technische universität
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fakultät für informatik
informatik 12

Specifications, Modeling, and Model of Computation

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(slides are based on Peter Marwedel)
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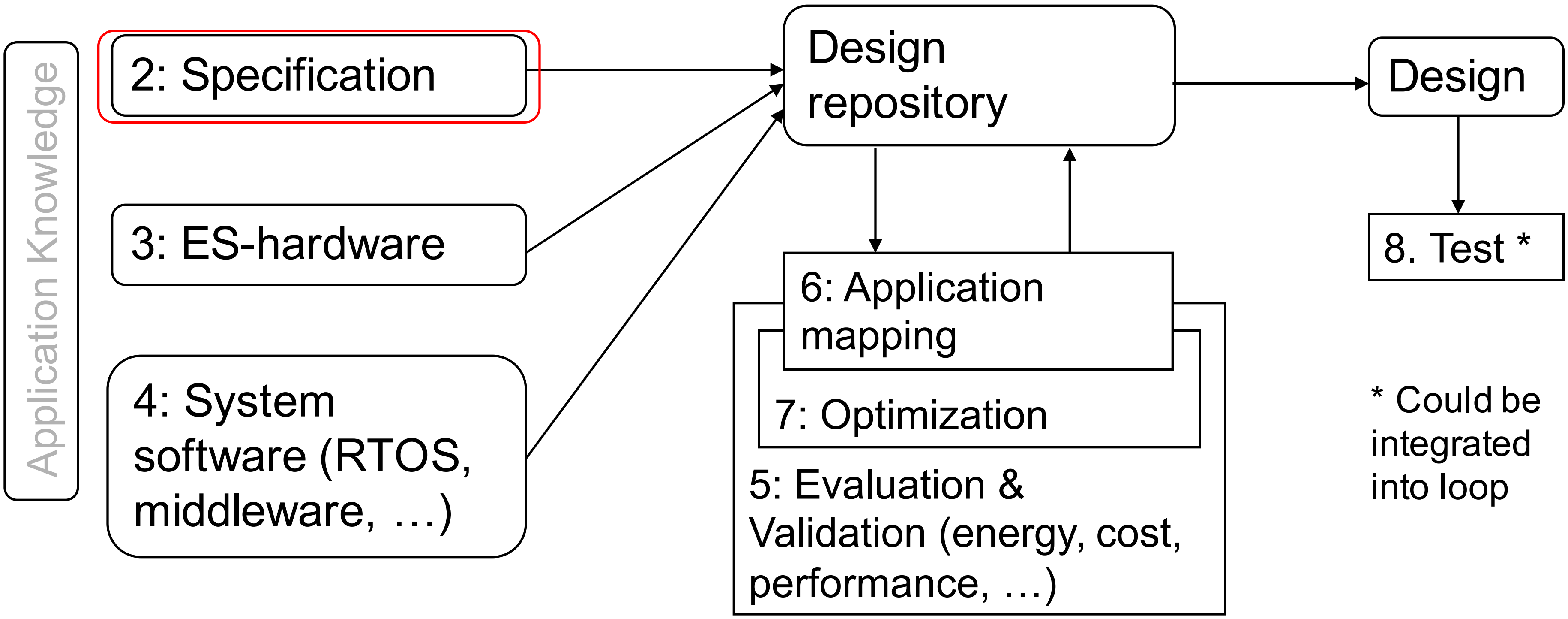
Hypothetical design flow

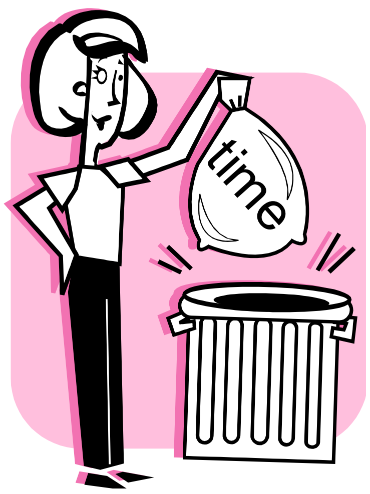


Numbers denote sequence of chapters

Motivation for considering specs & models

- Why considering specs and models in detail?
- If something is wrong with the specs,
then it will be difficult to get the design right,
potentially wasting a lot of time.
- Typically, we work with **models** of the **system under design** (SUD)

☞ What is a *model*?



