1. Introduction

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Embedded Software Group
Embedded System – Definition

- Many different definitions, some of them:
  - a computer system with a dedicated function within a larger mechanical or electrical system
  - ..., often with real-time computing constraints
  - A computing system that fulfills the task of monitoring and controlling the technical context
  - Without the computing system, the whole system is useless
Examples
In use by the ES group

NEAT power logger

Quadcopter / Emb. RTS

SOWNet G-Node

Power Cast
Embedded Software – Definition

- Many different definitions, some of them:
  - computer software written to control machines or devices that are not typically thought of as computers
  - A computer program that fulfills the task of monitoring and controlling the technical context
  - Without the right firmware, the whole system is useless
In this course …

- You will learn about:
  - Programming of embedded system
  - Real-time programming with RTOSs
- We will explore:
  - Principles of “good” embedded systems design
  - Time and complexity
- You will engage in low-level programming:
  - C language
  - Arduino microcontroller platform
## Course setup

<table>
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<th>TI2726-B</th>
<th>2016-2017</th>
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<tr>
<td>Credit points</td>
<td>5 EC</td>
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<tr>
<td>Lectures</td>
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<td>Exam</td>
<td>Chap 1, 4-10 + lect. notes C, FSM</td>
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The book

• Chapter 1 – Introduction to embedded systems (today)
• Chapter 4 – Interrupts
• Chapter 5 – Survey of software architectures
• Chapter 6 – Introduction to RTOS
• Chapter 7 – More OS services
• Chapter 8 – Basic design with RTOS
• Chapter 9 – Toolchain
• Chapter 10 – Debugging
ES Example – Telegraph
ES Example – Telegraph

- Out-of-order data
- Negotiate with multiple clients (print jobs) + status reqs.
- Adapt to different printers
- Response time to certain requests
- Data throughput / buffering
- Debugging and software updates

Telegraph is more complex than anticipated!
Underground Tank Monitoring Sys.

- Guard levels, detect leaks
- Extremely low-cost design (proc)
- Very simple arithmetic CPU - response time problem
- Model of normal drainage vs. leaking drainage
Cruise Control System

- Stabilize car speed when engaged
- Extremely low processor cycle budget
- Small control loop jitter due to other activities
- Reliable operation
Characteristics of Embedded Sys.

- No / restricted user interface
- Specific connectors for sensors/actuators
- Restricted memory size and processing power
- Predictable timing behavior
- Suitable for extreme operation environments
Typical Platform for ES

- Microcontroller
- 8 bit RISC Processor
- EEPROM & RAM
- UART (serial line)
- Timer
- A/D converter
- Digital I/O Lines
Typical Platform for ES

- PC/104
  - Typical PC platform
  - Flash, RAM, Drives
  - Many possible connectors and interfaces
  - Many available OSs
A different example - kilobot

M. Rubenstein - KiloBot: A Robotic Modules for Demonstrating Collective Behaviors, ICRA2010
Another Typical Platform for ES

- FPGA
- Build your own hardware (I/O)
- High performance
- High-level programming
Embedded Systems Boom

- Provides functionality (intelligence) of almost everything
- Annual growth 25-60% (Emb Linux > 60%)
- 100 x PC market
- Accounts for 25-40% costs in automotive
- Very large societal dependence
- Very high performance demands
- More and more integration of systems

www.linuxdevices.com
Embedded Software Boom

- **Software**
  - is more and more executed on standard hardware
- Accounts to a large extent for the
  - Product functionality
  - Intelligence / smartness
  - User ergonomics & look and feel
- Has an increasing added value
- Increased volume and complexity

50% Development Cost for Software alone!

90% of the Innovations Coming from Electronics & Software
CAN-Netw. Devices in a VW Phaeton
Embedded Software Crisis

- Functionality migrates from HW to SW
- Standard cores combined with FPGAs, rather than ASICs
- Programming-centred design (incl. HDLs)
- TV, mobile, car, .. 10+ MLOC code, exp. growth!
- Despite SW engineering: 1 – 10 bug / KLOC
- 100 Billion $ / yr on bugs (Mars Polar Lander, Mars Climate Orbiter, Ariane 5, Patriot, USS Yorktown, Therac-25, ... )
A new Embedded Software crisis?
Embedded Programming

- More difficult than “classical” programming
  - Interaction with hardware
  - Real-time issues (timing)
  - Concurrency (multiple threads, scheduling, deadlock)
  - Need to understand underlying RTOS principles
  - Event-driven programming (interrupts)
- Lots of (novice) errors (hence the crisis)
- That’s why we have this course already in 2nd year!
Embedded Programming Example

- Automatic sliding gate task (thread):

```c
for (;;) {
    // wait to open
    while (inp(sensor) != 1) ;
    out(door,OPEN);
    // wait to close
    while (inp(sensor) == 1) ;
    sleep(1000);
    // close after timeout
    out(door,CLOSE);
}
```

