Backtracking temporal logic synthesis for uncertain environments
Scott C. Livingston, Richard M. Murray, and Joel W. Burdick

Abstract—This paper considers the problem of synthesizing correct-by-construction robotic controllers in environments with uncertain but fixed structure. “Environment” has two notions in this work: a map or “world” in which some controlled agent must operate and navigate (i.e., evolve in a configuration space with obstacles); and an adversarial player that selects continuous and discrete variables to try to make the agent fail (as in a game). Both the robot and the environment are subjected to behavioral specifications expressed as an assume-guarantee linear temporal logic (LTL) formula. We then consider how to efficiently modify the synthesized controller when the robot encounters unexpected changes in its environment. The crucial insight is that a portion of this problem takes place in a metric space, which provides a notion of nearness. Thus if a nominal plan fails, we need not resynthesize it entirely, but instead can “patch” it locally. We present an algorithm for doing this, prove soundness (correctness of output), and demonstrate it on an example gridworld.

I. MOTIVATION AND INTRODUCTION
Consider the hypothetical office floor map shown in Fig. 1, and suppose a robot is tasked with always visiting the lounge and printing room. If a special “espresso ready” flag is received, then the robot must eventually go to the coffee nook. Additionally, there are safety requirements, e.g.,
• avoid collisions with a priori known walls (appearing in given map); and
• avoid collisions with short-term static (e.g., trash bins) and dynamic (e.g., people) objects in the area.

Given a floor map and assumptions about
• arrival rate of the “espresso ready” flag; and
• how static and dynamic obstacles can appear or move,
a controller $M$, generally taking the form of a hybrid system, can be synthesized to guarantee this behavior. During online operation, errors in the nominal map may be discovered. In this illustration, the “lounge” room has been newly partitioned with cubicles. Thus the map needs mending, as may the robot’s control system.

Assuming the nominal controller $M$ is large and computationally difficult to completely re-synthesize on the new map, the algorithm proposed in this paper can locally “patch” it to recover global correctness. It does so by exploiting the fact that most behavior in the office continues to be correct, if only we can negotiate the discovered change locally. Of course, the change may indeed have global consequences, and in that case, the entire control system will be resynthesized.

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the effect of probabilistic errors in determining proposition values (motivated by sensor errors), providing some insight into fragility of the original specification [9]. Belta et al. have framed uncertainty in the language of Markov decision processes and proposed algorithms for discrete policies that maximize probability of satisfying a given temporal logic specification [10], [11].

This paper considers, in the formal system framework, a type of uncertainty which has heretofore been largely ignored—potential topological changes in the robot’s environment. To address this type of uncertainty, we try to bridge the gap of abstraction that previously formed a strong separation between the underlying continuous dynamics of a physical system and the discrete variables over which reactive synthesis occurs. That is, we wish to recover some of the structure of the underlying Banach space and use it to repair flawed models originally used to create nominal plans. Our approach is dubbed “backtracking reactive synthesis.” Philosophically, our method can be considered a generalization of the concepts behind Stentz’s D* algorithm [12], to the problem of creating correct and always running hybrid controllers. Whereas D* “patches” a motion plan in order to handle unforeseen problems in the environment, this paper “patches” a general hybrid automaton. The most similar prior work is that of Wongpiromsarn et al. [4], who show a method for decomposing a large reactive synthesis problem into a partial order of receding horizon subproblems. A major limitation in that work is the need to construct the decomposition by hand, i.e., no automatic horizon selection procedure is given. In this paper, we use the metric of the underlying space to provide a notion of “localness”, which permits “patching” a nominal solution. The “patches” can be thought of as “short horizon problems,” in the terminology of [4].

II. DEFINITIONS AND PROBLEM SETTING

Let $Y$ be a set of “system” variables, and $X$ a set of “environment” variables, both finite and boolean. Throughout the paper these sets of variables are assumed disjoint, i.e., $X \cap Y = \emptyset$. Individual variables are written as uppercase letters, e.g., $V \in X$. Write the set of valuations of the controlled variables as $\Sigma_Y$; i.e., any particular setting of these variables is some $y \in \Sigma_Y$. Note that what we call “valuations” is also variously called “states”, but we reserve the word for continuous dynamics in a “state” space. The variables in $Y$ may be labeled and ordered such that for $y \in \Sigma_Y$, $y_i$ denotes the valuation of the $i$-th variable in $Y$ at $y$. Similar notation is used for the environment variables $X$.

