Design, Simulate, Execute Embedded Systems

CPAL: High-Level Abstractions for Safe Embedded Systems

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Software has become the key to innovation

Amount of software is growing exponentially – what about productivity gains in software development ?

Innovation increasingly relies on software

Model-Driven Development is a powerful enabler but ..

Programming environments still lack

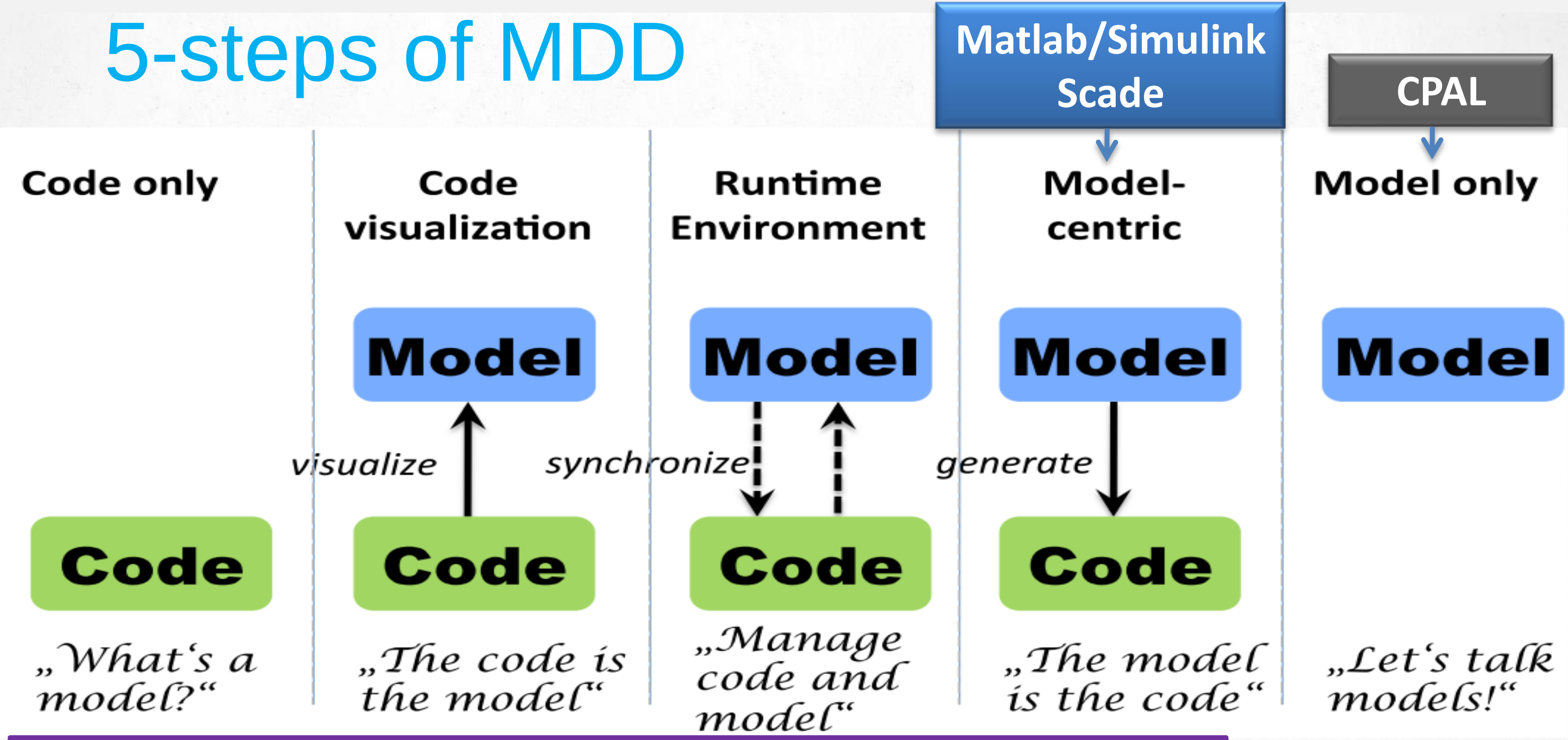
- ✓ the high-level concepts: embedded system specific language abstractions
- ✓ automation features ("*state the what, not the how*") that would make them more productive

CPAL : high-level programming model for embedded systems

- ✓ **Allow to express non-functional requirements, timing for now**
- ✓ **Synthesis step ensures requirements are met**

[Inspired from posts at http://www.theenterprisearchitect.eu/]

