Feature-Oriented Software Evolution (Vision paper)

<u>Leonardo Passos</u>¹ Krzysztof Czarnecki¹ Sven Apel² Andrzej Wąsowski³ Christian Käster⁴ Jianmei Guo¹ Claus Hunsen²

¹University of Waterloo ²University of Passau ³IT University ⁴CMU

The Seventh International Workshop on Variability Modelling of Software-intensive Systems

Software evolves...

Automotive embedded software:

• Changing regulations

- Changing regulations
 - $\circ\:$ ABS is now mandatory in the EU

- Changing regulations
 - o ABS is now mandatory in the EU
- Market differentiating enhancements

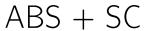
- Changing regulations
 - ABS is now mandatory in the EU
- Market differentiating enhancements
 - \circ Electronic stability control (SC) improves ABS by preventing skidding

- Changing regulations
 - ABS is now mandatory in the EU
- Market differentiating enhancements
 - $\circ\;$ Electronic stability control (SC) improves ABS by preventing skidding
- New technology availability

- Changing regulations
 - ABS is now mandatory in the EU
- Market differentiating enhancements
 - o Electronic stability control (SC) improves ABS by preventing skidding
- New technology availability
 - o Laser-based distance sensors are more precise than radio-based ones

Understanding the evolution in

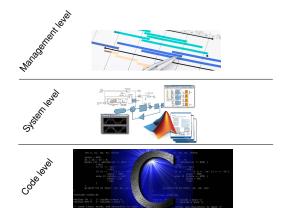
place is not easy...



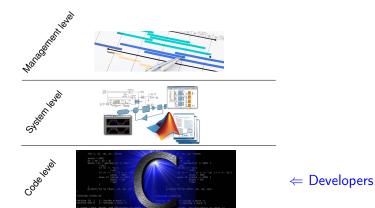
• Integration can scatter different artifacts

- Integration can scatter different artifacts
- Different levels of abstractions not mastered by all stakeholders

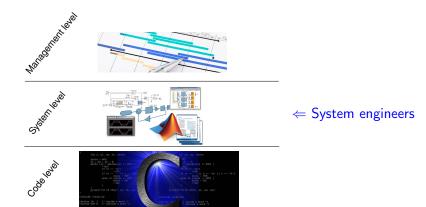
- Integration can scatter different artifacts
- Different levels of abstractions not mastered by all stakeholders



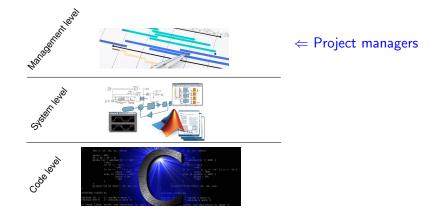
- Integration can scatter different artifacts
- Different levels of abstractions not mastered by all stakeholders



- Integration can scatter different artifacts
- Different levels of abstractions not mastered by all stakeholders



- Integration can scatter different artifacts
- Different levels of abstractions not mastered by all stakeholders



In practical settings...

In practical settings...

 ${\ \ \, Complex\ \ and\ \, large\ \, software\ \, systems\ \, have:}$

In practical settings. . .

Complex and large software systems have:

• Diverse set of stakeholders

In practical settings...

Complex and large software systems have:

- Diverse set of stakeholders
- Diverse set of artifacts

In practical settings. . .

Complex and large software systems have:

- Diverse set of stakeholders
- Diverse set of artifacts
- Different stakeholders have particular "views" over the software

In practical settings. . .

Complex and large software systems have:

- Diverse set of stakeholders
- Diverse set of artifacts
- Different stakeholders have particular "views" over the software

Stakeholders need a common meeting point

(no common meeting point)

Otherwise... (no common meeting point)

Ineffective communication

(no common meeting point)

Ineffective communication Software flaws

(no common meeting point)

Ineffective communication Software flaws

Architecture decay

(no common meeting point)

Ineffective communication Software flaws

Architecture decay Higher maintenance costs

Managing evolution at the <u>level of features</u> can address the challenges describe above

 $\label{lem:arguments} \mbox{Arguments favouring the hypothesis:}$

Arguments favouring the hypothesis:

