**Overture – Open-source Tools for Formal Modelling TR-2010-02**
**January 2010**

# Tutorial to Overture/VDM-RT

by

Peter Gorm Larsen
John Fitzgerald
Sune Wolff
Nick Battle
Kenneth Lausdahl
Augusto Ribeiro
Kenneth Pierce

# Contents

# Chapter 3

# Overture Tool Support for VDM-RT: an Introductory Guide

## Preamble

This is an introduction to the Overture Integrated Development Environment (IDE) and its facilities for supporting modelling and analysis in VDM-RT the VDM extended language for modelling real-time systems, formerly known as VICE (VDM in Constrained Environments). It may be used as a substitute for Chapter 3 of "Validated Designs for Object-oriented Systems"[1] or as a free-standing guide. Additional material is available on the book's web site[2]. Throughout this guide we will refer to the textbook as "the book" and the book's web site simply as "the web site".

We use examples based on an *in-car navigation* case study and VDM-RT model presented in Appendix A.

We introduce the features of Overture that support the combination of formal modelling in VDM++ with object-oriented design using UML. This is done by providing a "hands-on" tour of Overture, providing enough detail to allow you to use Overture for serious applications, including the exercises in the book. However, this is by no means a complete guide to Overture; more information can be obtained from `www.overturetool.org`.

## 3.1 Introduction

In this chapter, an in-car radio navigation system which supports the Traffic Message Channel (TMC) will used as example.

The system is composed of three main clusters of functionality;

- The man-machine interface (MMI) takes care of user interaction such as handling key press input and graphical display output.

[1] John Fitzgerald, Peter Gorm Larsen, Paul Mukherjee, Nico Plat and Marcel Verhoef. *Validated Designs for Object-oriented Systems*, Springer, New York. 2005, ISBN 1-85233-881-4.
[2] `www.vdmbook.com`.

- The navigation is responsible for destination entry, route planning and turn-by-turn guidance.
- The radio is responsible for basic tuner and volume control as well as handling traffic information from the TMC.

Figure 3.1 gives an overview of the in-car navigation system.

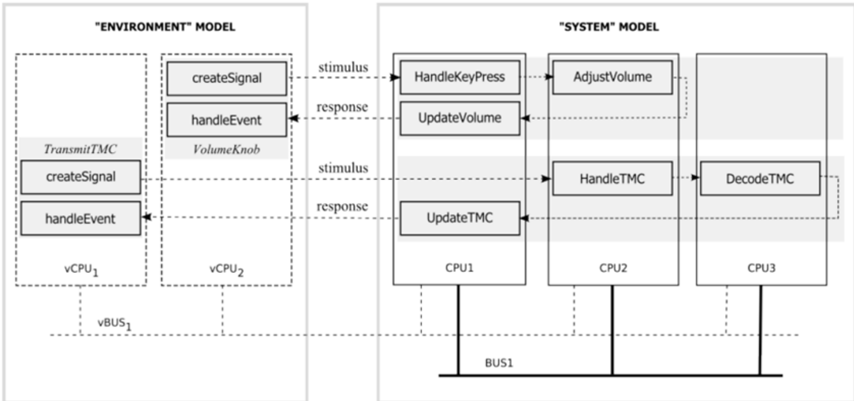



Figure 3.1: Car Navigation System Overview

The system must be able to support the following three use cases:

**Change Volume:** The user turns the rotary button and expects near instant audible feedback from the system. Furthermore, the visual feedback (the volume setting on the screen) should be timely and synchronized with the audible feedback.

**Address Look-up:** Destination entry is supported by a smart "typewriter" style interface. By turning a knob the user can move from letter to letter; by pressing it the user will select the currently highlighted letter. The map database is searched for each letter that is selected and only those letters in the on-screen alphabet are enabled that are potential next letters in the list.

**TMC Message Handling:** Digital traffic information is important for in-car radio navigation systems. It enables features such as automatic re-planning of the planned route in case a traffic jam occurs ahead. It is also increasingly important to enhance road safety by warning the driver, for example when a ghost driver is spotted just ahead on the planned route. TMC is such a digital traffic information service.

When developing a Real-time model, it is adviced to create an object-oriented model first outside the real-time domain. This will enable the developer to focus on the structure of the system as well as eliminating any concurrency issued before moving on to the real-time domain. This proposed process is described in much more detail in [Larsen&09].

The rest of this chapter has the following outline; Section 3.2 describes how to obtain the Overture tools. Section 3.3 provides an initial introduction to the terminology used by Eclipse tools like Overture. Section 3.4 shows how VDM-RT models can be connected to UML. Section 3.5 describes the process of testing and debugging VDM-RT models using Overture. Section 3.6 goes on to show the Real-Time Log Viewer which gives a graphical presentation of thread execution. Section 3.7 demonstrates the automatic generation of the additional checks (called *proof obligations*) needed to ensure that a model is consistent. Finally, Section 3.8 illustrates how parts of Overture's functionality can be accessed from a command line, including support for test coverage analysis which is not currently available from the Overture IDE.

## 3.2 Obtaining the Overture Tools

In order to run the examples and exercises presented in the book, you will need to download the Overture tools from the Internet. Overture is an open source tool, developed by volunteers and built on the Eclipse platform. The project is managed on SourceForge[3]. The best way to run Overture is to download a special version of Eclipse with the Overture functionality already pre-installed. If you go to:

`http://sourceforge.net/projects/overture/files/`

you will find pre-installed versions of Overture for Windows, Linux and Mac[4].

A library of sample VDM-RT models, including all those needed for the exercises in the book, is available and can be downloaded from SourceForge under the `files/Examples` section using the URL[5]:

`https://sf.net/projects/overture/files/Examples/`

You can import the example library zip folder as described in Section 3.3. Finally, the web site `www.vdmbook.com` contains all the examples used in this book as plain text files but these are also all present in the above mentioned zip file.

**Note for VDMTools® users.** Overture provides a new open source VDM tool set, but it can also work in conjunction with the VDMTools® tool set originally developed by IFAD A/S and now maintained and developed by CSK Systems (see `http://www.vdmtools.jp/en/`). Overture accesses VDMTools functionality via a remote API, and the integration is to some extent limited by the API capabilities. However, the additional features provided by the Overture GUI make it worth considering as a front end to the VDMTools functionality.

