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Online Fault Diagnosis of Discrete Event Systems Modeled With Labeled Petri Nets Using an Overall Fault Status

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Abstract—In this paper we present a fault diagnosis approach using labeled Petri nets, where the faults are modeled by unobservable transitions and the unobservable subnet is acyclic. In contrast to detecting the individual faults separately, a new specification called an overall fault status is introduced, which indicates the occurrence of faults from a global system perspective. Due to the introduction of the overall fault status, a more precise and informative diagnosis result can be provided and in some cases, the occurrence of some faults in a system can be detected before the actual faults are isolated, i.e., we are certain about the occurrence of faults but which faults have not been ascertained. An integer linear programming (ILP) problem is built according to the observed word. We prove that all transition sequences determined by solutions to the ILP problem constitute the set of sequences consistent with the observed word. By specifying different objective functions to the ILP problem, the diagnosis results of each individual fault and the overall fault status can be obtained. An online diagnosis algorithm is developed to implement the proposed diagnosis process, which reports the diagnosis results after the occurrence of every observable event.

Index Terms—Fault diagnosis, discrete event system, Petri net, integer linear programming, overall fault status.

I. INTRODUCTION

A. Position of the paper

With the development of contemporary information technology, the man-made mechanical and electronic systems that can be characterized as discrete event systems (DES) are becoming more and more complicated. To ensure their stable and correct operations, fault diagnosis has been an active research area in recent decades. A fault is a kind of event that causes a deviation in system’s behavior such that the performance or throughput of the system is degraded. Fault diagnosis aims to detect and isolate a fault when it occurs such that it can be fixed and the system can recover from it.

The diagnosis of discrete event systems was originally discussed in [1], [2] using an automaton model with faulty (unobservable) events, where a diagnoser, i.e., a deterministic finite automaton (DFA), is first built and then based on the observed sequence the diagnosis result can be directly obtained by checking the diagnoser. The authors also define the diagnosability of an automation model and provide a necessary and sufficient condition for diagnosability.

An alternative to automata for modeling DES is provided by Petri nets. Their structural properties offer a new perspective for supervisory control [3], [4], model identification [5], [6], performance optimization [7], and knowledge discovery [8], [9]. In addition, the state equation of a Petri net provides a linear algebraic technique to deal with the issue of state estimation [10]–[14], which is always more efficient than exhaustively enumerating the reachability graph. In particular, we in this paper deal with the fault diagnosis issue using Petri nets.

In the context of Petri nets, Prock [15] proposed a diagnosis approach for a nuclear power plant by monitoring the number of tokens residing in places associated with P-invariants in a Petri net. Wu and Hadjicostis [16] developed an algebraic approach for fault diagnosis, where both place and transition faults are defined. By introducing additional places into a net, a redundant Petri net can be obtained. The place and/or transition faults can be detected by inspecting the current marking of the redundant net. Ramírez-Treviño et al. [17] proposed a modeling methodology to build an interpreted Petri net (IPN) model of a system and then a fault detection algorithm based on the built IPN is provided. Benveniste et al. [18] reported a net unfolding approach to explore the diagnosis of asynchronous systems, which can be used in a distributed environment.

On the other hand, there is a deluge of studies that use Petri nets by explicitly modeling faults of a system as unobservable transitions [19], i.e., Petri nets, called faulty Petri nets, that contain not only regular but faulty behavior of a system. Genc et al. [20] originally extended the event-based diagnosis using automata to the case of faulty Petri nets. They construct a diagnoser, i.e., a labeled Petri net, according to the original net model of a system and a diagnosis result can be provided online when observing an event. The main drawback of this approach is the computational complexity due to the reachability analysis at each step. Giua and Seatzu [21] proposed a basis-marking-based approach. By means of basis markings and the corresponding justifications, the
enumeration of paths in a reachability graph can be avoided. Cabasino et al. [22]–[24] extended this approach to the case of labeled Petri nets, i.e., nets where two or more transitions can share the same label. They develop a basis reachability graph (BRG), which can be built off-line and provides an efficient method for online diagnosis. In [25], Basile et al. defined a new type of marking with negative elements, called \textit{g-marking}, and proposed an online diagnosis algorithm based on it. Integer linear programming (ILP) is a typical technique to deal with the issue of state estimation in a Petri net. An online diagnosis approach using ILP is reported in [26].

More specifically, the authors first build an integer linear programming model without objective function according to the observed transition sequence. Then, by assigning different objective functions to it, the occurrence of a fault can be detected. Ru et al. [27] addressed the issue of fault diagnosis using a partially observed Petri net (POPN), where a POPN is first converted into a labeled net and then an algorithm based on the reachability graph is proposed.

![Fig. 1. A plant model producing bolts and nuts.](image)

**B. Motivation**

In a faulty Petri net model, faults are explicitly modeled as unobservable transitions and the transition set \( T \) is divided into two disjoint subsets \( T_o \) and \( T_u \) with \( T = T_o \cup T_u \), where \( T_o \) denotes the set of observable transitions and \( T_u \) the set of unobservable transitions. Transitions \( t_1 \in T_o \) and \( t_2 \in T_u \) are assigned a label from the event set \( E \) and an empty string \( \varepsilon \), respectively. In general, the diagnosis result provided by approaches based on faulty Petri nets [12], [21]–[23], [25], [28] can be represented by a function \( \Delta : E^* \times T_f \rightarrow \{0, 1, 2\} \), where \( E \) is the set of events associated with a faulty net, \( T_f = \{f_1, \ldots, f_{n_f}\} \subseteq T_u \) is the set of \( n_f \) fault transitions, and 0, 1 and 2 denote that fault transition \( f_i \in T_f \) does not occur for sure, \( f_i \) may occur and \( f_i \) occurs with certainty, respectively. For example, assuming that the observed sequence is \( \omega \), \( \Delta(\omega, f_1) = 1 \) indicates that \( f_1 \) may (possibly) occur till the observation of \( \omega \).

We next provide an example to show the motivation of introducing an \textit{overall fault status}. Consider the net in Fig. 1 that models a plant producing bolts and nuts. This plant has two production lines: one (upper part) produces mini-size bolts and nuts and the other (lower part) produces medium-size ones. In Fig. 1, we have \( E = \{a, b, c, d\} \), \( T_o = \{t_2, t_3, t_6, t_9, f_1, f_2, f_3\} \), \( T_f = \{f_1, f_2, f_3\} \), \( T_a = \{t_1, t_8\} \), \( T_b = \{t_5, t_7, t_{10}\} \), \( T_c = \{t_4, t_{11}\} \), and \( T_d = \{t_{12}\} \). The unobservable transitions are represented as gray bars (fault transitions \( f_1, f_2 \) and \( f_3 \) are colored red), and \( T_x \) denotes the set of transitions labeled \( x \) with \( x \in \{a, b, c, d\} \). It is significant to design an algorithm to solve the following problem.

