for all } x \in \mathbb{Z}$$

. The reduction relation $\bullet \dot{\twoheadrightarrow} \bullet \subseteq \mathcal{M}(A) \times \mathbb{R}_{\geq 0} \times \mathcal{M}(A)$ is defined as

$$\frac{}{\mu \xrightarrow{0} \mu} \qquad \frac{a \xrightarrow{w} \delta}{\{ \# 1 : a \# \} \xrightarrow{w} \delta} \qquad \frac{\mu_i \xrightarrow{w_i} \nu_i}{\biguplus_{i \in I} p_i \cdot \mu_i \xrightarrow{w} \biguplus_{i \in I} p_i \cdot \nu_i}$$

. Now a reduction using `geo` looks as follows:

$$\{ \# 1 : \text{geo}(1) \# \} \xrightarrow[\text{geo}]{1}$$

Probabilistic Abstract Reduction Systems (PARS)

A PARS over A is given by the ternary relation $\bullet \dot{\rightarrow} \bullet \subseteq A \times \mathbb{R}_{\geq 0} \times \mathcal{D}(A)$ where a rule is written as $a \xrightarrow{w} \delta$. For example the program `geo` is modeled by the PARS

$$\text{geo}(x) \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2 \cdot x, \frac{1}{2} : \text{geo}(2 \cdot x) \# \} \quad \text{for all } x \in \mathbb{Z}$$

. The reduction relation $\bullet \dot{\rightarrow} \bullet \subseteq \mathcal{M}(A) \times \mathbb{R}_{\geq 0} \times \mathcal{M}(A)$ is defined as

$$\frac{}{\mu \xrightarrow{0} \mu} \quad \frac{a \xrightarrow{w} \delta}{\{ \# 1 : a \# \} \xrightarrow{w} \delta} \quad \frac{\mu_i \xrightarrow{w_i} v_i}{\biguplus_{i \in I} p_i \cdot \mu_i \xrightarrow{w} \biguplus_{i \in I} p_i \cdot v_i}$$

. Now a reduction using `geo` looks as follows:

$$\{ \# 1 : \text{geo}(1) \# \} \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2, \frac{1}{2} : \text{geo}(2) \# \} \xrightarrow[\text{geo}]{\frac{1}{2}}$$

Probabilistic Abstract Reduction Systems (PARS)

A PARS over A is given by the ternary relation $\bullet \dot{\rightarrow} \bullet \subseteq A \times \mathbb{R}_{\geq 0} \times \mathcal{D}(A)$ where a rule is written as $a \xrightarrow{w} \delta$. For example the program `geo` is modeled by the PARS

$$\text{geo}(x) \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2 \cdot x, \frac{1}{2} : \text{geo}(2 \cdot x) \# \} \quad \text{for all } x \in \mathbb{Z}$$

. The reduction relation $\bullet \dot{\twoheadrightarrow} \bullet \subseteq \mathcal{M}(A) \times \mathbb{R}_{\geq 0} \times \mathcal{M}(A)$ is defined as

$$\frac{}{\mu \xrightarrow{0} \mu} \quad \frac{a \xrightarrow{w} \delta}{\{ \# 1 : a \# \} \xrightarrow{w} \delta} \quad \frac{\mu_i \xrightarrow{w_i} v_i}{\biguplus_{i \in I} p_i \cdot \mu_i \xrightarrow{w} \biguplus_{i \in I} p_i \cdot v_i}$$

. Now a reduction using `geo` looks as follows:

$$\{ \# 1 : \text{geo}(1) \# \} \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2, \frac{1}{2} : \text{geo}(2) \# \} \xrightarrow[\text{geo}]{\frac{1}{2}} \{ \# \frac{1}{2} : 2, \frac{1}{4} : 4, \frac{1}{4} : \text{geo}(4) \# \} \xrightarrow[\text{geo}]{\frac{1}{4}}$$

Probabilistic Abstract Reduction Systems (PARS)

A PARS over A is given by the ternary relation $\bullet \dot{\rightarrow} \bullet \subseteq A \times \mathbb{R}_{\geq 0} \times \mathcal{D}(A)$ where a rule is written as $a \xrightarrow{w} \delta$. For example the program `geo` is modeled by the PARS

$$\text{geo}(x) \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2 \cdot x, \frac{1}{2} : \text{geo}(2 \cdot x) \# \} \quad \text{for all } x \in \mathbb{Z}$$

. The reduction relation $\bullet \dot{\twoheadrightarrow} \bullet \subseteq \mathcal{M}(A) \times \mathbb{R}_{\geq 0} \times \mathcal{M}(A)$ is defined as

$$\frac{}{\mu \xrightarrow{0} \mu} \quad \frac{a \xrightarrow{w} \delta}{\{ \# 1 : a \# \} \xrightarrow{w} \delta} \quad \frac{\mu_i \xrightarrow{w_i} v_i}{\biguplus_{i \in I} p_i \cdot \mu_i \xrightarrow{w} \biguplus_{i \in I} p_i \cdot v_i}$$

. Now a reduction using `geo` looks as follows:

$$\{ \# 1 : \text{geo}(1) \# \} \xrightarrow[\text{geo}]{1} \{ \# \frac{1}{2} : 2, \frac{1}{2} : \text{geo}(2) \# \} \xrightarrow[\text{geo}]{\frac{1}{2}} \{ \# \frac{1}{2} : 2, \frac{1}{4} : 4, \frac{1}{4} : \text{geo}(4) \# \} \xrightarrow[\text{geo}]{\frac{1}{4}} \dots$$

Soundness & Completeness

1. $\text{ect}[\rightarrow](f)(\bullet \triangleright \mathbf{C}) = \text{ect}[\mathbf{C}](f)$
2. $\text{ecost}[\rightarrow](\bullet \triangleright \mathbf{C}) = \text{ecost}[\mathbf{C}]$

Soundness & Completeness

1. $\text{ect}[\rightarrow](f)(\bullet \triangleright \mathbf{C}) = \text{ect}[\mathbf{C}](f)$
2. $\text{ecost}[\rightarrow](\bullet \triangleright \mathbf{C}) = \text{ecost}[\mathbf{C}]$

Upper Invariants

In order to find closed-forms of a loop we need to find a upper invariants. Such invariants are prefix points of the loops characteristic function.