[3] `https://sourceforge.net/projects/overture/`

[4] It is planned to develop an update facility, allowing updates to be applied directly from within the Overture tools without requiring a reinstallation. However, this can be a risky process because of the dependencies on non-Overture components and so is not yet supported.

[5] The library files are created to be used with Eclipse, but can be opened with file compression programs like `Winrar` on Windows

## 3.3 Using the Overture Perspective

Eclipse is an open source platform based on a *workbench* that provides a common look and feel for a large collection of extension products. Thus if a user is familiar with one Eclipse-based product, it will generally be easy to start using a different product on the same workbench. The Eclipse workbench consists of several panels called *views*, such as the Script Explorer view at the top left of Figure 3.2. A particular collection of panels designed to assist a specific activity is called a *perspective*. For example Figure 3.2 shows the standard Overture perspective which contains views for managing Overture projects, and viewing and editing files. As we shall show later, several other perspectives are avilable in Overture.

The *Script Explorer view* helps you create, select, and delete Overture projects and navigate between the files in these projects. Start by importing the car navigation project from the book's web site. This can be done by right clicking the project view and selecting *Import*, followed by *General → Existing Projects into Workspace*. In this way the projects from `.zip` file mentioned above can be imported very easily.

The panel to the right of the Explorer is the *editor area*. An editor customised to the dialect of VDM being used in the project will appear here.

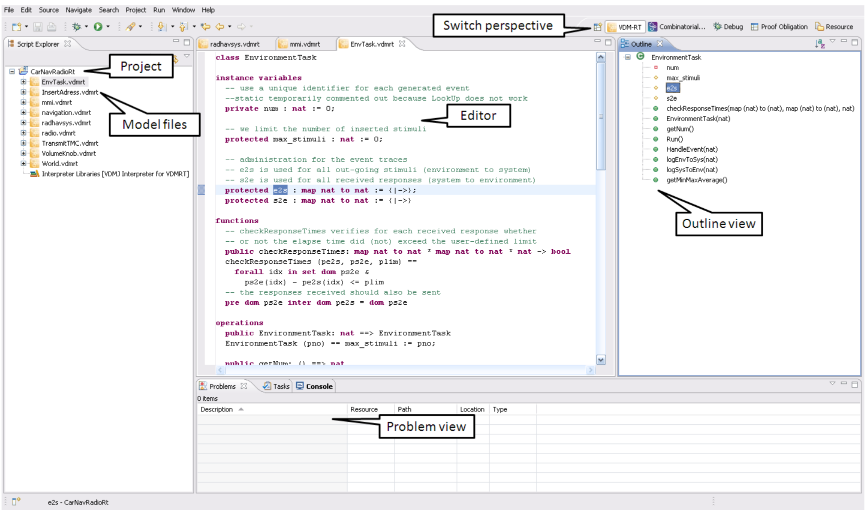



Figure 3.2: The Overture Perspective

The *Outline view*, to the right of the editor (see Figure 3.3), displays an outline of the file selected in the editor. It shows all declared classes, their instance variables, values, types, functions, operations and traces. Figure 3.2 shows the outline view on the right hand side. Clicking on an operation or function in the outline will move the cursor in the editor view to its definition. At the top of the outline view there is a button to (optionally) display the items in the outline view in alphabetical order.

The *Problems view* presents information about the projects you are working on, including warnings and error messages.

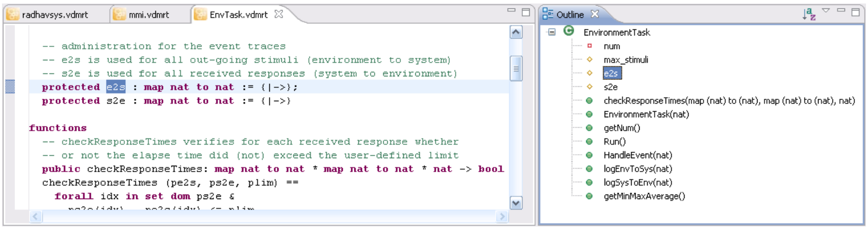


Figure 3.3: The Outline View

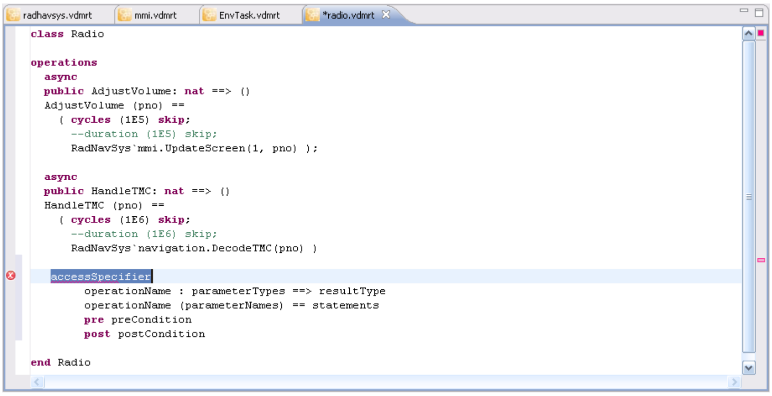


Figure 3.4: Explicit operation template

Most of the other features of the workbench, such as the menus and toolbars, are similar to other Eclipse applications, though for newcomers to Eclipse it is worth noting that there is a special menu with Overture-specific functionality. One convenient feature is a toolbar of shortcuts to switch between different perspectives that appears on the right side of the screen; these vary dynamically according to context and history.

When making corrections to the model, you can use the Overture IDE templates. When you hit the key combination *CTRL+space* after entering the initial characters of the template needed, Overture will offer possible completions. For example, if you typ "op" followed by *CTRL+space*, Overture will propose the use of an implicit or explicit operation template.

The Overture IDE supports many templates for language constructs including cases statements, classes, quantified expressions, functions (explicit/implicit), operations (explicit/implicit) and many more. Further templates can easily be added in the future. The use of templates makes it more concenient to write VDM models without detailed prior knowledge of the language syntax.

When editing a VDM model, the Overture IDE parses the content of the editor buffer continuously as changes are made. If there are any syntax errors, these will be reported in the problems view, as well as being highlighted in the editor. See the bottom of Figure 3.2. Each time a VDM-RT model file is saved the editor type checks the model and reports any errors or warnings. Note also that the suggestions made about missing characters in the error messages may not always be entirely the action you may wish to take when correcting the source since the tool cannot guess what you intended to write.