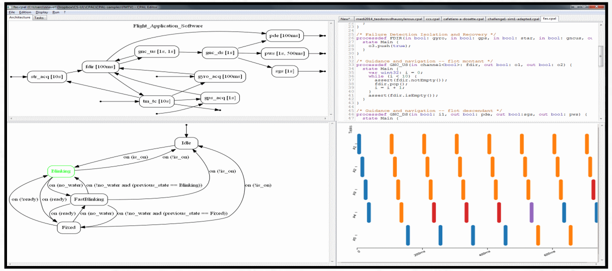
5-steps of MDD



Inspired from interpreter-based interlocking systems e.g.: RATP, SNCF [4], Westingshouse

Figure from [2] and [3]

CPAL is a real-time embedded systems specific language

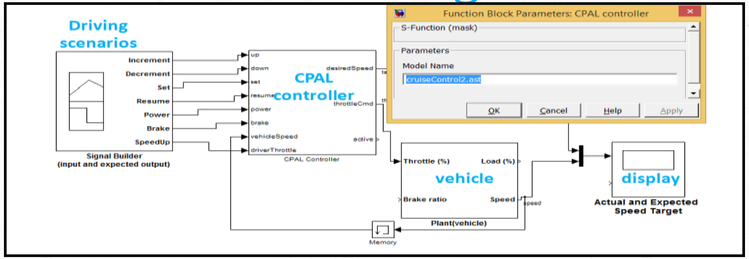


A Model and program

functional and non-functional concerns

B Simulate

possibly embedded within external tools such as RTaW-Pegase™ and Matlab/Simulink ™



C Execute

bare metal or hosted by an OS - prototypes or real systems

A joint project of RealTime-at-Work and University of Luxembourg since 2012

RTaW RealTime-at-Work

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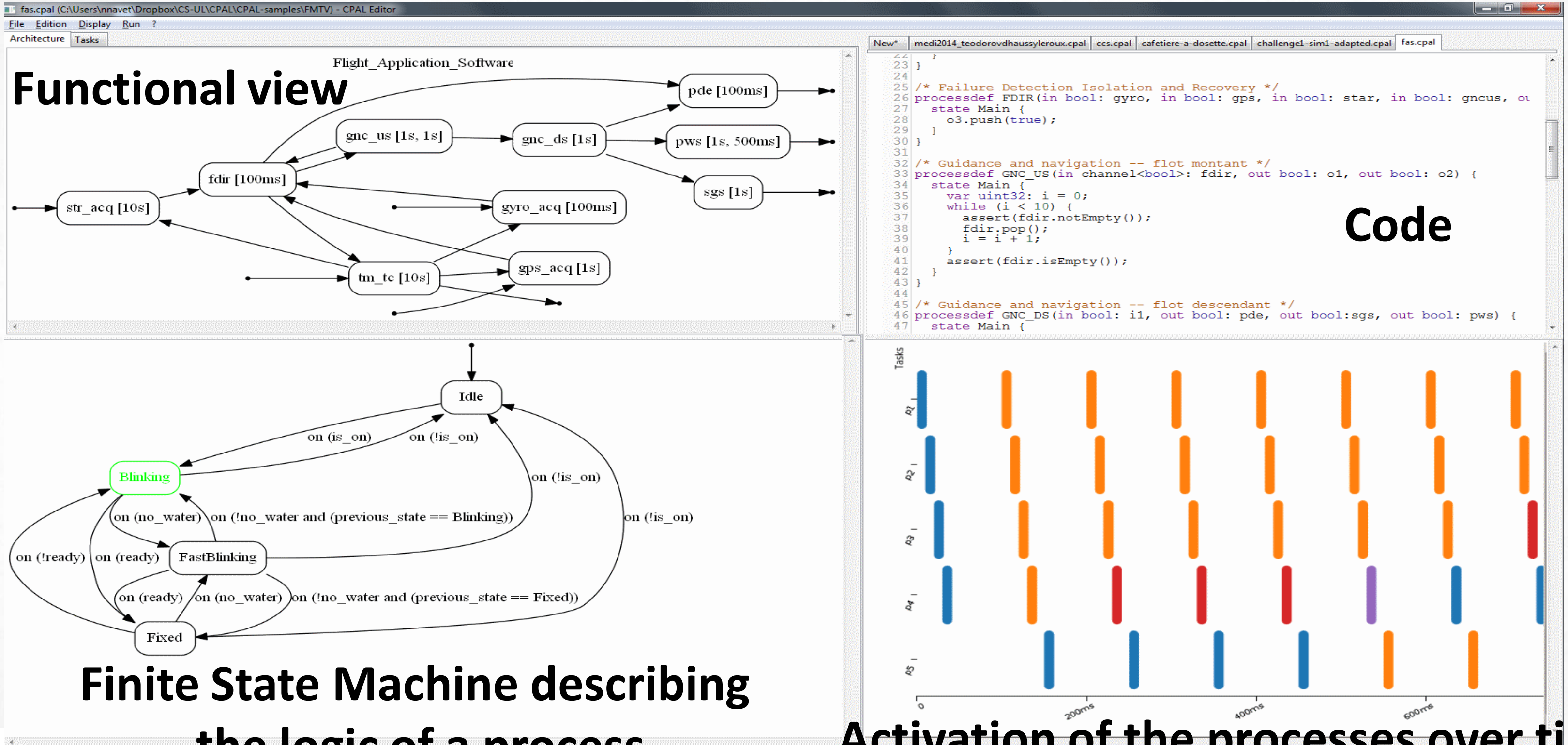
CPAL : views created out of the code



