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System/product architecture document for Sapien 190

Embedded Real-Time Systems (TI-IRTS) Spring 2010

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Document history

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1. INTRODUCTION

1.1 Purpose and Scope

The Sapien 190 is a patient simulator, simulating human physiological behaviour according to different patient scenarios. Scenarios are written in an open format and can be downloaded to the Sapien 190 that contains patient records from the PhysioBank¹ database.

In conjunction with the Sapien 110 human doll, the Sapien system provides a complete simulated human interface, with EKG, ECG and respiratory measuring spots and medicine injection spots.

1.2 References

- [1] Erich Gamma et al., Design Patterns: Elements of Reusable Object-Oriented Software, Addison Wesley (GoF)
- [2] Bruce Powell Douglass, Real-Time Design Patterns: Robust Scalable Architecture for Real-Time Systems
- [3] PhysioNet and PhysioBank the research resource for complex physiologic signals. <http://www.physionet.org/>
- [4] Project specification for PSIMU: Patient Simulator System
<http://kurser.iha.dk/eit/tiirts/Projekter/PSIMU-project.doc>
- [5] Project specification for LMON: Local Monitor System
<http://kurser.iha.dk/eit/tiirts/Projekter/LMON-project.doc>
- [6] Project specification for IPUMP: Infusion Pump System
<http://kurser.iha.dk/eit/tiirts/Projekter/IPUMP-project.doc>
- [7] Project Interface Specification
<http://kurser.iha.dk/eit/tiirts/Projekter/ProjectInterfaces.doc>
- [8] Requirement specification for Sapien 190
<http://code.google.com/p/iirtsf10grp5/downloads/detail?name=Sapien190Spec.doc&can=2&q=>
- [9] Getting started with Qt
<http://devkit8000.wikispaces.com/Qt+and+Qt+Everywhere>
- [10] Specification Abstract, objektorienteret operativsystem-API

¹ <http://www.physionet.org/physiobank/>

1.3 Definitions and acronyms

- **Model** – A model that represents one physical individual. The model may consist of sub-models for different body subsystems. The model uses an algorithm to compute the output signals based on the input signals or patient records.
- **Model Parameters** – Parameters used in the model.
- **Record** – A patient record file taken from the PhysioBank database
- **Scenario** – Model parameters and a collection of records taken from the PhysioBank database.
- **Scenario Configuration** – A set of files that represents model parameters and patient records.
- **Signals** – Signals in form of waveform files or input from external equipment
- **Simulation** – A continuous mode, where the physiological output signals are updated according to the model and the scenario applied to it.
- **ECG** – Electrocardiogram
- **EDR** – ECG–Derived Respiration
- **PDU** – Protocol Data Unit - Information that is delivered as a unit among peer entities of a network
- **D/A Converter** – Digital to Analog Converter
- **OS** – Operating System

1.4 Document structure and reading guide

Chapter 2 and 3 gives an overview of the product and the interfaces to the patient simulator in terms of other devices and user operation.

The document describes the design using the “4+1” view. For each iteration as specified in ROPES [2] we have selected one or more use cases that is used in describing the Use Case, Logical, Process, Deployment and Implementations Views. These views are described in chapters 5 – 8.

In the logical- and process view sections, class names have been written in *italic* and pattern names have been written in **bold**.

