



# RES

## Introduction & Real-Time Languages

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## Real-Time & Embedded Systems

### References for this chapter

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The Esterel v3 Language Primer (Version 5.21 release 2.0)  
Technical report: centre de Mathématiques Appliquées, Ecole des Mines and INRIA

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[Cohen96] Norman H. Cohen  
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[G98] eds. GI-working group 4.4.2 PEARL 90, Language report, Version 2.2 Technical report GI

[Bollella01] Greg Bollella, Ben Brosgol, Steve Furr, David Hardin, Peter Dibble, James Gosling, Mark Turnbull & Rudy Belliardi  
The Real-Time Specification for Java <http://www.rti.org>

all references and some links are available on the course page

## Real-Time & Embedded Systems

### Features of a Real-Time System?

- Fast context switches?
- Small size?
- Quick responds to external interrupts?
- Multitasking?
- 'low level' programming interfaces?
- Interprocess communication tools?
- High processor utilization?

## Real-Time & Embedded Systems

### Features of a Real-Time System?

- Fast context switches? ⇒ should be fast anyway
- Small size? ⇒ should be small anyway
- Quick responds to external interrupts? ⇒ not 'quick', but predictable
- Multitasking? ⇒ real time systems are often multitasking systems
- 'low level' programming interfaces? ⇒ needed in many applications
- Interprocess communication tools? ⇒ Feature of any distributed system
- High processor utilization? ⇒ Fault tolerance builds on redundancy!

## Real-Time & Embedded Systems

### Features of a Real-Time System

The correctness of a real-time systems depends on:

- the logical correctness of the results as well as
- the time the result was delivered

according to the specification.

⇒ All results are to be delivered **just-in-time** – not too early, not too late.

Timing constraints are specified in many different ways ...  
... often as a response to 'external' events ⇒ reactive systems

## Real-Time & Embedded Systems

### Typical Real-Time Systems

- System sizes vary from traffic light controllers, or heating regulators to big aircrafts (Boeing, Airbus), satellites, or high speed trains (TGV)
- High degree of concurrency
- Close connections to real-world entities (sensors, actuators)
- Often a part of a real-world device (embedded systems)
- Failures may often lead to loss of life, or environmental damages.

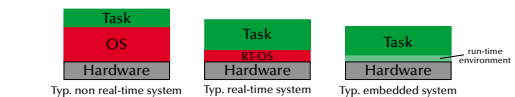
⇒ Predictability is more important than any other criterion

## Real-Time & Embedded Systems

### Typical Real-Time Operating Systems

Often implemented as an integrated run-time environment i.e. there is 'no operating system' (⇒ embedded systems)

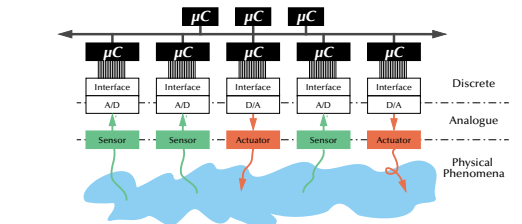
⇒ RT-OSs have the smallest possible impact on the timing behaviour



Typ. non real-time system: OS on Hardware  
Typ. real-time system: Task on RT-OS on Hardware  
Typ. embedded system: Task on Hardware (run-time environment)

## Real-Time & Embedded Systems

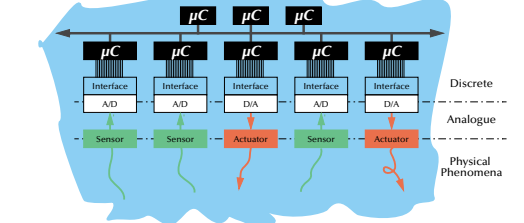
### Real-Time Systems Components



Discrete: μC, Interface, A/D, D/A  
Analogue: Sensor, Actuator  
Physical Phenomena

## Real-Time & Embedded Systems

### Real-Time Systems ⇒ Embedded Systems



Discrete: μC, Interface, A/D, D/A  
Analogue: Sensor, Actuator  
Physical Phenomena

## Real-Time & Embedded Systems

### what is this course about?

#### Parts of a Real-Time System

- A set of physical processes
- Physical sensors transforming all values into analogue voltages
- Physical actuators delivering forces, lights, temperatures, etc. pp.
- D/A and A/D converters synchronize and discretize all voltages
- Interfaces and buses feeding the measurements into a computer
- One or many controllers (computers)
- Algorithms, Languages & Real-Time Software

## Real-Time & Embedded Systems

### Programming styles

- Imperative (sequential) ⇒ Ada, RT-JAVA, Eiffel, ...
- Functional (recursive) ⇒ Lisp, OCaml, ...
- Declarative (logic) ⇒ Prolog, ...
- Data-flow machines ⇒ Lustre, Signal, ...
- (hierarchical) Finite state machines ⇒ synchronous languages: Esterel, syncEifel, synERYJ, ...