Finite State Machine describing the logic of a process

Activation of the processes over time

Available from http://designcps.com

CPAL language design objectives

1. Facilitating the writing of **correct embedded code**
2. Speeding up the development through **domain-specific abstractions** for:
   - Periodic activities and real-time scheduling
   - Time measurements and manipulation
   - Finite state machines
   - High-level interfaces to I/Os
   - etc
3. "Write once, Run Anywhere" with **equally acceptable timing behaviour** on different platforms

Facilitating the writing of correct code/system

- Designed with simplicity in mind - small and readable language
- Strongly typed language: conversions must be explicit
- No dynamic memory & no pointers
- Built-in `loop over` construct to prevent “off-by-one” errors when iterating over collections
- Testing the equality of floating-point numbers is forbidden
- All processes are known before run-time - workload is bounded
- Built-in code execution time monitoring support
- Can run on bare hardware without OS
- Utilities: schedulability analysis, code formatter and naming convention verifier

```
Fruit {
APPLE,
BANANA,
ORANGE
};

struct Item {
uint32: quantity
Fruit: f;
```

Domain-specific constructs

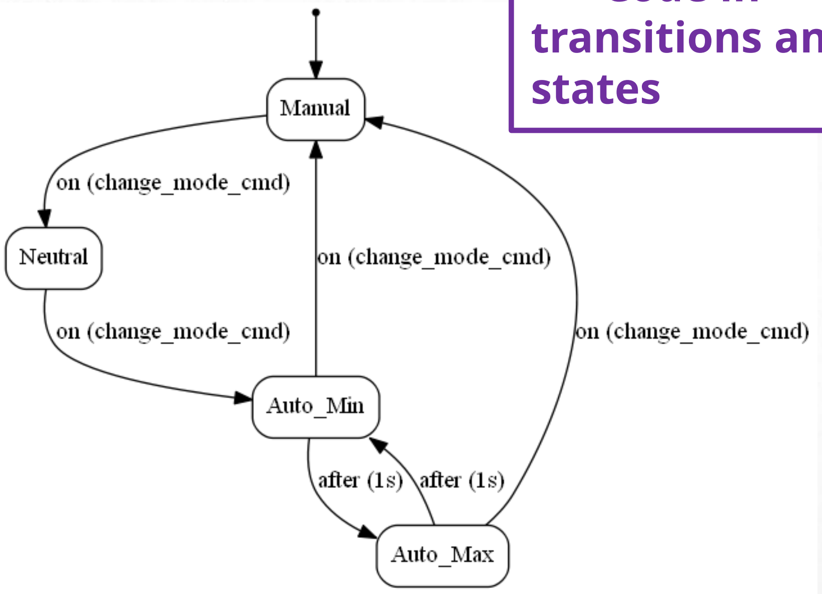
Hello, World

```
processdef Hello_World()
{
  state Main {
    IO.println("Hello, world");
  }
}

process Hello_World: a_task[100ms]();
```

FSM in processes

```
processdef Servo_Tester(
  in bool: change_mode_cmd,
  in uint16: manual_position,
  out int32: position)
{

  state Manual {
    position = int32.as(manual_position) + int32.FIRST;
  }
  on (change_mode_cmd) to Neutral;

  state Neutral {
    position = 0;
  }
  on (change_mode_cmd) to Auto_Min;

  state Auto_Min {
    position = int32.FIRST;
  }
  on (change_mode_cmd) to Manual;
  after (1s) to Auto_Max;

  state Auto_Max {
    position = int32.LAST;
  }
  on (change_mode_cmd) to Manual;
  after (1s) to Auto_Min;
}

var bool: pin_gpio_c10_in;
var uint16: pin_adc16_0_1;
var int32: pwm_c_0_0;

process Servo_Tester: main_task[100ms](pin_gpio_c10_in,
                                       pin_adc16_0_1,
                                       pwm_c_0_0);
```