Most of the imported files in the car navigation project should be syntactically correct, but the `World.vdmrt` file contains one deliberate syntax error. The error in this case is a common one: a semicolon separating the different definitions has been forgotten.

**Exercise 3.1**⋆ Correct all the errors discovered by the type checker and syntax and type check your corrected files until no errors appear. **Hint:** Consult the model presented in Appendix A to see how values (note using "=" rather than "`:=`"), types and constructors should be defined and how access modifiers should be used. □

## 3.4 Mapping UML to VDM

In order to map the UML class diagram created in Enterprise Architect to VDM, a new project must be created in the Overture IDE to receive it. This is done by right-clicking in the *Script Explorer* view, and creating a new VDM-RT project and for example naming it `CarRadioNavUML`. If the desired language dialect (say a VDM-RT project) is not directly available in the right-click menu, please choose *Other* and browse to the VDM-RT project. By right-clicking the new project root in the *Script Explorer*, *UML Transformation* can be chosen, followed by *Import XMI*. Now browse to the XMI/XML file exported from EA called `carradnavuml.xmi` and open this.

The transformation from UML to VDM is not entirely automated right now. For example, any custom types are transformed to VDM++ definitions using machine-generated identifiers since custom types are not named in UML. As a result, you have to expect to make minor modifications to the generated VDM files.

### 3.4.1 Mapping VDM to UML

It is possible to automatically transform all the classes from the car radio navigation project to UML. To do this, simply right click the project root and choose *UML Transformation → Export XMI*. The XMI file can subsequently be imported in EA, enabling the user to get an overview of the complete model.

## 3.5 Debugging

This section describes how to debug a model by testing it using the Overture IDE. The model can be exercised by running the operations *RunScenario1* or *RunScenario2* in the *World* class:

```
class World

types
```

```
public perfdata = nat * nat * real

instance variables

static public envTasks : map seq of char
                         to EnvironmentTask := {|->};

operations

addEnvironmentTask: seq of char * EnvironmentTask ==> ()
addEnvironmentTask (pnm, penv) ==
( envTasks := envTasks munion { pnm |-> penv };
  penv.Run() );

public RunScenario1 : () ==> map seq of char
                             to perfdata
RunScenario1 () ==
( addEnvironmentTask("VolumeKnob",
                     new VolumeKnob(10));
  addEnvironmentTask("TransmitTMC",
                     new TransmitTMC(10));
  return { name |-> envTasks(name).getMinMaxAverage()
         | name in set dom envTasks } );
...
end World
```

### 3.5.1 The Debug configuration

Before you start to debug a model in Overture, you need to set up a *debug configuration*. Right click the project and choose *Debug As* → *Debug configuration*[6]. The dialog requires the project name, the class, the operation/function used as the entry point of the test and the source file containing the entry point definition. As an example, Figure 3.5 shows the debug configuration for the car navigation model. The class and operation/function name can be chosen from a Browse dialog. If the operation or function has arguments, these must be typed in manually between the brackets of the entry point function/operation.

Once the configuration is ready, the model can be debugged. The Overture IDE will change to the *Debug perspective* which contains the views needed for debugging in VDM. Breakpoints can easily be set by double clicking in the left margin of the editor view. When the debugger reaches a breakpoint, evaluation suspends and the user can inspect the values of different variables and step

[6]Note that the *Run As* functionality existing Eclipse users are used to is not supported in the current version of Overture.

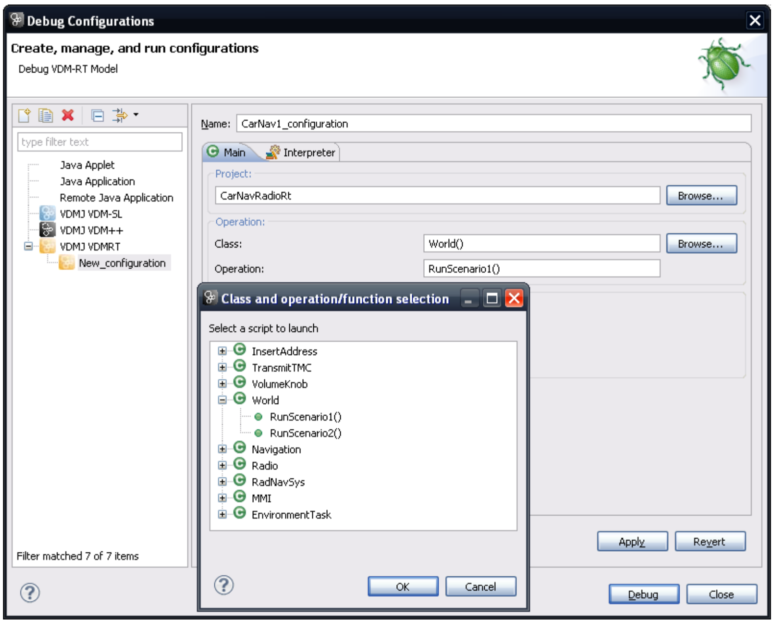



Figure 3.5: The debug configuration dialog

through the VDM model line by line.

The Debug perspective is illustrated on figure 3.6 The *Debug view* in the upper left corner of the Debug perspective shows all running models and their call stacks. It also shows whether a given model is stopped, suspended or running. All threads are also shown, along with their running status. It is possible to switch between threads from the Debug view.

At the top of the view are standard Eclipse buttons (see Table 3.1) for controlling debugging, allowing you to stop, step into, step over and resume.

The *Variables view* in the upper right corner of the Debug perspective shows all the variables in a given context, when a breakpoint is reached. The variables and their displayed values are automatically updated when stepping through a model.

The *Breakpoints view* gives an overview of all breakpoints set (see Figure 3.7). From this view the user can easily navigate to the location of a given breakpoint, disable or delete them, or set their properties.

The *Expressions view* allows the user to enter *watch* expressions whose values are automatically displayed and updated when stepping. Watch expressions can be added manually or created by selecting *create watch expression* from the Variables view. It is possible to edit existing expressions. Like the Breakpoints view, this view is hidden in the upper right hand corner in Figure 3.6.