Models

Definition: *A model is a simplification of another entity, which can be a physical thing or another model. The model contains exactly those characteristics and properties of the modeled entity that are relevant for a given task. A model is minimal with respect to a task if it does not contain any other characteristics than those relevant for the task*.

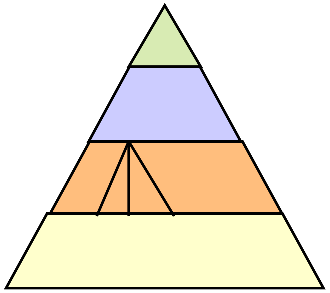
[Jantsch, 2004]:

Which requirements do we have for our models?

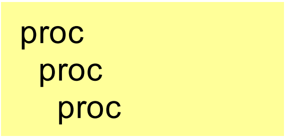
Requirements for specification & modeling techniques: Hierarchy

Hierarchy

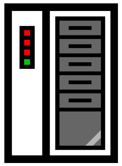
Humans not capable to understand systems containing more than ~5 objects.
Most actual systems require more objects
☞ Hierarchy (+ abstraction)



- Behavioral hierarchy
  Examples: states, processes, procedures.

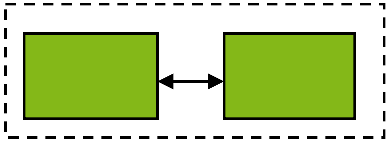


- Structural hierarchy
  Examples: processors, racks, printed circuit boards



Requirem. for specification & modeling techniques (2): Component-based design

- Systems must be designed from components
- Must be "easy" to derive behavior from behavior of subsystems



☞ Work of Sifakis, Thiele, Lee, Lee, Ernst, …

- Concurrency
- Synchronization and communication

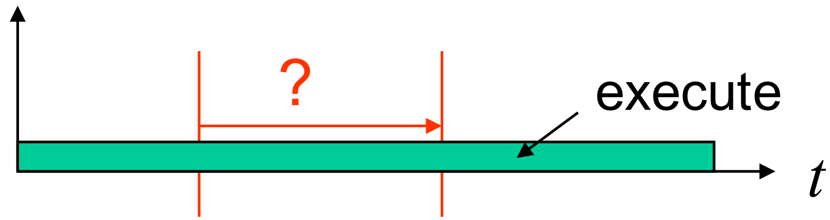
Requirements for specification & modeling techniques (3): Timing

- Timing behavior
  Essential for embedded and cy-phy systems!
  - Additional information (periods, dependences, scenarios, use cases) welcome
  - Also, the structure of the underlying platform must be known

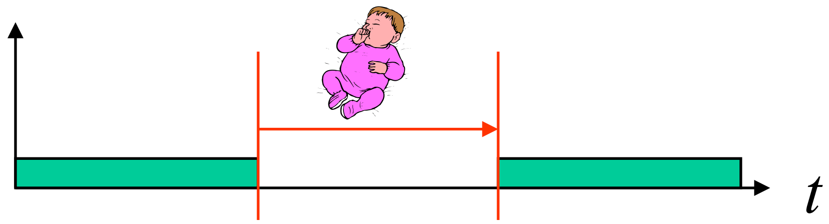
Requirements for specification & modeling techniques (3): Timing (2)

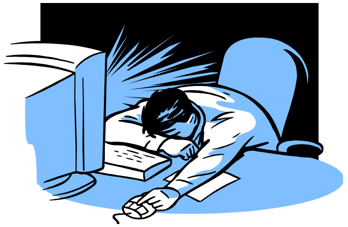
4 types of timing specs required, according to Burns, 1990:

1. Measure elapsed time
   Check, how much time has elapsed since last call



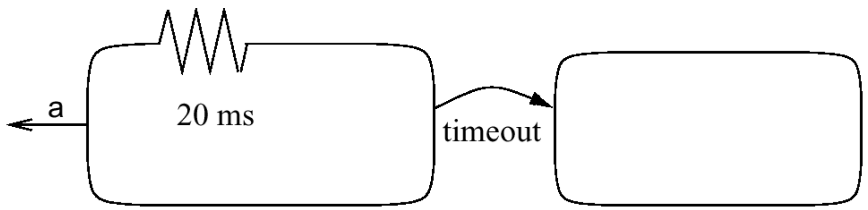
2. Means for delaying processes



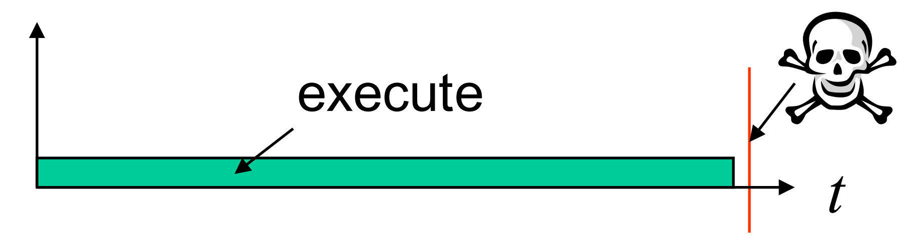


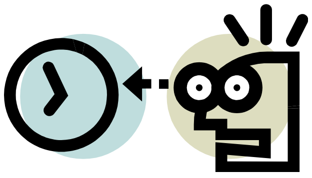
Requirements for specification & modeling techniques (3): Timing (3)

3. Possibility to specify timeouts
   Stay in a certain state a maximum time.



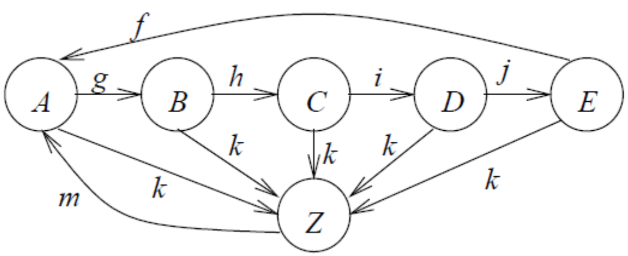
4. Methods for specifying deadlines
   Not available or in separate control file.