**Problem 1.** Consider the net shown in Fig. 1 and assume that the observed sequence is \( \omega = abb \). Does the plant modeled by this net run normally till the observation of \( \omega \)? (i.e., have some faults occurred in the plant?)

The existing approaches for fault diagnosis, such as those in [12], [21], [23], [25], [28], provide an ambiguous answer to Problem 1 only. The procedure in [23], [25], [28] to solve Problem 1 can be summarized as follows.

\begin{itemize}
  \item **Step 1:** Compute the diagnosis results of \( f_1 \), \( f_2 \) and \( f_3 \), respectively, and obtain that \( \Delta(\omega, f_1) = 1 \), \( \Delta(\omega, f_2) = 1 \) and \( \Delta(\omega, f_3) = 0 \).
  \item **Step 2:** Because of the ambiguous diagnoses of \( f_1 \) and \( f_2 \), one cannot unambiguously determine the occurrence of faults and only an answer that the plant \textit{may} run abnormally can be provided.
\end{itemize}

In fact, the exact answer is that the plant runs abnormally and one of \( f_1 \) and \( f_2 \) necessarily occurs. This situation can be explained by Fig. 2(a), where the symbol \( \varepsilon \) denotes an empty string. As a part of reachability graph of the net shown in Fig. 1, it shows all sequence transitions consistent with \( \omega \). In Fig. 2(a), \( M_0 \) is the initial marking, and \( M_{\omega_1} \) and \( M_{\omega_2} \) are the markings reachable by firing the sequences consistent with \( \omega = abb \). We observe that each path from \( M_0 \) to \( M_{\omega_1} \) or \( M_{\omega_2} \) either goes through \( f_1 \) or \( f_2 \), i.e., there is no path that passes none of faults. Fig. 2(a) can be condensed as Fig. 2(b) which shows all the paths more intuitively. By considering all possible evolutions of the plant consistent with the observation \( abb \), there does not exist a possibility that no fault occurs since each path contains a fault transition. This implies that a fault must occur till the observation of \( abb \) and the plant does not run normally.

![Fig. 2. (a) All paths consistent with abb and (b) an intuitive representation of (a).](image)
This paper will provide a more precise and informative solution to Problem 1 by extending the existing diagnosis function. The new diagnosis function is defined as $\Delta : E^* \times T_j S \rightarrow \{0, 1, 2\}$, where $T_j S = T_j \cup \{F\}$ and $F$ stands for the overall fault status. In contrast to detecting the individual fault separately, the overall fault status indicates the occurrence of faults from a global system perspective. In particular, $\Delta(\omega, F) = 0$ denotes that a system is running normally, $\Delta(\omega, F) = 1$ some faults may occur in the system, and $\Delta(\omega, F) = 2$ some faults must have occurred. Note that, in some cases, the diagnosis of $F$, i.e., $\Delta(\omega, F)$, can be directly inferred from $\Delta(\omega, f_i)$ with $i = 1 \ldots n_f$. However, in other cases, novel methodologies have to be proposed to compute $\Delta(\omega, F)$.

Due to the use of the overall fault status, in some cases, one can detect the occurrence of faults before the actual faults are isolated. Let us consider the net in Fig. 1 again. The diagnosis can detect the occurrence of faults before the actual faults are reported according to the overall fault status $F$. However, in other cases, novel methodologies have to be proposed to compute $\Delta(\omega, F)$.

This framework is appropriate for faults that cause significant changes in the system state but do not bring the system to a halt. In a real-world system, the overall fault status $F$ can be viewed as a fault indicator light that has three colors of green ($\Delta(\omega, F) = 0$), yellow ($\Delta(\omega, F) = 1$), and red ($\Delta(\omega, F) = 2$). If the light is green, it implies that the system is running normally and no fault is detected. Whereas a red light indicates that one or more faults have occurred and then one can check $\Delta(\omega, f_i)$ with $i = 1, \ldots, n_f$ to localize and fix the faults. Graphically, the diagnosis flow can be described by Fig. 3.

### Table I

| $\Delta(\omega, f)$ | $\omega$ | $a$ | $ab$ | $abb$ | $\ldots$ | $abbaaca$ |
|---------------------|----------|-----|------|-------|----------|
| $f_1$               |          | 0   | 1    | 1     | $\ldots$ | 2         |
| $f_2$               |          | 0   | 0    | 1     | $\ldots$ | 0         |
| $f_3$               |          | 0   | 0    | 0     | $\ldots$ | 0         |
| $F$                 |          | 0   | 1    | 2     | $\ldots$ | 2         |

This is particularly meaningful for a system that needs to respond to failures in time. For example, consider an aircraft with five faults from $f_1$ to $f_5$. If we detect that $\Delta(\omega, f_1) = 1$, $\Delta(\omega, f_2) = 1$, $\Delta(\omega, f_i) = 0$ for $i = 3, \ldots, 5$, and $\Delta(\omega, F) = 2$, some faults must occur in the aircraft though we cannot determine which faults occur at present. The captain of the aircraft can deal with this situation immediately before an unambiguous fault is reported.

However, for systems that can tolerate failures, we can wait for a longer observation of an event sequence in order to exactly find the faults with less cost. For example, some components of a system are hard to access and one should exactly identify the location of a fault before taking any corrective action that may involve component inspection and replacement [2]. If the occurrence of faults in a system is detected according to the overall fault status $F$ and the exact faults cannot be currently ascertained, we can consider the following two ways to find the exact faults:

1. Observe continuously the output of a net till a sufficiently long sequence is observed if the net is diagnosable (see Section V);
2. Stop the real-world system and inspect all the faults $f$'s with $\Delta(\omega, f) = 1$ one by one.

The first way provides exact fault locations such that they can be fixed in a short time. But a long wait may be needed to precisely identify the faults. For example, considering Fig. 1 and Table I, we detect the occurrence of faults ($\Delta(abb, F) = 2$) but cannot determine that the fault is $f_1$ or $f_2$ when $\omega = abb$. If the plant continues to run and the observed word is $\omega = abbaaca$, we then conclude that fault $f_1$ must happen ($\Delta(\omega, f_1) = 2$) and $f_2$ not ($\Delta(\omega, f_2) = 0$). On the other hand, for the second way, one has to stop (part of) the plant and further test it to find the faulty components. This will possibly reduce the throughput of the plant and increase the cost of isolating faults.

When performing diagnosis in a system, we will first try to detect any abnormal behavior of the system based on the observation. If the behavior is found to be abnormal, we will refine the diagnosis by using new observations and possibly further testing the system until the faulty components are found [29]. In this paper, a framework to isolate and fix faults in a system is proposed based on the overall fault status $F$. This framework is appropriate for faults that cause significant changes in the system state but do not bring the system to a halt. In a real-world system, the overall fault status $F$ can be viewed as a fault indicator light that has three colors of green ($\Delta(\omega, F) = 0$), yellow ($\Delta(\omega, F) = 1$), and red ($\Delta(\omega, F) = 2$). If the light is green, it implies that the system is running normally and no fault is detected. Whereas a red light indicates that one or more faults have occurred and then one can check $\Delta(\omega, f_i)$ with $i = 1, \ldots, n_f$ to localize and fix the faults. Graphically, the diagnosis flow can be described by Fig. 3.