While the Overture Expressions view allows you to easily inspect values, the functionality is somewhat limited. For more thorough inspections in Overture, the *Interactive Console view* is provided. Here commands can be executed in a given context, i.e. when the debugger is at a breakpoint. The Interactive Console keeps a command history, so that previously executed commands can be run again easily. The interactive console can be seen at the bottom of Figure 3.6.

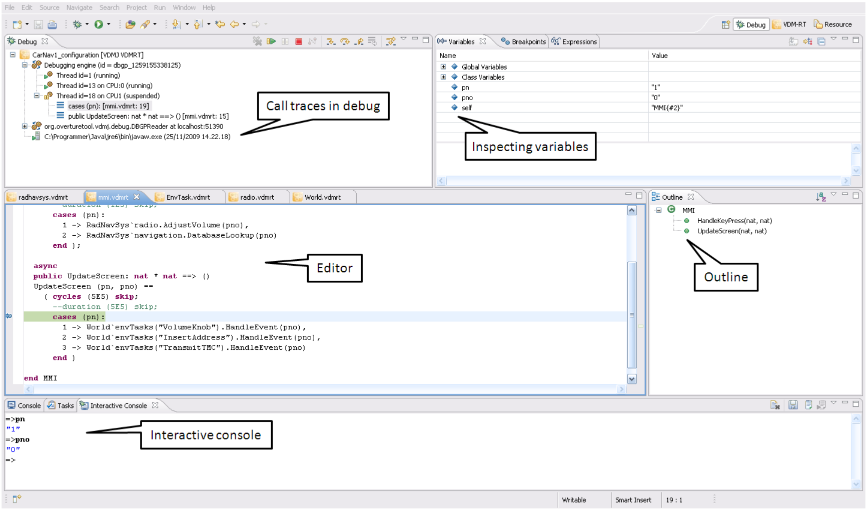
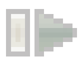
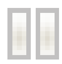
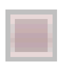
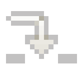
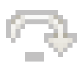
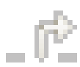
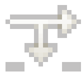



Figure 3.6: Debugging perspective

Table 3.1: Overture debugging buttons

| Button | Explanation |
|---|---|
|  | Resume debugging |
|  | Suspend debugging |
|  | Terminate debugging |
|  | Step into |
|  | Step over |
|  | Step return |
|  | Use step filters |

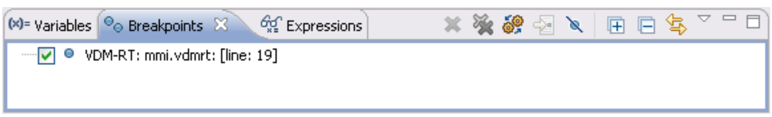



Figure 3.7: Breakpoint View

## 3.6 Realtime Log Viewer

When a VDM-RT model is being executed a textual logfile is created in a ”logs/debugconfig” folder with the *.logrt* extension. This logfile can be viewed in the build-in RealTime Log Viewer, by double-clicking the file in the project view. The viewer allows you to explore system execution in different ways. In Figure 3.8 the architectural overview of the system is given, describing the distributed nature of the model.

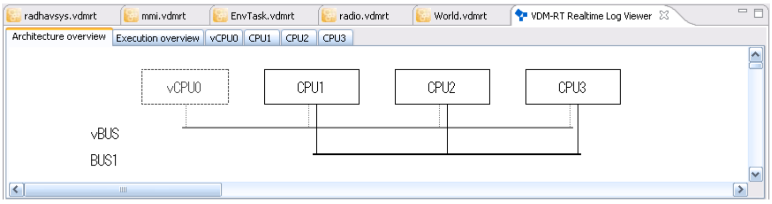



Figure 3.8: Architectural overview

The RealTime Log Viewer also enables the user to get an overview of the model execution on a system level – this can be seen in Figure 3.9. This view shows how the different CPUs communicate via the BUSes of the system.

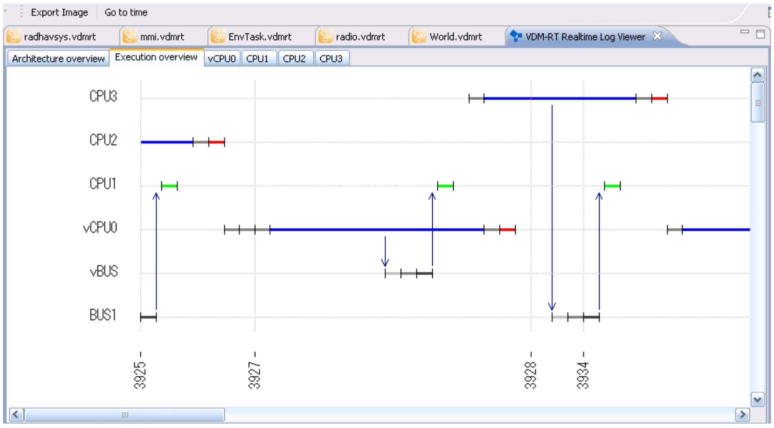



Figure 3.9: Execution overview

Since the complete execution of the model cannot be shown in a normal sized window, you have the option of jumping to a certain time using the *Go to time* button. It is also possible to export all the generated views to *JPG* format using the *Export Image* button. All the generated pictures will be placed in the ”log” folder.

In addition to the execution overview, the RealTime Log Viewer can also give an overview of all executions on a single CPU. This view gives a detailed description of all operations and functions invoked on the CPU as well as the scheduling of concurrent processes. This can be seen in Figure 3.10.