Specification of ES (4): Support for designing reactive systems

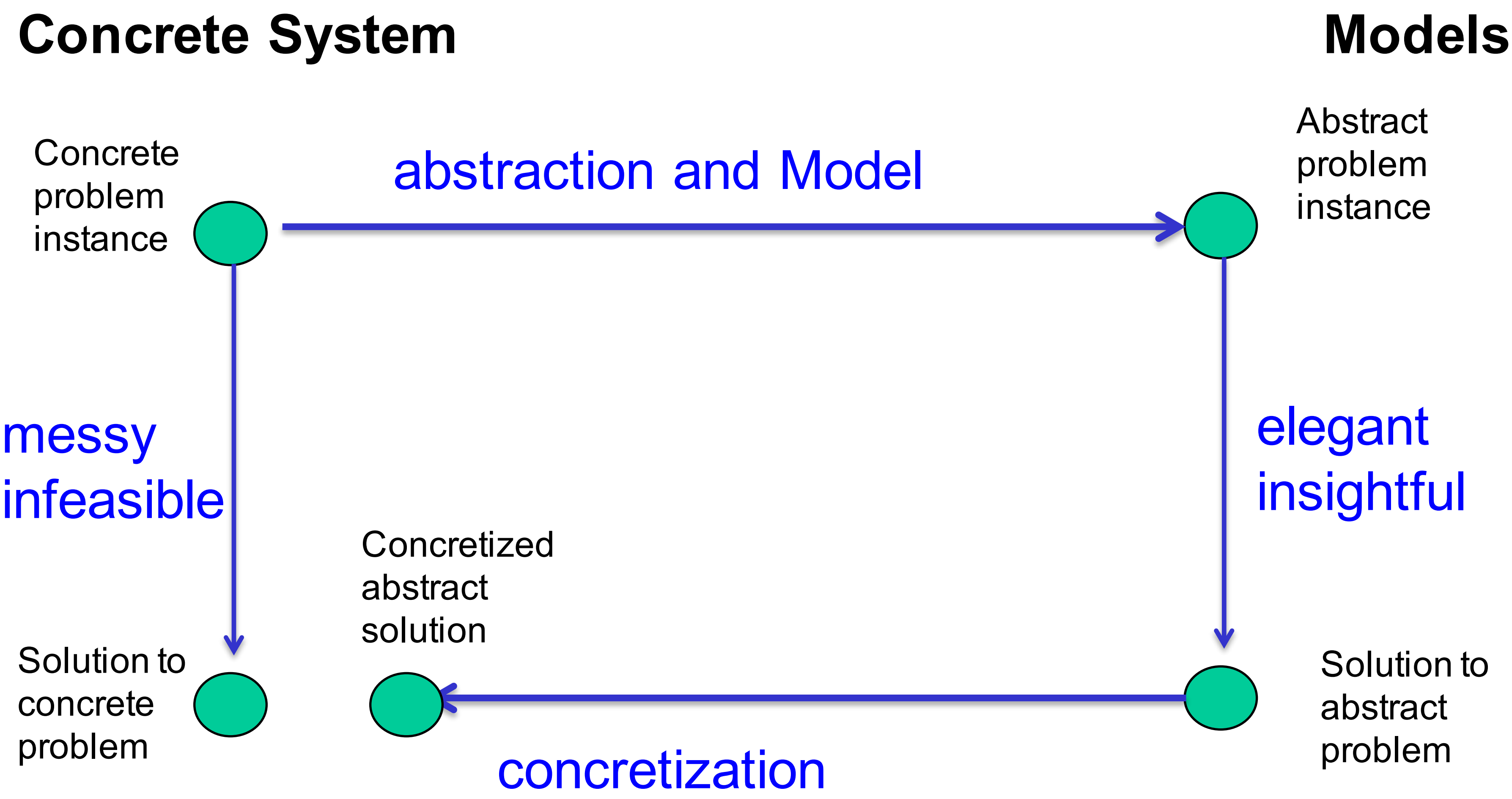
- **State-oriented behavior**
  Required for reactive systems; classical automata insufficient.
- **Event-handling**
  (external or internal events)
- **Exception-oriented behavior**
  Not acceptable to describe exceptions for every state



Requirements for specification & modeling techniques (5): More Features

- **Presence of programming elements**
- **Executability** (no algebraic specification)
- **Support for the design of large systems** (☞ OO)
- **Domain-specific support**
- **Readability**
- **Portability and flexibility**
- **Termination**
- **Support for non-standard I/O devices**
- **Non-functional properties**
- **Support for the design of dependable systems**
- **No obstacles for efficient implementation**
- **Adequate model of computation**

Then, Always Remember



Problems with classical CS theory and von Neumann (thread) computing

Even the core … notion of "computable" is at odds with the requirements of embedded software.

In this notion, useful computation terminates, but termination is undecidable.

In embedded software, termination is failure, and yet to get predictable timing, subcomputations must decidably terminate.

What is needed is nearly a reinvention of computer science.

Edward A. Lee: Absolutely Positively on Time, *IEEE Computer*, July, 2005

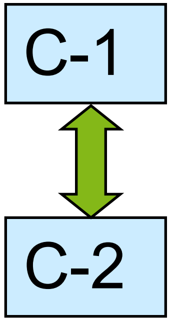
☞ Search for non-thread-based, non-von-Neumann MoCs.

