

# **Real-time system for air traffic monitoring and control**

COEN 320: Introduction to Real-Time Systems - Fall 2024

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We certify that this submission is the original work of members of the group and meets the  
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## 1. Objectives

The objective of this project is to design, implement, and test a real-time Air Traffic Control (ATC) system. The primary goals include ensuring the safe separation of aircraft within a specified en-route airspace, enabling real-time monitoring of aircraft positions and speeds, and allowing operators to issue commands to adjust aircraft trajectories. This system aims to improve airspace safety and efficiency through modular design and robust real-time performance.

## 2. High-Level System Description

### 2.1 Purpose

The Air Traffic Control (ATC) system is designed to monitor and manage aircraft within a specified en-route airspace to ensure safe separation and efficient navigation. The system's core objectives are:

- **Safe Separation:** Ensuring minimum safe distances between aircraft both horizontally and vertically.
- **Real-Time Monitoring:** Continuously tracking each aircraft's position, speed, and altitude to allow timely detection of potential safety violations.
- **Operator Control:** Enabling the operator to issue commands, such as adjusting speed or altitude, to individual aircraft based on observed conditions.

The system is composed of several interconnected modules that collectively handle data acquisition, processing, and display, enabling the operator to manage the controlled airspace. These modules include radar for position data acquisition, a computer system for data processing and safety validation, an operator console for command issuance, and a data display for visual feedback. This system operates in real time, with continuous position updates and safety checks to ensure rapid detection of potential conflicts.

## 2.2 System Components

The ATC system consists of several subsystems that interact to provide seamless aircraft monitoring and control. The major components include:

- **Primary and Secondary Radars:**
  - **Primary Surveillance Radar (PSR)** emits radio waves that reflect off objects in the airspace. It provides a raw position of aircraft, useful for general detection.
  - **Secondary Surveillance Radar (SSR)** interacts with aircraft transponders, providing detailed information, such as flight ID, altitude, and speed.
- **Computer System:**
  - Manages calculations related to the safe separation of aircraft and triggers alerts if violations are detected.
  - Processes radar data and checks aircraft positions against separation criteria, sending alerts for potential conflicts.
- **Operator Console:**
  - Provides an interface for the ATC operator to issue commands to the aircraft, such as adjusting their flight parameters (speed, altitude, position).
  - Enables the operator to request additional information on specific aircraft for closer monitoring.
- **Communication System:**
  - Facilitates data transmission between the ATC system and aircraft, enabling command relay to the aircraft for necessary adjustments in flight parameters.

## 2.3 Airspace and Separation Requirements

The system is designed to control an en-route airspace defined as a 3D rectangular area, with a height of 25,000 units and a horizontal plane of 100,000 x 100,000 units. The separation requirements dictate that aircraft must maintain a minimum vertical distance of 1,000 units and a horizontal distance of 3,000 units from other aircraft to avoid collision risk.

### 3. Analysis

The project requirements define the creation of a simplified Air Traffic Control (ATC) system, primarily centered on en-route control. To facilitate implementation, the following assumptions have been established:

- **Aircraft Behavior:** All aircraft are assumed to maintain a constant speed and altitude unless instructed otherwise by the operator.
- **Separation Constraints:** A minimum separation of 1,000 units vertically and 3,000 units horizontally is maintained to ensure safety.
- **System Periodicity:** Core tasks, such as radar sweeps and safety checks, operate periodically, with dynamic adjustments based on the level of airspace congestion.

## 4. Software Design and Architecture

### 4.1 Module Overview

The software implementation of the ATC system is divided into multiple modules, each responsible for specific functions within the system:

- **Aircraft.cpp:**
  - Defines the **Aircraft** class, handling attributes like position, speed, and ID.
  - Each aircraft is represented as a periodic task that updates its position every second and responds to radar queries, sending its ID, speed, and position.
- **ATC.cpp:**
  - Implements the core ATC logic, including monitoring aircraft in the airspace, checking for safety violations, and managing the hand-off process as aircraft enter or exit the controlled area.
  - Includes functions for maintaining a list of active aircraft and evaluating separation constraints between them.