Let $\text{form}_Y : \Sigma_Y \rightarrow \text{Bool}(Y)$ be the map taking valuations of $Y$ to boolean formulae such that the resulting formula is true precisely when the variables have the given valuation.

$$\text{form}_Y(y) \triangleq \left( \bigwedge_{i \in I_T} y_i \right) \land \left( \bigwedge_{j \in I_F} \neg y_j \right),$$  \hspace{1cm} (1)

where the index sets $I_T$ and $I_F$ denote indices for which the variables are true and false, respectively. The domain can be restricted to a particular set of variables in the natural way; this is indicated by changing the subscript, e.g., $\text{form}_X$.

When we are concerned with both sets of variables, we will drop the subscript and write

$$\text{form} : \Sigma_X \times \Sigma_Y \rightarrow \text{Bool}(X \cup Y),$$

$$\text{form}(xy) = \text{form}(x) \land \text{form}(y).$$

An execution trace is a sequence of environment and system valuations, occurring as turns in a game; write such a sequence as

$$\sigma := x_0 y_0 x_1 y_1 \ldots,$$

where the subscripts indicate (discrete) time steps. For reactive synthesis, we wish to generate a strategy function

$$M : (\Sigma_X \Sigma_Y)^* \Sigma_X \rightarrow \Sigma_Y,$$

where the superscript * denotes Kleene closure. $M$ selects values for controlled variables that satisfy a behavioral specification, given the environment variables satisfy an assumption. Given the specification $\varphi$, an LTL formula over variables $X \cup Y$, we seek an $M$ such that for any resulting trace $\sigma$, $\sigma \models \varphi$. Informally, this notation means “the execution $\sigma$ is correct with respect to the specification $\varphi$.”

In this paper, we consider a restricted class of linear temporal logic (LTL) formulae with which the synthesis problem can be efficiently solved, called GR(1) (Generalized Reactivity) [13], [14]. A GR(1) formula $\varphi$ has the form

$$\psi_e := \psi_{e,\text{init}} \land \left( \bigwedge_{i \in I_{e,t}} \Box \psi_{e,t_i} \right) \land \left( \bigwedge_{i \in I_{e,g}} \Diamond \psi_{e,g_i} \right) \hspace{1cm} (2)$$

$$\psi_s := \psi_{s,\text{init}} \land \left( \bigwedge_{i \in I_{s,t}} \Box \psi_{s,t_i} \right) \land \left( \bigwedge_{i \in I_{s,g}} \Diamond \psi_{s,g_i} \right)$$

$$\varphi := \psi_e \implies \psi_s,$$

where $\psi_{e,t_i}$ are state formulae defined over $X \cup Y \cup \bigcup X$, $\psi_{s,t_i}$ are state formulae defined over $X \cup Y \cup \bigcup X \cup Y$, $\psi_{e,g_i}$, and $\psi_{s,g_i}$ are state formulae defined over $X \cup Y, \psi_{e,\text{init}}$ and $\psi_{s,\text{init}}$ are initial conditions. We refer to subformulae of the form $\Box \psi_{e,t}$ as “safety” properties, and subformulae of the form $\Diamond \psi_{e,g_i}$ as “progress” properties. The index sets for the subformulae are $I_{e,t}, I_{e,g}, I_{s,t}, I_{s,g}$.
A cellular decomposition \( P \) of \( Z \) is chosen such that it is proposition-preserving and satisfies a reachability condition (defined below; also see [5]).

For any cell \( \zeta_j \in Z/P \), a valuation \( y \in \Sigma_Y \) is said to take place in that cell if it implies that the continuous state \( z \) is in \( \zeta_j \). In this case, we write

\[ y \implies \zeta_j. \]

**Definition 3:** Let \( \zeta_i, \zeta_j \in Z/P \). \( \zeta_j \) is said to be reachable from \( \zeta_i \) if for any \( z_0 \in \zeta_i \), there exists some finite control sequence \( \mu : \{0, \ldots, k-1\} \rightarrow U \) such that applying \( \mu \) to dynamics Eq. (3) with initial condition \( z_0 \) yields a final state of \( z_k \in \zeta_j \).

**Definition 4:** \( V \in X \cup \bar{Y} \) is said to be a spatially-dependent variable if its truth-value is a function of the continuous state \( Z \), written \( V : Z \rightarrow \{ \text{True, False} \} \).