Models of computation

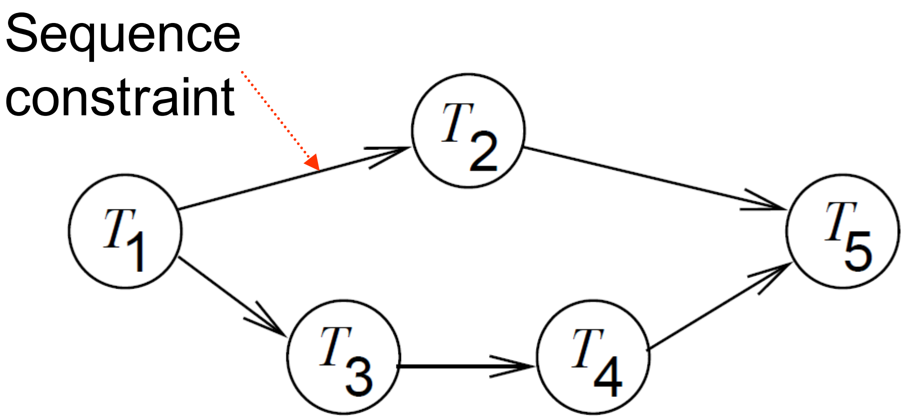
What does it mean, "to compute"?

Models of computation define:

- Components and an execution model for computations for each component
- Communication model for exchange of information between components.



Dependence graph: Definition



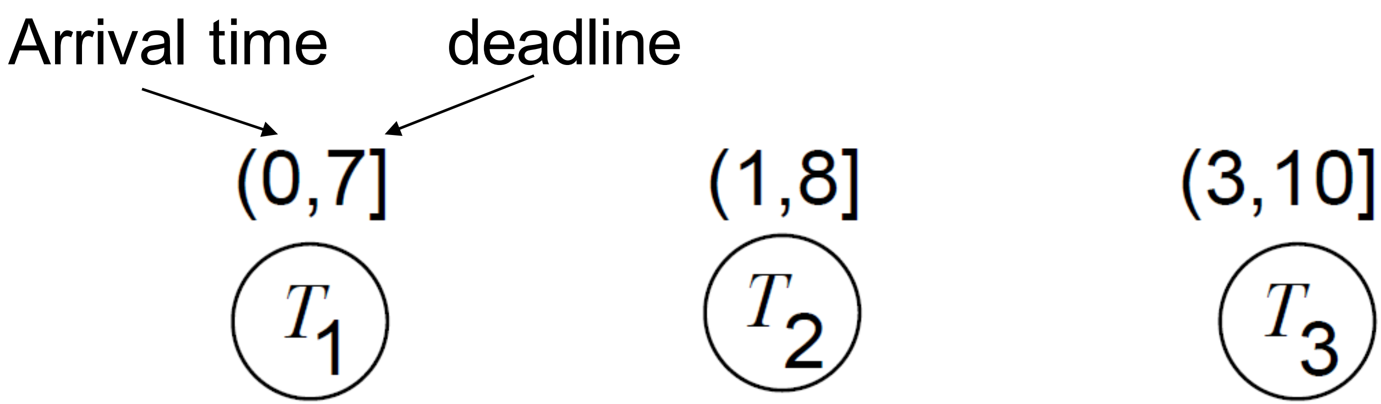
Nodes could be programs or simple operations

Def.: A **dependence graph** is a directed graph $G=(V,E)$ in which $E \subseteq V \times V$ is a relation.
If $(v_1, v_2) \in E$, then v_1 is called an **immediate predecessor** of v_2 and v_2 is called an **immediate successor** of v_1.
Suppose E^* is the transitive closure of E.
If $(v_1, v_2) \in E^*$, then v_1 is called a **predecessor** of v_2 and v_2 is called a **successor** of v_1.