As shown in Fig. 3, there are two processes in the system: diagnosis process and supervision process. The diagnosis process makes a diagnosis when observing an event and enters the diagnosis result into a log file (see Fig. 3(a)). Note that a plant may continue to run and record the diagnosis result even if some faults have occurred. The supervision process monitors...
the operation of the plant and decides whether to stop it to fix
faults when the indicator light is red (see Fig. 3(b)).

C. Contribution

In this paper, we extend the approach in [26] to explore an
improved diagnosis algorithm based on labeled Petri nets and
the overall fault status. As done in the literature [22, 25],
the approach in [26] can only be used for a special class of
labeled Petri nets, i.e., nets in which each observable transition
is assigned a unique label. We first extend the approach in [26]
to the case of a labeled Petri net with an arbitrary labeling
function, i.e., two or more transitions can share the same label,
and then propose some new theoretical results to compute
\(\Delta(\omega, T)\). An online diagnosis approach is presented, which
implements the diagnosis process described in Fig. 3(a).

Note that Fanti et al. [30] also extend the approach in [26] to
the case of a labeled Petri net. They first build an ILP problem
based on a transition sequence \(\sigma_o \in T_o^*\) using a special class
of labeled Petri net where an observable transition is assigned
a unique label. Then, for an observed word \(\omega \in E^*\), they
exhaustively enumerate all possible sequences \(\sigma_o's\) with \(\sigma_o \in
T_o^*\) whose projections on \(E\) are \(\omega\) and, for each sequence
\(\sigma_o,\) solve a number of ILP problems built from it to perform
online diagnosis. For an observed word \(\omega,\) there may exist a
lot of transition sequences \(\sigma_o's\) whose projection on \(E\) are
\(\omega\). Thus, a large number of ILP problems may need to be
solved according to the approach in [30], which is infeasible
in general due to prohibitive computational cost.

Different from the work in [30], we in this paper extend
and improve the approach in [26] from a different perspective.
Specifically, our extension is completely based on labeled Petri
nets and an ILP problem is constructed based on the observed
word \(\omega\) not a transition sequence \(\sigma_o \in T_o^*\). Compared with
the approach in [30], the number of times of solving ILP
problems of our approach is usually considerably small when
perform diagnosis for an observed word (see Section VI for
an example).

The main contributions of the paper can be summarized as
follows.

1. We introduce a new diagnosis specification called an
overall fault status and extend the diagnosis function such
that a more precise and informative diagnosis result can
be provided.

2. We extend and improve the approach in [26] to the case
of general labeled Petri nets, i.e., nets where two or more
transitions can share the same label. Different from the
extension in [30], we do not need to enumerate all possible
sequences of observable transitions consistent with an
observed word \(\omega \in E^*\) and just solve an ILP problem
built according to \(\omega\) to perform diagnosis.

3. In contrast to the work in [30], our approach is usually
more efficient, demonstrated by extensive experimental
studies (see Section VI).

This paper is organized in seven sections. We in Section I
review the related literature and show the motivation of
introducing the overall fault status. The basic definitions
and preliminaries on Petri nets are recalled in Section II.
Section III defines the problem on which this paper focuses.
In Section IV, a solution based on integer linear programming
is proposed. Section V discusses the relationship between
the diagnosability and the overall fault status. We present
an example to compare the proposed approach with the one
in [30] in Section VI. Finally, we conclude the paper in
Section VII.

II. Preliminaries

This section recalls the Petri net formalism and some
preliminary results used throughout the paper. The readers can
refer to [31] and [32] for more details on Petri nets. We denote
by \(\mathbb{N}\) the set of non-negative integers.

A. Basics of Petri nets

A Petri net is a four-tuple \(N = (P, T, \text{Pre}, \text{Post}),\) where
\(P = \{p_1, \ldots, p_m\}\) is a set of \(m\) places, \(T = \{t_1, \ldots, t_n\}\)
is a set of \(n\) transitions with \(P \cup T \neq \emptyset\) and \(P \cap T = \emptyset,\)
\(\text{Pre} : P \times T \rightarrow \mathbb{N}\) and \(\text{Post} : P \times T \rightarrow \mathbb{N}\) are the pre-
and post-incidence matrices, respectively, which specify the
structure of the net. Graphically, places and transitions are
represented by circles and bars, respectively. For each arc with
weight \(\gamma\) from place \(p\) (transition \(t\)) to transition \(t\) (place \(p\)), it
holds \(\text{Pre}(p, t) = \gamma \text{ Post}(p, t) = \gamma\). The other elements of
\(\text{Pre} \) and \(\text{Post}\) are 0. The incidence matrix of a net is denoted by
\(C = \text{Post} - \text{Pre} \). A Petri net is said to be acyclic if there
is no directed cycle.

For a transition \(t \in T,\) its \(\text{ preset}\) is defined as \(\bullet t = \{p \in
P \mid \text{ Pre}(p, t) > 0\}\), and its \(\text{ postset}\) is defined as \(t^* = \{p \in
P \mid \text{ Post}(p, t) > 0\}\). A transition \(t\) is said to be a \(\text{ source transition}\) if \(\bullet t = \emptyset\).

A marking of a Petri net is a vector \(M : P \rightarrow \mathbb{N}\), and \(M(p)\)
indicates the number of tokens, pictorially denoted by black
dots, in place \(p\). We use \(x_1p_1 + \cdots + x_mp_m\) to denote the
marking \([x_1, \ldots, x_m]^T\) for economy of space. A net system
\(\langle N, M_0 \rangle\) is a Petri net \(N\) with an initial marking \(M_0\).

A transition \(t \in T\) is \(\text{ enabled at}\) marking \(M\) if for all \(p \in
\bullet t, M(p) \geq \text{ Pre}(p, t),\) which is denoted by \(M[t]\). An enabled
transition \(t \in M\) can fire yielding a new marking \(M'\) such
that \(M' = M + C(\cdot, t),\) which is denoted by \(M[t]M'\).

For a transition sequence \(\sigma \in T^*\) and a marking \(M, M[\sigma]\)
denotes that \(\sigma\) is enabled at marking \(M\) and \(M[\sigma]M'\) denotes
that a new marking \(M'\) is \(\text{ reachable}\) from \(M\) after firing \(\sigma\).
The set of all the markings reachable from \(M_0\) is denoted by
\(R(N, M_0),\) called the \(\text{ reachability set}\) of a Petri net. The set
of transition sequences enabled at the initial marking \(M_0\) is
defined as

\[\mathcal{L}(N, M_0) = \{\sigma \in T^* \mid M_0[\sigma]\}\]

which is called the \(\text{ language}\) of Petri net system \(\langle N, M_0 \rangle\).