- **CommunicationSystem.cpp:**
  - Handles the communication protocol between the ATC and the aircraft.
  - Facilitates the sending of commands from the operator to aircraft, allowing control over their movement parameters.
- **ComputerSystem.cpp:**
  - Contains algorithms to periodically compute aircraft positions and detect separation violations.
  - Issues alerts if a potential safety conflict is detected or is projected to occur within a predefined time frame.
- **cTimer.cpp:**
  - Manages timing operations for various periodic tasks, including updating aircraft positions and performing radar sweeps at intervals.
- **DataDisplay.cpp:**
  - Visualizes the airspace for the operator, displaying the current positions and IDs of all active aircraft, as well as any alert indicators for safety violations.
- **OperatorConsole.cpp:**
  - Captures user inputs for adjusting aircraft parameters, such as issuing speed, altitude, and position commands.
  - Sends operator requests to the **ComputerSystem**, which then processes and relays these to the aircraft.
- **Radar.cpp:**
  - Simulates radar functionality by querying each aircraft in the airspace for updated position and identification data.
  - Provides real-time data to the **ComputerSystem** for processing and visualization.

## 4.2 Data Flow and Interactions

The modules interact in the following sequence:

1. **Radar Scanning:** The **Radar** module periodically queries all aircraft for updated information, receiving their ID, position, and speed.
2. **Computer System Processing:** Using radar data, the **ComputerSystem** calculates potential conflicts by checking separation constraints. If an alert is triggered, it notifies the **DataDisplay** and prepares data for operator review.
3. **Data Display:** Visual information on the airspace status is presented to the operator via **DataDisplay**, highlighting any aircraft approaching unsafe proximity.
4. **Operator Command Relay:** The **OperatorConsole** allows the operator to send commands, which are transmitted by **CommunicationSystem** to the appropriate aircraft to alter their trajectory as needed.

## 5. Modeling of the ATC System

### 5.1 Aircraft Handling

Each aircraft is represented as an independent task (thread or process), responsible for:

- **Position Updates:** Every second, each aircraft updates its position based on its current speed and direction.
- **Radar Responses:** When queried by the **Radar** module, the aircraft responds with its ID, speed, and position, allowing real-time tracking by the ATC system.

### 5.2 Detection Algorithms

The ATC system includes an algorithm for **distance calculations**:

- **Horizontal Separation:** Ensures a minimum horizontal distance of 3,000 units between any two aircraft.
- **Vertical Separation:** Maintains a minimum vertical distance of 1,000 units.
- If either of these constraints is violated, an alert is triggered in the **ComputerSystem**, which notifies the operator to take corrective action.

The **timing and frequency of position checks** can be dynamically adjusted based on congestion within the airspace. Operators can adjust the check-ahead time (**n** seconds) to control the horizon of violation detection, enabling the system to respond flexibly to varying traffic loads.

### 5.3 System Periodicity and Timing

The ATC system operates in a cyclic manner with periodic checks:

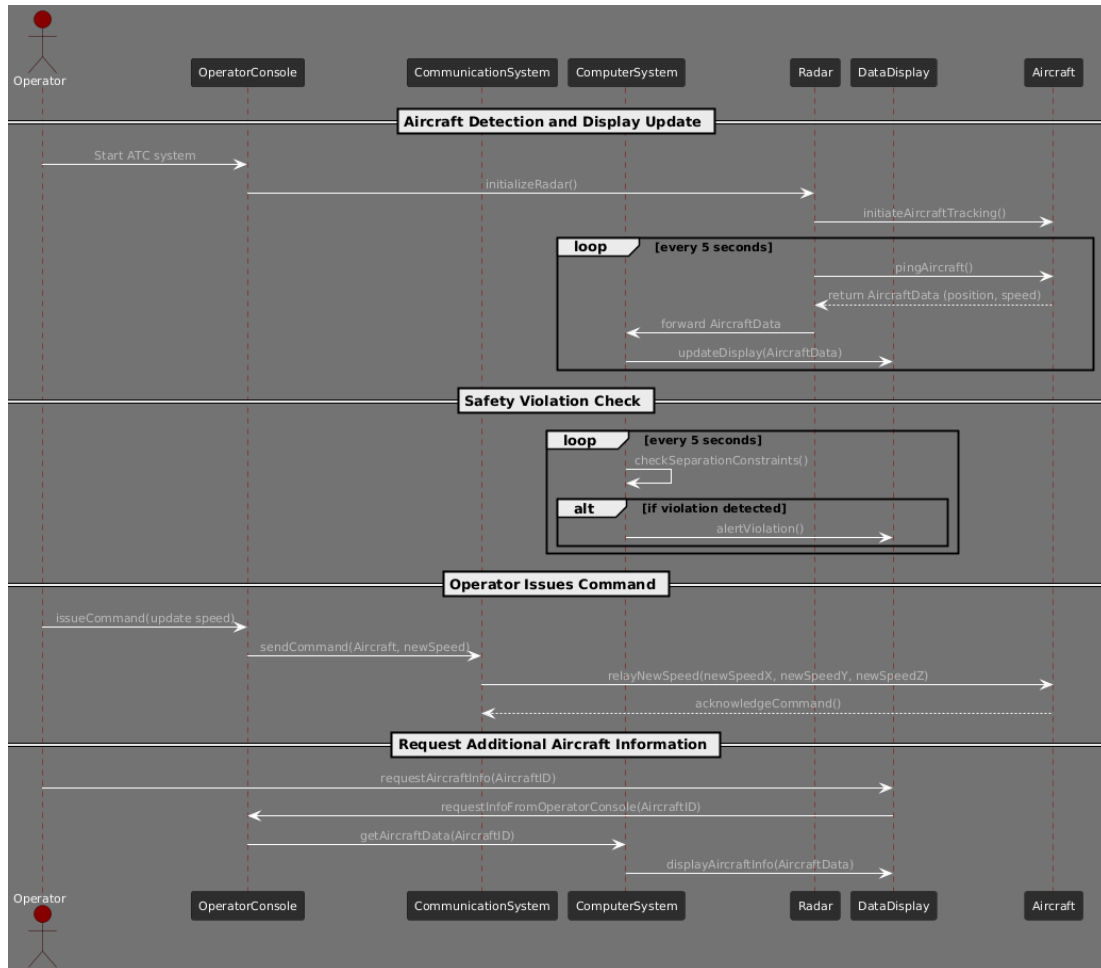
- **Radar Sweep:** The **Radar** queries aircraft every 5 seconds for updated position data.
- **Safety Checks:** The **ComputerSystem** evaluates separation constraints at defined intervals and emits alerts as necessary.
- **Data Storage:** Every 30 seconds, the system logs airspace data for historical tracking and analysis.
- **Alarm Threshold:** Alerts are triggered if a violation is detected within 3 minutes, allowing operators sufficient time for response.



## 5.4 Class Diagram



### 3.5 System Sequence Diagram



This interaction diagram demonstrates the ATC system's real-time operational flow, focusing on aircraft monitoring, safety management, and responsive operator control. Initially, the operator starts the system, which initiates radar tracking and aircraft monitoring. The **Radar** component continuously pings each aircraft at regular intervals, gathering position and speed data that is forwarded to the **ComputerSystem**. This information is updated in the **DataDisplay**, providing the operator with a current overview of the airspace. Simultaneously, the **ComputerSystem** checks for safety violations to ensure minimum separation between aircraft, and any detected violation triggers an alert to **DataDisplay**.

In addition, the diagram illustrates how operators can issue commands to individual aircraft. For example, the operator may update an aircraft's speed through the **OperatorConsole**, which relays the command to the **CommunicationSystem** and then to the aircraft, receiving an acknowledgment upon successful delivery. Finally, if additional details are required for a specific aircraft, the operator requests this through **DataDisplay**, which gathers data from the **ComputerSystem** and displays it. This interaction loop enables the ATC system to maintain continuous monitoring, enforce safety protocols, and allow operator-driven control adjustments to manage the airspace effectively.

## 6. Technologies and Tools Used

The ATC system is developed in C++ and is designed to run on the QNX real-time operating system (RTOS), utilizing the QNX Momentics IDE. Momentics provides a development environment specifically designed for real-time applications, supporting essential features like real-time thread management, scheduling, and inter-process communication.

- **QNX RTOS:** QNX ensures real-time scheduling, crucial for the system's timing requirements. Given the safety-critical nature of air traffic control, QNX's deterministic behavior is ideal for handling high-priority tasks like aircraft separation checks and radar data processing.
- **Momentics IDE:** This integrated development environment provides advanced debugging tools, real-time performance analysis, and multi-core optimization, which are essential for developing and maintaining a real-time system like the ATC.
- **POSIX Threads (Pthreads):** The ATC system uses POSIX threads to implement multithreading across various tasks. Each aircraft runs as a separate thread, allowing concurrent position updates and real-time interaction with the radar and communication systems.

- **Inter-Process Communication (IPC):** QNX's native inter-process communication mechanisms allow modules to communicate efficiently. For example, radar data is shared with the computer system in real time, and commands from the operator console are relayed to specific aircraft without delay.