**Definition 5:** Let \( S' \subseteq S \), and let \( \{\zeta_k\}_k \subseteq Z/P \), where \( k \in K \) is an index set. We define the region nodes to be

\[ \text{Reg}(S', \{\zeta_k\}_k) \triangleq \{v \in S' \mid \exists k \in K . g(v) \implies \zeta_k \}. \]

Intuitively, \( \text{Reg}() \) is the set of nodes that satisfy some set of cells of the continuous space — i.e., if the valuation of the node holds (or equivalently, if an execution path has led to that node), then the underlying continuous system must be in one of the given cells.

**Definition 6:** Let \( \gamma > 0 \). The abstract neighborhood is

\[ B_\gamma (\zeta_i) \triangleq \{\zeta_j \in Z/P \mid \exists z_1 \in \zeta_i, z_2 \in \zeta_j . \|z_1 - z_2\| < \gamma \}. \]

For completeness, define \( B_0 (\zeta_i) = \{\zeta_i\} \).

Intuitively, the abstract neighborhood lifts the ball of radius \( \gamma \) from the continuous space up into the discrete abstraction in such a way that mapping the \( B_\gamma \) back down into the continuous space will cover the original norm ball.

**Definition 7:** Let \( S' \subseteq S \), and let \( \psi \) be a boolean formula. We define the satisfying nodes to be

\[ \text{Sat}(S', \psi) \triangleq \left\{ v' \in S' \mid \exists e' \in \text{In}(v') . \right. \]

\[ \left. h(e')(g(v')) \models \psi \right\}. \]

Intuitively, \( \text{Sat}() \) gives all nodes for which the corresponding valuation label and some inward edge label satisfies the given formula.

**Definition 8:** Let \( M \) be a solution automaton, and let \( S' \subseteq S \). Then the set of exit nodes is defined

\[ \text{Exit}(S') \triangleq \left\{ v_1 \in S' \mid \exists x \in \Sigma_X, v_2 \in S \setminus S' . \delta(v_1, x) = v_2 \right\}. \]

Or equivalently,

\[ \text{Exit}(S') \triangleq \{ v_1 \in S' \mid \exists v_2 \in S \setminus S' . (v_1, v_2) \in E(M) \}. \]

The set of entry nodes is defined in a similar manner,

\[ \text{Entry}(S') \triangleq \left\{ v_1 \in S' \mid \exists x \in \Sigma_X, v_2 \in S \setminus S' . \delta(v_2, x) = v_1 \right\}. \]
Definition 9: Let \( l \in S' \), where \( S' \subseteq S \). Define the restricted reachable set to be
\[
\text{Reach}^*(l, S') \triangleq \left\{ v \in S' \mid (l, p_1, \ldots, p_k, v) \text{ is a path with } p_1, \ldots, p_k \in S' \right\}
\]
The path of zero length is included, i.e., \( l \in \text{Reach}^*(l, S') \).

III. ALGORITHM

A. Overview

We assume there is a nominal robot controller \( M \) that realizes a (global) specification \( \varphi \). This controller is “nominal” in that it was constructed based on a model of the world \( Z/P \), wherein the robot can move among cells of interest subject to some dynamics. If from online sensing one of the cells \( \zeta_i \in Z/P \) is discovered to be unreachable, then \( M \) must be corrected if the robot is still to satisfy \( \varphi \). Hence initialization of our algorithm.

Execution begins when a cell \( \zeta_i \in Z/P \) expected to be reachable turns out not to be. Suppose this is first sensed when the automaton \( M \) is at node \( v \in S \). There are two main parts to our approach:

1) find a neighborhood around \( \zeta_i \) such that a set of local specifications \( \{ \varphi_t \}_t \) can be realized; and
2) replace defunct parts of \( M \) with the synthesized local patches \( \{ M_{\text{new}, t} \}_t \).

1) Finding locally realizable specifications: The first step proceeds by iteratively considering larger neighborhoods until local patches are realized or the global problem is obtained. The latter eventually occurs because for a sufficiently large neighborhood, synthesizing patches is as hard as re-synthesis of the entire strategy \( M \). If the global problem has become infeasible, then terminate with failure.