- Any issues with this code?
Specification: Finite State Machine

- Red arc missing from the specification
- Door can slam in your face!
Door Controller in VHDL

• VHDL: FSM in entity door_controller

• Advantages
  • Separate hardware: no sharing of a processor (no scheduling, no priorities)
  • Fast and synchronous programming model: high frequency clocked process with simple polling for \( s \) and \( t \)

• Disadvantages
  • VHDL too cumbersome / prohibitive for large applications
  • Lots of legacy code written in C
A VHDL Solution

process -- fsm
begin
  wait until rising_edge(clk);
  case state is
    when S0 => if (s = '1') then
              state <= S1;
    when S1 => if (s = '0') then
              state <= S2;
    when S2 => if (s = '1') then -- red arc in FSM
            state <= S1;
                  if (t = '1' and s = '0') then
                  state <= S0;
    end case;
  door <= '1' when (state != S0) else '0';
  timer_enable <= '1' when (state = S2) else '0';
end process;
A C Implementation

- C: FSM in a task door_controller

Advantages
- simple (sequential) programming model

Disadvantages
- can’t be invoked periodically by a high-frequency clock (timer) because of polling overhead
- busy waiting (polling) is not an option (see above) -> concurrent (event) programming (e.g., using interrupts and semaphores)

- So the while loops in the example code are wrong
- Only use a delay that is not based on busy wait
- Ergo: interrupt programming, using an RTOS
A better (but not ideal) C Solution

void isr_sensor(void)  // process sensor IRQ
{
    OS_Post(semaphore_event_on_s);  // signal s changed
}

void task_door_controller(void)
{
    for (;;) {
        OS_Pend(semaphore_event_on_s);  // wait for s = 1
        out(door,OPEN);
        do {
            OS_Pend(semaphore_event_on_s);  // wait for s = 0
            OS_Delay(1000);
        } while (inp(sensor) != 0);  // timeout
        out(door,CLOSE);
    }
}
Issues

- Efficient, no busy waiting any more (OS_Pend, OS_Delay)
- Still, code is not correct: interrupts (entering/leaving persons within delay period are not properly handled, and are only accumulated in semaphore (wrong))
- Cannot afford to just “sit” in a delay, AND ...
- The ability to simultaneously wait for two events (s or t):

```c
void isr_sensor_and_timer(void) {
  // handle both IRQs
  // either s or t
  // changed
  OS_Post(s_or_t);
}
```
void task_door_controller(void) {
    for (;;) {
        switch (state) {
            STDBY: OS_Pend(s_or_t); // wait for 0-1
                out(door,OPEN);
                state = OPEN;
            OPEN:  OS_Pend(s_or_t); // wait for 1-0
                timer_enable();
                state = TIMING;
            TIMING: OS_Pend(s_or_t); // wait 0-1 || t
                if (inp(sensor) == 0) { // timeout
                    out(door,CLOSE);
                    timer_disable();
                    state = STDBY;
                } else state = OPEN;
        }
    }
}
Course Organization

- Grade = 0.5 exam + 0.5 lab

- Lectures (tutti): weeks 2.1 – 2.6
  - Monday, 13.45 – 15.30
  - Wednesday, 10.45 – 12.30

- C programming (solo): weeks 2.2 – 2.4
  - Thursday, 08.45 – 12.30

- Robot Lab (duet): weeks 2.5 – 2.9
  - Mandatory presence!
  - Thursday 08:45 – 12:30 XOR Friday 13:45 – 17:30
Example exam questions

The “Embedded Software Crisis” refers to the “year 2000” bug.
  • true/false?

An embedded program can be coded as a finite state machine where interrupts trigger state transitions.
  • true/false?
Lab: C programming

- **Language**
  - C-syntax, pointers, memory management, ...

- **Tools**
  - Gdb, valgrind

- **Assignment (graded)**
  - Hash table with bucket lists
Lab: Robot line follower

- Hardware
  - Base
  - Arduino Atmega2560
  - Android phone

- Software
  - ROS
  - C
  - C++
Conclusion

- Embedded programming is not so easy
- Neither in C nor VHDL
- C:
  - Concurrency needed (seq. prog. model): RTOS support
  - Event programming needed: interrupts + RTOS support

- Learn the basics of interrupt programming & RTOS (in C)
- Learning is (lots of) programming!
- Lab: C (solo) + Robot (duet)
Enrollment

- C programming (solo)
  - Tutorial (wk 2) – WebLab
  - Tools (wk 3) + hashmap (wk 4) – CPM

- Robot lab (duet)
  - Line follower – CPM

- Register at
  - Blackboard (announcements, slides, etc.)
  - WebLab
  - CPM: google form (team of 2, Thur/Friday availability)