• Feature = cohesive requirements bundle

Arguments favouring the hypothesis:

- Feature = cohesive requirements bundle
- Requirements are a common point among all stakeholders

Arguments favouring the hypothesis:

- Feature = cohesive requirements bundle
- Requirements are a common point among all stakeholders
- Features are more coarse-grained than individual requirements

Arguments favouring the hypothesis:

- Feature = cohesive requirements bundle
- Requirements are a common point among all stakeholders
- Features are more coarse-grained than individual requirements
 - Facilitates understanding

Arguments favouring the hypothesis:

- Feature = cohesive requirements bundle
- Requirements are a common point among all stakeholders
- Features are more coarse-grained than individual requirements
 - Facilitates understanding
- Evolution can be put in simple terms

Hypothesis

Arguments favouring the hypothesis:

- Feature = cohesive requirements bundle
- Requirements are a common point among all stakeholders
- Features are more coarse-grained than individual requirements
 - o Facilitates understanding
- Evolution can be put in simple terms
 - o Add new feature, retire old ones, etc.

Our vision

(Assuming the validity of our hypothesis)

Feature-oriented evolution based on:

Feature-oriented evolution based on:

Tracing

Analyses

Feature-oriented evolution based on:

Tracing

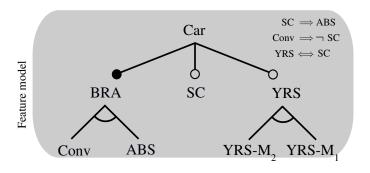
Analyses

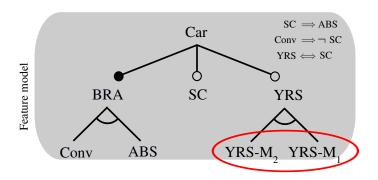
Recommendations

Purpose of our work

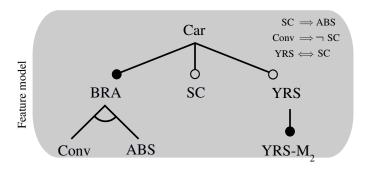
Research agenda based on our vision for feature-oriented software evolution

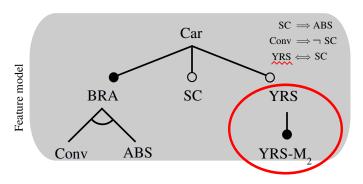
This presentation covers part of that agenda (see paper for more details)



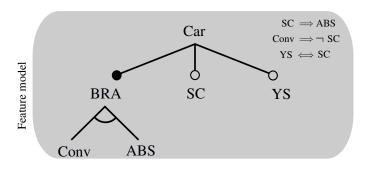


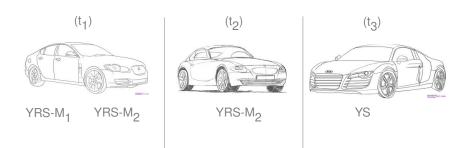
Merge + clone yaw rate prediction

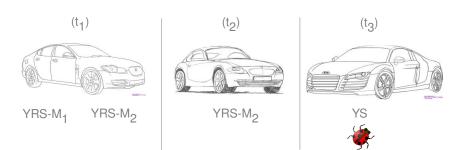




Merge YRS- M_2 into YRS + rename YRS to YS



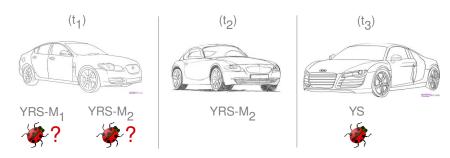




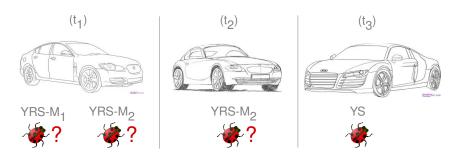
 $\mathsf{Bug} \; \mathsf{found} \; \mathsf{in} \; \mathsf{YS}$



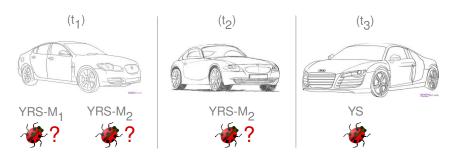
Does the bug exist in YRS-M₂ (t_2) ?