## 7. Testing and Results

### 7.1. Air Traffic Control System

The Air Traffic Control (ATC) system was rigorously tested under varying operational conditions to evaluate its performance and ensure compliance with real-time constraints. Testing scenarios simulated different levels of airspace congestion by adjusting the number of aircraft and the intensity of input/output (IO) operations. Key metrics such as task execution times and the system's response to safety violations were analyzed to determine the feasibility of Rate Monotonic (RM) fixed-priority scheduling. Below, the results for each congestion scenario are summarized, along with relevant code explanations showcasing how the system handles critical tasks. Test cases for all congestion levels are included in the code and saved on the local VM.

- **Low Congestion:** This scenario involved three aircraft with minimal IO traffic and sporadic updates. The `separationCheck` function verified the separation distance between all aircraft pairs. Safety violations were minimal, confirming that the system efficiently executed tasks under low congestion.

```
void ComputerSystem::separationCheck() {
    name_attach_t *attach;
    string attachPoint = string(ATTACH_POINT) + "_separation";

    if ((attach = name_attach(NULL, attachPoint.c_str(), 0)) == NULL) {
        perror("Error occurred while creating the attach point separation");
    }

    int n = 180; // Number of seconds to predict into the future
    int p = 5; // Interval for checking separation
    SeparationData separationCommand;
    cTimer timer(p, 0);

    while (true) {
        alarm();
        int rcvid;
        for (int i = 0; i < 2; i++) { // Attempt to receive a message up to 2 times
            if ((rcvid = MsgReceive(attach->chid, &separationCommand, sizeof(separationCommand), NULL)) != -1) {
                n = separationCommand.n_seconds;
                timer.setTimerSpec(separationCommand.p_interval, 0);
                cout << "Message Received N: " << n << " P:" << separationCommand.p_interval << endl;
                MsgReply(rcvid, EOK, NULL, 0);
                i = 200; // Exit loop after receiving a message
            }
        }

        // Define separation constraint dimensions
        string output = "";
        int width = 3000;
        int height = 1000;
    }
}
```

```

// Define separation constraint dimensions
string output = "";
int width = 3000;
int height = 1000;

for (Aircraft* a : aircrafts) {
    int x = a->getPositionX() + n * a->getSpeedX();
    int y = a->getPositionY() + n * a->getSpeedY();
    int z = a->getPositionZ() + n * a->getSpeedZ();

    for (Aircraft* b : aircrafts) {
        if (a != b) {
            int bx = b->getPositionX() + n * b->getSpeedX();
            int by = b->getPositionY() + n * b->getSpeedY();
            int bz = b->getPositionZ() + n * b->getSpeedZ();

            // Check separation constraints
            if (bx > x + width || bx < x - width || by > y + width || by < y - width || bz > z + height || bz < z - height) {
                continue;
            }

            // Append message if separation constraint violation is detected
            output.append(" " + std::to_string(a->getFlightId()) + " close to " + std::to_string(b->getFlightId()) + "\n");
        }
    }
}

if (output != "") {
    cout << "SEPARATION CONSTRAINT VIOLATION AT CURRENT TIME + " << n << " seconds " << endl;
    cout << output;
}

sleep(p);
}

```

This function checks the separation distance between all pairs of aircraft. In low congestion, violations are minimal, ensuring the system handles tasks efficiently.

- Medium Congestion:** This scenario included five aircraft and moderate IO traffic with frequent radar updates. Under medium congestion, the **separationCheck** function played a critical role in detecting and alerting safety violations amidst increased IO activity. Radar sweeps prompted frequent position updates, leading to potential task queuing. The system successfully handled the increased load, maintaining RM scheduling feasibility.
- High Congestion:** In this scenario, over seven aircraft were tested with high IO activity, causing task overlap and more frequent safety alerts. Overlapping tasks, such as radar sweeps and safety checks, occasionally delayed responses, pushing the system toward its feasibility boundary. While RM scheduling remained effective under low and medium congestion, high congestion exposed delayed task execution, testing the system's performance limits.

Despite increasing loads, Low and Medium congestions have the system meet Rate Monotonic (RM) scheduling feasibility. Whereas High congestion has the system approaching its feasibility boundary, reflected in delayed task execution and overlapping tasks.