The sets of spatially-dependent environment and system variables are \( X_{\text{spatial}} \) and \( Y_{\text{spatial}} \), respectively. By the assumption that the initial cellular decomposition \( P \) of the state space \( Z \) is proposition-preserving, the notion of neighborhood for our purposes is some subset of \( Z/P \). Hence the definition of abstract neighborhood, \( B_{\text{inc}} (\zeta_i) \subseteq Z/P \). The radius \( r_{\text{inc}} \) is iteratively incremented by \( \gamma \), which has the same units as the continuous state space \( Z \). Given that the control strategy will change only when the robot is in this neighborhood, some of the spatially-dependent variables will have fixed truth-value and thus need not be included in the patch synthesis problem. The restricted set of variables is called \( X'_{\text{inc}} \cup Y_{\text{inc}} \) in the algorithm.

Since we seek to correct “local” behavior, all parts of the original strategy \( M \) that correspond to the robot being in the neighborhood \( B_{\text{inc}} (\zeta_i) \subseteq Z/P \) must be replaced. The corresponding set of nodes in \( M \) is \( \text{Reg}(S, B_{\text{inc}} (\zeta_i)) \). This set is important for two purposes. First, any system goals \( \psi_{s, gi} \) that are satisfied at some node in it must be included as local goals in the patch. Otherwise the environment might be able to drive the system into this patched cell indefinitely, leading to a specification violation.

Second, by examining how nodes from \( S' := \text{Reg}(S, B_{\text{inc}} (\zeta_i)) \) connect with the remainder of the strategy automaton, entry and exit points for patches can be determined. Specifically, the entry nodes are \( \text{Entry}(S') \cup \{ v \} \cup \text{Init} \). Nodes in \( \text{Entry}(S') \) are just those from the original \( M \) that have an incoming transition from a node outside the abstract neighborhood. Thus for an execution path to lead from outside a patch to \( l \in \text{Entry}(S') \), the continuous state of the robot must transition from outside to in \( B_{\text{inc}} (\zeta_i) \).

The other set of entry nodes, \( \{ v \} \cup \text{Init} \), handles special cases. \( v \) is the node at which the unreachable cell \( \zeta_i \) was discovered. We must ensure initialization from \( v \) is satisfiable since we want the algorithm to perform patching online—with no need for “restarts.” Nodes in \( \text{Init} \) are those from which the robot can be started in the neighborhood \( B_{\text{inc}} (\zeta_i) \), thus possibly never encountering a transition into it.

Complementary to entry nodes \( l \), we must find exit points to return to \( M \) after local correction \( M_{\text{patch}, t} \), except in a special case described below. To ensure correctness of the output of the algorithm \( M_{\text{new}} \) with respect to the global specification, a list of possible exit points is formed of those nodes that

- were reachable in \( M \) from \( l \) by paths restricted to \( S' \), and
- correspond to continuous states \( z \) that can be driven out of the neighborhood \( B_{\text{inc}} (\zeta_i) \) in one (abstract) transition.

This set is \( \text{Reach}^*(l, S') \cap \text{Exit}(S') \).

As noted earlier, the local patch may be required to satisfy some global system goals. Therefore it does not suffice to immediately return to \( M \) when execution in a patch automaton reaches one of the above exit nodes. In the special case that these system goals were only satisfied in the abstract neighborhood, the environment might drive the system to the same exit node every time a patch is visited and prevent infinite-often satisfaction of these goals. This case is addressed by adding finite memory \( \{ \xi_t \}_t \) to the strategy. The goal indicators \( \{ \xi_t \}_t \) allow an execution path that enters the patch to remain there until all local system goals are satisfied. Of course, such “indicators” could be incorporated into the system variables \( Y \) without loss of generality.

There is a special case where, for some entry node \( l \),
\[
\text{Reach}^*(l, S') \cap \text{Exit}(S') = \emptyset.
\]
If such a node \( l \) was reached by \( M \) during an execution trace, then the continuous state \( z \) would enter the neighborhood and never leave it. Since the given controller \( M \) is assumed to be correct for the nominal model, such an execution trace is in fact correct (nominally). It follows that all global system goals could be satisfied using \( M \) restricted to the abstract neighborhood, hence a patch \( M_{\text{patch}, l} \) beginning at \( l \) would not need to eventually return to \( M \).