We define a function \(\pi : T^* \rightarrow \mathbb{N}^n\) that maps a transition
sequence \(\sigma \in T^*\) to \(n\)-dimensional column vector \(y = \pi(\sigma),\)
called \(\text{ firing vector},\) such that \(y_i(t) = k\) if transition \(t\) appears
\(k\) times in \(\sigma\). Write \(t \in \sigma\) to denote that \(t\) is contained in \(\sigma\).

Given \(M_0[\sigma]M,\) we have

\[M = M_0 + C \cdot \pi(\sigma).\]  \hspace{1cm} (1)
Eq. (1), called the state equation, shows that there exists a non-negative integer vector \( y \) such that \( M = M_0 + C \cdot y \) if \( M \) is reachable from \( M_0 \), which is a necessary but not sufficient condition for the reachability of marking \( M \) from \( M_0 \). However, for an acyclic net, it is necessary and sufficient, as verified by the following result.

**Theorem 1.** [31] Let \( (N, M_0) \) be an acyclic Petri net. A marking \( M \geq 0 \) is reachable from \( M_0 \) if and only if (iff) there exists a non-negative integer vector \( y \) satisfying \( M = M_0 + C \cdot y \).

**B. Labeled Petri net**

Given a Petri net \( N = (P, T, Pre, Post) \) and the event set \( E \), a labeling function \( \lambda: T \to E \cup \{ \varepsilon \} \) assigns to each transition \( t \in T \) either a symbol from the event set \( E \) or an empty string \( \varepsilon \). In the case of no confusion, a labeled Petri net in this paper refers to a net with an arbitrary labeling function, i.e., two or more transitions can share the same label. A Petri net system \( (N, M_0) \) with an arbitrary labeling function, \( \pi \), is called a labeled Petri net system, denoted by \( (N, M_0, E, \lambda) \).

A transition \( t \) is said to be unobservable or silent if it is associated with the label \( \varepsilon \), i.e., \( \lambda(t) = \varepsilon \). The set of unobservable transitions is denoted by \( T_u = \{ t \in T \mid \lambda(t) = \varepsilon \} \) with cardinality \( n_u \). All other transitions whose labels come from event set \( E \) constitute the set of observable transitions \( T_o = \{ t \in T \mid \lambda(t) \neq \varepsilon \} \) with cardinality \( n_o \). Thus, set \( T \) is divided into two disjoint subsets \( T_o \) and \( T_u \) with \( T = T_o \cup T_u \). For a faulty Petri net, the faults are always modeled by unobservable transitions and accordingly the set of unobservable transitions is also divided into two disjoint subsets \( T_{reg} \) and \( T_f \), i.e., \( T_u = T_{reg} \cup T_f \), where \( T_{reg} \) denotes the set of regular unobservable transitions and \( T_f \) the set of \( n_f \) fault transitions. We use \( T_e = \{ t \in T \mid \lambda(t) = \varepsilon \} \) to represent the set of transitions with the same label \( \varepsilon \) in \( E \).

Analogously to the definition of function \( \pi \), for each sequence \( \sigma_o \in T_o^* \), we define a function \( \pi_o: T_o^* \to N^{n_o} \) such that \( y = \pi_o(\sigma_o) \) and \( y(t) = k \) if \( t \in T_o \) appears \( k \) times in \( \sigma_o \). Similarly, the function \( \pi_u: T_u^* \to N^{n_u} \) associates a sequence \( \sigma_u \in T_u^* \) with an \( n_u \)-dimensional vector \( \pi_u(\sigma_u) \).

We extend the definition of labeling function \( \lambda \) to a sequence \( \sigma \in T^* \) such that \( \lambda(\sigma) = \lambda(\sigma(t)) \), i.e., for a sequence \( \sigma \in T^* \), \( \lambda(\sigma) \) is an observed word composed of the labels of observable transitions contained in \( \sigma \). The set of observed words in a labeled Petri net system \( (N, M_0, E, \lambda) \) is defined as

\[
\mathcal{L}^E(N, M_0) = \{ \omega \in E^* \mid \sigma \in \mathcal{L}(N, M_0), \omega = \lambda(\sigma) \}.
\]

Equation (1) is called the state equation, which shows that there exists a non-negative integer vector \( y \) such that \( M = M_0 + C \cdot y \) if \( M \) is reachable from \( M_0 \), which is a necessary but not sufficient condition for the reachability of marking \( M \) from \( M_0 \). However, for an acyclic net, it is necessary and sufficient, as verified by the following result.

**Theorem 1.** [31] Let \( (N, M_0) \) be an acyclic Petri net. A marking \( M \geq 0 \) is reachable from \( M_0 \) if and only if (iff) there exists a non-negative integer vector \( y \) satisfying \( M = M_0 + C \cdot y \).

## III. Problem Statement

Fault diagnosis consists in determining if faults have occurred in a system according to the observed system output, such as the observed word \( \omega \) in a Petri net. As done in the literature, we can design a diagnoser, i.e., a diagnosis function, to show the diagnosis result. For a labeled Petri net with event set \( E \), a diagnoser is a function \( \Delta: E^* \times T_f \to \{ 0, 1, 2 \} \) such that a fault \( f \in T_f \) does not occur if \( \Delta(\omega, f) = 0 \), may occur if \( 1 \), and necessarily occurs if \( 2 \). Next, we provide the formal definition of diagnosis function \( \Delta \).

**Definition 2.** Let \( (N, M_0, E, \lambda) \) be a labeled Petri net system. The diagnosis function \( \Delta: E^* \times T_f \to \{ 0, 1, 2 \} \) associates an observed word \( \omega \in \mathcal{L}^E(N, M_0) \) and a fault \( f \in T_f \) with a diagnosis state such that

1. \( \Delta(\omega, f) = 0 \) if for all \( \sigma \in \overline{C}(\omega), f \notin \sigma \), i.e., each path consistent with \( \omega \) in the reachability graph does not pass fault transition \( f \).
2. \( \Delta(\omega, f) = 1 \) if there exist \( \sigma_1, \sigma_2 \in \overline{C}(\omega) \) such that \( f \notin \sigma_1 \) and \( f \in \sigma_2 \), i.e., there exist two paths, one of which passes \( f \) and the other does not.
3. \( \Delta(\omega, f) = 2 \) if for all \( \sigma \in \overline{C}(\omega), f \in \sigma \).

Note that some existing studies [21], [22] additionally consider the possible fault transitions after the last observed event of \( \omega \) when performing diagnosis, i.e., the definition of \( \Delta \) is based on \( C(\omega) \) not \( \overline{C}(\omega) \). However, in this paper we do not adopt this setting and detect only the fault transitions occurring before the last event of \( \omega \) in order to be consistent with the seminal work in [1].
From Definition 2, we observe that the diagnoser $\Delta$ only concerns if an individual fault $f \in T_f$ has occurred during the system evolution and there is no information to indicate the overall system fault state, i.e., the diagnosis results of all fault transitions cannot completely describe the fault state of the system. To overcome this, we introduce the notion of the overall fault status $F$ in Subsection I-B.