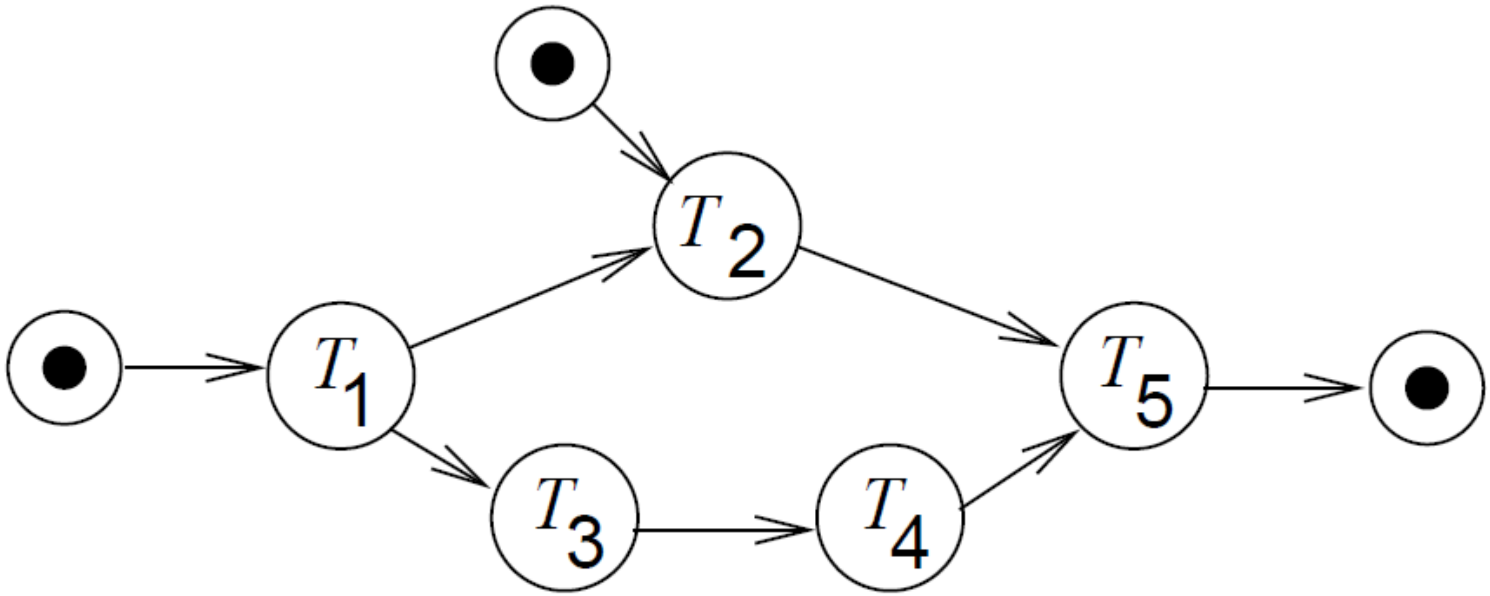
Dependence graph: Timing information

Dependence graphs may contain additional information, for example:

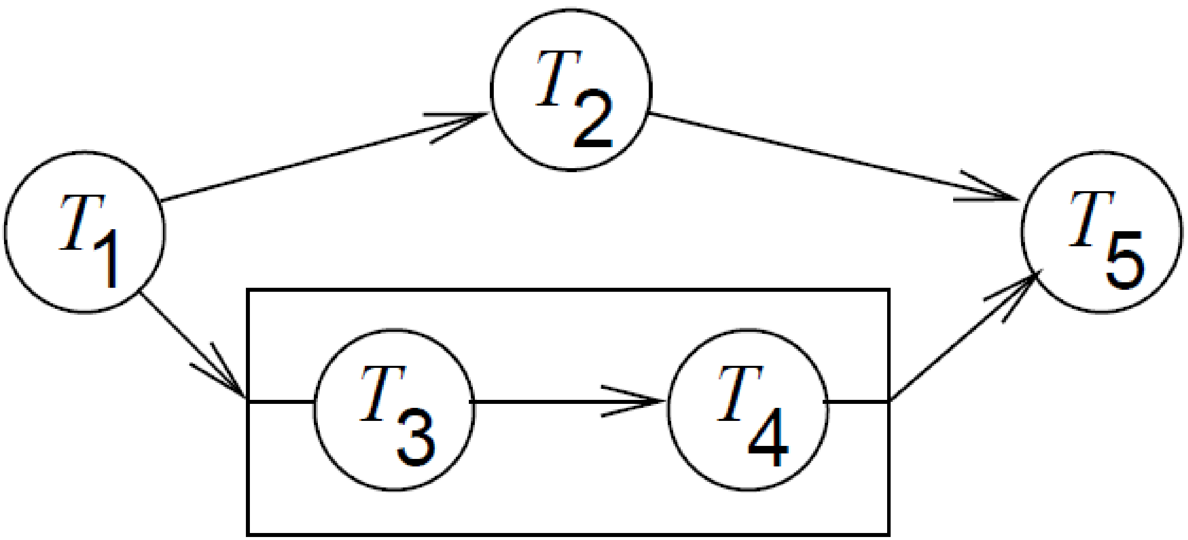
- Timing information



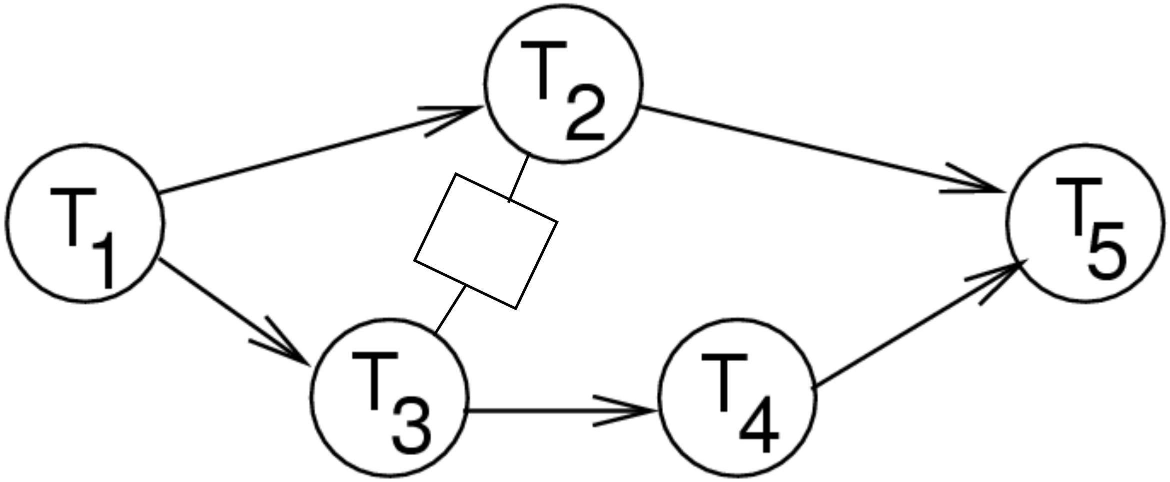
Dependence graph: I/O-information

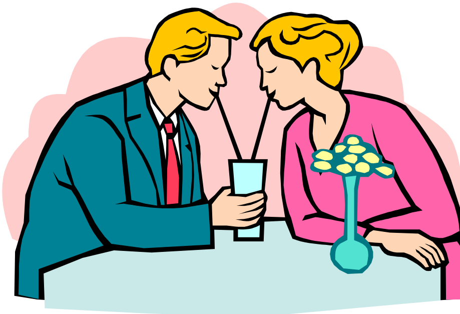


Dependence graph: Hierarchical task graphs

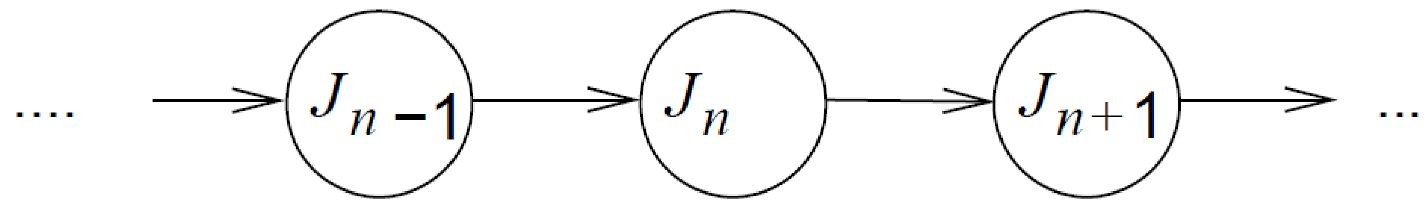


Dependence graph: Shared resources





Dependence graph: Periodic schedules



- A **job** is single execution of the dependence graph
- Periodic dependence graphs are infinite

Communication

- **Shared memory**

Comp-1 ⟷ memory ⟷ Comp-2

Variables accessible to several components/tasks.