From the above description, a patch synthesis problem with an appropriate “patch” specification \( \varphi_t \) rooted at each entry node. If all \( \{ \varphi_t \}_t \) are realizable, then the algorithm has succeeded. It remains only to merge the results \( \{ M_{\text{patch}, l} \}_l \) into the original \( M \).
2) Patching in the corrections: There are two major steps to merge each patch automaton $M_{\text{patch}, l}$ into $M$. First, recall that $l$ is an “entry” node in the original $M$. By definition of $\varphi_l$, the truth-value of environment and system variables at $l$ is matched by some initialization node in $M_{\text{patch}, l}$; call it $l'$. Each outgoing transition from $l$ that matches (i.e. has same environment label $x$) an outgoing transition from $l'$ is replaced such that the new transition leads into $M_{\text{patch}, l}$. Thus the patch automaton is “entered” when the continuous state $z$ of the robot enters the neighborhood $B_{r_{\text{inc}}} (\zeta_i)$.

Second, if there is no exit point (recall the special case noted earlier), then remaining in $M_{\text{patch}, l}$ is correct. Otherwise, there must be some way to leave $M_{\text{patch}, l}$. By definition of $\varphi_l$, the label of at least one “exit” node $p \in \text{Reach}^* (l, S') \cap \text{Exit}(S')$ in $M$ must be satisfied infinitely often for an execution contained entirely in $M_{\text{patch}, l}$. Thus after entering $M_{\text{patch}, l}$, an execution path will always eventually be able to return to $M$ at a transition reachable before patching. Now using the local goal indicators $\{\xi_i\}_l$, exiting $M_{\text{patch}, l}$ can only occur after all locally satisfiable goals are met. Because they are guaranteed to be met eventually by $\varphi_l$, matching nodes in $M_{\text{patch}, l}$ can have outward transitions augmented to allow returning to $M$ when all indicators $\{\xi_i\}_l$ are True.

Once all patches $\{M_{\text{patch}, l}\}_l$ are merged as above, the invalid nodes $\text{Reg}(S, \{\xi_i\})$ corresponding to reaching the unreachable $\zeta_i$ can be removed. Return the final solution $M_{\text{new}}$.

B. Formal statement

The algorithm is listed in Figs. 2 through 6. The division into two blocks of code follows the “two part” description given in the overview of the previous section. Four subroutines, RuleClear, RuleSetIfSat, CondAll, and CondAnyNot, for working with finite memory have obvious implementations and are omitted.

Clarifications of code in Fig. 2:

- Line 4 checks whether the abstract neighborhood is sufficiently large to warrant global re-synthesis.
- Lines 8–15 build sets of environment and system variables that could change in the local problem—in particular (line 11), those spatially-dependent variables that could change value for some continuous trajectory in the abstract neighborhood.
- Line 23 defines initial conditions for the patch specification. This ensures correct “entry points.”
- Line 24 accounts for the special case that $I_{s,g}' = I_{s,g}$ and from entry point $l$ an execution path will never leave the neighborhood. Hence local navigation goal $\psi_{\text{patch}, l}$ is set to be vacuously satisfied on line 25.
- Lines 29–31 define exit conditions for the patch specification. These ensure possible “exit points.”
- Lines 32–34 include safety properties and global goals that are relevant in the local problem. Line 34 defines the patch specification $\varphi_l$.

Clarifications of code in Fig. 3:

- Line 1 creates a new node set by taking the disjoint union of the original node set and those of all patch strategies. In the pseudocode, references to $S_{\text{patch}, l}$, $\text{Reg}(S, \{\xi_i\})$, etc. are to the corresponding subsets of $S_{\text{new}}$.
- Lines 7–14 find all nodes from $M_{\text{patch}, l}$ that share labeling with $l$. Edges are then replaced to cause $M_{\text{new}}$ to transition into $S_{\text{patch}, l}$ when appropriate.
- Line 15 finds all nodes in $S_{\text{patch}, l}$ that satisfy one of the disjuncts in $\psi_{\text{patch}, l}$ from the patch specification $\varphi_l$.
- Lines 16–23 find among the possible exit nodes in the original strategy $M$ those which match one of the patch exit nodes in $S_{\text{exit}}$. Outgoing transitions are appended to $p' \in S_{\text{new}, l}$. Conditions are added such that a transition out of the patch can only be taken if all local goals have been met at least once (Line 20). Otherwise, execution must continue in the patch (Line 21).
- Lines 24–30 add memory rules to nodes such that appropriate indicators are set when system goals are satisfied.