### Real-Time styles

Imperative ↔ Functional ↔ Declarative ↔ Data-flow ↔ Finite state machines  
Static ↔ Dynamic  
Modular ↔ Concurrent ↔ Distributed  
Synchronous ↔ Continuous time  
Control oriented ↔ Data oriented

## Real-Time & Embedded Systems

### Programming styles

#### What makes a language suitable for real-time systems?

- Predictability ⇒ no operations which will lead to unforeseeable timing behaviours (e.g. garbage collection)
- Real-time!! ⇒ support for temporal scopes
- Concurrency ⇒ support for tasking/threading
- Distribution ⇒ support for message passing or rpc
- Reliability ⇒ detect errors at compile-time or in the run-time environment
- Large systems ⇒ scalable, modular, or object-oriented + separate compilation

## Real-Time & Embedded Systems

### Programming styles

#### Languages considered in this course

- Ada95 (used for assignments ⇒ introduced first)
- Esterel
- Pearl
- Real-time JAVA
- POSIX
- ... others in places

## Real-Time & Embedded Systems

### Ada95

Ada95 is a **standardized** (ISO/IEC 8652:1995(E)) 'general purpose' language with **core** language primitives for

- strong typing, separate compilation (specification and implementation), object-orientation,
- concurrency, monitors, rpcs, timeouts, scheduling, priority ceiling locks
- strong run-time environments

... and **standardized** language-**annexes** for

- additional real-time features, distributed programming, system-level programming, numeric, informations systems, safety and security issues.

## Real-Time & Embedded Systems

### Ada95

#### A crash course

... refreshing:

- specification and implementation (body) parts, basic types
- exceptions
- information hiding in specifications ('private')
- generic programming
- class-wide programming ('tagged types')
- monitors and synchronisation ('protected', 'entries', 'selects', 'accepts')
- abstract types and dispatching

## Real-Time & Embedded Systems

### Ada95

#### Basics

... introducing:

- specification and implementation (body) parts
- constants
- some basic types (integer specifics)
- some type attributes
- parameter specification

A simple queue specification

```
package Queue_Pack_Simple is
  QueueSize : constant Positive := 10;
  type Element is new Positive range 1..40..200;
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_Type is record
    Top, Free : Marker := Marker'First;
    Elements : List;
  end record;
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type);
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type);
end Queue_Pack_Simple;
```

A simple queue implementation

```
package body Queue_Pack_Simple is
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type) is
  begin
    Queue.Elements (Queue.Free) := Item;
    Queue.Free := Queue.Free - 1;
  end Enqueue;
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type) is
  begin
    Item := Queue.Elements (Queue.Top);
    Queue.Top := Queue.Top + 1;
  end Dequeue;
end Queue_Pack_Simple;
```

A simple queue test program

```
with Queue_Pack_Simple; use Queue_Pack_Simple;
procedure Queue_Test_Simple is
  Queue : Queue_Type;
  Item : Element;
begin
  Enqueue (2000, Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue); -- will produce an unpredictable result!
end Queue_Test_Simple;
```

Ada95

Exceptions

- ... introducing:
- exception handling
  - enumeration types
  - functional type attributes

A queue specification with proper exceptions

```
package Queue_Pack_Exceptions is
  QueueSize : constant Integer := 10;
  type Element is (Up, Down, Spin, Turn);
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_State is (Empty, Filled);
  type Queue_Type is record
    Top, Free : Marker := Marker'First;
    State : Queue_State := Empty;
    Elements : List;
  end record;
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type);
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type);
  Queueoverflow, Queueunderflow : exception;
end Queue_Pack_Exceptions;
```

A queue implementations with proper exceptions

```
package body Queue_Pack_Exceptions is
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Filled and Queue.Top = Queue.Free then
      raise Queueoverflow;
    end if;
    Queue.Elements (Queue.Free) := Item;
    Queue.Free := Marker'Pred (Queue.Free);
    Queue.State := Filled;
  end Enqueue;
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Empty then
      raise Queueunderflow;
    end if;
    Item := Queue.Elements (Queue.Top);
    Queue.Top := Marker'Pred (Queue.Top);
    if Queue.Top = Queue.Free then Queue.State := Empty; end if;
  end Dequeue;
end Queue_Pack_Exceptions;
```

A queue test program with proper exceptions

```
with Queue_Pack_Exceptions; use Queue_Pack_Exceptions;
with Ada.Text_IO; use Ada.Text_IO;
procedure Queue_Test_Exceptions is
  Queue : Queue_Type;
  Item : Element;
begin
  Enqueue (Turn, Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue); -- will produce a 'Queue underflow'
exception
  when Queueunderflow => Put ("Queue underflow");
  when Queueoverflow => Put ("Queue overflow");
end Queue_Test_Exceptions;
```

Ada95

Information hiding (private parts)

- ... introducing:
- private = assignments and comparisons are allowed
  - limited private = entity cannot be assigned or compared

A queue specification with proper information hiding

```
package Queue_Pack_Private is
  QueueSize : constant Integer := 10;
  type Element is new Positive range 1..1000;
  type Queue_Type is limited private;
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type);
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type);
  Queueoverflow, Queueunderflow : exception;
private
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_State is (Empty, Filled);
  type Queue_Type is record
    Top, Free : Marker := Marker'First;
    State : Queue_State := Empty;
    Elements : List;
  end record;
end Queue_Pack_Private;
```

A queue implementation with proper information hiding

```
package body Queue_Pack_Private is
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Filled and Queue.Top = Queue.Free then
      raise Queueoverflow;
    end if;
    Queue.Elements (Queue.Free) := Item;
    Queue.Free := Queue.Free - 1;
    Queue.State := Filled;
  end Enqueue;
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Empty then
      raise Queueunderflow;
    end if;
    Item := Queue.Elements (Queue.Top);
    Queue.Top := Queue.Top + 1;
    if Queue.Top = Queue.Free then Queue.State := Empty; end if;
  end Dequeue;
end Queue_Pack_Private;
```

