$$
\textsc{Inv+Obs}\;\dfrac{\textsc{InvImpl}\;\dfrac{\textsc{K-Ind}\;\dfrac{k \in \mathbb{N} \qquad \textsc{Smt}\;\dfrac{\vdots}{B_k \vDash_{\mathcal{L}} \bot} \qquad \textsc{Smt}\;\dfrac{\vdots}{S_k \vDash_{\mathcal{L}} \bot}}{\mathsf{invariant}(I, T, \phi)} \qquad \textsc{Smt}\;\dfrac{\vdots}{\phi \vDash_{\mathcal{L}} P}}{\mathsf{invariant}(I, T, P)} \qquad \textsc{ObsEq}\;\dfrac{\textsc{K-Ind}\;\dfrac{\vdots}{\mathsf{invariant}(I_o, T_o, \phi_o)} \qquad \textsc{Smt}\;\dfrac{\vdots}{\phi_o \vDash_{\mathcal{L}} P_o}}{\mathsf{invariant}(I_o, T_o, P_o)}}{\mathsf{safe}(I, T, P)} \qquad \mathsf{woe}(I, T, P, I', T', P')
$$