IV. Analysis

Several sets are invoked in the algorithm in such a way that, if they were empty, then the algorithm would fail to run. We show this is not the case. Let $\zeta_i$ be the unreachable cell, let $S' := \text{Reg}(S, B_{r_{\text{inc}}} (\zeta_i))$, and let $l \in \text{Entry}(S') \cup \{v\} \cup \text{Init}$.

Remark 1: Merging only occurs at nodes corresponding to reachable cells, i.e.

$\text{Entry}(S') \cap \text{Reg}(S, \{\zeta_i\}) = \text{Exit}(S') \cap \text{Reg}(S, \{\zeta_i\}) = \emptyset$

Remark 2: $S_{\text{exit}}$ is nonempty. $M_{\text{patch}, l}$ is a realization of $\varphi_l$, thus by construction of the patch goals $\psi_{\text{patch}, l}$, at least one match will be found.

As stated, the algorithm is not complete due to the simplifying assumption regarding environment behavior in the patch cell. We do not require the adversarial environment to satisfy all of its global “infinitely often” behaviors. A simple counterexample is navigating a vehicle through a thin passageway. Under the patch assumption, it could be blocked indefinitely by an environmentally-controlled obstacle. In contrast, the global specification could require it to clear the passageway always eventually, hence realizability.

However, increasing the radius $r_{\text{inc}}$ causes the algorithm to reduce to the global problem after a finite number of iterations. So in that (degenerate) sense, it is complete.

Theorem 1: Any successfully patched controller $M_{\text{new}}$ realizes the original specification Eq. (2).

Proof: Let $\zeta_i$ be the cell discovered to be unreachable. Let $N = B_{r_{\text{inc}}} (\zeta_i) \subseteq \mathbb{Z}/P$ be the abstract neighborhood. Set $r_{\text{inc}}$ to its value at algorithm termination, and let $S' = \text{Reg}(S, B_{r_{\text{inc}}} (\zeta_i))$.

Aside from initial conditions, the assumption of the global specification Eq. (2) implies the assumptions of all patch
There are two cases to consider. First, for any execution path that is a subset of $S' \setminus \text{Reg}(S, \{\zeta\})$, the global specification is satisfied by hypothesis.

It remains to address execution paths that include nodes from $S_{\text{patch},l}$ for some $l$. There are two basic possibilities from which the more general case can be composed: an execution path that enters then leaves a patch automaton in finitely many steps; or an execution path that enters but does not leave a patch automaton.

For the former case, let $\rho$ be an execution path that enters and leaves in finitely many steps a patch automaton with index $l$. Recall the new strategy $M_{\text{new}}$ is an automaton with finite memory in which an execution path cannot leave one of the sets of patch nodes $S_{\text{patch},l}$ unless all system goals satisfied in $S'$ are satisfied. By the fact that $M_{\text{patch},l}$ realizes specification $\varphi_l$, $S_{\text{patch},l}$ can eventually be departed for any admissible environment behavior.

Given all locally satisfiable system goals have been visited at least once, the execution path $\rho$ returns to the original automaton at a node $v$ that was previously reachable from the same node at which the patch set $S_{\text{patch},l}$ was entered,
Fig. 4. FindTrans(). Subroutine to find relevant safety properties.

1: \( I'_{\alpha,t} \leftarrow \emptyset \)
2: for \( i \) in \( I_{\alpha,t} \) do
3: if \( \exists e \in \Sigma_{\text{inc}}, y \in \Sigma_{\text{term}} : \forall y \neq \psi_{\alpha,t} \) then
4: \( I'_{\alpha,t} \leftarrow I'_{\alpha,t} \cup \{i\} \)
5: end if
6: end for
7: return \( I'_{\alpha,t} \)

Fig. 5. LocalGoals(). Subroutine to find goals locally satisfied in original strategy \( M \).

1: \( I'_{\alpha,g} \leftarrow \emptyset \)
2: for \( i \) in \( I_{\alpha,g} \) do
3: if \( \text{Sat}(S, \psi_{\alpha,g,i}) \cap \text{Reg}(S, B_{\text{inc}}(\zeta_i)) \neq \emptyset \) then
4: \( I'_{\alpha,g} \leftarrow I'_{\alpha,g} \cup \{i\} \)
5: end if
6: end for
7: return \( I'_{\alpha,g} \)

Fig. 6. FindMatches(). Subroutine to find nodes with matching valuations and outward edges.