A diagnostic Petri net system $(N, M_0, E, \lambda, F)$ is a labeled Petri net system $(N, M_0, E, \lambda)$ with an overall fault status $F$. For $(N, M_0, E, \lambda, F)$, the diagnosis function is extended as $\Delta: E^* \times T_f S \rightarrow \{0, 1, 2\}$, where $T_f S = T_f \cup \{F\}$. The diagnosis of $F$ is defined as follows.

**Definition 3.** Let $(N, M_0, E, \lambda, F)$ be a diagnostic Petri net system. For an observed word $\omega \in L^E(N, M_0)$, the diagnosis of $F$ is represented by a diagnosis function $\Delta: E^* \times T_f S \rightarrow \{0, 1, 2\}$ such that

1. $\Delta(\omega, F) = 0$ if for all $\sigma \in \widehat{C}(\omega)$ and for all $f \in T_f$, $f \notin \sigma$.
2. $\Delta(\omega, F) = 1$ if there exist $\sigma_1, \sigma_2 \in \widehat{C}(\omega)$ such that (i) for all $f \in T_f$, $f \notin \sigma_1$ and (ii) there exists $f \in T_f$, $f \in \sigma_2$.
3. $\Delta(\omega, F) = 2$ if for all $\sigma \in \widehat{C}(\omega)$, there exists $f \in T_f$ such that $f \in \sigma$.

In some cases, the value of $\Delta(\omega, F)$ can be directly deduced from $\Delta(\omega, f)$, where $f$ is the overall fault status and extend this approach to the case of a labeled Petri net. First, we give a theorem that is the cornerstone of the proposed ILP-based approach.

**Theorem 2.** Given a labeled Petri net $(N, M_0, E, \lambda)$ and an observed word $\omega = e_1 e_2 \ldots e_h \in L^E(N, M_0)$, there exists a sequence $\sigma = \sigma_{u_1} t_{o_1} \ldots \sigma_{u_h} t_{o_h} \in \widehat{C}(\omega)$ if and only if there exist vectors $y_i$ and binary variables $z_i$ with $i = 1, \ldots, h$ and $j = 1, \ldots, n_{e_i}$, satisfying the following equation

$$
\begin{align*}
&\{M_0 + C_u \sum_{\gamma=1}^i y_\gamma + \sum_{\gamma=1}^{i-1} \sum_{\delta=1}^{n_\gamma} C(t_{o_\gamma}, t_{e_\gamma}) \cdot (1 - z_{e_\gamma}) - P_{re}(y_i) \geq -z_{e_1} \cdot K \\
&\vdots \\
&\{M_0 + C_u \sum_{\gamma=1}^i y_\gamma + \sum_{\gamma=1}^{i-1} \sum_{\delta=1}^{n_\gamma} C(t_{o_\gamma}, t_{e_\gamma}) \cdot (1 - z_{e_\gamma}) - P_{re}(t_{e_\gamma}) \geq -z_{e_1} \cdot K \\
&z_{e_1} + \ldots + z_{n_{e_i}} = n_{e_i} - 1 \\
&T_{e_i} = \{t_{e_1}, \ldots, t_{e_i}\}, \\
y_i \in \mathbb{N}^{n_{e_i}} \\
z_{e_1}, \ldots, z_{n_{e_i}} \in \{0, 1\} \\
i = 1, \ldots, h,
\end{align*}
$$

(2)

where $h \in \mathbb{N}$ is the length of the observed word, $n_{e_i}$ is the cardinality of set $T_{e_i}$, $\sigma_{u_i} \in T_{u_i}^\ast$, $t_{o_i} \in T_{o_i}$, $y_i = \pi_u(\sigma_{u_i})$ is a firing vector, and $K$ is a sufficiently large positive integer.

**Proof.** For $i = 1, \ldots, h$, Eq. (2) contains $h$ groups of constraints. For $i = 1$, we obtain the first group of constraints shown as follows:

$$
\begin{align*}
&\{M_0 + C_u \cdot y_1 - P_{re}(y_i) \geq -z_{e_1} \cdot K \\
&\vdots \\
&\{M_0 + C_u \cdot y_1 - P_{re}(t_{e_1}) \geq -z_{e_1} \cdot K \\
z_{e_1} + \ldots + z_{n_{e_1}} = n_{e_1} - 1
\end{align*}
$$

Since $z_{k_{e_1}}$ with $k = 1, \ldots, n_{e_1}$ are binary variables, there must exist a variable with value 0 among them. Without loss of generality, we assume $z_{e_1} = 0$. Then we have $M_0 + C_u y_1 \geq P_{re}(t_{e_1})$. Considering that the unobservable subnet is acyclic, there exists a transition sequence $\sigma_{u_1} \in T_{u_1}^\ast$ such that
Given a labeled Petri net \((N, M_0, E, \lambda)\) and an observed word \(\omega = e_1 e_2 \ldots e_h\), for each \(f \in T_f\), \(\Delta(\omega, f) = 2\) if ILPP 3 admits \(\gamma > 0\) or \(\Delta(\omega, f) = 0\) or 1 if \(\gamma = 0\).

ILPP 3: \[
\gamma = \min \sum_{i=1}^{h} y_i(f) \\
\text{s.t. Eq. (2)}
\]

Proof. Note that objective function \(\sum_{i=1}^{h} y_i(T_f)\) denotes the sum of projections of \(n_u\)-dimensional column vectors \(y_i\)'s over the set \(T_f\). If \(\gamma = 0\), there exists a group of unobservable sequences \(\sigma_{u_i}\) corresponding to \(y_i\) with \(i = 1, \ldots, h\) such that \(\sigma = \sigma_{u_1} t_{a_1} \ldots \sigma_{u_k} t_{a_k}\) and \(f \notin \sigma\) for each \(f \in T_f\), i.e., there exists at least one path which passes none of fault transitions in the reachability graph from \(M_0\) to \(\overline{D(\omega)}\). Thus, in this case, \(\Delta(\omega, F) = 0\) or 1 according to Definition 3. On the contrary, if \(\gamma > 0\), there does not exist such a path, i.e., each path must pass one or more fault transitions. Thus, we have \(\Delta(\omega, F) = 2\).

Now, an online algorithm to Problem 2 can be provided. Algorithm 1 describes the basic steps of how to perform diagnosis in a labeled Petri net by using the ILP technique only. The correctness of this algorithm is ensured by Proposition 1 and Corollaries 1, 2 and 3.