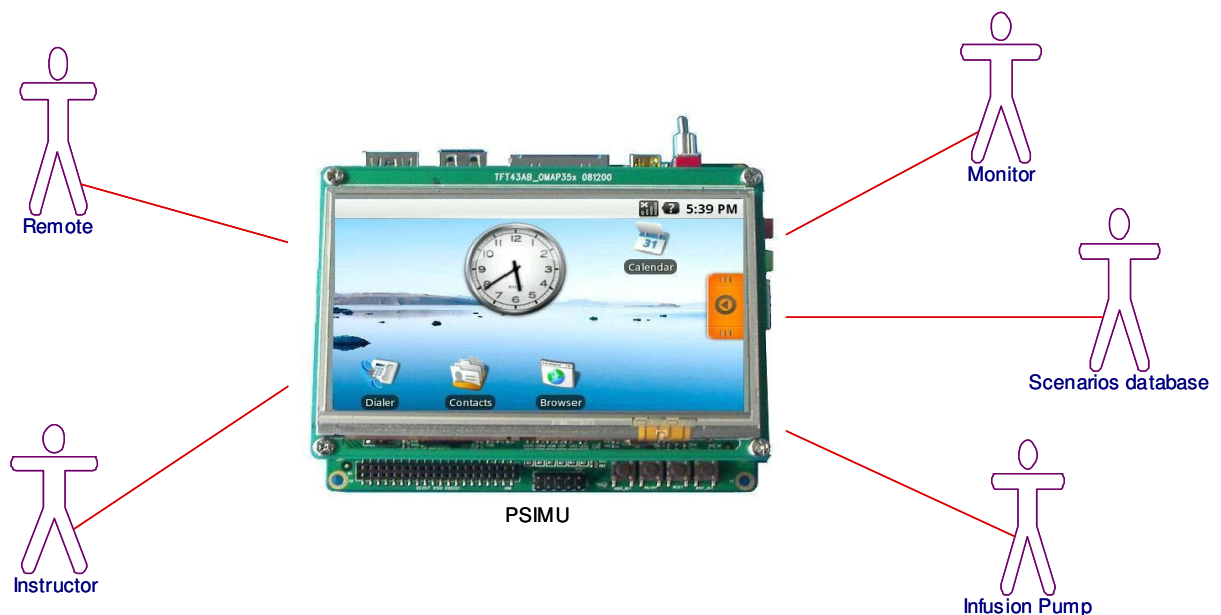
1.5 Document role in an iterative development process

This document is updated in using the ROPES development process [2]. The document is updated for every design cycle of the ROPES spiral microcycle. Every design microcycle is using the 4+1 view

2. SYSTEM OVERVIEW

The Sapien 190 is a compact unit with a graphical user interface (GUI) and interfaces to a range of body monitoring and injection equipment. The Sapien 190 can be operated by the instructor and connected to a bedside monitor that used the output signals from the patient simulator. Optional a medicine infusion pump can be connected to the simulator.

2.1 System context



2.2 System introduction

The instructor will be able to control the simulation like forcing a heart attack and monitor the waveform of the signals that is send to the bedside monitor. Two analogue outputs signals can be connected to a bedside monitor to display ECG and EDR signals. It is possible remotely using an Ethernet connection to the patient simulator to update and delete files in the scenarios database on Sapien 190. The optional infusion pump injects medicine into the patient and the flow of medicine can be monitored on the Sapien 190 LCD display.

3. SYSTEMET INTERFACES

3.1 Interface to human actors

Instructor controls the patient simulation by inputs to the LCD touch screen

3.2 Interface to external system actors

Remotely it is possible to update the scenarios database by use of an ftp connection with Ethernet connected to the patient simulator.

3.3 Interface to hardware actors

Analogue outputs signals to the LMON has a resolutions of 12 bits sampled at 250 hz. The analogue output has a voltage range of 0 - 4.096 volts.

3.3.1 Pulse interface

The pulse is send to a connected monitor using an RS232 connection (115200 baud, 8 data bits, no parity, 1 stop bit).

Format of the pulse signal is a maximum 3 bytes ASCII value (beats/minute). It is transmitted from the PSIMU to the LMON with a rate corresponding to the current heart rate or at least every second. The pulse value is terminated with a <CR>.

The format is : <16-bit pulse value > <CR>

Example a terminal can be connected to display the pulse values updated each second:

103<CR>

107<CR>

3.3.2 Infusion pump interface

The infusion pump is connected using a RS232 connection with the protocol described below.

A fixed 64 bytes ASCII PDU is transmitted from IPUMP to PSIMU.

This PDU is transmitted every second when the pump is started.

PDU format:

4 bytes startframe (##?*)

46 bytes medicin name

12 bytes volume infused (since started)

2 bytes CRC checksum

3.4 Interface to external software actors

WHAT TO WRITE HERE?

Iflg spec sect 3.3 skal vi benytte ftp. Og iht use case XX. Dette kræver at en Linux FTP daemon installers på target. Ex

4. USE CASE VIEW

In the first iteration the UC #1 has been selected since it provides the main functionality and is the essential use case for the architecture of the patient simulator.