- ✓ **Transition first semantics**
- ✓ **Code in transitions and states**



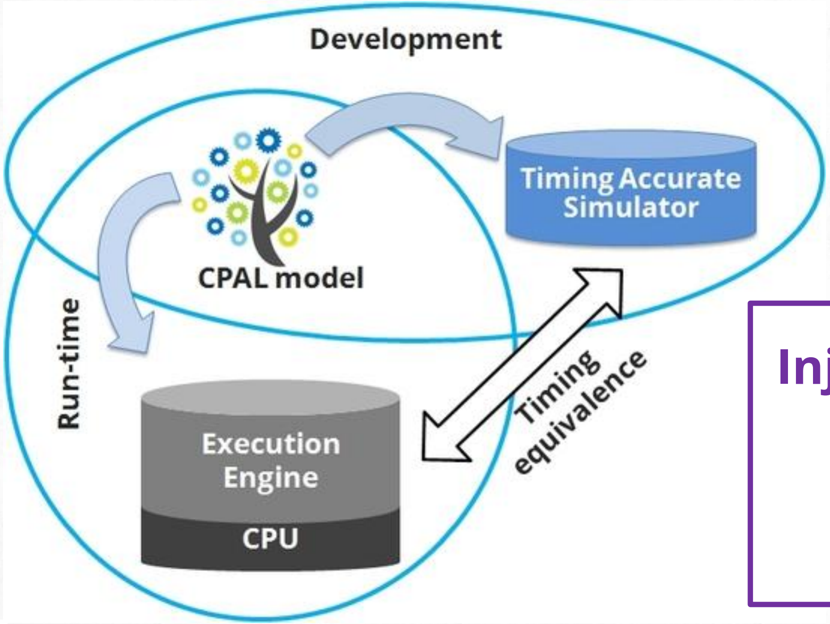
Working with time

```
const time64: sleep_time = 3ms;

processdef Manipulating_Time() {
  /* Internal granularity of time is picosecond (ps) */
  var time64: a_duration = 5s + 150ms + 3ns + 1ps;
  var time64: same_duration = 5s150ms3ns1ps;
  var time64: another_duration = 2 * a_duration - 1ps;
  var time64: t0 = time64.time();
  var time64: t1;

  state A {
    IO.println("Value of a_duration is %t", a_duration);
    assert(1s  == 1000ms);
    assert(1ms == 1000us);
    assert(1us == 1000ns);
    assert(1ns == 1000ps);
    sleep(sleep_time);
    t1 = time64.time();
    assert(t1 - t0 >= sleep_time);
  }
}

process Manipulating_Time: p1[100ms]();
process Manipulating_Time: p2[0.1Hz]();
```

`time64` type to measure and manipulate time – granularity is `picosecond`

Units: `s`, `ms`, `ns`, `us`, `ps` and `Hz`

Designer's objective: model behaves as the real-system

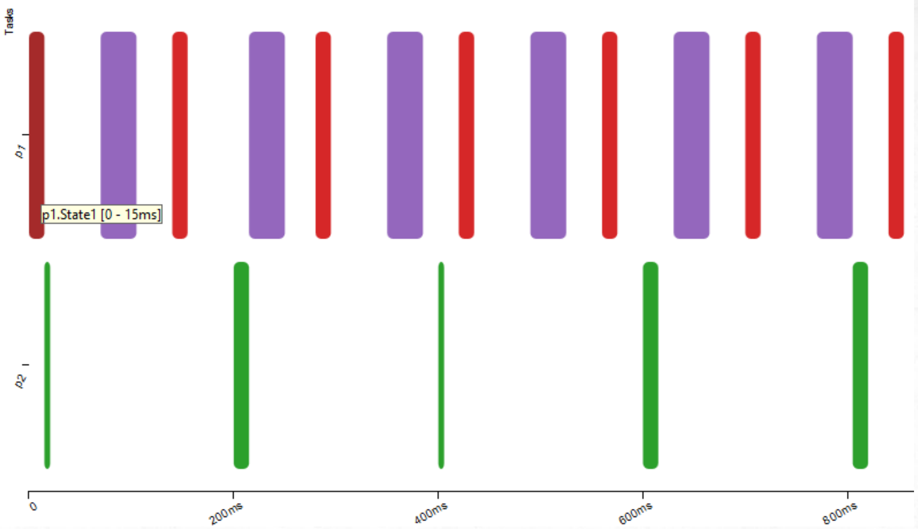


"digital mockups"
"digital twins"