A queue test program with proper information hiding

```
with Queue_Pack_Private; use Queue_Pack_Private;
with Ada.Text_IO; use Ada.Text_IO;
procedure Queue_Test_Private is
  Queue: Queue_Type;
  Item : Element;
begin
  Queue_Copy := Queue;
  -- compiler-error: left hand of assignment must not be limited type
  Enqueue (Item => 1, Queue => Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue); -- will produce a 'Queue underflow'
exception
  when Queueunderflow => Put ("Queue underflow");
  when Queueoverflow => Put ("Queue overflow");
end Queue_Test_Private;
```

Ada95

Generic packages

- ... introducing:
- specification of generic packages
  - instantiation of generic packages

A generic queue specification

```
generic
  type Element is private;
package Queue_Pack_Generic is
  QueueSize : constant Integer := 10;
  type Queue_Type is limited private;
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type);
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type);
  Queueoverflow, Queueunderflow : exception;
private
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_State is (Empty, Filled);
  type Queue_Type is record
    Top, Free : Marker := Marker'First;
    State : Queue_State := Empty;
    Elements : List;
  end record;
end Queue_Pack_Generic;
```

A generic queue implementation

```
package body Queue_Pack_Generic is
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Filled and Queue.Top = Queue.Free then
      raise Queueoverflow;
    end if;
    Queue.Elements (Queue.Free) := Item;
    Queue.Free := Queue.Free - 1;
    Queue.State := Filled;
  end Enqueue;
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Empty then
      raise Queueunderflow;
    end if;
    Item := Queue.Elements (Queue.Top);
    Queue.Top := Queue.Top + 1;
    if Queue.Top = Queue.Free then Queue.State := Empty; end if;
  end Dequeue;
end Queue_Pack_Generic;
```

A generic queue test program

```
with Queue_Pack_Generic; use Queue_Pack_Generic;
with Ada.Text_IO; use Ada.Text_IO;
procedure Queue_Test_Generic is
  package Queue_Pack_Positive is
    new Queue_Pack_Generic (Element => Positive);
  use Queue_Pack_Positive;
  Queue : Queue_Type;
  Item : Positive;
begin
  Enqueue (Item => 1, Queue => Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue); -- will produce a 'Queue underflow'
exception
  when Queueunderflow => Put ("Queue underflow");
  when Queueoverflow => Put ("Queue overflow");
end Queue_Test_Generic;
```

Ada95

Object oriented programming I

- ... introducing:
- tagged types = the Ada-way to say that this type can be extended
  - derivation of tagged types
  - method overwriting
  - usage of parent entities

An open queue base class specification

```
package Queue_Pack_Object_Base is
  QueueSize : constant Integer := 10;
  type Element is new Positive range 1..1000;
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_State is (Empty, Filled);
  type Queue_Type is tagged record
    Top, Free : Marker := Marker'First;
    State : Queue_State := Empty;
    Elements : List;
  end record;
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type);
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type);
  Queueoverflow, Queueunderflow : exception;
end Queue_Pack_Object_Base;
```

An open queue base class implementation

```
package body Queue_Pack_Object_Base is
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Filled and Queue.Top = Queue.Free then
      raise Queueoverflow;
    end if;
    Queue.Elements (Queue.Free) := Item;
    Queue.Free := Queue.Free + 1;
    Queue.State := Filled;
  end Enqueue;
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Empty then
      raise Queueunderflow;
    end if;
    Item := Queue.Elements (Queue.Top);
    Queue.Top := Queue.Top + 1;
    if Queue.Top = Queue.Free then Queue.State := Empty; end if;
  end Dequeue;
end Queue_Pack_Object_Base;
```

A derived open queue class specification

```
with Queue_Pack_Object_Base; use Queue_Pack_Object_Base;
package Queue_Pack_Object is
  type Ext_Queue_Type is new Queue_Type with record
    Reader : Marker := Marker'First;
    Reader_State : Queue_State := Empty;
  end record;
  procedure Enqueue (Item: in Element; Queue: in out Ext_Queue_Type);
  procedure Read_Queue (Item: out Element; Queue: in out Ext_Queue_Type);
end Queue_Pack_Object;
```

A derived open queue class implementation

```
package body Queue_Pack_Object is
  procedure Enqueue (Item: in Element; Queue: in out Ext_Queue_Type) is
  begin
    Enqueue (Item, Queue_Type (Queue));
    Queue.Reader_State := Filled;
  end Enqueue;
  procedure Read_Queue (Item: out Element; Queue: in out Ext_Queue_Type) is
  begin
    if Queue.Reader_State = Empty then
      raise Queueunderflow;
    end if;
    Item := Queue.Elements (Queue.Reader);
    Queue.Reader := Queue.Reader + 1;
    if Queue.Reader = Queue.Free then Queue.Reader_State := Empty; end if;
  end Read_Queue;
end Queue_Pack_Object;
```

An open class test program

```
with Queue_Pack_Object_Base; use Queue_Pack_Object_Base;
with Queue_Pack_Object; use Queue_Pack_Object;
with Ada.Text_IO; use Ada.Text_IO;
procedure Queue_Test_Object is
  Queue : Ext_Queue_Type;
  Item : Element;
begin
  Enqueue (Item => 1, Queue => Queue);
  Read_Queue (Item, Queue);
  Enqueue (Item => 5, Queue => Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue); -- will produce a 'Queue underflow'
exception
  when Queueunderflow => Put ("Queue underflow");
  when Queueoverflow => Put ("Queue overflow");
end Queue_Test_Object;
```