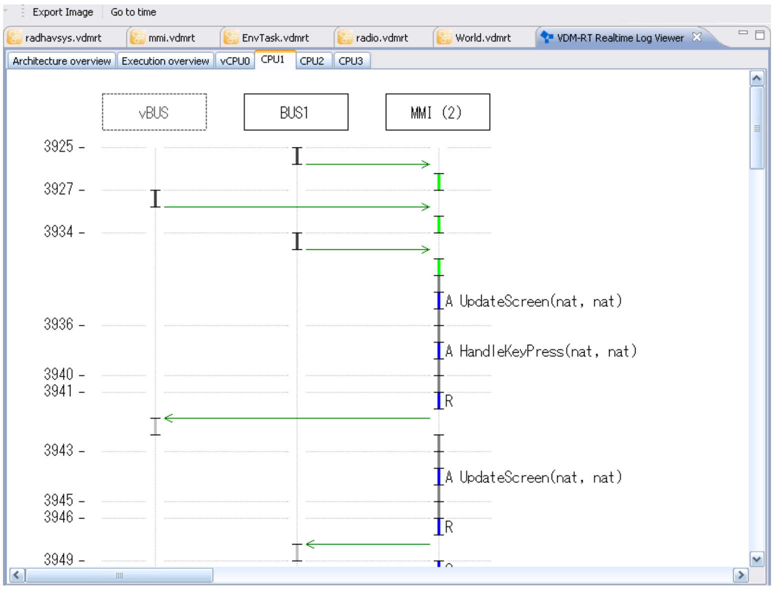



Figure 3.10: Execution on single CPU

## 3.7 Proof Obligations

The Overture tool is also able to generate *Proof Obligations* automatically for VDM-RT models. Proof obligations are boolean expressions that describe constraints to be met at various points in the model in order to ensure that the model is internally consistent (i.e. no run-time errors will occur while debugging if these are all satisfied). Proof obligations are generated to ensure, for example, that operations will always respect invariants on instance variables. Each proof obligation generated from a model should evaluate to *true*.

The proof obligation generator is invoked by right clicking on the project in the *Explorer view* and then selecting the *Proof Obligations −> Generate Proof Obligations* entry. This will start up a proof obligation perspective with a special *PO view*. For the alarm example this view takes the form shown in Figure 3.11.

One of the first proof obligations listed for this example is related to the `RunScenario1` operation, which is defined as:

```
public RunScenario1 : () ==> map seq of char to perfdata
RunScenario1 () ==
 (addEnvironmentTask("VolumeKnob", new VolumeKnob(10));
  addEnvironmentTask("TransmitTMC", new TransmitTMC(10));
  return { name |-> envTasks(name).getMinMaxAverage()
         | name in set dom envTasks } );
```

The proof obligation records the constraint that the mapping application `envTasks(name)`

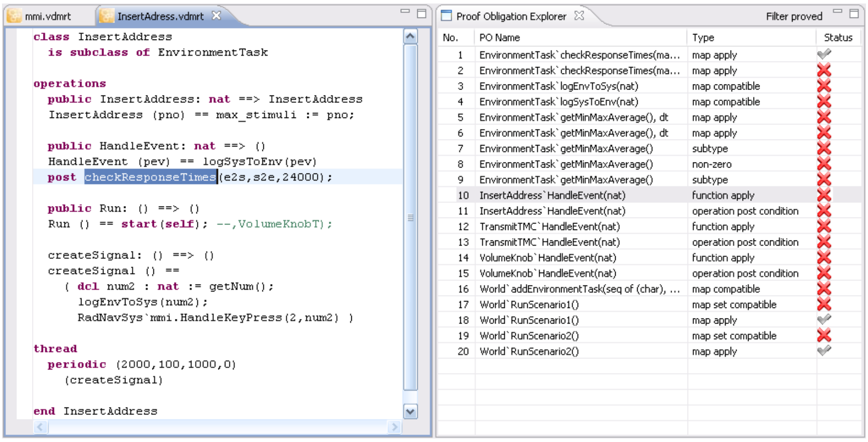



Figure 3.11: The Proof Obligation view for the Car Navigation VDM-RT model

is indeed defined (i.e. that the `name` is in the domain of the mapping `envTasks`). This is described as a proof obligation in the following form:

```
forall name in set (dom envTasks) &
  name in set dom envTasks
```

Proof obligations represent checks that should be made on a model in order to gain confidence in its consistency. At present, proof obligations have to be checked by manual inspection of the model code. Tools are being developed for Overture to check as many as possible of the proof obligations automatically, but there are always likely to be some that have to be checked manually.

## 3.8 A Command-Line Interface

So far only the graphical user interface of the Overture IDE has been presented but the engine underlying Overture, called VDMJ, also provides a simple command line interface. This is useful for the automatic batch execution of tests, though the command line also provides a full set of interactive execution and debugging commands which can be useful when examining batch tests. The command line also provides access to tool facilities that have not yet been included in the Overture IDE.

VDMJ is written in Java, and so to run it from the command line, the VDMJ jar file [7] should be executed with a Java JRE (version 5 or later):

```
java -jar vdmj-2.0.0.jar
```

[7] See the Overture documentation at `sourceforge.net/projects/overture` for the location of the jar file.

If the jar file is executed with no further options like this, it will print a list of available options and exit. The most important option is the VDM dialect that the tool should use. In the case of our alarm example, we want to use VDM-RT for which the option is `-vdmrt`. After this, we can simply specify the names of the VDM-RT model files to load, or the name of a directory in which all the files reside:

```
java -jar vdmj-2.0.0.jar -vdmrt CarNaviRadio
```

That will perform a syntax and type check of all the VDM-RT model files in the directory `CarNaviRadio`, producing any errors and warning messages on the console, before terminating:

```
Parsed 9 classes in 0.61 secs. No syntax errors
Type checked 11 classes in 0.093 secs. No type errors
Initialized 11 classes in 0.079 secs.
```

In the case of our example, there are no syntax or type checking errors. Warnings can be suppressed using the `-w` option.

If a VDM-RT model has no type checking errors, it can either be given an expression to evaluate as an option on the command line, or the user can enter an interactive mode to evaluate expressions and debug their execution.

To evaluate an expression from the command line, the `-e` option is used, followed by a VDM expression to evaluate. You may also find the `-q` option useful, as this suppresses the informational messages about the parsing and type checking:

```
java -jar vdmj-2.0.0.jar -vdmrt -w -q -e
    "new World().RunScenario1()" CarNaviRadio
```

This produces a single line of output for the evaluation, since the parsing and checking messages are suppressed, as are the warnings:

```
{"TransmitTMC" |-> mk_(3904, 12574, 6836.25),
 "VolumeKnob" |-> mk_(3935, 16268, 8106.416666666667)}
```

Clearly a batch of test evaluations could be performed automatically by running a series of similar commands and saving the output results for comparison against expected results.