## 7.2. Operator Command Testing.

- Aircraft Information Display.

```
// Displays specific aircraft data based on received commands
void* OperatorConsole::displayAircraftData() {
    name_attach_t *attach;

    // Generate the unique attach point name
    string attachPointInner = string(ATTACH_POINT) + "info";

    // Create an attach point for the data display command
    if ((attach = name_attach(NULL, attachPointInner.c_str(), 0)) == NULL) {
        perror("Error occurred while creating the attach point displayAircraftData");
        return (void*)EXIT_FAILURE;
    }

    AircraftData aircraftCommand;
    while (true) {
        int rcvid = MsgReceive(attach->chid, &aircraftCommand, sizeof(aircraftCommand), NULL);

        if (rcvid == -1) { // Error condition
            break;
        }

        // Display data if command type matches expected values
        if (aircraftCommand.header.type == 0x04 && aircraftCommand.header.subtype == 0x02) {
            int coid;
            if ((coid = name_open(ATTACH_POINT, 0)) == -1) {
                perror("Error occurred while attaching the channel DISPLAYAIRCRAFTDATA FUNCTION");
                return (void*)EXIT_FAILURE;
            }

            aircraftCommand.header.type = 0x02;
            aircraftCommand.header.subtype = 0x01;

            // Send aircraft data expecting no response
            if (MsgSend(coid, &aircraftCommand, sizeof(aircraftCommand), NULL, 0) == -1) {
                cout << "Error while sending the message for aircraft CSOP " << ": " << strerror(errno) << endl;
                name_close(coid);
                return (void*)EXIT_FAILURE;
            }

            MsgReply(rcvid, EOK, NULL, 0);
            name_detach(attach, 0);

            break;
        }
    }

    return EXIT_SUCCESS;
}
```

---

The `displayAircraftData` method receives and processes aircraft data via an attach point. It continuously listens for incoming messages and logs interactions in the console. Upon receiving valid requests, it provides accurate real-time data on aircraft position and speed.

Example:

A request for Flight 2's data accurately displayed its real-time position and speed. The system demonstrated event-driven updates, where information consistency between outputs confirmed sporadic task execution rather than fixed intervals.

```
1
Enter Flight Id: 2
Enter your choice... (1 to display an aircraft's info, 2 to update an aircraft's speed, 3 for separation constraint)

-----
Flight ID      Pos X      Pos Y      Pos Z      Speed X      Speed Y      Speed Z
      2      8250         0         0        250         0         0
-----
Alarm: safety violation will happen within 3 minutes
2 close to 5

=====
Map Update at Sat Nov 16 20:00:28 2024
=====
      0 1000 2000 3000 4000 5000 6000 7000 8000 9000 10000 11000 12000 13000 14000 15000 16000 17000 18000 19000 20000 21000 22000 23000 24000
0  --  --  --  --  F4  F3  --  --  --  F2  --  --  --  --  --  --  --  --  --  --  --  --  --  --
1000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
2000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
3000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
4000 --  --  --  --  F1  --  --  --  --  F5  --  --  --  --  --  --  --  --  --  --  --  --  --
5000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
6000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
7000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
8000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
9000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
10000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
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18000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
19000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
20000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
21000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
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23000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
24000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
```

In this example, we can see that Flight 2 is accurately described, showcasing its real-time position and speed data. The system efficiently provides detailed information, ensuring precise monitoring and tracking of the aircraft. This provides insight that the task is sporadic, as the information remains consistent with the next map output, indicating that updates are event-driven rather than occurring at fixed intervals.

- Update the Aircraft Speed.

```
// Updates the speed of an aircraft based on received commands
void* OperatorConsole::updateAircraftSpeed() {
    name_attach_t *attach;

    // Generate the unique attach point name
    string attachPointInner = string(ATTACH_POINT) + "inner_transfer";

    // Create an attach point for the update command
    if ((attach = name_attach(NULL, attachPointInner.c_str(), 0)) == NULL) {
        perror("Error occurred while creating the attach point updateAircraftSpeed");
        return (void*)EXIT_FAILURE;
    }

    AircraftData aircraftCommand;
    while (true) {
        int rcvid = MsgReceive(attach->chid, &aircraftCommand, sizeof(aircraftCommand), NULL);

        if (rcvid == -1) { // Error condition
            break;
        }

        // Update speed if command type matches expected values
        if (aircraftCommand.header.type == 0x04 && aircraftCommand.header.subtype == 0x01) {
            MsgReply(rcvid, EOK, NULL, 0);
            name_detach(attach, 0);

            // Establish connection for the update
            int coid;
            if ((coid = name_open(ATTACH_POINT, 0)) == -1) {
                perror("Error occurred while attaching the channel UPDATEAIRCRAFTSPEED FUNCTION");
                return (void*)EXIT_FAILURE;
            }

            aircraftCommand.header.type = 0x02;
            aircraftCommand.header.subtype = 0x00;

            // Send updated speed command expecting no response
            if (MsgSend(coid, &aircraftCommand, sizeof(aircraftCommand), NULL, 0) == -1) {
                cout << "Error while sending the message for aircraft CSOP " << ": " << strerror(errno) << endl;
                name_close(coid);
                return (void*)EXIT_FAILURE;
            }

            break;
        }
    }

    return EXIT_SUCCESS;
}
```

