

The Importance of Timing

- In “hard real-time” systems, meeting timing requirements is just as important as getting the logic of the functionality correct
- In “soft real-time” systems, meeting timing requirements is important, but it is usually treated as a probabilistic requirement
- The pacemaker is definitely a hard real-time system!

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Functional Timing Reqs - 1

- We need to examine functional timing requirements in more detail.
- As an example, consider a sensor trip that depends on a sensor (signal) being in a trip state for a sustained period of time.

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Functional Timing Reqs - 2

$f_HTLFSentrip_i, i=1,..,4$
 {For each $i = 1,..,4$ }

Condition		Result
	$f_HTLFSentrip_i$	
$t_{now} \geq k_HTLFDelay$	$(f_HTLFImsentrip_i = e_Trip)$ Held for $(k_HTLFDelay)$ <i>{Immediate sensor trip active for at least past k_HTLFDelay time period}</i>	e_Trip
	NOT [$(f_HTLFImsentrip_i = e_Trip)$ Held for $(k_HTLFDelay)$] <i>{Immediate sensor trip not active for at least one instant in past k_HTLFDelay time period}</i>	$e_NotTrip$
$t_{now} < k_HTLFDelay$	$(f_HTLFImsentrip_i = e_Trip)$ Held for (t_{now}) <i>{Immediate sensor trip active since initialization}</i>	e_Trip
	NOT [$(f_HTLFImsentrip_i = e_Trip)$ Held for (t_{now})] <i>{Immediate sensor trip not active for at least one instant since initialization}</i>	$e_NotTrip$

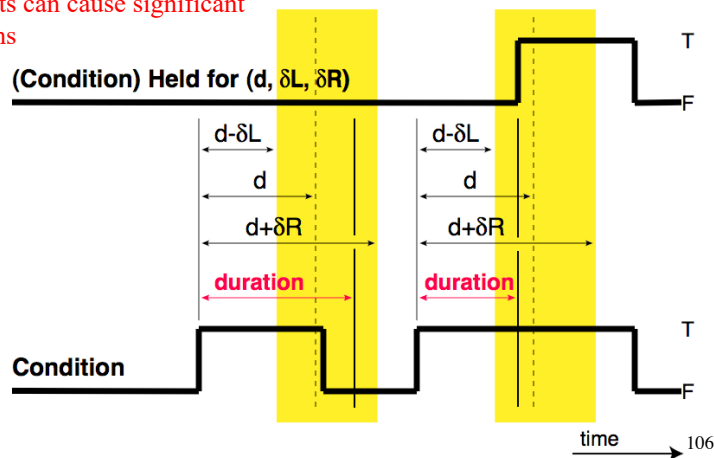
So - what is this "Held for" thing?

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Functional Timing Reqs - 3

Allowing tolerances on timing constants can cause significant problems



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Definition of Held for

(Condition: bool) Held for ($d: \mathbb{R}^{>0}$, $\delta L, \delta R: \mathbb{R}^{\geq 0}$): bool

duration(Condition: bool): $[d - \delta L, d + \delta R]$

Event_start_time(Condition: bool): $\mathbb{R}^{\geq 0}$

Initially:

duration = any value in $[d - \delta L, d + \delta R]$; Event_start_time.₁ = 0; Condition.₁ = False

duration		Event_start_time
(Condition = True) & (Condition. ₁ = False)		Any value in $[d - \delta L, d + \delta R]$
(Condition = False) or (Condition. ₁ = True)		No Change