To run the command line interpreter interactively, the `-i` command line option must be given. Instead of terminating after the type check, this will cause VDMJ to enter its interactive mode, and give the interactive > prompt:

```
Parsed 9 classes in 0.61 secs. No syntax errors
Type checked 11 classes in 0.093 secs. No type errors
```

```
Initialized 11 classes in 0.079 secs.
Interpreter started
>
```

From this prompt, various interactive commands can be given to evaluate expressions, debug their evaluation, or examine the VDM-RT model environment. The `help` command lists the commands available. The `quit` command leaves the interpreter.

For example, the following session illustrates the creation of a test object, followed by an evaluation of its `RunScenario2` operation, and a debug session with a breakpoint at the start of the same operation:

```
> create world := new World()
> p world.RunScenario2()
= {"InsertAddress" |-> mk_(3993, 16132, 7759.2727272727),
   "TransmitTMC" |-> mk_(3871, 12128, 6980.714285714285)}
Executed in 0.312 secs.

> break World`addEnvironmentTask
Created break [1] in 'World' (CarNaviRadio\World.vdmrt)
at line 12:5
12:      ( envTasks := envTasks munion { pnm |-> penv };

> p world.RunScenario2()
Stopped break [1] in 'World' (CarNaviRadio\World.vdmrt)
at line 12:5
12:      ( envTasks := envTasks munion { pnm |-> penv };
[thread 1]> print penv
penv = InsertAddress{#77, max_stimuli:=10, e2s:={|->},
 s2e:={|->},EnvironmentTask{#76, max_stimuli:=10, num:=0,
 e2s:={|->},s2e:={|->}}}
[thread 1]> continue
Runtime: Error 4021: Duplicate map keys have different
values:
    "InsertAddress" in 'World' (CarNaviRadio\World.vdmrt)
at line 12:28
Stopped in 'World' (CarNaviRadio\World.vdmrt)
at line 12:28
12:      ( envTasks := envTasks munion { pnm |-> penv };
[thread 1]> continue
>
```

Notice that the `print` command is available at the breakpoint to examine the runtime state of the system. In the example, we show the value of the `penv` variable. Continuing from this point, the VDM-RT model raises a runtime error because the previous execution's results are still in the (static) `envtasks` map. The VDM-RT model can be re-initialized between runs with the `init` command to avoid this.

The `help` command is context sensitive, and will list the extra debugging commands available at a breakpoint, such as `continue`, `step`, `stack`, `list` and so on. The full set of commands is described in the VDMJ User Guide[8].

When any evaluation is performed on a VDM model, VDMJ records the lines of the VDM-RT model that are executed. This permits the line coverage to be examined after a test to identify the parts of the VDM-RT model that have not yet been exercised – coverage is cumulative, so a set of tests can be executed and their total coverage examined at the end.

In our simple example, the single test executes the body of the `RunScenario2` operation, but the `RunScenario1` operation remains unused. To display coverage, the `coverage <file>` command is used. Lines that have been executed are listed with a '+' prefix, while those that have not have a '-' prefix; lines that are not executable have no prefix. Alternatively, coverage can be generated as a LaTeXoutput file, which displays parts oflines that have been executed. This is produced with the `latex` command.

```
> coverage CarNaviRadio/World.vdmrt
Test coverage for CarNaviRadio\World.vdmrt:

  class World

  types
    public perfdata = nat * nat * real

  instance variables
+ static public envTasks : map seq of char to
                             EnvironmentTask := {|->};

  operations
  addEnvironmentTask: seq of char * EnvironmentTask
                    ==> ()
  addEnvironmentTask (pnm, penv) ==
+  (envTasks := envTasks munion { pnm |-> penv };
+   penv.Run() );

  public RunScenario1: () ==> map seq of char to perfdata
  RunScenario1 () ==
-  (addEnvironmentTask("VolumeKnob", new VolumeKnob(10));
```

[8]Supplied with the Overture documentation.

```
-   addEnvironmentTask("TransmitTMC",
                       new TransmitTMC(10));
-   return { name |-> envTasks(name).getMinMaxAverage()
-          | name in set dom envTasks } );

  public RunScenario2: () ==> map seq of char to perfdata
  RunScenario2 () ==
+  (addEnvironmentTask("InsertAddress",
                       new InsertAddress(10));
+   addEnvironmentTask("TransmitTMC",
                       new TransmitTMC(10));
+   return { name |-> envTasks(name).getMinMaxAverage()
+          | name in set dom envTasks } );


  end World

Coverage = 63%


> latex CarNaviRadio/World.vdmrt
Latex coverage written to CarNaviRadio\World.vdmrt.tex
>
```

## 3.9 Summary

This chapter has introduced the following major features of tool support for VDM-RT:

- syntax checking of VDM-RT models;
- type checking of VDM-RT models;
- executing and debugging VDM-RT models;
- combinatorial testing enabling automation of parts of the testing process;
- proof obligation generation and
- a command-line interface enabling access to test coverage.

# References

[Larsen&09] Peter Gorm Larsen and John Fitzgerald and Sune Wolff. Methods for the Developing Distributed Real-Time Systems using VDM. *International Journal of Software and Informatics*, 3(2-3), October 2009.

# Appendix A

# A Car Navigation System Example

This section presents the requirements for a in-car radio navigation system which supports the Traffic Message Channel (TMC). It forms a running example that serves to illustrate the process described earlier and to introduce elements of the VDM++ modelling language with the Real-time extension VICE. Although the modelling process is described here as though it were a single-pass activity, a real development would usually be iterative.

## A.1 System Overview of the Car Navigation example

In Figure 3.1 an overview of the in-car navigation system is shown. Similarily Figure A.2 provides an overview of the `World` class and the environment classes.