The `updateAircraftSpeed` method processes speed update commands, validates the data, and applies changes to aircraft speed and position. These adjustments are reflected in the console logs and subsequent map outputs.

Example:

When Aircraft F3's speed was set to 251 (X-axis), it gradually closed the distance to Aircraft F2 at 250. After reducing F3's speed to 150, the map outputs showed F3 falling behind, increasing its distance from F2. This dynamic response demonstrated successful speed adjustment and real-time tracking of aircraft behavior.



[illegible][illegible][illegible]

When F3's X-axis speed is reduced to 150, the next three map outputs show a significant shift in the aircraft's behavior. F3 starts to fall behind F2, creating an increasing gap between the two. This clearly indicates that the speed adjustment successfully slowed down F3. This example demonstrates that the task is sporadic, as the speed update occurred and was reflected in the subsequent map output.

```

150
Enter SpeedY: 0
Enter SpeedZ: 0
Enter your choice... (1 to display an aircraft's info, 2 to update an aircraft's speed, 3 for separation constraint)

=====
Map Update at Sat Nov 16 20:37:09 2024
=====
      0  1000  2000  3000  4000  5000  6000  7000  8000  9000 10000 11000 12000 13000 14000 15000 16000 17000 18000 19000 20000 21000 22000 23000 24000
0  --  --  --  --  --  --  --  --  --  --  --  --  --  --  F3  --  --  --  --  F2  --  --  --  --  --
1000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
2000 --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --  --
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Map Update at Sat Nov 16 20:37:14 2024
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Map Update at Sat Nov 16 20:37:14 2024
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```

- Update the Separation Constraints.

The `separationCheck` function predicts future aircraft positions based on speed and current location, ensuring safe separation. It checks for potential violations within a specified prediction window (N seconds) at regular intervals (P seconds).

Example:

Initially, predictions were set for 180 seconds with checks every 5 seconds. These parameters were updated to a 150-second prediction window and a 2-second interval. Subsequent map outputs showed the shorter prediction window, with alarms still actively monitoring potential violations. This showcased the system's ability to dynamically adjust and enforce safety constraints.

Alarm: safety violation will happen within 3 minutes  
 2 close to 3  
 3 close to 2  
 SEPARATION CONSTRAINT VIOLATION AT CURRENT TIME + 180 seconds  
 2 close to 3  
 3 close to 2

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Map Update at Sat Nov 16 22:01:13 2024

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	0	1000	2000	3000	4000	5000	6000	7000	8000	9000	10000	11000	12000	13000	14000	15000	16000	17000	18000	19000	20000	21000	22000	23000	24000
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Enter N seconds for separation constraint: 150

Enter interval for separation constraint: 2  
 Alarm: safety violation will happen within 3 minutes  
 2 close to 3  
 3 close to 2  
 Message Received N: 150 P:2

Enter your choice... (1 to display an aircraft's info, 2 to update an aircraft's speed, 3 for separation constraint)

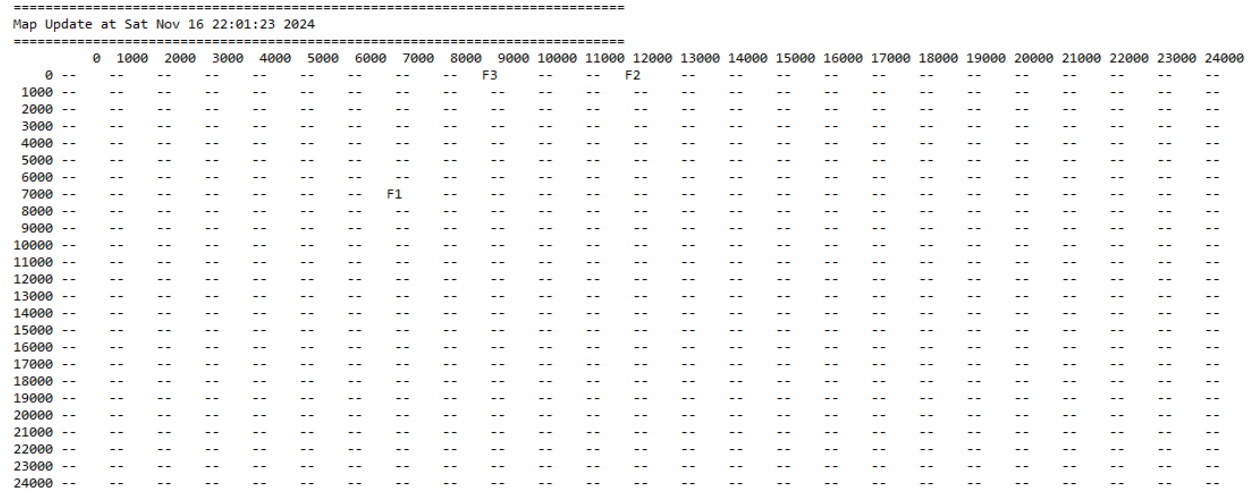
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Map Update at Sat Nov 16 22:01:18 2024

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	0	1000	2000	3000	4000	5000	6000	7000	8000	9000	10000	11000	12000	13000	14000	15000	16000	17000	18000	19000	20000	21000	22000	23000	24000