We briefly illustrate how Algorithm 1 works. It is described in C-like syntax. For example, we use the symbol "\(=\)" to represent an assignment operation and "\(==\)" to indicate that two variables are equal. In Line 1, \(R = \{0^n\}\) is an \(n_f\)-dimensional column vector that records the diagnosis result of each \(f \in T_f\). For a fault \(f\), its diagnosis is denoted by \(R(f)\). Note that \(n_f\) is the cardinality of set \(T_f\). Variable \(s\) represents the diagnosis of the overall fault status \(F\), i.e., \(\Delta(\omega, F)\). The diagnosis results \(R\) and \(s\) are written into a log file in Line 26. We in Section I discuss how to use the log file to refine the diagnosis result (see Fig. 3(b)). The value of \(\Delta(\omega, f)\) with \(f \in T_f\), i.e., \(R(f)\), is first computed by Lines 4–13 according to Corollaries 1 and 2. In some cases, \(\Delta(\omega, F)\) can be directly derived from \(R\) (see Proposition 1 for details). Thus by Lines
Algorithm 1: Online fault diagnosis using a diagnostic Petri net system

**Input:** A diagnostic Petri net system $(N, M_0, E, \lambda, F)$

**Output:** The diagnosis result for each observed event $e \in E$

1. $\omega = \varepsilon$, $\mathcal{R} = \emptyset$, $s = 0$;
2. Wait until a new event $e$ is observed;
3. $\omega = \omega e$;
4. for each $f \in T_f$ do
   5. Set $\gamma_1$ be the maximal objective value of ILPP 1;
      if $\gamma_1 = 0$ then
         7. $\mathcal{R}(f) = \Delta(\omega, f) = 0$;
      else
         8. Set $\gamma_2$ be the minimal objective value of ILPP 2;
            if $\gamma_2 > 0$ then
               10. $\mathcal{R}(f) = \Delta(\omega, f) = 2$;
            else
               12. $\mathcal{R}(f) = \Delta(\omega, f) = 1$;
      end
   end
   14. if $\mathcal{R} == \emptyset$ then
      15. $s = \Delta(\omega, F) = 0$;
   else if there exists an entry $r$ in vector $\mathcal{R}$ such that $r == 2$ then
      17. $s = \Delta(\omega, F) = 2$;
   else if there exists only an entry $r$ in vector $\mathcal{R}$ such that $r == 1$ then
      19. $s = \Delta(\omega, F) = 1$;
   end
20. $\mathcal{R}$ and $s$ and write them into log file; **Goto 2**;

14–19, we compute $\Delta(\omega, F)$ according to the diagnosis of each $f \in T_f$, i.e., $\mathcal{R}$. If $\Delta(\omega, F)$ cannot be directly obtained by $\mathcal{R}$, we have to solve ILPP 3 to determine $\Delta(\omega, F)$ according to Corollary 3 (Lines 21–25). When the algorithm completes the diagnosis of the current step, it returns to Line 2 to wait for a new observed event.

The main computational cost of Algorithm 1 stems from the solutions of ILPPs 1, 2, 3. As known, solving an integer linear programming problem is NP-hard. Further, the computational cost mainly depends on its size, i.e., the number of integer variables and constraints. We next analyze the size of the programming problem Eq. (2).

For $\omega = e_1 \ldots e_{14}$, it is readily to verify that the number of variables in Eq. (2) can be represented as

$$
\mathcal{I} = (n_u + n_{e_1}) + (n_u + n_{e_2}) + \ldots + (n_u + n_{e_{14}}) = h \cdot (n_u + n_f),
$$

where $n_u = |T_u|$, $n_f = |T_f|$, $n_{e_i} = |T_{e_i}|$. Eq. (2) contains $h \cdot |\cdot|$ denotes the cardinality of a set.

V. DIAGNOSABILITY AND OVERALL FAULT STATUS

The diagnosability of a Petri net is discussed in [34]–[36]. If a fault $f$ is diagnosable, then the occurrence of $f$ can be detected in a finite number of steps. Given a Petri net language $\mathcal{L}$, its post-language after a transition sequence $\sigma \in \mathcal{L}$ is defined as $\mathcal{L}/\sigma = \{ \tau \in T^* \mid \sigma \tau \in \mathcal{L} \}$. Formally, the diagnosability of $f$ is defined as follows.

**Definition 4.** [35] Given a labeled net $(N, M_0, E, \lambda, F)$, a fault transition $f$ is diagnosable if there exists an integer $K \in \mathbb{N}$ such that

$$
\forall \sigma = \delta f \in \mathcal{L}(N, M_0), \forall \tau \in \mathcal{L}(N, M_0)/\sigma \text{ with } |\tau| > K \Rightarrow \forall \sigma' \in \overline{\mathcal{T}}(\lambda(\sigma \tau)), f \in \sigma', \text{ where } \delta \in \mathcal{L}(N, M_0).
$$

### TABLE II

<table>
<thead>
<tr>
<th></th>
<th>$e_1$</th>
<th>$e_2$</th>
<th>$e_3$</th>
<th>$e_4$</th>
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<tr>
<td>$f_1$</td>
<td>0</td>
<td>1</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>$f_2$</td>
<td>0</td>
<td>0</td>
<td>1</td>
<td>1</td>
</tr>
<tr>
<td>$f_3$</td>
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<td>0</td>
<td>0</td>
<td>0</td>
</tr>
<tr>
<td>$F$</td>
<td>0</td>
<td>1</td>
<td>2</td>
<td>2</td>
</tr>
</tbody>
</table>
Time (s) | 0.0115 | 0.0107 | 0.0209 | 0.0233 |

Example 2. Let us consider the net shown in Fig. 1. Assume that the observed word is $\omega = abba$. The diagnosis result and running time are shown in Table II, where, for each event $e_i$, there is a column which lists the diagnosis result and running time corresponding to $e_i$. For example, considering $e_3 = b$ (i.e., $\omega = e_1 e_2 e_3 = abbb$), the diagnosis results are $\Delta(\omega, f_1) = 1$, $\Delta(\omega, f_2) = 1$, $\Delta(\omega, f_3) = 0$, and $\Delta(\omega, F) = 2$ and the running time is 0.0209s. Note that the time is obtained by executing a MATLAB procedure with GUROBI solver (academic license) [33] on a laptop computer with Intel i5-4200M 2.5GHz processor and 8G DDR3 1600Hz RAM.
If all fault transitions of a Petri net system are diagnosable, then the Petri net system is said to be diagnosable. For a diagnosable labeled Petri net, we have the following proposition.

**Proposition 2.** Consider a diagnosable labeled Petri net system \((N, M_0, E, \lambda)\) with an overall fault status \(F\). For each sequence \(\sigma f\sigma' \in L(N, M_0)\), it holds \(\Delta(\omega, F) = 2\), where \(\sigma \in T^*, f \in T_f, \sigma' \in T^+\) with \(|\sigma'| > K\), and \(\omega = \lambda(\sigma f\sigma')\).