Soundness & Completeness

1. $\text{ect}[\rightarrow](f)(\bullet \triangleright \mathbf{C}) = \text{ect}[\mathbf{C}](f)$
2. $\text{ecost}[\rightarrow](\bullet \triangleright \mathbf{C}) = \text{ecost}[\mathbf{C}]$

Upper Invariants

In order to find closed-forms of a loop we need to find a upper invariants. Such invariants are prefix points of the loops characteristic function. For every cost function I over a state Σ

$$\phi \models \text{ect}[\mathbf{C}](I) \leq I \wedge \neg\phi \models f \leq I$$

Soundness & Completeness

1. $\text{ect}[\rightarrow](f)(\bullet \triangleright \mathbf{C}) = \text{ect}[\mathbf{C}](f)$
2. $\text{ecost}[\rightarrow](\bullet \triangleright \mathbf{C}) = \text{ecost}[\mathbf{C}]$

Upper Invariants

In order to find closed-forms of a loop we need to find a upper invariants. Such invariants are prefix points of the loops characteristic function. For every cost function I over a state Σ

$$\phi \models \text{ect}[\mathbf{C}](I) \leq I \wedge \neg\phi \models f \leq I \implies \text{ect}[\text{while}(\phi) \{\mathbf{C}\}](f) \leq I$$

Soundness & Completeness

1. $\text{ect}[\rightarrow](f)(\bullet \triangleright \mathbf{C}) = \text{ect}[\mathbf{C}](f)$
2. $\text{ecost}[\rightarrow](\bullet \triangleright \mathbf{C}) = \text{ecost}[\mathbf{C}]$

Upper Invariants

In order to find closed-forms of a loop we need to find a upper invariants. Such invariants are prefix points of the loops characteristic function. For every cost function I over a state Σ

$$\phi \models \text{ect}[\mathbf{C}](I) \leq I \wedge \neg\phi \models f \leq I \implies \text{ect}[\text{while}(\phi) \{\mathbf{C}\}](f) \leq I$$

Example – geo

Define $I = [b = 1] \cdot 2$.

Soundness & Completeness

1. $\text{ect}[\rightarrow](f)(\bullet \triangleright \mathbf{C}) = \text{ect}[\mathbf{C}](f)$
2. $\text{ecost}[\rightarrow](\bullet \triangleright \mathbf{C}) = \text{ecost}[\mathbf{C}]$

Upper Invariants

In order to find closed-forms of a loop we need to find a upper invariants. Such invariants are prefix points of the loops characteristic function. For every cost function I over a state Σ

$$\phi \models \text{ect}[\mathbf{C}](I) \leq I \wedge \neg\phi \models f \leq I \implies \text{ect}[\text{while}(\phi) \{\mathbf{C}\}](f) \leq I$$

Example – geo

Define $I = [b = 1] \cdot 2$. Thus we have to check $b = 1 \models \text{ect}[\mathbf{C}_{\text{geo}}](I) \leq I$ and $b \neq 1 \models 0 \leq I$.

Consider C_{geo} denoting the body of geo and $I = [b = 1] \cdot 2$ the upper invariant:

Example – geo

```
b := 1;  
x := 1;  
while(b = 1) {  
  consume(1);  
  x := x * 2;  
  b := ber(1, 1)}
```

Consider C_{geo} denoting the body of geo and $I = [b = 1] \cdot 2$ the upper invariant:

$$\text{ect}[C_{\text{geo}}](I) =$$

Example – geo

```
 $b := 1;$   
 $x := 1;$   
while( $b = 1$ ) {  
  consume(1);  
   $x := x * 2;$   
   $b := \text{ber}(1, 1)$ }
```

Consider C_{geo} denoting the body of `geo` and $I = [b = 1] \cdot 2$ the upper invariant:

$$\begin{aligned} \text{ect}[C_{\text{geo}}](I) &= \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\text{ect}[b := \text{ber}(1, 1)](I))) \end{aligned}$$

Example – `geo`

```
b := 1;
x := 1;
while(b = 1) {
  consume(1);
  x := x * 2;
  b := ber(1, 1)}
```

Consider C_{geo} denoting the body of geo and $I = [b = 1] \cdot 2$ the upper invariant:

$$\begin{aligned} \text{ect}[C_{\text{geo}}](I) &= \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\text{ect}[b := \text{ber}(1, 1)](I))) \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\frac{1}{2} \cdot I[b/1] + \frac{1}{2} \cdot I[b/0])) \end{aligned}$$

Example – geo

```
b := 1;
x := 1;
while(b = 1) {
  consume(1);
  x := x * 2;
  b := ber(1, 1)}
```

Consider C_{geo} denoting the body of geo and $I = [b = 1] \cdot 2$ the upper invariant:

$$\begin{aligned} \text{ect}[C_{\text{geo}}](I) &= \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\text{ect}[b := \text{ber}(1, 1)](I))) \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\frac{1}{2} \cdot I[b/1] + \frac{1}{2} \cdot I[b/0])) \\ &= \text{ect}[\text{consume}(1)](\frac{1}{2} \cdot I[b/1, x/2 \cdot x] + \frac{1}{2} \cdot I[b/0, x/2 \cdot x]) \end{aligned}$$

Example – geo

```
b := 1;  
x := 1;  
while(b = 1) {  
    consume(1);  
    x := x * 2;  
    b := ber(1, 1)}
```

Consider C_{geo} denoting the body of geo and $I = [b = 1] \cdot 2$ the upper invariant:

$$\begin{aligned} \text{ect}[C_{\text{geo}}](I) &= \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\text{ect}[b := \text{ber}(1, 1)](I))) \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\frac{1}{2} \cdot I[b/1] + \frac{1}{2} \cdot I[b/0])) \\ &= \text{ect}[\text{consume}(1)](\frac{1}{2} \cdot I[b/1, x/2 \cdot x] + \frac{1}{2} \cdot I[b/0, x/2 \cdot x]) \\ &= 1 + \frac{1}{2} \cdot I[b/1, x/2 \cdot x] + \frac{1}{2} \cdot I[b/0, x/2 \cdot x] \end{aligned}$$