Ada95

Object oriented programming II

- ... introducing:
  - private tagged types
  - objects which are protected against their children also

An encapsulated queue base class specification

```
package Queue_Pack_Object_Base_Private is
  QueueSize : constant Integer := 10;
  type Element is new Positive range 1..1000;
  type Queue_Type is tagged limited private;
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type);
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type);
  Queueoverflow, Queueunderflow : exception;
private
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_State is (Empty, Filled);
  type Queue_Type is tagged limited record
    Top, Free : Marker := Marker'First;
    State : Queue_State := Empty;
    Elements : List;
  end record;
end Queue_Pack_Object_Base_Private;
```

An encapsulated queue base class implementation

```
package body Queue_Pack_Object_Base_Private is
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Filled and Queue.Top = Queue.Free then
      raise Queueoverflow;
    end if;
    Queue.Elements (Queue.Free) := Item;
    Queue.Free := Queue.Free + 1;
    Queue.State := Filled;
  end Enqueue;
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type) is
  begin
    if Queue.State = Empty then
      raise Queueunderflow;
    end if;
    Item := Queue.Elements (Queue.Top);
    Queue.Top := Queue.Top + 1;
    if Queue.Top = Queue.Free then Queue.State := Empty; end if;
  end Dequeue;
end Queue_Pack_Object_Base_Private;
```

A derived encapsulated queue class specification

```
with Queue_Pack_Object_Base_Private; use Queue_Pack_Object_Base_Private;
package Queue_Pack_Object_Private is
  type Ext_Queue_Type is new Queue_Type with private;
  subtype Depth_Type is Positive range 1..QueueSize;
  procedure Look_Ahead (Item: out Element;
    Depth: in Depth_Type; Queue: in out Ext_Queue_Type);
private
  type Ext_Queue_Type is new Queue_Type with null record;
end Queue_Pack_Object_Private;
```

A derived encapsulated queue class implementation

```
package body Queue_Pack_Object_Private is
  procedure Look_Ahead (Item: out Element;
    Depth: in Depth_Type; Queue: in out Ext_Queue_Type) is
  Storage : Queue_Type;
  ShuffleItem : Element;
  begin
    for I in 1..Depth - 1 loop
      Dequeue (ShuffleItem, Queue);
      Enqueue (ShuffleItem, Storage);
    end loop;
    Dequeue (Item, Queue);
    Enqueue (Item, Storage);
  end Look_Ahead;
end Queue_Pack_Object_Private;
```

...

```
Read_The_Rest:
  begin
    for I in 1..QueueSize - Depth loop
      Dequeue (ShuffleItem, Queue);
      Enqueue (ShuffleItem, Storage);
    end loop;
  exception
    when Queueunderflow => null; -- read the rest is done
  end Read_The_Rest;
Restore_The_Queue:
  begin
    for I in 1..QueueSize - Depth loop
      Dequeue (ShuffleItem, Storage);
      Enqueue (ShuffleItem, Queue);
    end loop;
  exception
    when Queueunderflow => null; -- restore is done
  end Restore_The_Queue;
end Look_Ahead;
end Queue_Pack_Object_Private;
```

An encapsulated class test program

```
with Queue_Pack_Object_Base_Private; use Queue_Pack_Object_Base_Private;
with Queue_Pack_Object_Private; use Queue_Pack_Object_Private;
with Ada.Text_IO; use Ada.Text_IO;
procedure Queue_Test_Object_Private is
  Queue : Ext_Queue_Type;
  Item : Element;
begin
  Enqueue (Item => 1, Queue => Queue);
  Enqueue (Item => 1, Queue => Queue);
  Look_Ahead (Item => Item, Depth => 2, Queue => Queue);
  Enqueue (Item => 5, Queue => Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue);
  Dequeue (Item, Queue); -- will produce a 'Queue underflow'
exception
  when Queueunderflow => Put ("Queue underflow");
  when Queueoverflow => Put ("Queue overflow");
end Queue_Test_Object_Private;
```

Ada95

Tasks & Monitors

- ... introducing:
  - protected types
  - tasks (definition, instantiation and termination)
  - task synchronisation
  - entry guards
  - entry calls
  - accept and selected accept statements

A protected queue specification

```
Package Queue_Pack_Protected is
  QueueSize : constant Integer := 10;
  subtype Element is Character;
  type Queue_Type is limited private;
  Protected type Protected_Queue is
    entry Enqueue (Item: in Element);
    entry Dequeue (Item: out Element);
  private
    Queue : Queue_Type;
  end Protected_Queue;
private
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_State is (Empty, Filled);
  type Queue_Type is record
    Top, Free : Marker := Marker'First;
    State : Queue_State := Empty;
    Elements : List;
  end record;
end Queue_Pack_Protected;
```

A protected queue implementation

```
package body Queue_Pack_Protected is
  protected body Protected_Queue is
    entry Enqueue (Item: in Element) when
      Queue.State = Empty or Queue.Top /= Queue.Free is
    begin
      Queue.Elements (Queue.Free) := Item;
      Queue.Free := Queue.Free + 1;
      Queue.State := Filled;
    end Enqueue;
    entry Dequeue (Item: out Element) when
      Queue.State = Filled is
    begin
      Item := Queue.Elements (Queue.Top);
      Queue.Top := Queue.Top + 1;
      if Queue.Top = Queue.Free then Queue.State := Empty; end if;
    end Dequeue;
  end Protected_Queue;
end Queue_Pack_Protected;
```