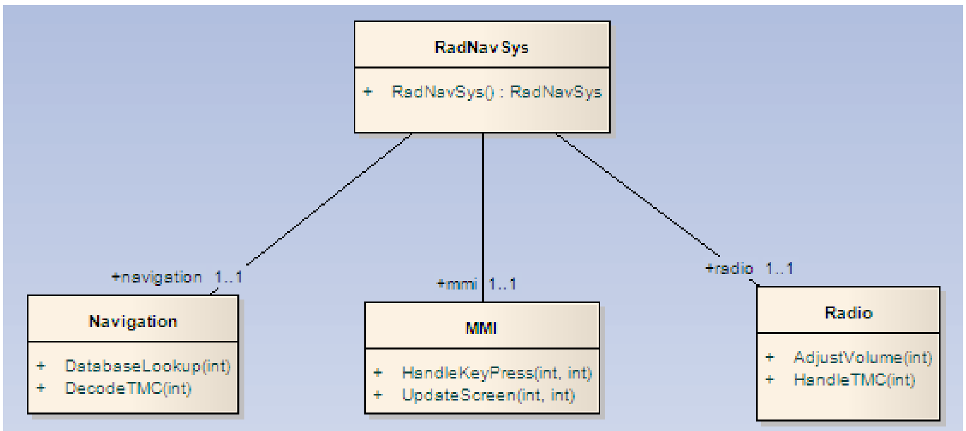



Figure A.1: Car Navigation System Overview

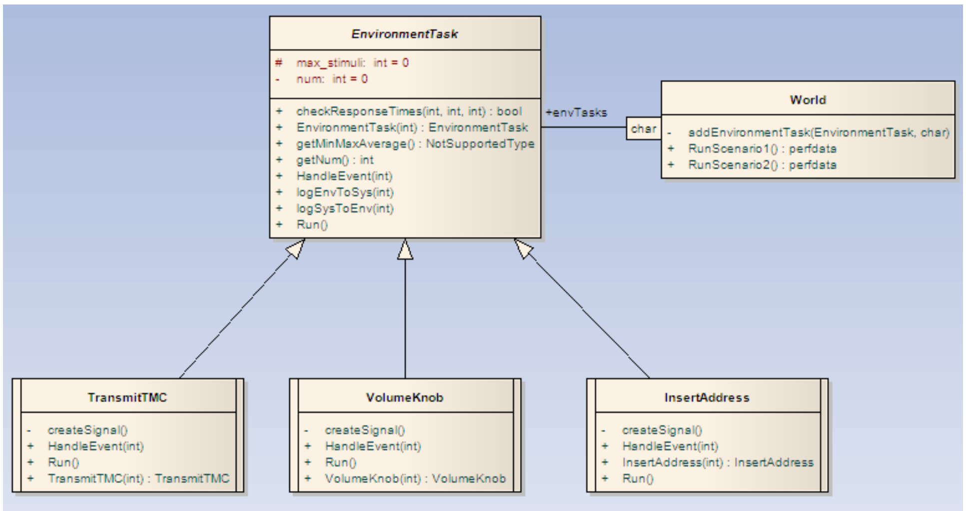



Figure A.2: Overview of the Wolrd and Environment Classes

## A.2 The Radio Navigation System Class

The RadNavSys class is the system class that all VDMRT models must include.

```
system RadNavSys

instance variables
  -- create an MMI class instance
  static public mmi : MMI := new MMI();
  -- define the first CPU with fixed priority
  -- scheduling and 22E6 MIPS
  CPU1 : CPU := new CPU (<FP>, 22E6);

  -- create an Radio class instance
  static public radio : Radio := new Radio();
  -- define the second CPU with fixed priority
  -- scheduling and 11E6 MIPS
  CPU2 : CPU := new CPU (<FP>, 11E6);

  -- create an Navigation class instance
  static public navigation : Navigation := new Navigation();
  -- define the third CPU with fixed priority
  -- scheduling and 113 MIPS
  CPU3 : CPU := new CPU (<FP>, 113E6);
```

```
  -- create a communication bus that links the three
  -- CPU's together
  BUS1 : BUS := new BUS (<CSMACD>, 72E3, {CPU1, CPU2, CPU3})
```

```
operations
  public RadNavSys: () ==> RadNavSys
  RadNavSys () ==
    ( -- deploy mmi on CPU1
      CPU1.deploy(mmi,"MMIT");
      CPU1.setPriority(MMI`HandleKeyPress,100);
      CPU1.setPriority(MMI`UpdateScreen,90);
      -- deploy radio on CPU2
      CPU2.deploy(radio,"RadioT");
      CPU2.setPriority(Radio`AdjustVolume,100);
      CPU2.setPriority(Radio`DecodeTMC,90);
      -- deploy navigation on CPU3
      CPU3.deploy(navigation,"NavT");
      CPU3.setPriority(Navigation`DatabaseLookup, 100);
      CPU3.setPriority(Navigation`DecodeTMC, 90)
      -- starting the CPUs and BUS is implicit
    );
end RadNavSys
```

## A.3 The MMI Class

```
class MMI

operations
  async
  public HandleKeyPress: nat * nat ==> ()
  HandleKeyPress (pn, pno) ==
    ( cycles (1E5) skip;
      cases (pn):
        1 -> RadNavSys`radio.AdjustVolume(pno),
        2 -> RadNavSys`navigation.DatabaseLookup(pno)
      end );

  async
```

```
  public UpdateScreen: nat * nat ==> ()
  UpdateScreen (pn, pno) ==
    ( cycles (5E5) skip;
      cases (pn):
        1 -> World`envTasks("VolumeKnob").HandleEvent(pno),
        2 -> World`envTasks("InsertAddress").HandleEvent(pno),
        3 -> World`envTasks("TransmitTMC").HandleEvent(pno)
      end )

end MMI
```

## A.4 The Radio Class

```
class Radio

operations
  async
  public AdjustVolume: nat ==> ()
  AdjustVolume (pno) ==
    ( cycles (1E5) skip;
      RadNavSys`mmi.UpdateScreen(1, pno) );

  async
  public HandleTMC: nat ==> ()
  HandleTMC (pno) ==
    ( cycles (1E6) skip;
      RadNavSys`navigation.DecodeTMC(pno) )

end Radio
```

## A.5 The Navigation Class

```
class Navigation

operations
  async
```

```
  public DatabaseLookup: nat ==> ()
  DatabaseLookup (pno) ==
    ( cycles (5E6) skip;
      RadNavSys`mmi.UpdateScreen(2, pno) );

  async
  public DecodeTMC: nat ==> ()
  DecodeTMC (pno) ==
    ( cycles (5E5) skip;
      RadNavSys`mmi.UpdateScreen(3, pno) )

end Navigation
```