Example – geo

```
b := 1;
x := 1;
while(b = 1) {
  consume(1);
  x := x * 2;
  b := ber(1, 1)}
```


Consider C_{geo} denoting the body of geo and $I = [b = 1] \cdot 2$ the upper invariant:

$$\begin{aligned} \text{ect}[C_{\text{geo}}](I) &= \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\text{ect}[b := \text{ber}(1, 1)](I))) \\ &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\frac{1}{2} \cdot I[b/1] + \frac{1}{2} \cdot I[b/0])) \\ &= \text{ect}[\text{consume}(1)](\frac{1}{2} \cdot I[b/1, x/2 \cdot x] + \frac{1}{2} \cdot I[b/0, x/2 \cdot x]) \\ &= 1 + \frac{1}{2} \cdot I[b/1, x/2 \cdot x] + \frac{1}{2} \cdot I[b/0, x/2 \cdot x] \\ &= 1 + \frac{1}{2} \cdot [1 = 1] \cdot 2 + \frac{1}{2} \cdot [0 = 1] \cdot 2 \end{aligned}$$

Example – geo

```
b := 1;  
x := 1;  
while(b = 1) {  
    consume(1);  
    x := x * 2;  
    b := ber(1, 1)}
```

Consider C_{geo} denoting the body of geo and $I = [b = 1] \cdot 2$ the upper invariant:

$$\begin{aligned}
 \text{ect}[C_{\text{geo}}](I) &= \\
 &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\text{ect}[b := \text{ber}(1, 1)](I))) \\
 &= \text{ect}[\text{consume}(1)](\text{ect}[x := x * 2](\frac{1}{2} \cdot I[b/1] + \frac{1}{2} \cdot I[b/0])) \\
 &= \text{ect}[\text{consume}(1)](\frac{1}{2} \cdot I[b/1, x/2 \cdot x] + \frac{1}{2} \cdot I[b/0, x/2 \cdot x]) \\
 &= 1 + \frac{1}{2} \cdot I[b/1, x/2 \cdot x] + \frac{1}{2} \cdot I[b/0, x/2 \cdot x] \\
 &= 1 + \frac{1}{2} \cdot [1 = 1] \cdot 2 + \frac{1}{2} \cdot [0 = 1] \cdot 2 \\
 &= 2
 \end{aligned}$$

Example – geo

```

b := 1;
x := 1;
while(b = 1) {
    consume(1);
    x := x * 2;
    b := ber(1, 1)}
    
```

Why Do We Need Modularity?

For two nested while loops `while(ϕ) {while(ψ) {C}}`, we cannot synthesize the inner (I) and outer (O) upper invariant independently.

Why Do We Need Modularity?

For two nested while loops `while(ϕ) {while(ψ) {C}}`, we cannot synthesize the inner (I) and outer (O) upper invariant independently. We get the following constraints in order to synthesize those:

$$\phi \models I \leq O \wedge \neg\phi \models f \leq O$$

Why Do We Need Modularity?

For two nested while loops `while(ϕ) {while(ψ) {C}}`, we cannot synthesize the inner (I) and outer (O) upper invariant independently. We get the following constraints in order to synthesize those:

$$\phi \models I \leq O \wedge \neg\phi \models f \leq O \wedge \psi \models \text{ect}[\mathbf{C}](I) \leq I \wedge \neg\psi \models O \leq I$$

Why Do We Need Modularity?

For two nested while loops `while(ϕ) {while(ψ) {C}}`, we cannot synthesize the inner (I) and outer (O) upper invariant independently. We get the following constraints in order to synthesize those:

$$\phi \models I \leq O \wedge \neg\phi \models f \leq O \wedge \psi \models \text{ect}[C](I) \leq I \wedge \neg\psi \models O \leq I$$

Modularity

We achieve modularity by first calculating the cost of one loop iteration and then analyze how possible values in a state evolve during execution.

Separating Expected Cost and Value

First we have to separate the analysis into a cost and value analysis:

$$\text{ect}[\mathbf{C}](f) \leq \text{ecost}[\mathbf{C}] + \text{value}[\mathbf{C}](f)$$

Separating Expected Cost and Value

First we have to separate the analysis into a cost and value analysis:

$$\text{ect}[\mathbf{C}](f) \leq \text{ecost}[\mathbf{C}] + \text{value}[\mathbf{C}](f)$$

Modular Upper Invariants

$$\begin{aligned} 1) \phi \models \text{ecost}[\mathbf{C}] + \kappa(\text{value}[\mathbf{C}](b_1), \dots, \text{value}[\mathbf{C}](b_n)) &\leq \kappa(b_1, \dots, b_n) \\ \Rightarrow \text{ecost}[\text{while}(\phi) \{\mathbf{C}\}] &\leq \kappa(b_1, \dots, b_n) \end{aligned}$$

Separating Expected Cost and Value

First we have to separate the analysis into a cost and value analysis:

$$\text{ect}[\mathbf{C}](f) \leq \text{ecost}[\mathbf{C}] + \text{value}[\mathbf{C}](f)$$

Modular Upper Invariants

- 1) $\phi \models \text{ecost}[\mathbf{C}] + \kappa(\text{value}[\mathbf{C}](b_1), \dots, \text{value}[\mathbf{C}](b_n)) \leq \kappa(b_1, \dots, b_n)$
 $\Rightarrow \text{ecost}[\text{while}(\phi) \{\mathbf{C}\}] \leq \kappa(b_1, \dots, b_n)$
- 2) $\phi \models \kappa(\text{value}[\mathbf{C}](b_1), \dots, \text{value}[\mathbf{C}](b_n)) \leq \kappa(b_1, \dots, b_n) \wedge \neg\phi \models f \leq \kappa(b_1, \dots, b_n)$
 $\Rightarrow \text{value}[\text{while}(\phi) \{\mathbf{C}\}](f) \leq \kappa(b_1, \dots, b_n)$

Separating Expected Cost and Value

First we have to separate the analysis into a cost and value analysis:

$$\text{ect}[\mathbf{C}](f) \leq \text{ecost}[\mathbf{C}] + \text{value}[\mathbf{C}](f)$$