Inject delays in simulation mode so as to reproduce the time it takes to execute the code on a specific platform

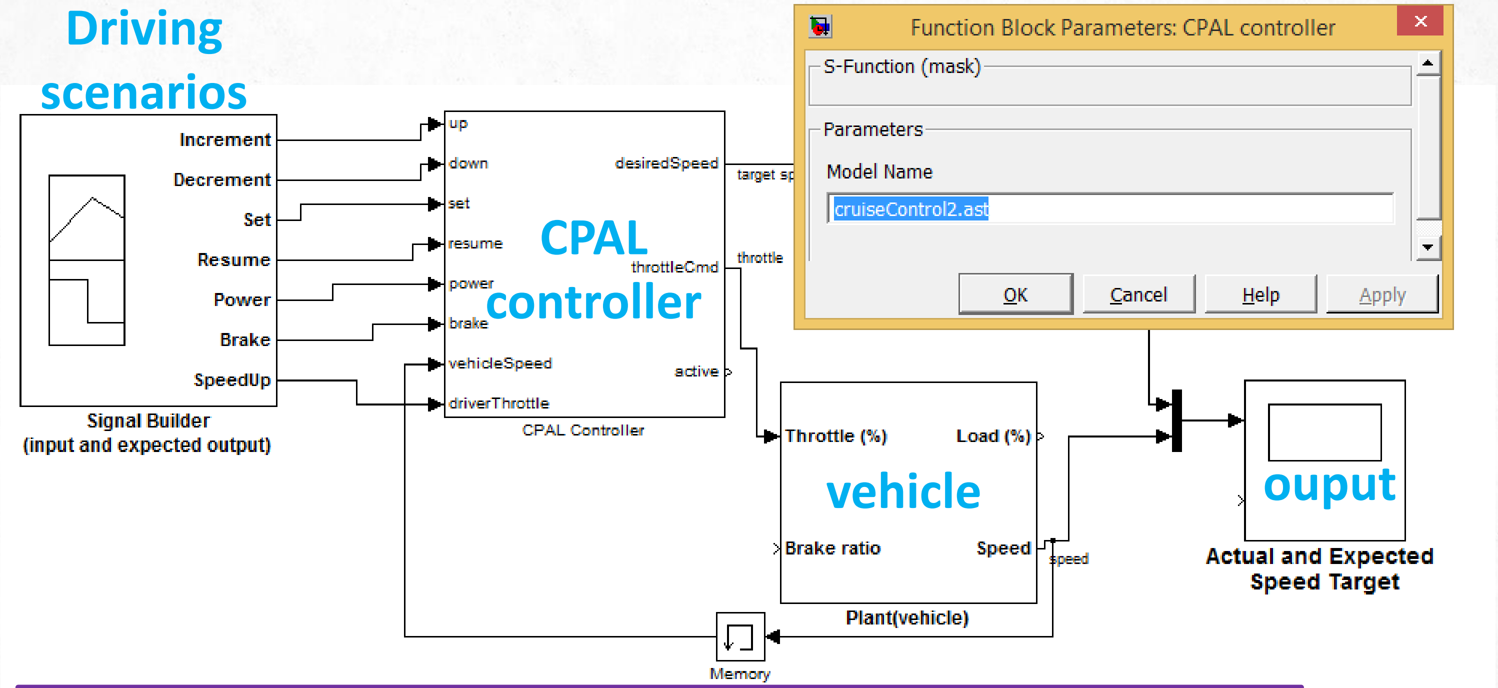
```
processdef Varying_Execution_Time()
{
  state State1 {
    @cpal:time {
      State1.execution_time = 15ms;
    }
  }
  on (true) to State2;

  state State2 {
    a_named_block: {
      @cpal:time {
        block.execution_time = 35ms;
      }
    }
  }
  on (true) to State1;
}

processdef Conditional_Execution_Time()
{
  state Main {
    @cpal:time {
      if (uint16.rand_uniform(0,2)==0) {
        Main.execution_time = 1ms;
      } else {
        Main.execution_time = 15ms;
      }
    }
  }
}

process Varying_Execution_Time: p1[70ms]();
process Conditional_Execution_Time: p2[200ms]();
```

Simulating execution time



- ✓ Annotations for real-time scheduling and activation patterns others than periodic
- ✓ Delays can be obtained from runtime monitoring

Co-simulation in Matlab/Simulink® [7]