Does the bug exist in YRS-M $_{1/2}$ (t_1)?



Does the bug exist in both t_1 and t_2 ?



Answering requires tracing the evolution of single features

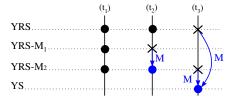
• Traceability has to be recovered from a multi-space setting:

- Traceability has to be recovered from a multi-space setting:
 - Recover traceability of different artifacts (e.g.: FM, Build files, C code)

- Traceability has to be recovered from a multi-space setting:
 - Recover traceability of different artifacts (e.g.: FM, Build files, C code)
 - Integrate the evolution history of those artifacts over time

- Traceability has to be recovered from a multi-space setting:
 - Recover traceability of different artifacts (e.g.: FM, Build files, C code)
 - o Integrate the evolution history of those artifacts over time
 - o Draw an evolution history (timeline)

- Traceability has to be recovered from a multi-space setting:
 - Recover traceability of different artifacts (e.g.: FM, Build files, C code)
 - Integrate the evolution history of those artifacts over time
 - Draw an evolution history (timeline)



• Tracing certain artifacts can be daunting

- Tracing certain artifacts can be daunting
 - o Individual build rules in build files (e.g., make is Turing-complete)

- Tracing certain artifacts can be daunting
 - Individual build rules in build files (e.g., make is Turing-complete)
 - o Fine-grained variability analysis in code is costly

- Tracing certain artifacts can be daunting
 - o Individual build rules in build files (e.g., make is Turing-complete)
 - o Fine-grained variability analysis in code is costly

RQ: How to recover traceability links in build files and source code in variability-aware systems?

- Tracing certain artifacts can be daunting
 - o Individual build rules in build files (e.g., make is Turing-complete)
 - o Fine-grained variability analysis in code is costly

RQ: How to recover traceability links in build files and source code in variability-aware systems?

RQ: Once recovered, how to update them to reflect the temporal evolution in place?

• Different artifacts = different sources to draw the evolution in place

• Different artifacts = different sources to draw the evolution in place

Mailing lists

- Different artifacts = different sources to draw the evolution in place
 - Mailing lists
 - o Commit patches and log messages

- Different artifacts = different sources to draw the evolution in place
 - Mailing lists
 - Commit patches and log messages
 - Bug reports in bug tracking systems

- Different artifacts = different sources to draw the evolution in place
 - Mailing lists
 - Commit patches and log messages
 - Bug reports in bug tracking systems

RQ: Which sources are trustworthy?

Analyses

(Back to the motivating example)

After the evolution of the SPL, stakeholders noticed that:

After the evolution of the SPL, stakeholders noticed that:

• Maintenance is taking longer

After the evolution of the SPL, stakeholders noticed that:

- Maintenance is taking longer
- Productivity has decreased

After the evolution of the SPL, stakeholders noticed that:

- Maintenance is taking longer
- Productivity has decreased
- Bugs are starting to rise

After the evolution of the SPL, stakeholders noticed that:

- Maintenance is taking longer
- Productivity has decreased
- Bugs are starting to rise

Well-known phenomena of software aging

We envision three analyses to prevent aging:

We envision three analyses to prevent aging:

• Consistency checking analysis

We envision three analyses to prevent aging:

- Consistency checking analysis
- Change impact analysis

We envision three analyses to prevent aging:

- Consistency checking analysis
- Change impact analysis
- Architectural analysis

Goal: prevent inconsistencies in different artifacts

Goal: prevent inconsistencies in different artifacts

```
abs.c(1) abs.c(2)
...
#ifdef Conv
// switch
// to Conv
// if ABS
// fails
#endif
...
#endif
react_oversteering())
...
```

```
abs.c(3)
...
#ifdef SC && YRS_M1
double predicted_value
...
#endif
...
```

```
abs.c (4)

#ifdef SC && YRS_M1
predictor_t p;
#else
int p = 0;
#endif
...
predicted_value=p->get();
```