A multitasking protected queue test program

```
with Queue_Pack_Protected; use Queue_Pack_Protected;
with Ada.Text_IO; use Ada.Text_IO;
procedure Queue_Test_Protected is
  Queue : Protected_Queue;
  task Producer is entry shutdown; end Producer;
  task Consumer is
  end Consumer;
  task body Producer is
    Item : Element;
    GotIt : Boolean;
  begin
    loop
      select
        accept shutdown; exit; -- main task loop
      else
        Get_Immediate (Item, GotIt);
        if GotIt then
          Queue.Enqueue (Item); -- task might be blocked here!
        else
          delay 0.1; --sec.
        end if;
      end select;
    end loop;
  end Producer;
  (...)
end Queue_Test_Protected;
```

...)

```

task body Consumer is
  Item : Element;
begin
  loop
    Queue.Dequeue (Item); -- task might be blocked here!
    Put ("Received: "); Put (Item); Put_Line ("!");
    if Item = 'q' then
      Put_Line ("Shutting down producer"); Producer.Shutdown;
      Put_Line ("Shutting down consumer"); exit; -- main task loop
    end if;
  end loop;
end Consumer;

begin
  null;
end Queue_Test_Protected;
    
```

Ada95

Abstract types & dispatching

... introducing:

- abstract tagged types
- abstract subroutines
- concrete implementation of abstract types
- dispatching to different packages, tasks, and partitions according to concrete types

An abstract queue specification

```

package Queue_Pack_Abstract is
  subtype Element is Character;
  type Queue_Type is abstract tagged limited private;
  procedure Enqueue (Item: in Element; Queue: in out Queue_Type) is
    abstract;
  procedure Dequeue (Item: out Element; Queue: in out Queue_Type) is
    abstract;
private
  type Queue_Type is abstract tagged limited null record;
end Queue_Pack_Abstract;
    
```

A concrete queue specification

```

with Queue_Pack_Abstract; use Queue_Pack_Abstract;
package Queue_Pack_Concrete is
  QueueSize : constant Integer := 10;
  type Real_Queue is new Queue_Type with private;
  procedure Enqueue (Item: in Element; Queue: in out Real_Queue);
  procedure Dequeue (Item: out Element; Queue: in out Real_Queue);
  Queueoverflow, Queueunderflow : exception;
private
  type Marker is mod QueueSize;
  type List is array (Marker..Range) of Element;
  type Queue_State is (Empty, Filled);
  type Real_Queue is new Queue_Type with record
    Top, Free : Marker := Marker'First;
    State : Queue_State := Empty;
    Elements : List;
  end record;
end Queue_Pack_Concrete;
    
```

A concrete queue implementation

```

package body Queue_Pack_Concrete is
  procedure Enqueue (Item: in Element; Queue: in out Real_Queue) is
  begin
    if Queue.State = Filled and Queue.Top = Queue.Free then
      raise Queueoverflow;
    end if;
    Queue.Elements (Queue.Free) := Item;
    Queue.Free := Queue.Free + 1;
    Queue.State := Filled;
  end Enqueue;
  procedure Dequeue (Item: out Element; Queue: in out Real_Queue) is
  begin
    if Queue.State = Empty then
      raise Queueunderflow;
    end if;
    Item := Queue.Elements (Queue.Top);
    Queue.Top := Queue.Top + 1;
    if Queue.Top = Queue.Free then Queue.State := Empty; end if;
  end Dequeue;
end Queue_Pack_Concrete;
    
```

A multitasking dispatching test program

```

with Queue_Pack_Abstract; use Queue_Pack_Abstract;
with Queue_Pack_Concrete; use Queue_Pack_Concrete;
procedure Queue_Test_Dispatching is
  type Queue_Class is access all Queue_Type'class;
  task Queue_Holder is -- could be on an individual partition
    entry Queue_Filled;
  end Queue_Holder;
  task Queue_User is -- could be on an individual partition
    entry Send_Queue (Remote_Queue: in Queue_Class);
  end Queue_User;
  (
    begin null; end Queue_Test_Dispatching;
    
```

Local\_Queue := new Real\_Queue; -- could be a different implementation!

```

task body Queue_Holder is
  Local_Queue : Queue_Class;
  Item : Element;
begin
  Local_Queue := new Real_Queue;
  Queue_User.Send_Queue (Local_Queue);
  accept Queue_Filled do
    Dequeue (Item, Local_Queue.all); -- Item will be 'r'
  end Queue_Filled;
end Queue_Holder;

task body Queue_User is
  Local_Queue : Queue_Class;
  Item : Element;
begin
  Local_Queue := new Real_Queue;
  accept Send_Queue (Remote_Queue: in Queue_Class) do
    Enqueue ('r', Remote_Queue.all); -- potentially a rpe!
    Enqueue ('l', Local_Queue.all);
  end Send_Queue;
  Queue_Holder.Queue_Filled;
  Dequeue (Item, Local_Queue.all); -- Item will be 'l'
end Queue_User;

begin null; end Queue_Test_Dispatching;
    
```

Ada95

Ada95 language status

- Established language standard with free and commercial compilers available for all major OSs.
- Stand-alone runtime environments for embedded systems (some are only available commercially).
- Special (yet non-standard) extensions (i.e. language reductions and proof systems) for extreme small footprint embedded systems or high integrity real-time environments available ⇨ Ravenscar profile systems.
- ⇨ has been used and is in use in numberless large scale projects (e.g. in the international space station, and in some spectacular crashes: e.g. Ariane 5)

Esterel

Transformational ↔ Interactive ↔ Reactive

- **Transformational (functional) systems:**  
... generating outputs based on input and stop, utilizing no or a small number of internal states.
- **Interactive systems:**  
... servers and other systems in longer long-term operation, requesting occasional inputs, and accepting service-calls, when there are resources to do so.
- **Reactive (reflex) systems:**  
... systems, which are reacting to external stimuli only (by generating other stimuli). Can be viewed as a predictable, functional system, which is listening to inputs continuously, while holding enough resources to ensure reasonable reaction times.