Ongoing work: characterize HW resources required for timing correctness and ensure them at run-time

Interacting with hardware

```
processdef LED_Control(in bool: button, out bool: led)
{
  /* IO.sync() implicitly called upon each activation of task */
  state Main {
    /* Some bit banging */
    if (button) {
      led = true;
      IO.sync(); /* Explicitly synchronizes I/Os */
      sleep(250ms);
      led = false;
    }
  }
  /* IO.sync() implicitly called at the end of execution of the process*/
}

process LED_Control: blinker[500ms](pin2_in, pin0_out);
```

IOs are synced upon the activation and exit of the process, and calls to `IO.sync()`

Introspection features

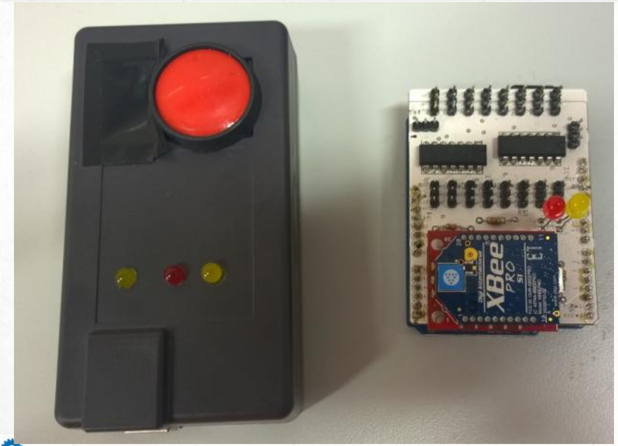
```
processdef Self_Adapting()
{
  var time64: jitter_threshold = self.period * 3/2;
  common{

    /* Query process pid and activation offset at startup */
    IO.println("pid: %u offset: %t", self.pid, self.offset);

    /* A strictly periodic process would start to execute every period */
    if (self.current_activation - self.previous_activation > jitter_threshold){
      /* Warning: start-of-execution jitter is currently very high, possible
      counter-measures that can be taken at run-time include adapting
      1) the control algorithm (e.g. mode change),
      2) the process activation pattern (e.g. increase period),
      3) the scheduling parameters (e.g. increase process priority*/
    }
  }
  /* Body of the process */
  state A {
    /* ... */
  }
}

process Self_Adapting: p1[100ms]();
```

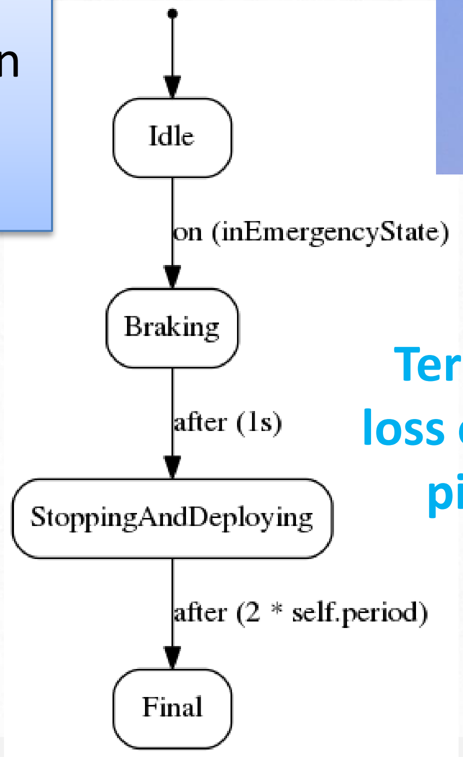
Eases portability and self-adaptive behaviour

Use-Case

Developing CPS: a smart parachute for UAV [5]

UAVs autopilots cannot be trusted –
minimal safety through a remote termination component
Joint project with Alerion company