Goal: prevent inconsistencies in different artifacts

```
abs.c (1)
                             abs.c (2)
                                                                  abs.c (3)
                                                                                                  abs.c (4)
                                                         #ifdef SC && YRS M1
                                                                                         #ifdef SC && YRS M1
#ifdef Conv
                 sensor data t data ;
                                                            double predicted_value
                                                                                            predictor_t p ;
                 #ifdef_SC
  // switch
                                                                                         #else
  // to Conv
                   data = get value(data) ;
                                                         #endjf
                                                                                            int p = 0:
   // if ABS
                 #endif
                                                                                         #endif
   // fails
                 if (data->check oversteering())
#endif
                    react_oversteering();
                                                                                         predicted_value=p->get();
```

Dead code

Goal: prevent inconsistencies in different artifacts

```
abs.c (1)
                             abs.c (2)
                                                                  abs.c (3)
                                                                                                  abs.c (4)
                                                         #ifdef SC && YRS M1
                                                                                         #ifdef SC && YRS M1
#ifdef Conv
                 sensor data t data ;
                                                            double predicted_value
                                                                                            predictor_t p ;
   // switch
                 #ifdef SC
                                                                                         #else
   // to Conv
                   data = get value(data) ;
                                                         #endif
                                                                                            int p = 0:
                 #endif
   // if ABS
                                                                                         #endif
   // fails
                 if (data->check oversteering())
#endif
                    react_oversteering();
                                                                                         predicted_value=p->get();
```

Null pointer exception

Goal: prevent inconsistencies in different artifacts

```
abs.c (1)
                             abs.c (2)
                                                                  abs.c (3)
                                                                                                  abs.c (4)
                                                         #ifdef SC && YRS M1
                                                                                         #ifdef SC && YRS M1
#ifdef Conv
                 sensor data t data ;
                                                            double predicted_value
                                                                                            predictor_t p ;
                 #ifdef_SC
   // switch
                                                                                         #else
   // to Conv
                   data = get value(data) ;
                                                         #endif
                                                                                            int p = 0:
                 #endif
   // if ABS
                                                                                         #endif
   // fails
                 if (data->check oversteering())
#endif
                    react_oversteering();
                                                                                         predicted_value=p->get();
```

Syntax error

Goal: prevent inconsistencies in different artifacts

```
abs.c (1)
                             abs.c (2)
                                                                  abs.c (3)
                                                                                                  abs.c (4)
                                                         #ifdef SC && YRS M1
                                                                                         #ifdef SC && YRS M1
#ifdef Conv
                 sensor data t data ;
                                                            double predicted_value
                                                                                            predictor t p ;
                 #ifdef_SC
   // switch
                                                                                         #else
   // to Conv
                   data = get value(data) ;
                                                         #endif
                                                                                            int p = 0:
                 #endif
   // if ABS
                                                                                         #endif
   // fails
                 if (data->check oversteering())
#endif
                    react_oversteering();
                                                                                         predicted_value=p->get();
```

Type error

Goal: prevent inconsistencies in different artifacts

```
abs.c (1)
                             abs.c (2)
                                                                   abs.c (3)
                                                                                                   abs.c (4)
                                                         #ifdef SC && YRS M1
                                                                                         #ifdef SC && YRS M1
#ifdef Conv
                 sensor data t data ;
                                                            double predicted value
                                                                                            predictor_t p ;
   // switch
                 #ifdef SC
                                                                                         #else
   // to Conv
                   data = get value(data) ;
                                                         #endif
                                                                                            int p = 0:
                 #endif
   // if ABS
                                                                                         #endif
   // fails
                 if (data->check oversteering())
#endif
                    react_oversteering();
                                                                                         predicted value=p->get();
```

Other types of analysis exist: e.g., model-checking

• Variability aware-analysis is costly.

Variability aware-analysis is costly.

RQ: Do existing approaches for variability-aware typechecking, flow-analysis and model-checking scale to large systems?

Variability aware-analysis is costly.

RQ: Do existing approaches for variability-aware type-checking, flow-analysis and model-checking scale to large systems?

• Existing flow-analysis is intra-procedural.

Variability aware-analysis is costly.