Esterel

Strong synchrony or 'zero delay' assumption:

- ⇨ theoretical perspective: all operations are 'instantaneous'
- ... or a little bit more realistic:
- ⇨ there is no observable delay, i.e. all operations are finished before the next signal occurs.

Esterel

Control- ↔ Data-handling

- **Data-handling:**  
... continuous data-streams, functional processing (DSPs, 'number crunching'), ⇨ high bandwidth
- **Control-handling:**  
... discrete signals, controlling data-streams and processes, ⇨ low bandwidth

Esterel

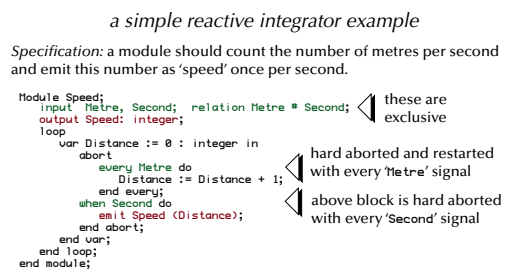
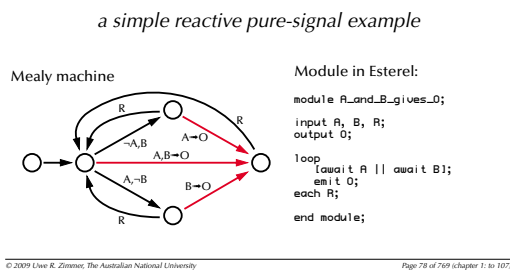
Control-dominated reactive systems

- **Real-Time process control:**  
... reaction to (sparse) stimuli in predefined time-spans
- **Embedded systems / device control:**  
... local, discrete control
- **Complex systems control:**  
... supervision of complex data-streams
- **Communication protocols:**  
... control part of communication systems
- **Human-machine interface:**  
... switching modes, event handling
- **Control logic (hardware):**  
... glue logic, interfaces, pipe control

Esterel

Determinism

- Control-dominated reactive systems ⇨ mostly deterministic  
... e.g. real-time & embedded systems
- Interactive systems ⇨ usually non-deterministic  
... e.g. operating systems, IP-servers
- ⇨ is determinism lost automatically in concurrent systems?



Esterel

Immediate reactions:

by default all synchronization points:

```

await (Ssignal);
abort _ when (Ssignal);
every (Ssignal) do _ end every;
loop _ each (Ssignal);
    
```

wait for the next signal occurrence ('rising edge trigger').  
... but with an additional 'immediate':

```

await immediate (Ssignal);
abort _ when immediate (Ssignal);
every immediate (Ssignal) do _ end every;
loop _ each immediate (Ssignal);
    
```

a currently active signal will trigger these statements ('level trigger').

Weak aborts:

by default a code block is aborted immediately, when a signal occurs:

```
abort
[<statement>];+
when <signal>;
```

Sometimes the semantic like

'activate the code block for one last time, when <signal> occurs'  
is more useful and expressed in Esterel as:

```
weak abort
[<statement>];+
when <signal>;
```

the code block is now activated for a 'final wish', when <signal> occurs.

Parallel signals

assuming 'Metre' and 'Second' occur simultaneously => **this code is wrong!**

```
Module Speed;
input Metre, Second;
output Speed: integer;
loop
var Distance := 0 : integer in
abort
every Metre do
Distance := Distance + 1;
end every;
when Second do
emit Speed (Distance);
end abort;
end var;
end loop;
end module;
```

- these are no longer exclusive
- 2. 'every Metre' waits for the next 'Metre' => **1 metre is lost**
- 1. above block is immediately aborted

Parallel signals

'Metre' and 'Second' occur simultaneously – using 'weak abort':

```
Module Speed;
input Metre, Second;
output Speed: integer;
loop
var Distance := 0 : integer in
weak abort
every Metre do
Distance := Distance + 1;
end every;
when Second do
emit Speed (Distance);
end abort;
end var;
end loop;
end module;
```

- these are no longer exclusive
- above block is activated one last time, when 'Second' occurs. Therefore the simultaneous 'Metre' is taken into account

Parallel signals

'Metre' and 'Second' occur simultaneously – using 'every immediate':

```
Module Speed;
input Metre, Second;
output Speed: integer;
loop
var Distance := 0 : integer in
abort
every immediate Metre do
Distance := Distance + 1;
end every;
when Second do
emit Speed (Distance);
end abort;
end var;
end loop;
end module;
```

- these are no longer exclusive
- 2. 'every immediate' takes the current 'Metre' into account
- 1. above block is immediately aborted

Causality and synchronous languages

Causality in general terms: 'the future should not influence the past'

Technically:

Causal synchronous programs need to be

- Reactive provides a well-defined output for each signal sequence
- Deterministic provides exactly one output for each signal sequence

Causality: counter examples

```
≠ non-reactive programming:
module non-reactive;
output O;
present 0 else emit 0 end;
end module;

≠ non-deterministic programming:
module non-deterministic;
output O;
present 0 then emit 0 end;
end module;
```

```
≠ cyclic dependencies with multiple signals:
module cyclic_dependency;
output A, B;
[ present A then emit B end || present B else emit A end ]
end module;
```

Causality and synchronous languages

≠ Cyclic dependencies can cause causality problems in synchronous languages (similar to potential dead-locks in asynchronous languages).