**Require:** \( l \) node, and \( S \) set of nodes

1: Match \( \leftarrow \emptyset \)
2: for \( w \) in \( S \) do
3: if \( \exists e_1 \in \text{In}(l), e_2 \in \text{In}(w) : h(e_1)g(l) = h(e_2)g(w) \) then
4: for \( e'_1 \) in \( \text{Out}(l) \) do
5: for \( e'_2 \) in \( \text{Out}(w) \) do
6: if \( h(e'_1) = h(e'_2) \) then
7: Match \( \leftarrow \) Match \( \cup \{ (e'_1, w, e'_2) \} \)
8: end if
9: end for
10: end for
11: end if
12: end for
13: return Match

This follows from the local navigation goals in \( \psi_{\text{patch},l} \), which were selected to have the same valuation as reachable exit points in \( M \), i.e. \( \text{Reach}^*(l, S') \cap \text{Exit}(S') \).

The environment could have driven the system from \( l \) to \( v \) under the original strategy \( M \). Hence, any valuations on the execution trace after the path visits patch set \( S_{\text{patch},l} \) were reachable in the original \( M \). Therefore subsequent infinite-often satisfaction of system goals is preserved in this case under the new strategy \( M_{\text{new}} \).

The latter case is only possible for those \( M_{\text{patch},l} \) where \( \text{Reach}^*(l, S') \cap \text{Exit}(S') = \emptyset \), i.e. for which the original solution \( M \) would have a continuous trajectory forever remaining in \( N \). It follows that \( I'_{\alpha,g} \leftarrow I_{\alpha,g} \). Because \( M_{\text{patch},l} \) realizes \( \varphi_l \) by hypothesis, \( \text{exit points in } S_{\text{patch},l} \) must be correct with respect to the global specification Eq. (2).

If the structure of the continuous space changes as considered here, e.g. newly sensed unreachability of cell \( \zeta_i \in Z'/P \), then some safety properties of the original specification may need to be updated to reflect this. Therefore, soundness is with respect to the updated global specification.\(^1\)

V. EXAMPLES

Results below were obtained and displayed using the tools TuLiP \(^2\) [16] and Gephi [17]. Software implementing our algorithm and the gridworld setting has been released open source.\(^2\)

We first look at a specific example and then describe an experiment exploring typical performance. Consider the gridworld shown in Fig. 7. The robot begins operation in the upper-left cell and must visit both cells marked “G” infinitely often. Also it must avoid a dynamic obstacle in the shaded cells. As a fairness condition, the obstacle must always eventually return to the “E” cell. A nominal controller was synthesized using this map without the black wall. Its automaton is depicted above the map.

\[1\] Nonetheless with some abuse of terminology, we use “original” and “global” interchangeably.

\[2\] http://scottman.net/2012/btsynth
problems in simulation. Each randomly generated world has size $5 \times 10$, a density of blocked cells of $0.2$, two goals and one dynamic obstacle. Each such world has an additional blocked cell (not included for nominal planning), and has nominal and actual problems feasible. There were 82 trials in total, 2 of which were severe outliers and pathological nominal and actual problems feasible. There were 82 trials blocked cell (not included for nominal planning), and has one dynamic obstacle. Each such world has an additional

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<th>excluding two severe outliers</th>
<th>mean</th>
<th>std. dev.</th>
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<td>global synthesis time (in seconds)</td>
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<td>348.</td>
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<td>patching synthesis time (in seconds)</td>
<td>32.5</td>
<td>119.</td>
</tr>
<tr>
<td>ratio of patching-to-global time (per trial)</td>
<td>0.411</td>
<td>0.496</td>
</tr>
<tr>
<td>all trials</td>
<td>mean</td>
<td>std. dev.</td>
</tr>
<tr>
<td>global synthesis time (in seconds)</td>
<td>226.</td>
<td>345.</td>
</tr>
<tr>
<td>patching synthesis time (in seconds)</td>
<td>44.6</td>
<td>141.</td>
</tr>
<tr>
<td>ratio of patching-to-global time (per trial)</td>
<td>1.04</td>
<td>4.37</td>
</tr>
</tbody>
</table>

VI. CONCLUSION

Our approach focuses on reachability of the continuous state space. Future work will address changes in dynamic properties of the environment estimated online.

ACKNOWLEDGMENTS

The authors gratefully acknowledge Eric Wolff and Sandeep Chinchali for comments on an earlier draft. This work is partially supported by the Boeing Corporation.

REFERENCES