Modular Upper Invariants

- 1) $\phi \models \text{ecost}[\mathbf{C}] + \kappa(\text{value}[\mathbf{C}](b_1), \dots, \text{value}[\mathbf{C}](b_n)) \leq \kappa(b_1, \dots, b_n)$
 $\Rightarrow \text{ecost}[\text{while}(\phi) \{\mathbf{C}\}] \leq \kappa(b_1, \dots, b_n)$
- 2) $\phi \models \kappa(\text{value}[\mathbf{C}](b_1), \dots, \text{value}[\mathbf{C}](b_n)) \leq \kappa(b_1, \dots, b_n) \wedge \neg\phi \models f \leq \kappa(b_1, \dots, b_n)$
 $\Rightarrow \text{value}[\text{while}(\phi) \{\mathbf{C}\}](f) \leq \kappa(b_1, \dots, b_n)$

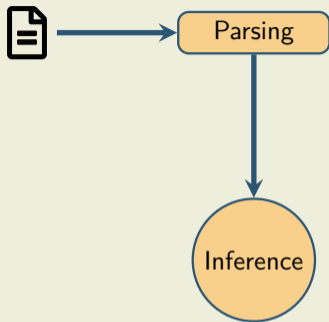
We need all this for the automation of ECT.

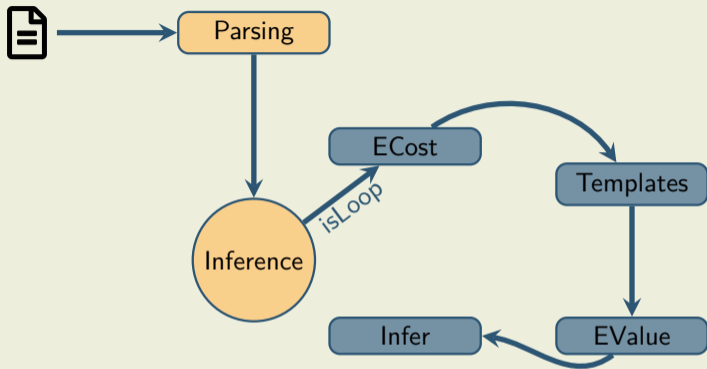
Overview

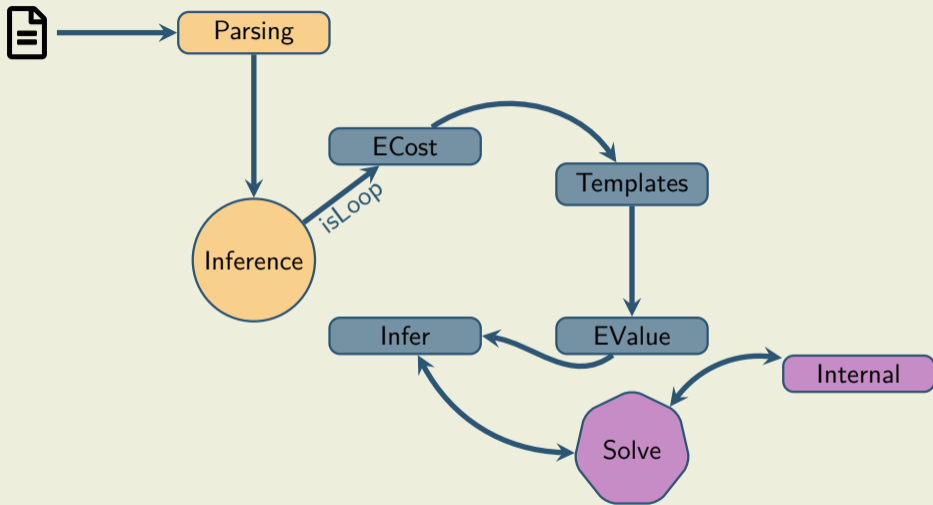
- Primer
- ERT
- ECT – Syntax & Semantic
- **Automation**
- Summary