- Strict synchronous languages: avoid all cyclic dependencies in signals.
- Esterel: fully acyclic programs are considered too restrictive, since cyclic dependencies can make programs more intuitive in places.
- Cyclic programs can still be reactive and deterministic.

More on 'strong synchrony' and 'zero delay' assumptions:

Assuming a system operates in three phases:

- collect current input signals
  - calculate responses
  - emit new output signals and goto step 1.
- The system is assumed to be 'synchronous' or 'instantaneous', iff the total worst case computation time is smaller than the minimal time between two observable changes in the environment.
  - Synchronous systems assume a logical rather than a continuous time.

More on 'strong synchrony' and 'zero delay' assumptions:

≠ In many applications these assumptions are justified and enable:

- a strong analysis and simplification theory (Boolean calculus and automata theory)
- a significantly easier program verification
- an easier hardware implementation

Esterel language status

- Created by the Esterel group at INRIA, France.
- Available freely for Linux, Solaris, and Windows NT.
- Produces C/C++ code, which need to be cross-compiled for an actual target system.
- Currently maintained by Esterel Technologies (a spin-off company).
- No standards.
- Employed in telecommunication, automotive, energy, aerospace, and defence projects by some major companies.

Process and Experiment Automation Realtime Language

- Simple and very 'readable' language for small projects.
- Supports tasking and timed activations.
- Supports interrupts, signals, semaphores, and bolt variables.
- Lacks any support for 'programming in the large'.

Is a settled standard:

- DIN 66253-1: Basic PEARL 1981
- DIN 66253-2: Full PEARL 1982
- DIN 66253-3: PEARL for distributed systems 1989

```
MODULE;
SYSTEM;
Alert: Hard_Int(7);

PROBLEM;
SPECIFY Alert INTERRUPT;
SPECIFY Help TASK GLOBAL;
SPECIFY Pushed BIT GLOBAL;
DECLARE Switch BIT INITIAL 0;

Init : TASK MAIN;
WHEN Alert ACTIVATE Recovery;
ENABLE Alert;
Switch := Pushed;
END;

Recovery: TASK PRIORITY 9;
DISABLE Alert;
IF Switch = 1 THEN ACTIVATE Help; FIN;
AFTER 30 MIN ALL 5 MIN DURING 1 HRS ACTIVATE Help;
END;

MODEND;
```

PEARL – language status

- Established standard.
- Compilers available for all major OSs (and some RT-OSS) as well as for a number of single-board systems (one free compiler for academic users).
- Used for educational purposes mainly.
- Currently maintained by a German special-interest community and a small company (IEP).

Specific Java engines and classes enhance:

- Threads: Priorities, scheduling, and dispatching
- Memory: Controlled garbage collection and physical memory access
- Synchronization: Ordered queues, and priority ceiling protocols
- Asynchronism: generalized asynchronous event handling, asynchronous transfer of control, timers, and an operational implementation of thread termination
- all current real-time Java extensions keep the underlying, consequent object orientation.
- some restrict the language standard, some extend it.

Real-Time Specification for Java 1.0

(final 11/01 – currently no release date for 1.0.1)

- enhanced thread model (memory attributes, more precise specs)
- enabling powerful and highly adaptive scheduling policies
- introducing scoped, immortal, and physical memory to Java
- introducing timers, interrupts, and more exceptions
- higher resolution time model
- optional support for POSIX signals

Real-Time Specification for Java 1.0

(final 11/01 – currently no release date for 1.0.1)

- Backward compatible: offers the full standard Java specification, no syntactical extensions
- Allows for different Java-engine implementations: in terms of completeness: e.g. scheduling is not mandatory in terms of interpretations: e.g. 'instantiations per time-span' (RationalTime) strongly suggests but does not enforce equal distance internals
- currently one reference implementation available (for TimeSys Linux)

RT-Java – Language status

- RT-Java is still a consequently object-oriented language.
- Garbage collection can be restricted or even fully suppressed (mandatory requirement for predictable systems).
- How do you program in a clean object oriented manner without garbage collection?
- Using it in hard-realtime environments implies to 'program badly' (in terms of strong OOP).

Many potential applications in soft- or mixed-realtime environments.

Portable Operating System Interface for Computing Environments

- IEEE/ANSI Std 1003.1 and following
- Program Interface (API) [C Language]
- more than 30 different POSIX standards (a system is 'POSIX compliant', if it implements parts of just one of them!)