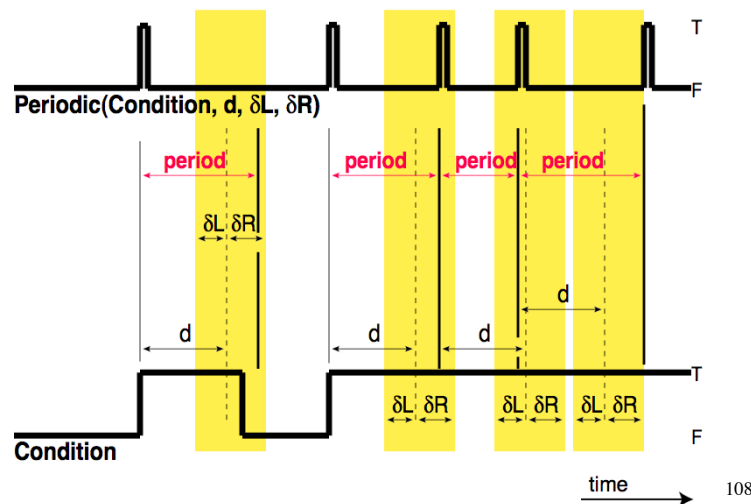
Held for	
Condition = True	$t_{\text{now}} - \text{Event_start_time} \geq \text{duration}$
	$t_{\text{now}} - \text{Event_start_time} < \text{duration}$
Condition = False	

Held for
True
False
False

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Another General FTR

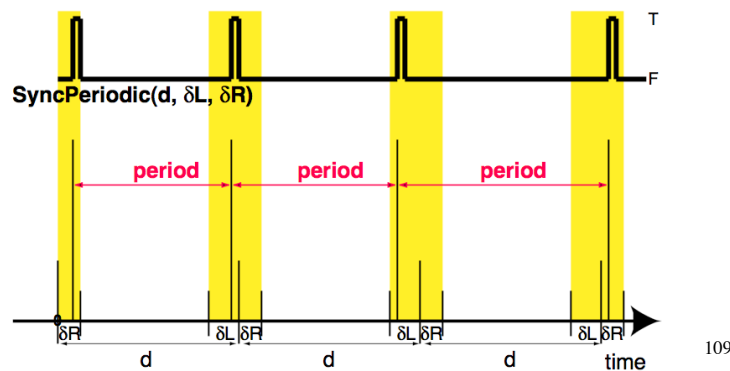


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And Another General FTR

This one is synchronized with an external clock.



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Functional Timing Requirements

- Functional timing requirements are timing requirements that are directly related to the required behaviour of the application
 - So, “Held for”, “Periodic” and “SyncPeriodic” are examples of templates describing functional timing requirements
 - Other common functional timing requirements can be modeled in similar fashion
 - These requirements are interpreted within the constraints of the governing model, in our case the discrete time FSM with arbitrarily small clock-tick. This describes *idealized behaviour* with the capability of including tolerances on all timing durations

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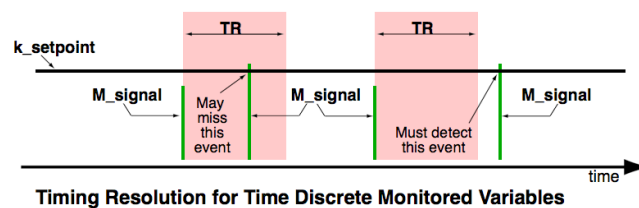
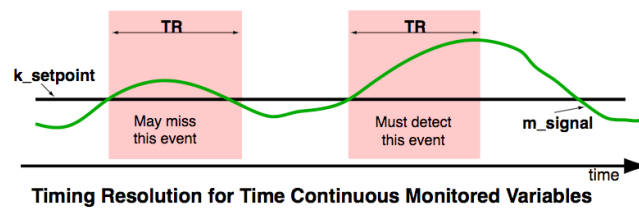
Performance Timing Requirements

- Idealized behaviour totally ignores the fact that an implementation cannot continuously monitor sensor values and requires a finite, non-zero amount of time to process its results
- To complete the description of the required behaviour, a requirements document must also specify the performance tolerances that are allowed in meeting functional timing requirements
- We identify two different performance timing requirements
 - Timing Resolution
 - Response Allowance

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Timing Resolution



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Response Allowance

- Response Allowance
 - The Response Allowance (RA) for a controlled-monitored variable pair specifies an allowable processing delay
 - Each controlled variable must have an RA specified for it. The RA applies to the controlled variable and the particular monitored variable on which the controlled variable's behaviour depends
 - The RA is measured from the time the event *actually occurred in the physical domain*, until the time the value of the controlled variable is generated and *crosses the application boundary into the physical domain*

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