## A.6 The Environment Tast Class

```
class EnvironmentTask

instance variables
  -- use a unique identifier for each generated event
  private num : nat := 0;

  -- we limit the number of inserted stimuli
  protected max_stimuli : nat := 0;

  -- administration for the event traces
  -- e2s is used for all out-going stimuli
  -- (environment to system)
  -- s2e is used for all received responses
  -- (system to environment)
  protected e2s : map nat to nat := {|->};
  protected s2e : map nat to nat := {|->}

functions
  -- checkResponseTimes verifies for each received response
  -- whether or not the elapse time did (not) exceed the
  -- user-defined limit
  public checkResponseTimes: map nat to nat *
                             map nat to nat * nat -> bool
  checkResponseTimes (pe2s, ps2e, plim) ==
```

```
    forall idx in set dom ps2e &
      ps2e(idx) - pe2s(idx) <= plim
  -- the responses received should also be sent
  pre dom ps2e inter dom pe2s = dom ps2e

operations
  public EnvironmentTask: nat ==> EnvironmentTask
  EnvironmentTask (pno) == max_stimuli := pno;

  public getNum: () ==> nat
  getNum () ==
  ( dcl res : nat := num;
    num := num + 1;
    return res );

  -- Run shall be overloaded to implement the event generation
  -- loop towards the system. typically, it starts a periodic
  -- thread
  public Run: () ==> ()
  Run () == is subclass responsibility;

  public HandleEvent: nat ==> ()
  HandleEvent (pev) == is subclass responsibility;

  -- logEnvToSys is used to register when an event was inserted
  -- into the system. Note that the 'time' keyword refers to
  -- the internal simulation wall clock of Overture
  public logEnvToSys: nat ==> ()
  logEnvToSys (pev) == e2s := e2s munion {pev |-> time};

  -- logSysToEnv is used to register when an event was received
  -- from the system. Note that the 'time' keyword refers to the
  -- internal simulation wall clock of Overture
  public logSysToEnv: nat ==> ()
  logSysToEnv (pev) == s2e := s2e munion {pev |-> time};

  -- getMinMaxAverage calculates the minimum, maximum and
  -- average response times that were observed during execution
  -- of the model note that getMinMaxAverage is blocked until
  -- the number of system responses is equal to the number of
  -- sent stimuli termination is ensured because only a maximum
  -- number of stimuli is allowed to be inserted in the system,
```

```
  -- so eventually all stimuli can be processed by the system.
  -- This method only works when each stimulus leads to exactly
  -- one response, which is the case in this instance.
  public getMinMaxAverage: () ==> nat * nat * real
  getMinMaxAverage () ==
    ( dcl min : [nat] := nil,
          max : [nat] := nil,
          diff : nat := 0;
      for all cnt in set dom s2e do
        let dt = s2e(cnt) - e2s(cnt) in
          ( if min = nil then min := dt
            else (if min > dt then min := dt);
            if max = nil then max := dt
            else (if max < dt then max := dt);
            diff := diff + dt );
      return mk_(min, max, diff / card dom s2e) )

sync
  -- getNum is mutually exclusive to ensure unique values
  mutex (getNum);
  -- getMinMaxAverage is blocked until all responses have been
  -- received
  per getMinMaxAverage => card dom s2e >= max_stimuli

end EnvironmentTask
```

## A.7 The Insert Address Class

```
class InsertAddress
  is subclass of EnvironmentTask

operations
  public InsertAddress: nat ==> InsertAddress
  InsertAddress (pno) == max_stimuli := pno;

  public HandleEvent: nat ==> ()
  HandleEvent (pev) == logSysToEnv(pev)
  post checkResponseTimes(e2s,s2e,24000);
```

```
  public Run: () ==> ()
  Run () == start(self); --,VolumeKnobT);

  createSignal: () ==> ()
  createSignal () ==
    ( dcl num2 : nat := getNum();
      logEnvToSys(num2);
      RadNavSys`mmi.HandleKeyPress(2,num2) )

thread
  periodic (2000,100,1000,0)
    (createSignal)

end InsertAddress
```

## A.8 The Transmit TMC Class

```
class TransmitTMC
  is subclass of EnvironmentTask

operations
  public TransmitTMC: nat ==> TransmitTMC
  TransmitTMC (pno) == max_stimuli := pno;

  public HandleEvent: nat ==> ()
  HandleEvent (pev) == logSysToEnv(pev)
  post checkResponseTimes(e2s,s2e,40000);

  public Run: () ==> ()
  Run () == start(self); --,TransmitTMCT);

  createSignal: () ==> ()
  createSignal () ==
    ( dcl num2 : nat := getNum();
      logEnvToSys(num2);
      RadNavSys`radio.HandleTMC(num2) )

thread
  periodic (4000,400,3910,0)
```

```
    (createSignal)

end TransmitTMC
```

## A.9 The Volume Knob Class

```
class VolumeKnob
  is subclass of EnvironmentTask

operations
  public VolumeKnob: nat ==> VolumeKnob
  VolumeKnob (pno) == max_stimuli := pno;

  public HandleEvent: nat ==> ()
  HandleEvent (pev) == logSysToEnv(pev)
  post checkResponseTimes(e2s,s2e,22000);

  public Run: () ==> ()
  Run () == start(self); --,VolumeKnobT);

  createSignal: () ==> ()
  createSignal () ==
    ( dcl num2 : nat := getNum();
      logEnvToSys(num2);
      RadNavSys`mmi.HandleKeyPress(1,num2) )

thread
  periodic (1000,50,500,0)
    (createSignal)

end VolumeKnob
```

## A.10 The World Class

```
class World
```

```
types
  public perfdata = nat * nat * real

instance variables
  static public
  envTasks : map seq of char to EnvironmentTask := {|->};

operations
  addEnvironmentTask: seq of char * EnvironmentTask ==> ()
  addEnvironmentTask (pnm, penv) ==
    ( envTasks := envTasks munion { pnm |-> penv };
      penv.Run() );

  public RunScenario1 : () ==> map seq of char to perfdata
  RunScenario1 () ==
    ( addEnvironmentTask("VolumeKnob", new VolumeKnob(10));
      addEnvironmentTask("TransmitTMC", new TransmitTMC(10));
      return { name |-> envTasks(name).getMinMaxAverage()
             | name in set dom envTasks } );

  public RunScenario2 : () ==> map seq of char to perfdata
  RunScenario2 () ==
    ( addEnvironmentTask("InsertAddress",new InsertAddress(10));
      addEnvironmentTask("TransmitTMC", new TransmitTMC(10));
      return { name |-> envTasks(name).getMinMaxAverage()
             | name in set dom envTasks } );

end World
```