1003.1 12/01	OS Definition	single process, multi process, job control, signals, user groups, file system, file attributes, file device management, file locking, device I/O, device-specific control, system database, pipes, FIFOs, ...
1003.1b 10/93	Real-time Extensions	real-time signals, priority scheduling, timers, asynchronous I/O, prioritized I/O, synchronized I/O, file sync, mapped files, memory locking, memory protection, message passing, semaphore, ...
1003.1c 6/95	Threads	multiple threads within a process; includes support for: thread control, thread attributes, priority scheduling, mutexes, mutex priority inheritance, mutex priority ceiling, and condition variables
1003.1d 10/99	Additional Real-time Extensions	new process create semantics (spawn), sporadic server scheduling, execution time monitoring of processes and threads, I/O advisory information, timeslots on blocking functions, device control, and interrupt control
1003.1j 1/00	Advanced Real-time Extensions	typed memory, nanosleep improvements, barrier synchronization, reader/writer locks, spin locks, and persistent notification for message queues
1003.21 -/-	Distributed Real-time	buffer management, send control blocks, asynchronous and synchronous operations, bounded blocking, message priorities, message labels, and implementation protocols

Frequently found POSIX RT-features include:

- **Timers:** delivery is accomplished using POSIX signals
- **Priority scheduling:** fixed priority, 32 priority levels
- **Real-time signals:** signals with multiple levels of priority
- **Semaphore:** named semaphore
- **Memory queues:** message passing using named queues
- **Shared memory:** memory regions shared between multiple processes
- **Memory locking:** no virtual memory swapping of physical memory pages

	POSIX 1003.1 (Base POSIX)	POSIX 1003.1b (Real-time extensions)	POSIX 1003.1c (Threads)
Solaris	Full support	Full support	Full support
IRIX	Conformant	Full support	Full support
Linux	Conformant	Full support	Conformant (Version 3.1)
QNX Neutrino	Full support	Partial support (no memory locking)	Full support
Linux	Full support	Partial support (no timers, no message queues)	Full support
VxWorks	Partial support (different process model)	Partial support (different process model)	Supported through third party product

POSIX is a 'C' standard ...

... but bindings to other languages are also (suggested) POSIX standards:

- Ada: 1003.5\*, 1003.24 (some PAR approved only, some withdrawn)
- Fortran: 1003.9 (6/92)
- Fortran90: 1003.19 (withdrawn)
- ... and there are POSIX standards for task-specific POSIX profiles, e.g.:
- Super computing: 1003.10 (6/95)
- Realtime: 1003.13, 1003.13b (3/98)
  - profiles 51-54: combinations of the above RT-relevant POSIX standards ⇐ RT-Linux
- Embedded Systems: 1003.13a (PAR approved only)

```
void timer_create(int num_secs, int num_nsecs)
{
    struct sigaction sa;
    struct sigevent sig_spec;
    sigset_t allsigs;
    struct itimerspec tmr_setting;
    timer_t timer_h;

    /* setup signal to respond to timer */
    sigemptyset(&sa.sa_mask);
    sa.sa_flags = SA_SIGINFO;
    sa.sa_sigaction = timer_intr;
    if (sigaction(SIGRTMIN, &sa, NULL) < 0)
        perror("sigaction");

    sig_spec.sigev_notify = SIGEV_SIGNAL;
    sig_spec.sigev_signo = SIGRTMIN;
}
```

```
/* create timer, which uses the REALTIME clock */
if (timer_create(CLOCK_REALTIME, &sig_spec, &timer_h) < 0)
    perror("timer create");

/* set the initial expiration and frequency of timer */
tmr_setting.it_value.tv_sec = 1;
tmr_setting.it_value.tv_nsec = 0;
tmr_setting.it_interval.tv_sec = num_secs;
tmr_setting.it_interval.tv_nsec = num_nsecs;
if (timer_settime(timer_h, 0, &tmr_setting, NULL) < 0)
    perror("settimer");

/* wait for signals */
sigemptyset(&allsigs);
while (1) {
    sigsuspend(&allsigs);
}

/* routine that is called when timer expires */
void timer_intr(int sig, siginfo_t *extra, void *cruf)
{
    /* perform periodic processing and then exit */
}
```

```
/* create timer, which uses the REALTIME clock */
if (timer_create(CLOCK_REALTIME, &sig_spec, &timer_h) < 0)
    perror("timer create");

/* set the initial expiration and frequency of timer */
tmr_setting.it_value.tv_sec = 1;
tmr_setting.it_value.tv_nsec = 0;
tmr_setting.it_interval.tv_sec = num_secs;
tmr_setting.it_interval.tv_nsec = num_nsecs;
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    perror("settimer");

/* wait for signals */
sigemptyset(&allsigs);
while (1) {
    sigsuspend(&allsigs);
}

/* routine that is called when timer expires */
void timer_intr(int sig, siginfo_t *extra, void *cruf)
{
    /* perform periodic processing and then exit */
}
```

remember the Pearl timers? AFTER 30 MIN ALL 5 MIN DURING 1 HR5 ACTIVATE HELP!

Suitable for which real-time systems?

	Ada	Esterel	Pearl	RT-Java	Posix
Predictability	*** (specific run-time env.)	*** (if logical time holds)	**	--- (if OOP)	/
Real-Time	**	logic time	**	***	**
Concurrency	***	**	*	**	***
Distribution	**	/	(dist. Pearl)	***	**
Error detection	** (strong typing)	*** (verification)	*	*	--- (C)
Large systems	***	*	---	***	/

Introduction & Real-Time Languages

- Features (and non-features) of a real-time system
- Components of a real-time system
- Real-time languages criteria
- Examples of actual real-time languages:
  - Ada95
  - Esterel
  - Pearl
  - Real-time JAVA
  - POSIX