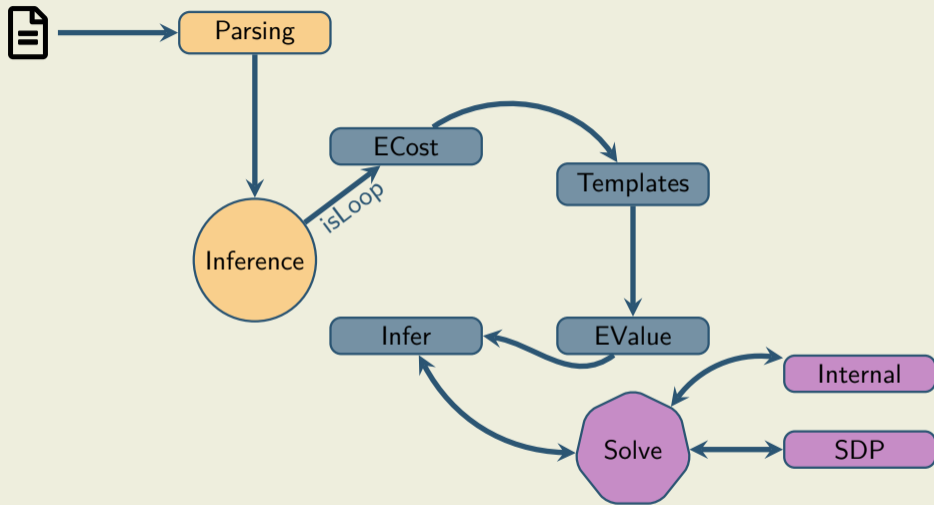


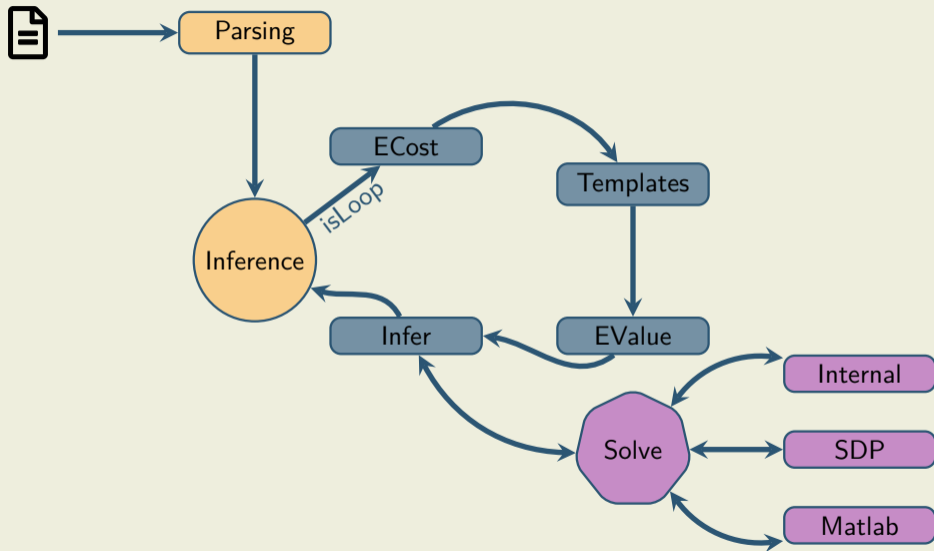


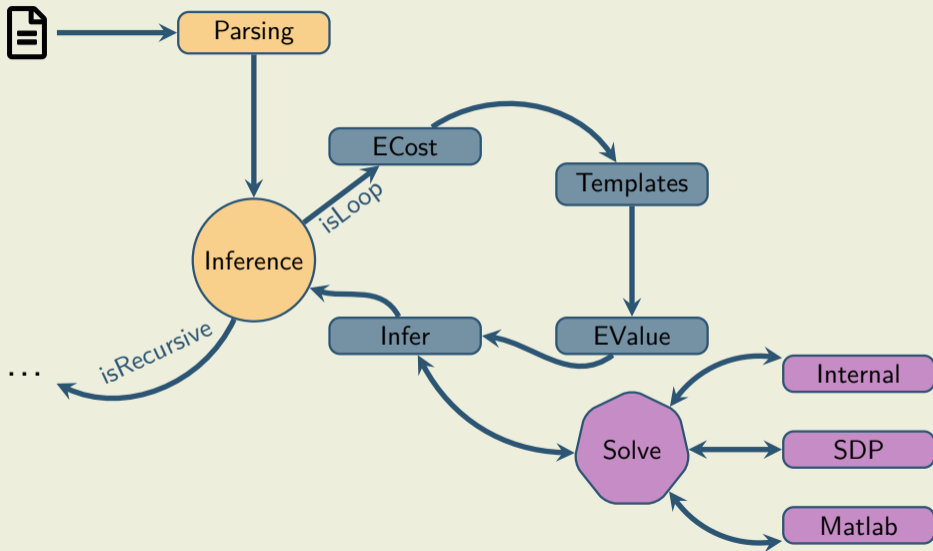


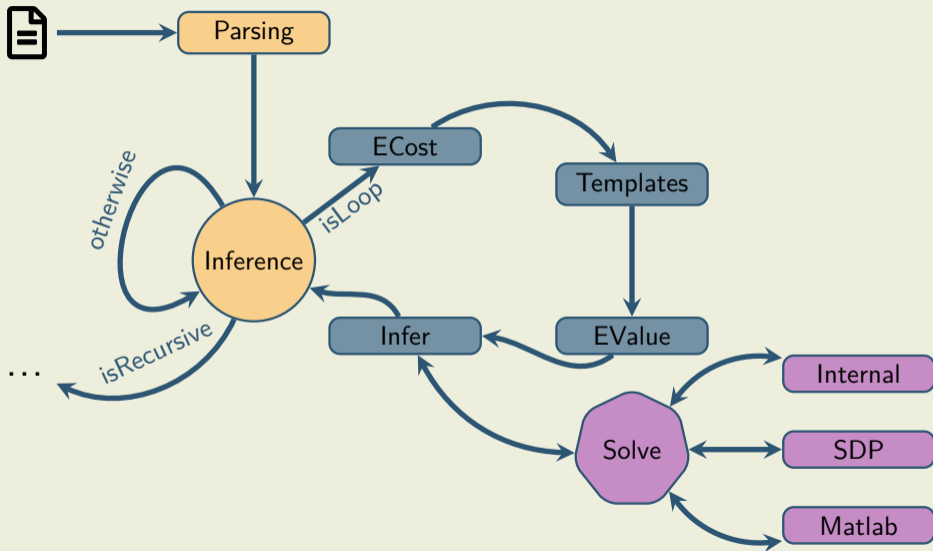


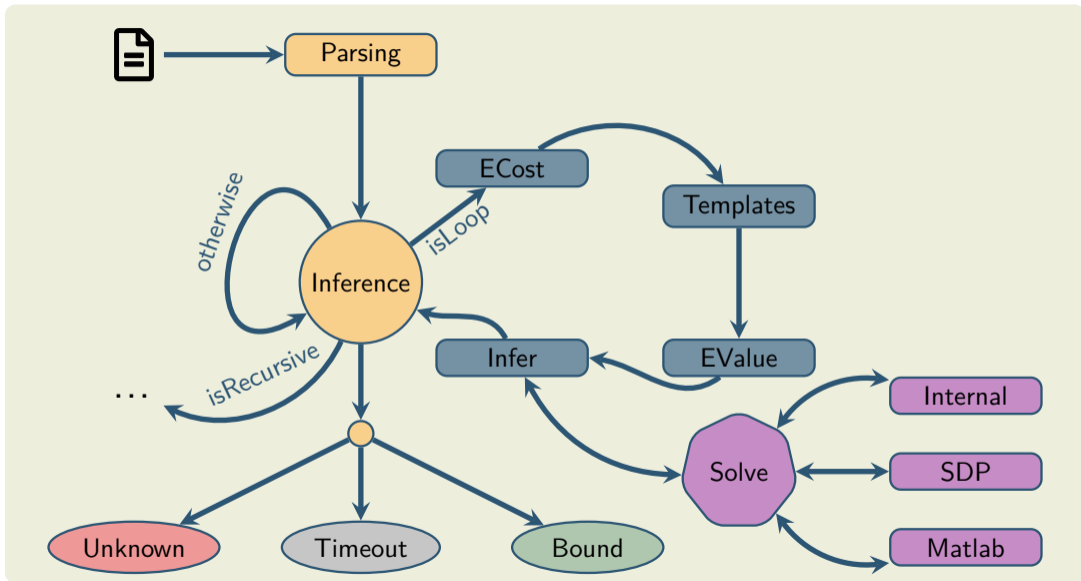


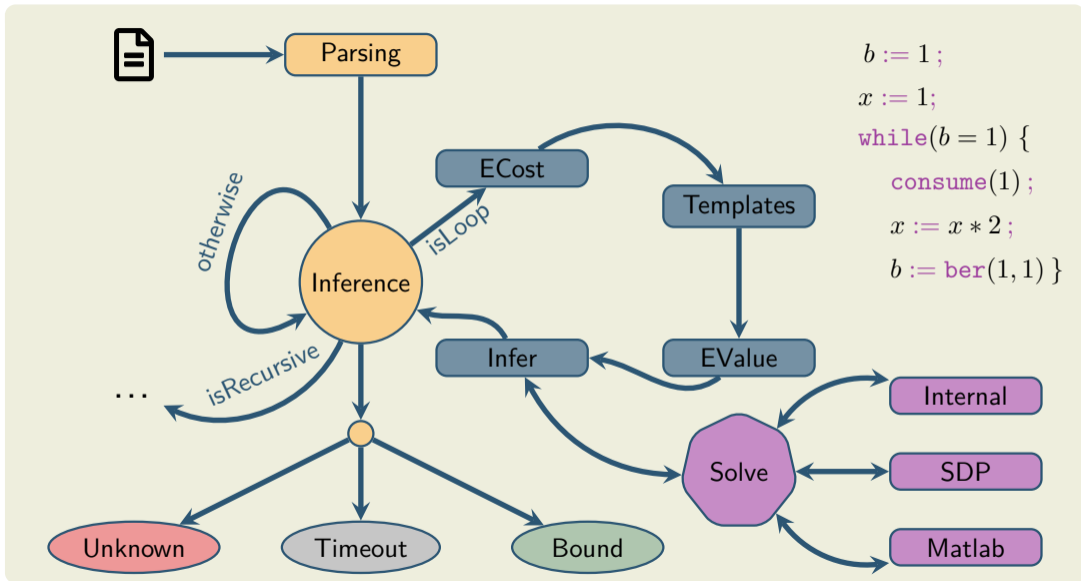


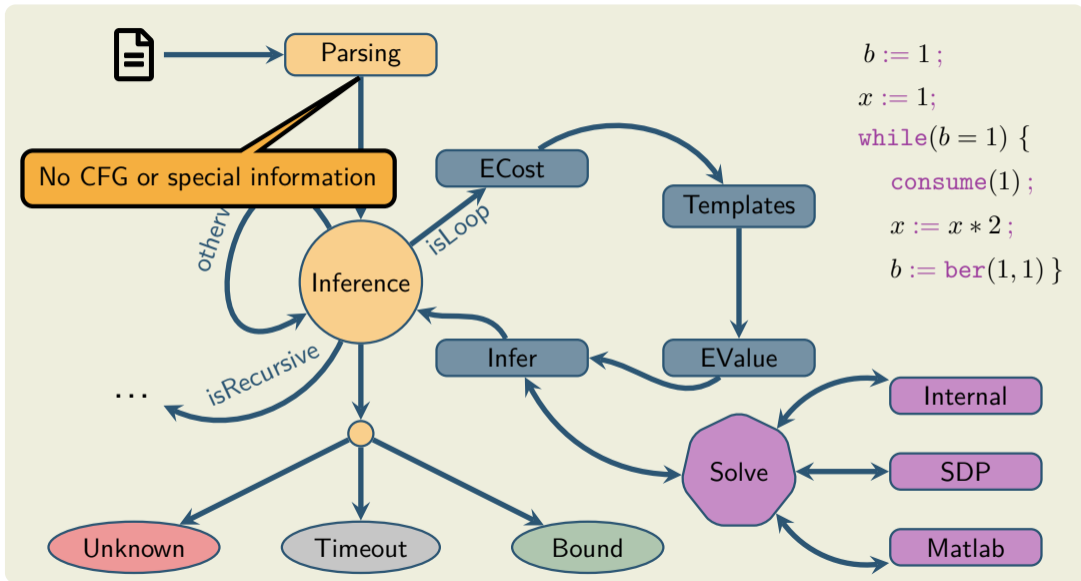






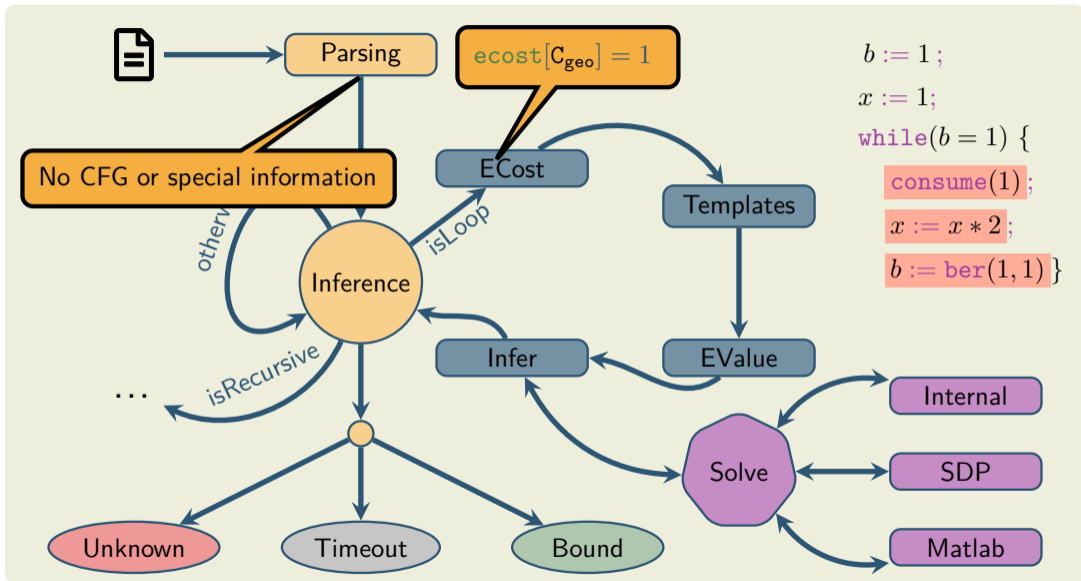


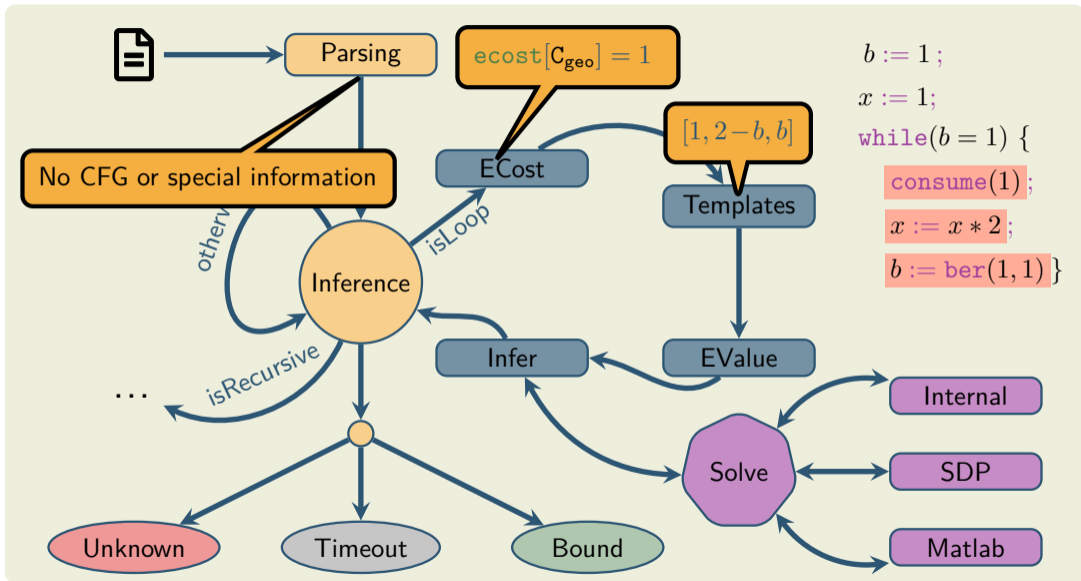


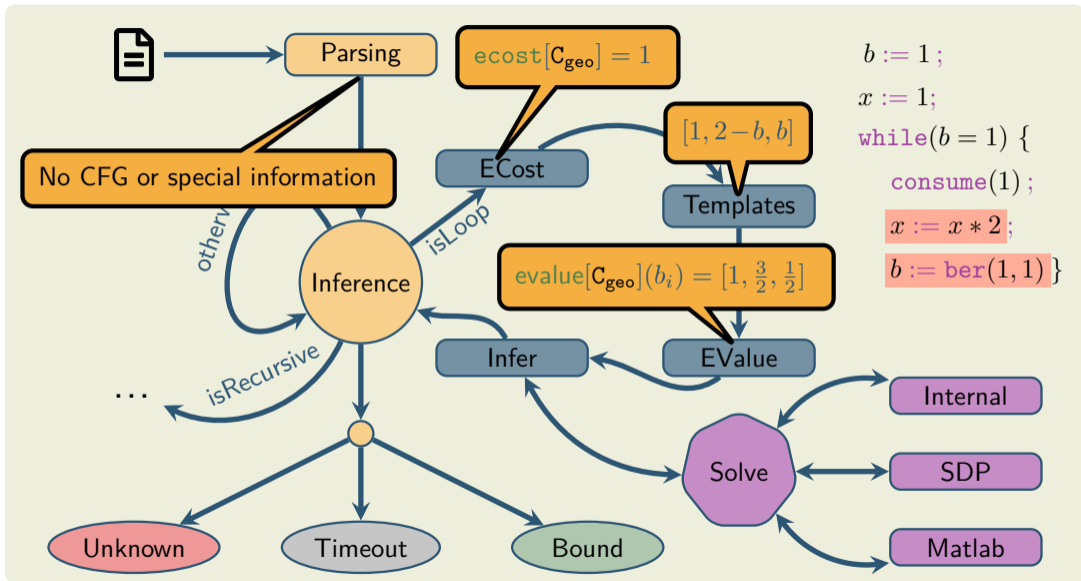


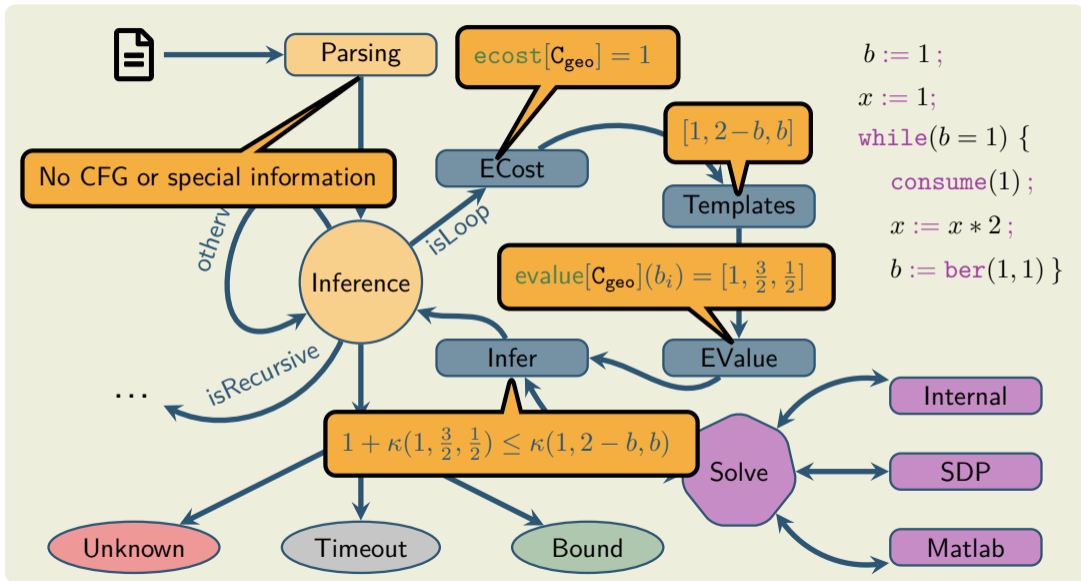
```

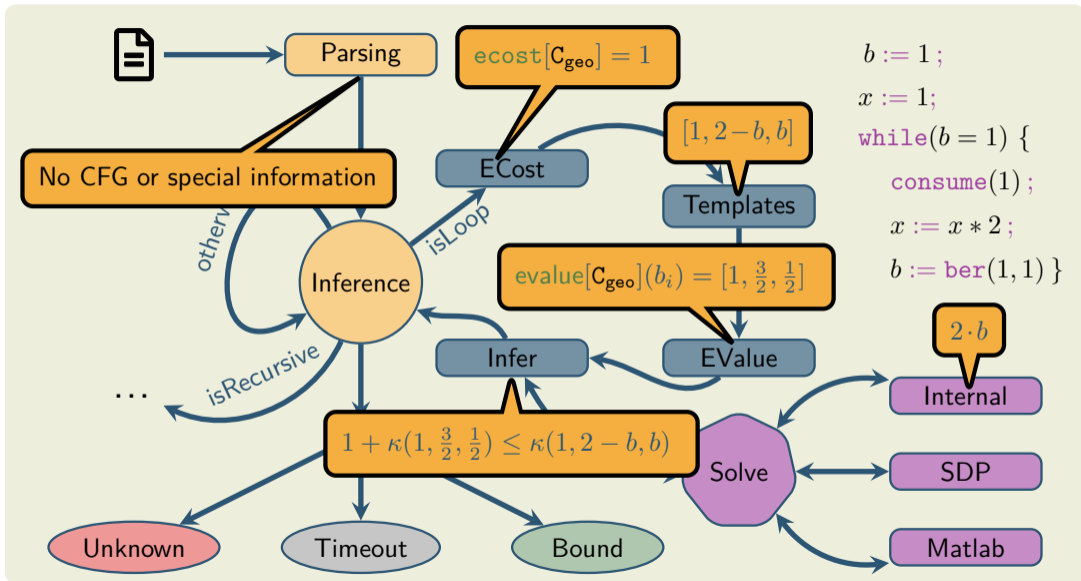
b := 1;