**Proof.** Since \(f\) is diagnosable, for each \(\sigma_1 \in \mathcal{C}(\omega)\), it holds \(f \in \sigma_1\). Thus, we have \(\Delta(\omega, F) = 2\) by Definition 3. \(\square\)

In plain words, when a system is running, a fault \(f \in T_f\) occurs and the process continues. After \(K\) steps, we are sure that \(f\) has occurred according to the observation \(\omega\). Thus, \(\Delta(\omega, F) = 2\) is true, which implies \(\Delta(\omega, F) = 2\).

Only when the Petri net model of a system is diagnosable (or 1-diagnosable [1]), can the diagnosis algorithms detect unambiguously which faults have occurred. However, due to the use of overall fault status \(F\), even if a net model of a system is not diagnosable, it is possible to detect the occurrence of faults in the system though we do not know exactly which fault occurs. An example is provided to clarify this.

**Example 3.** Consider the net shown in Fig. 4, where \(T_u = \{t_6, f_1, f_2\}\) and \(T_f = \{f_1, f_2\}\). According to Definition 4, both \(f_1\) and \(f_2\) are not diagnosable. Assume that the observed word is \(\omega = (\text{abb})(\text{abb})\cdots\). Then it holds \(\Delta(\omega, f_1) = \Delta(\omega, f_2) = 1\), i.e., the diagnosis results of \(f_1\) and \(f_2\) are ambiguous for infinite \(\omega\). However, for \(\omega' = \text{abb}\), it holds \(\Delta(\omega', F) = 2\), i.e., when observing only \(\text{abb}\), we have already known that some faults occur in the system. In this case, although we are sure that at least a fault has occurred, we are unable to exactly identify which faults have occurred. In real-world systems, a possible strategy is to stop the plant and inspect the faults one by one.

**VI. Case Study**

We in this section explore the computational overhead of the proposed algorithm and compare its efficiency with the one shown in [30] by an example. Consider the labeled Petri net shown in Fig. 5 that is originally introduced in [20] and slightly modified in this paper, where \(T_u = \{t_1, t_3, t_4, t_{11}, f_2\}\), \(T_f = \{f_1, f_2\}\), \(T_a = \{t_3, t_5, t_6, t_8\}\), \(T_e = \{t_7, t_9, t_{10}, t_{12}\}\), \(T_h = \{t_{16}\}\), \(T_g = \{t_{14}, t_{15}, t_{17}\}\). The initial marking is \(M_0 = p_1 + \alpha p_2 + \beta p_3\), where \(\alpha\) and \(\beta\) are two variables denoting the numbers of tokens in \(p_2\) and \(p_3\), respectively.

Let \(\alpha = 10\) and \(\beta = 10\), and assume that the observed word is \(\omega = \text{ae}(\text{aeg})^{10}\text{gggg}\), where \(\text{aeg}\) represents that the sequence \(\text{aeg}\) repeats 10 times. When observing an event, we make a diagnosis using Algorithm 1. The running time of Algorithm 1 for each observed event is shown in Fig. 6, where the \(x\)-axis represents the index of each event in sequence \(\omega\).

We have shown in Section IV that the size of programming model Eq. (2) is linear with respect to the length of the observed word. However, the difficulty of a generic ILP problem always increases exponentially with respect to its size, which is verified by Fig. 6. This implies that one probably cannot obtain the diagnosis result in real time if the observed sequence is very long. However, integer linear programming is a standard mathematical tool for diagnosis of Petri nets based on which some new approaches can be developed to overcome the complexity issue, which will be done in our subsequent work.

Fanti et al. [30] also proposed an algorithm for fault diagnosis using labeled Petri nets and integer linear programming. However, the key idea is different from us. They first build an integer programming problem according to a transition sequence \(\sigma \in T_u\) not an observed word \(\omega \in E^*\). Then, for an observed word \(\omega\), they explore all possible sequences of observable transitions whose projections over \(E\) are equal to \(\omega\). The size of the programming problem in [30] is smaller...
than the one in this paper. However, it has to be solved more times to obtain the diagnosis result.

The output and computational process of the algorithm proposed by Fanti et al. [30] are different from ours. In order to compare the efficiency of these two algorithms, we have to modify one of them to make them have the same input and output. We here choose to modify Fanti’s algorithm, though it is completely feasible to modify our algorithm (note that modifying our algorithm will lose some diagnostic information). The details of the modification of Fanti’s algorithm is discussed in Appendix A and this section mainly focuses on the comparison of these two algorithms. On the other hand, our algorithm, i.e., Algorithm 1, and the modified version of Fanti’s algorithm are both implemented in MATLAB language. The readers can refer to [37] for the source code.

Consider the net in Fig. 5 again and assume that \( \alpha = \beta = 7 \). If the observed word is \( \omega = \alpha e (a e g) g g g g g \), the comparison of these two algorithms is shown in Table III. The first row lists all events in \( \omega \). The second row shows the number of times to solve the programming problems defined in [30] when dealing with the diagnosis issue using the algorithm (modified version) developed in [30]. The fourth and fifth rows demonstrate the running time of diagnosis algorithms proposed by us and Fanti et al. [30], respectively. The running time is tested using GUROBI solver [33] on a laptop computer with Intel i5-4200M 2.5GHz processor and 8G DDR3 1600Hz RAM. The sixth row lists the diagnosis result for each event, which is represented as \( \Delta(\omega, f_1) = a, \Delta(\omega, f_2) = b, \) and \( \Delta(\omega, F) = c \). Note that the diagnosis of the fourth event from the last is \([1\ 1\ 2]\), i.e., we detect the occurrence of faults \([1\ 1\ 2]\) before the exact faults are ascertained. The detailed comparison of running time is also illustrated by Fig. 7. We observe that our approach is more efficient in this example.

![Fig. 7. Comparison of our approach with the one in [30].](image)

### VII. CONCLUSION

This paper addresses the problem of fault diagnosis by formulating and solving ILP problems. The main contributions consist in introducing the overall fault status and proposing an online diagnosis algorithm based on labeled Petri nets, in which two or more transitions can share the same label. The overall fault status provides a more informative diagnosis result, i.e., not only every fault but also the global system fault status can be detected. In addition, we show that, in some cases, a definite conclusion on the occurrence of faults in a system can be given even if the system is not diagnosable. We also compare the efficiency of the proposed approach with the one in [30] by a case study and the result shows that our approach is usually more efficient.

In future work, we plan to extend and modify the other diagnosis approaches, such as those in [25] and [21], to make them have a uniform interface. Then, we will develop a software package to compare their efficiency. On the other hand, we will explore the use of an overall fault status in a distributed environment.

### REFERENCES

TABLE III
COMPARISON OF OUR APPROACH WITH THE ONE IN [30].