RQ: Do existing approaches for variability-aware typechecking, flow-analysis and model-checking scale to large systems?

• Existing flow-analysis is intra-procedural.

RQ: How to adapt existing inter-procedural analyses to handle variability?

Analyses (Impact analysis)

Goal: assess impact of changes

Goal: assess impact of changes

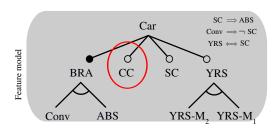
Scenario:

- To identify bugs, stakeholders in our SPL have created formal specifications of the system's features
- Support for cruise control (CC)

Goal: assess impact of changes

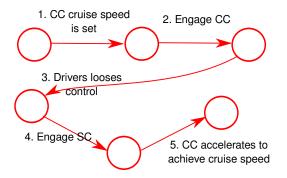
Scenario:

- To identify bugs, stakeholders in our SPL have created formal specifications of the system's features
- Support for cruise control (CC)

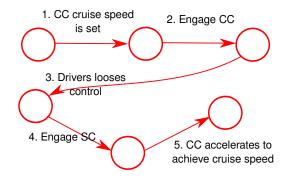


Stability-control behaviour property: *No subsystem increases* acceleration when *SC* is engaged

Stability-control behaviour property: *No subsystem increases* acceleration when *SC* is engaged

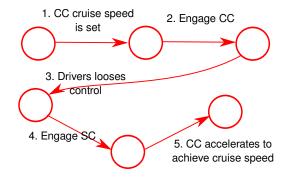


Stability-control behaviour property: *No subsystem increases* acceleration when *SC* is engaged



Adding CC violates the given property

Stability-control behaviour property: *No subsystem increases* acceleration when *SC* is engaged



Adding CC violates the given property (Impact analysis aims to detect that promptly)

Impact analysis (Research questions)

• Currently, consistency between implementation assets (code) and the system's specified property is mostly intractable.

Impact analysis (Research questions)

• Currently, consistency between implementation assets (code) and the system's specified property is mostly intractable.

RQ: How to verify that the system implementation does not break its specified properties?

Analyses (Architectural analysis)

Architectural analysis

- Feature model = view of the system architecture
- From the recovered traces, one can track the "health of the system"
- Different indicators can be collected to assess the system evolution:

code metrics

feature-model based metrics

process metrics

product-line based metrics

feature-based metrics

Architectural analysis

• Evidence relating scattering and defects is rather preliminary.

Architectural analysis

• Evidence relating scattering and defects is rather preliminary.

RQ: Can we provide more evidence for the relationship between scattering and defects?

33/3

Recommendations

Suggestions for:

Suggestions for:

• Consistency analysis

35/37

Suggestions for:

- Consistency analysis
- Impact analysis

Suggestions for:

- Consistency analysis
- Impact analysis
- Architectural analysis

Consistency:

• Fix recommendations for different artifacts types

Consistency:

• Fix recommendations for different artifacts types

RQ: How to devise a fixing recommender integrating different artifacts, with different abstraction levels?

Consistency:

• Fix recommendations for different artifacts types

RQ: How to devise a fixing recommender integrating different artifacts, with different abstraction levels?

Impact analysis:

• Point which features are more likely to have defects after a change

35/3

Consistency:

• Fix recommendations for different artifacts types

RQ: How to devise a fixing recommender integrating different artifacts, with different abstraction levels?

Impact analysis:

• Point which features are more likely to have defects after a change

RQ: Which feature-based metrics are good defect predictors?

Architectural analysis:

Architectural analysis:

• Propose merges (features are too similar)

Architectural analysis:

- Propose merges (features are too similar)
- Suggest feature retirement

Architectural analysis:

- Propose merges (features are too similar)
- Suggest feature retirement
- Suggest which features to modularize

Architectural analysis:

- Propose merges (features are too similar)
- Suggest feature retirement
- Suggest which features to modularize

RQ: Which scenarios should be supported (are required in practice)?

Conclusion

- We hypothesized that feature-oriented evolution can mitigate existing challenges in evolving large-complex systems
- From that hypothesis, we presented our vision based on tracing, analyses and recommendations
- We are have started working on the realization of that vision

Thanks for listening!