x := 1;
while(b = 1) {
  consume(1);
  x := x * 2;
  b := ber(1, 1) }
  
```

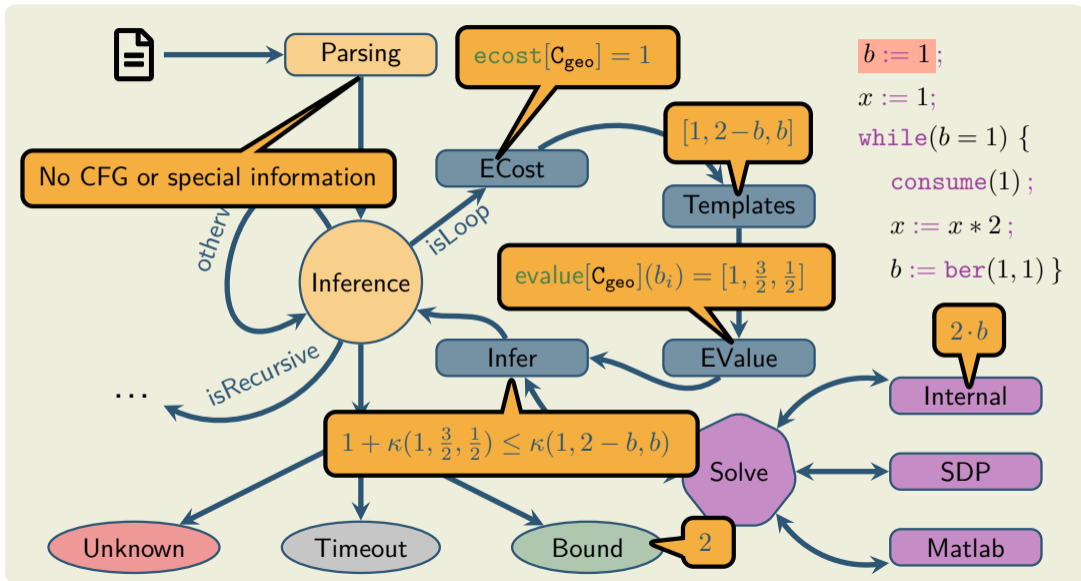












Summary

- static program analysis for probabilistic programs

Summary

- static program analysis for probabilistic programs
- ERT calculus for compositional analysis
- ECT calculus for compositional/modular analysis

Summary

- static program analysis for probabilistic programs
- ERT calculus for compositional analysis
- ECT calculus for compositional/modular analysis
- automation in ecoimp

Summary

- static program analysis for probabilistic programs
- ERT calculus for compositional analysis
- ECT calculus for compositional/modular analysis
- automation in ecoimp

Current/Future Research

- finishing recursion (modularity?)
- SDP solving

Summary




- static program analysis for probabilistic programs
- ERT calculus for compositional analysis
- ECT calculus for compositional/modular analysis
- automation in ecoimp

Current/Future Research

- finishing recursion (modularity?)
- SDP solving
- logarithmic bounds
- abstractions via coupling

Thank you for your attention!

References

-  Martin Avanzini, Georg Moser, and Michael Schaper.
A Modular Cost Analysis for Probabilistic Programs.
Proc. ACM Program. Lang., 4(OOPSLA), nov 2020.
-  E.W. Dijkstra.
Guarded Commands, Nondeterminacy and Formal Derivation of Programs.
Communications of the ACM, 1975.
-  Benjamin Lucien Kaminski, Joost-Pieter Katoen, Christoph Matheja, and Federico Olmedo.
Weakest Precondition Reasoning for Expected Runtimes of Randomized Algorithms.
J. ACM, 65(5), aug 2018.