Model mostly restricted to local systems.

Shared memory

```
thread a {
  u = 1; ..
  P(S)  //obtain mutex
  if u<5 {u = u + 1; ..}
  // critical section
  V(S)  //release mutex
}
```

```
thread b {
  ..
  P(S)  //obtain mutex
  u = 5
  // critical section
  V(S)  //release mutex
}
```

- Unexpected u=6 possible if P(S) and V(S) is not used (double context switch before execution of {u = u+1}
- S: semaphore
- P(S) grants up to n concurrent accesses to resource
- n=1 in this case (mutex/lock)
- V(S) increases number of allowed accesses to resource
- Thread-based (imperative) model should be supported by mutual exclusion for critical sections

Exercise

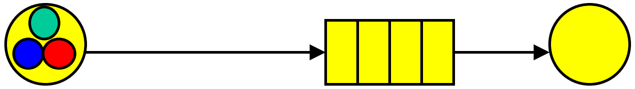
```
thread a {
  u = 3;               //op a1
P(s);
 if u<10               //op a2
     {u = u + 1; ..}   //op a3
  else u=5;            //op a4
V(s);
}

thread b {
  u = 2;               //op b1
P(s);
 if u<4                //op b2
     {u = u + 4; ..}   //op b3
  else u=10;           //op b4
V(s);
}
```

- Each thread is supposed to be executed once.
- Threads can be executed in any sequence and the execution can switch between the two threads at any time.
- For the sake of simplicity, we assume that each operation is executed in an atomic manner, i.e. there is no switch (called context switch) during the execution of ax and thread by.
- Which values of u are possible at the completion of both tasks?

Non-blocking/asynchronous message passing

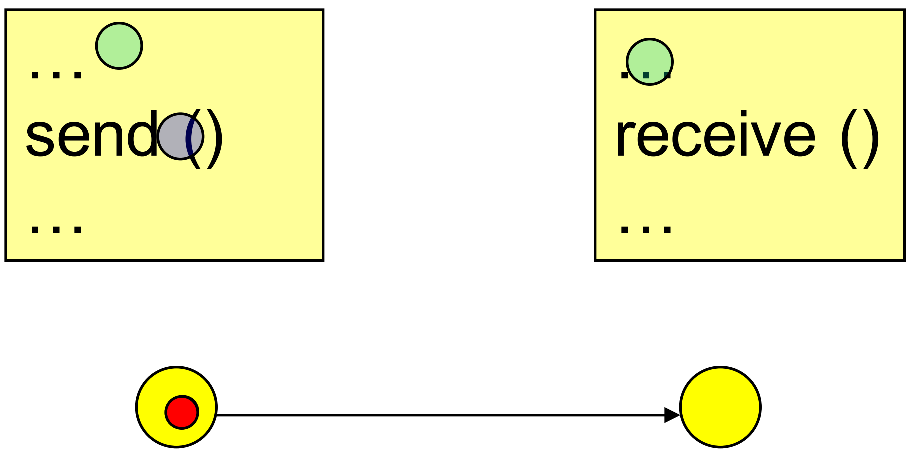
Sender does not have to wait until message has arrived;



Potential problem: buffer overflow

Blocking/synchronous message passing - *rendez-vous*

Sender will wait until receiver has received message



No buffer overflow, but reduced performance.

Organization of computations within the components (1)

- Finite state machines

Organization of computations within the components (2)

- Discrete event model

a 6
b 7
c 8

queue

time	5	10	13	15	19
action	a:=5	b:=7	c:=8	a:=6	a:=9

- Von Neumann model

Sequential execution, program memory etc.

Organization of computations within the components (3)

- Differential equations

$$\frac{\partial^2 x}{\partial t^2} = b$$

- Data flow
  (models the flow of data in a distributed system)

- Petri nets
  (models synchronization in a distributed system)

Summary

Requirements for specification & modeling

- Hierarchy
- ..
- Appropriate model of computation

Models of computation =

- Dependence graphs
- models for communication
- models of components