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Alarm: safety violation will happen within 3 minutes  
 2 close to 3  
 3 close to 2



The consecutive three map outputs above provide an overview of updating the separation checks timeline. We observe that the separation constraints were updated to 150 seconds, significantly reducing the prediction window. While the constraints no longer appear on the map due to the shorter timeline, they still trigger alarms, indicating active monitoring of potential violations.

## 7.3 Timing and Execution Times

Process Name	Running Time	Running Time (Sum)	Ready Time	Ready Time (Sum)
✓ ATC	21ms122us	21ms122us	40ms455us	47ms638us
mapInitializeThread	10ms818us	10ms818us	34ms34us	34ms34us
AircraftOperationStart	3ms464us	3ms464us	1ms745us	1ms745us
mapDisplayThread	1ms569us	1ms569us	3ms634us	3ms634us
Thread 2	960us633ns	960us633ns	255us504ns	255us504ns
separationThread	843us215ns	843us215ns	201us100ns	201us100ns
userInputThread	799us891ns	799us891ns	907us960ns	907us960ns
computerSystemThread	253us214ns	253us214ns	1ms477us	1ms477us
AircraftDisplay	141us234ns	141us234ns	27us406ns	27us406ns
Thread 3	112us796ns	112us796ns	960us19ns	960us19ns
updateAircraftSpeedThread	109us866ns	109us866ns	245us914ns	245us914ns
dataDisplayThread	99us478ns	99us478ns	500us488ns	500us488ns
Thread 4	91us411ns	91us411ns	1ms15us	1ms15us
AircraftDisplay	87us181ns	87us181ns	26us132ns	26us132ns
radarThread	86us510ns	86us510ns	534us722ns	534us722ns
AircraftDisplay	79us744ns	79us744ns	44us105ns	44us105ns

AircraftDisplay	72us310ns	72us310ns	19us442ns	19us442ns
AircraftDisplay	71us229ns	71us229ns	55us14ns	55us14ns
AircraftDisplay	68us965ns	68us965ns	17us611ns	17us611ns
AircraftDisplay	67us154ns	67us154ns	18us603ns	18us603ns
AircraftDisplay	66us244ns	66us244ns	30us331ns	30us331ns
AircraftDisplay	64us435ns	64us435ns	17us122ns	17us122ns
updateAircraftSpeedThread	58us304ns	58us304ns	179us277ns	179us277ns
AircraftDisplay	55us605ns	55us605ns	53us851ns	53us851ns
AircraftDisplay	52us560ns	52us560ns	29us745ns	29us745ns
displayDataThread	52us543ns	52us543ns	216us596ns	216us596ns
AircraftDisplay	49us794ns	49us794ns	16us432ns	16us432ns
AircraftDisplay	44us947ns	44us947ns	97us699ns	97us699ns
AircraftDisplay	41us723ns	41us723ns	38us355ns	38us355ns
AircraftInfo	40us914ns	40us914ns	66us596ns	66us596ns
AircraftDisplay	40us336ns	40us336ns	35us793ns	35us793ns
AircraftDisplay	39us663ns	39us663ns	84us326ns	84us326ns

AircraftDisplay	35us444ns	35us444ns	77us596ns	77us596ns
AircraftDisplay	33us868ns	33us868ns	31us440ns	31us440ns
AircraftDisplay	32us742ns	32us742ns	51us656ns	51us656ns
AircraftDisplay	32us698ns	32us698ns	33us197ns	33us197ns
AircraftDisplay	32us148ns	32us148ns	32us873ns	32us873ns
SpeedUpd	32us66ns	32us66ns	35us682ns	35us682ns
AircraftDisplay	31us981ns	31us981ns	51us722ns	51us722ns
AircraftDisplay	27us524ns	27us524ns	74us603ns	74us603ns
AircraftDisplay	27us154ns	27us154ns	61us911ns	61us911ns
AircraftDisplay	27us110ns	27us110ns	64us554ns	64us554ns
AircraftDisplay	26us747ns	26us747ns	35us99ns	35us99ns
AircraftDisplay	25us42ns	25us42ns	56us691ns	56us691ns
AircraftDisplay	24us713ns	24us713ns	24us460ns	24us460ns
AircraftDisplay	24us289ns	24us289ns	42us757ns	42us757ns
AircraftDisplay	21us877ns	21us877ns	33us165ns	33us165ns
AircraftDisplay	19us381ns	19us381ns	77us434ns	77us434ns

We can observe the **running time** and **ready time** of the majority of the threads that were created. In the beginning, the tasks requiring the most running time and encountering higher ready times are those involved in the **initial loading phase**. This is because these tasks are responsible for initializing the system, which may include creating other threads, setting up resources, or handling Input/Output (I/O) operations.