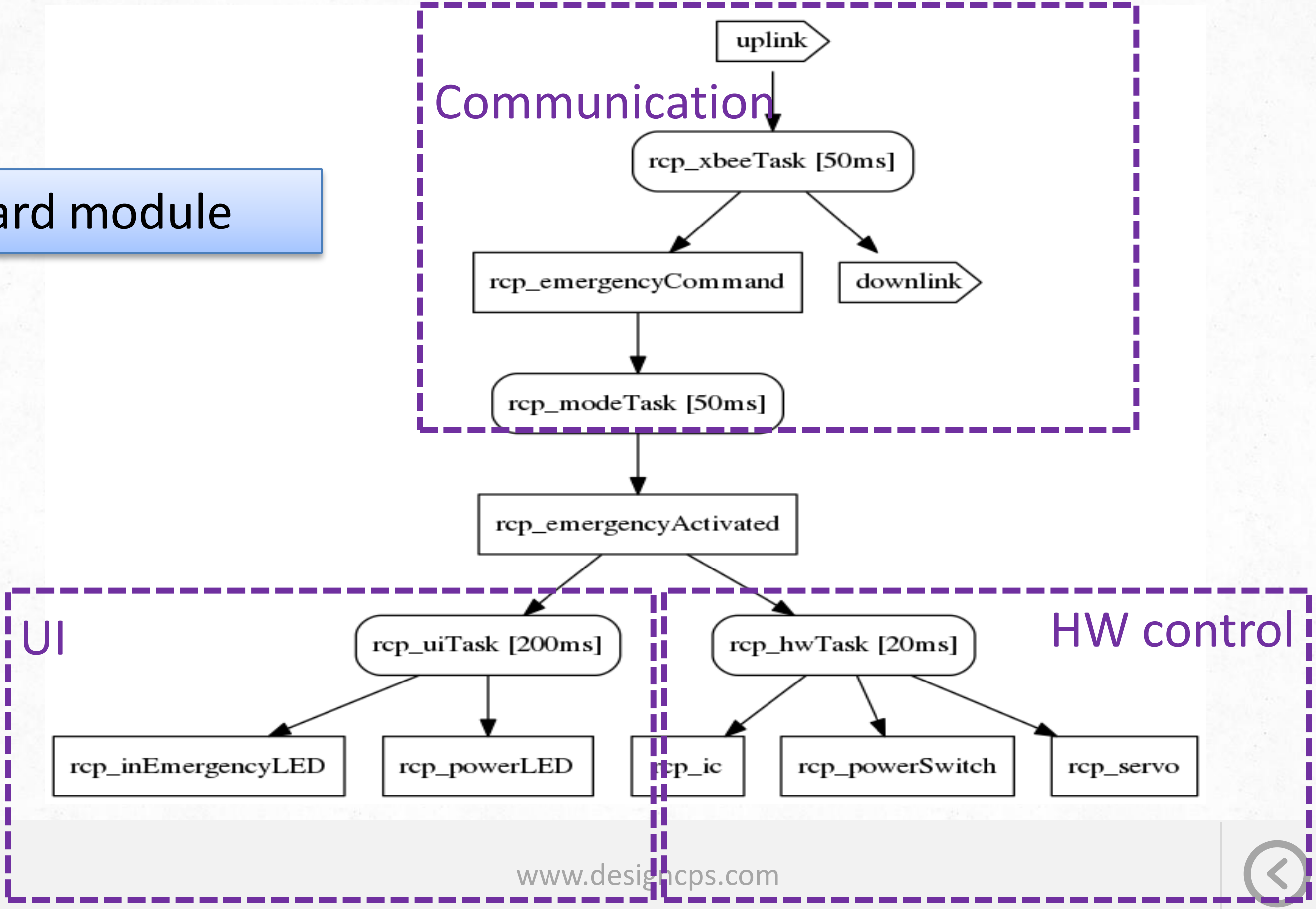




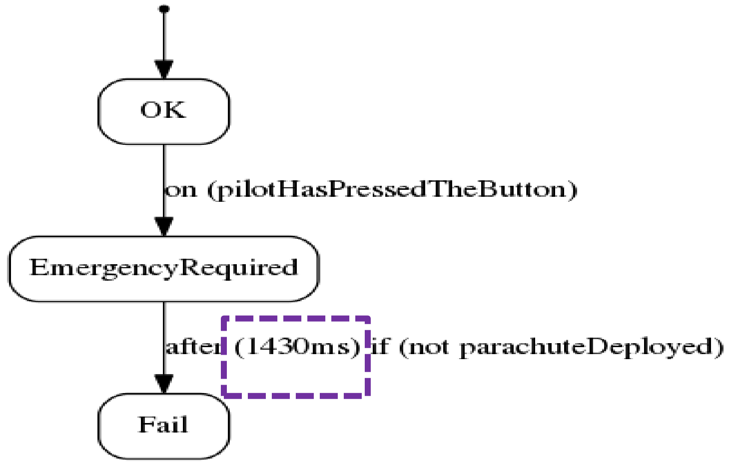
Termination upon loss of connection or pilot's decision