<table>
<thead>
<tr>
<th>event</th>
<th>$a$</th>
<th>$e$</th>
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<th>$a$</th>
<th>$e$</th>
<th>$g$</th>
<th>$g$</th>
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<td>5</td>
<td>3</td>
<td>3</td>
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<td>3</td>
</tr>
<tr>
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<td>$\cdots$</td>
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<td>$\cdots$</td>
<td>$\cdots$</td>
<td>$\cdots$</td>
<td>[1 1 2]</td>
<td>[0 2 2]</td>
</tr>
</tbody>
</table>

APPENDIX A
MODIFICATION DETAILS OF THE ALGORITHM IN [30]

The centralized fault diagnosis algorithm proposed in [30] has a different output with the one in this paper and thus we need to modify it, keeping the key idea unchanged, to compare its efficiency with our approach. We first briefly recall the ILP problem defined in [30] based on a sequence $\sigma_0 \in T^*_o$.

Given a sequence of observable transitions denoted by $\sigma_0 = t_{\alpha_1} t_{\alpha_2} \cdots t_{\alpha_h}$, the ILP problem without objective function can be defined as

\[
\begin{align*}
M_0 + C_u \cdot \sum_{k=1}^h y_k + \sum_{k=1}^h C(\cdot, t_{\alpha_k}) \geq Pre(\cdot, t_{\alpha_k}) \\
y_i \in \mathbb{N}^{n_u} \quad & i = 1, \ldots, h.
\end{align*}
\]

By specifying different objective functions to Eq. (3), we obtain three ILP models:

**ILPP 4:** $\phi_1 = \max \sum_{i=1}^h y_i(f)$ \quad s.t. Eq. (3)

**ILPP 5:** $\phi_2 = \min \sum_{i=1}^h y_i(f)$ \quad s.t. Eq. (3)

**ILPP 6:** $\phi_3 = \min \sum_{i=1}^h y_i(T_f)$ \quad s.t. Eq. (3).

On the basis of these ILP problems, the Fault Detection Algorithm (FDA) proposed in [30] (see Fig. 2 in [30]) is modified as Algorithm 2 which takes a transition sequence $\sigma_0 \in T^*_o$ as input. At the same time, the Diagnoser Algorithm (DA) proposed in [30] (see Fig. 3 in [30]) is modified as Algorithm 3 which enumerates all sequences of observable transitions consistent with an observed word and repetitively calls Algorithm 2. The data shown in rows 3 and 5 of Table III is computed by executing Algorithm 3. The readers can inspect the source code [37] for the details.

Note that the symbol $\otimes$ (not mentioned in [30]) in Line 11 of Algorithm 3 is another contribution of this paper, which is a binary operation defined in Table IV and very appropriate to compute the combination of diagnosis results of transition sequences $\sigma_0$’s consistent with an observed word $\omega$. We will extend the approaches shown in [21] and [25] to the case of labeled Petri nets using this symbol in the subsequent research. We next show the formal definition of symbol $\otimes$ and prove its correctness.

Analogous to the labeling function $\lambda$, we define a new function $\tau: T \to T^*_o \cup \{\epsilon\}$ such that $\tau(t) = t$ if $t \in T^*_o$ and $\tau(t) = \epsilon$ if $t \in T^*_o$. The function $\tau$ is extended to a sequence $\sigma t \in T^*_o$ such that $\tau(\sigma t) = \tau(\sigma) \tau(t)$, i.e., $\nu = \tau(\sigma)$ represents
Algorithm 2: A fault diagnosis algorithm denoted by
\((\mathcal{R}, s, \chi) = \text{new\_FDA}(\mathcal{N}, \sigma_o)\)

**Input:** A diagnostic Petri net system \(\mathcal{N} = (N, M_0, E, \lambda, \mathcal{F})\)
and a transition sequence \(\sigma_o \in T_o^*\)

**Output:** The diagnosis results \(\mathcal{R}\) and \(s\) of fault transitions and
the overall fault status, respectively, a flag \(\chi\) to denote
if an ILP problem admits a solution

1. \(\mathcal{R} = \bar{0}\), \(s = 0\), \(\chi = \text{true}\), build Eq. (3) according to \(\sigma_o\);
2. \(\text{if Eq. (3) has no feasible solution then}\)
   \(\chi = \text{false} \Rightarrow \text{return } \mathcal{R}, s\) and \(\chi\) (terminate the procedure);
3. \(\text{for each } f \in T_f\) do
   \(\text{if } \varphi_1 == 0 \text{ then}\)
   \(\mathcal{R}(f) = \Delta(\omega, f) = 0;\)
   \(\text{else}\)
   \(\mathcal{R}(f) = \Delta(\omega, f) = 1;\)
4. \(\text{if } \varphi_2 == 0 \text{ then}\)
   \(\mathcal{R}(f) = \Delta(\omega, f) = 1;\)
   \(\text{else}\)
   \(\mathcal{R}(f) = \Delta(\omega, f) = 2;\)
5. \(\text{if } \varphi_3 == 0 \text{ then}\)
   \(s = \Delta(\omega, \mathcal{F}) = 1;\)
6. \(\text{else}\)
   \(s = \Delta(\omega, \mathcal{F}) = 2;\)
7. \(\text{return } \mathcal{R}, s\) and \(\chi\);

Algorithm 3: An online fault diagnosis algorithm

**Input:** A diagnostic Petri net system \(\mathcal{N} = (\tilde{N}, M_0, E, \lambda, \mathcal{F})\)

**Output:** The diagnosis results \(\mathcal{R}\) and \(s\) for each event \(e\)

1. \(\mathcal{R} = \bar{0}\), \(s = 0\), \(\mathcal{N}' = \{\varepsilon\}\), \(\alpha = \text{true}\) (\(\alpha\) denotes if \(e\) is the first event);
2. \(\text{Wait until a new event } e \text{ is observed; } \Lambda = 0;\)
3. \(\text{for each } t \in T_e\) do
   \(\text{for each } \sigma_o \in \mathcal{N}' \text{ do}\)
   \(\sigma_o = \sigma_o; (\mathcal{R}', s', \chi) = \text{new\_FDA}(\mathcal{N}, \sigma_o);\)
   \(\text{if } \chi \text{ is true then}\)
   \(\Lambda = \Lambda \cup \{\sigma_o\};\)
   \(\text{if } \alpha \text{ is true then}\)
   \(\mathcal{R} = \mathcal{R}', s = s', \alpha = \text{false};\)
   \(\text{else}\)
   \(\mathcal{R} = \mathcal{R} \odot \mathcal{R}'; s = s \odot s';\)
4. \(\mathcal{N}' = \Lambda;\)
5. \(\text{Output } \mathcal{R}, s; \text{ Goto 2;}\)

the projection of \(\sigma \in T^*\) on the set of observable transitions. For an observed word \(\omega \in E^\mathcal{F}(\tilde{N}, M_0)\), we denote
\[\mathcal{T}_s(\omega) = \{\nu \in T_0^*: \sigma \in \tilde{C}(\omega), \nu = \tau(\sigma)\}\]
the set of observable projections of transition sequences consistent with \(\omega\).

**Proposition 3.** Given a diagnostic net system \(\langle N, M_0, E, \lambda, \mathcal{F} \rangle\) and an observed word \(\omega \in E^*\), for