The higher **ready time** compared to **running time** for these tasks can be explained by the fact that they are waiting for other processes to execute before they can proceed. For example, tasks

in the initial loading phase may depend on I/O operations, thread dependencies and resource contention.

We can observe that the AircraftDisplay threads are destroyed and recreated every 5 seconds as the map is updated. This behavior corresponds to the periodic refresh of the aircraft positions on the map. For example, if there are 5 aircraft, the system creates 5 corresponding threads during each map update. These threads are then destroyed after their purpose is served, and new threads are created with updated positions for the next refresh.

This design ensures that each map refresh reflects the most up-to-date aircraft positions, which is critical for real-time applications like air traffic control. However, this also introduces an overhead due to the repeated creation and destruction of threads.

## 8. Lessons Learned

This project offered valuable insights into the complexities of developing real-time systems. A key takeaway was the critical importance of **timing**. Meeting real-time constraints required meticulous task scheduling to ensure timely updates and responses. Another major lesson was the advantage of **modular design**, which not only enhanced system maintainability but also enabled parallel development, significantly improving efficiency.

However, significant challenges arose during real-time testing. Simulating varying levels of airspace congestion highlighted the need for comprehensive testing across diverse operational conditions to ensure the system's capability to handle real-world scenarios.

For future projects, a greater emphasis will be placed on optimizing **inter-process communication** and adopting more sophisticated **testing frameworks**. These improvements would help validate performance under extreme conditions and further strengthen the robustness of real-time systems.

## 9. Conclusion

The project successfully demonstrated the development of a simplified ATC system for monitoring and controlling aircraft within a defined airspace. Core functionalities, such as real-time tracking, safety violation detection, and operator control, were effectively implemented. While the system met most real-time requirements, future enhancements could focus on improving **scalability** and exploring more efficient **scheduling algorithms** to better manage higher levels of congestion.

Overall, this project reinforced essential principles of real-time system design and implementation, providing a strong foundation for tackling more complex challenges in future endeavors.

## 10. Team Contributions

Each team member played a critical role in the development, testing, and documentation of the ATC system. Below is an outline of individual contributions to specific modules and tasks:

- **Rory Poonyth**
  - **Primary Role:** Lead Developer, Tester
  - **Modules worked on:** Aircraft, ATC, Communication System, Computer System, Data Display, Operator Console, Radar
- **Omar Selim**
  - **Primary Role:** System Integrator, Tester
  - **Modules worked On:** ATC, Communication System, Data Display, Operator Console
- **Yazid Dawiss**
  - **Primary Role:** System Integrator, Tester
  - **Modules Worked On:** ATC, Communication System, Data Display, Operator Console