Software architecture

On-board module



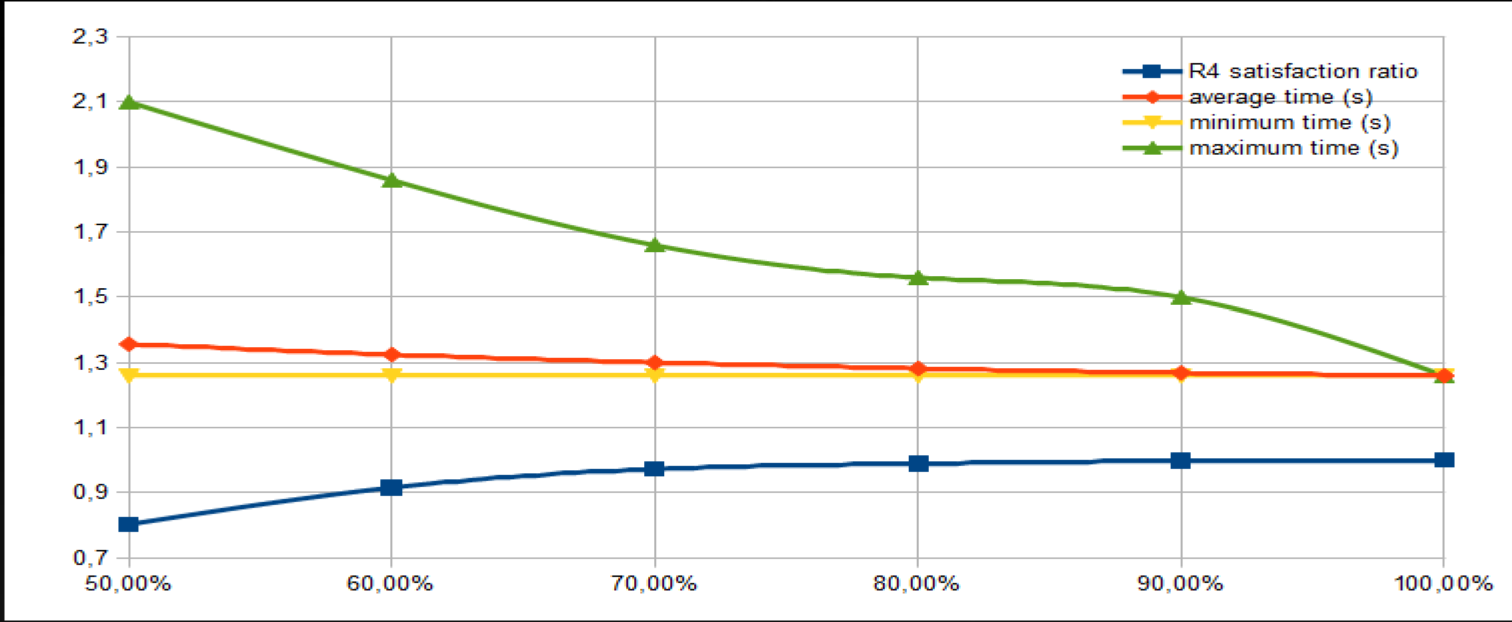
Executable requirements




```
processdef R4Observer (
   in bool : pilotHasPressedTheButton,
   in bool : parachuteDeployed)
{
   state OK {
   }
   on (pilotHasPressedTheButton)
     to EmergencyRequired;
   state EmergencyRequired {
   }
   after (1430ms) if (not parachuteDeployed)
     to Fail;
   state Fail {
     /* println("R4 FAILED"); */
     assert(false);
   }
}
```

- ✓ **Actual max. latency** depends on the ground speed target, the minimum acceptable altitude, the weight of the UAS and the characteristics of the parachute (opening time, lift, etc)

Model-based fault-injection



Time for the parachute to deploy (in seconds) and satisfaction of requirement R4 versus network quality ratio[5]

Ongoing & future work

- Upcoming releases: HW annotations, multi-core & power mode support
- Code generation and/or hook to native code for higher performances
- CPAL: MDD for IoT
- **Medium term:**
  - timing equivalence between simulation and execution
  - “State the what, not the how” for energy & safety
  - SILx qualification for the execution engine

CPAL is free to use

Thank you for your attention!

Want to give it a try? Binaries, code examples and playground at https://designcps.com

References

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5. L. Ciarletta, L. Fejoz, A. Guenard, N. Navet, "Development of a safe CPS component: the hybrid parachute, a remote termination add-on improving safety of UAS", Embedded Real-Time Software and Systems (ERTS 2016), Toulouse, France, January 27-29, 2016.
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7. S. M. Sundharam, S. Altmeyer, L. Havet, and N. Navet, "A model-based development environment for rapid-prototyping of latency-sensitive control software", in Proc. 2016 Sixth International Symposium on Embedded Computing and System Design (ISED), Patna, India, December 2016.