Execute and Control Simulation

When the patient simulation is running it will perform reading of the digitized physiologic signals and send these “real time” values as analogue signals to local connected bedside monitoring equipments. Up to 2 analogue channels with different signals is possible to be simulated simultaneously. The simulated signals can be ECG or EDR. The pulse will be signaled to the bedside monitoring equipment as a digital signal.

4.1 Overview of architecture significant Use cases

The UC #1 has been selected for the first iteration of the ROPES spiral microcycle [2] in making the architectural, mechanistic and detailed design. This use case is significant and provides the central functionality of the patient simulator. This use case provides the basis functionality that allows the monitor to be connected being able to display the ECG and EDR signals. It also reduces the risk for developing the patient monitor since it covers all the unknown technologies of the product like:

- Reading the patient record files on the target (Linux, WFDB and target)
- Generating the analogue output signals (Writing to drivers)
- Display of signal waveform using Qt on target (Working with Qt on target)

4.2 Use case #1: Execute and Control Simulation scenarios

4.2.1 Use case goal

To simulate signals from the patient based on the selected scenario.
The waveform of signals to monitor and the status of patient are displayed.
The instructor must be able to monitor the simulated patient.

4.2.2 Use case scenarios

Scenario 1 - normal:

1. Opens scenario file
2. Search for record file
3. Opens record file
4. Continues to reads samples from record file and performs:
 - a. Use patient model to generate ECG signal
 - b. Use patient model and ECG signal to calculate EDR signal
 - c. Use patient model and ECG signal to calculate pulse
 - d. Update output signals: Pulse, ECG and EDR

Scenario 2 – normal with alternative scenario record:

1. Opens scenario file
2. Search for record file
3. Opens record file
4. Continues to reads samples from record file and performs:
 - a. Use patient model to generate ECG signal
 - b. Use patient model and ECG signal to calculate EDR signal
 - c. Use patient model and ECG signal to calculate pulse
 - d. Update output signals: Pulse, ECG and EDR
5. Open alternative record file after specified simulation time and continues at 2.

Scenario 3 – normal with IPUMP:

1. Opens scenario file
2. Search for record file
3. Opens record file
4. Continues to reads samples from record file and performs:
 - a. Reads medicine and volume from IPUMP
 - b. Use patient model to generate ECG signal
 - c. Use patient model and ECG signal to calculate EDR signal
 - d. Use patient model and ECG signal to calculate pulse
 - e. Update output signals: Pulse, ECG and EDR

Scenario 4 – error opening record file:

1. Opens scenario file
2. Failed to search and open record file
3. Error message on LCD display

4.3 Use case # 2: Select and Initiate Scenario

Initiate the simulation using a scenario configuration chosen by the instructor.

This use case is modified for this version only to start, stop, pause and resume. A fixed pre-programmed scenario can be started only playing one record file.

4.3.1 Use case scenarios**Scenario 1 – start and stop simulation:**

1. Instructor selects to start the simulation
2. The patient simulator will start to perform simulation according to UC #1
3. Instructor selects to stop the simulation
4. The patient simulator will stopped and no signals will be updated

Scenario 1 – pause and resume simulation:

The simulation must be started as specified in the scenario above.

1. Instructor selects to pause simulation
2. The patient simulator will stop updating the output signals and pulse

3. Instructor selects to resume simulation
4. The patient simulator will continue to perform simulation according to UC #1 from where it was paused

4.4 Use Case #3: Adjust Scenario Parameters

4.4.1 Use case goal

Adjust the parameters available in the current model running

4.4.2 Use case scenarios

Scenario 1 – adjusting gain:

5. Instructor adjust the gain parameter
6. The patient simulator is updated with the new gain value
7. The output of the ECG, EDR signal is adjusted according to the new gain setting

Scenario 2 – adjusting rate:

1. Instructor adjust the rate parameter
2. The patient simulator is updated to replay with the new sampling rate
3. The output of the ECG, EDR signal is updated according to the rate independent on the recorded signal rate (Default 250 Hz)

5. LOGICAL VIEW

This section describes the functionality that the system provides to the end user. The system architecture will be described as introduction. Following this, the major design implementations will be described on a package basis.

5.1 Overview

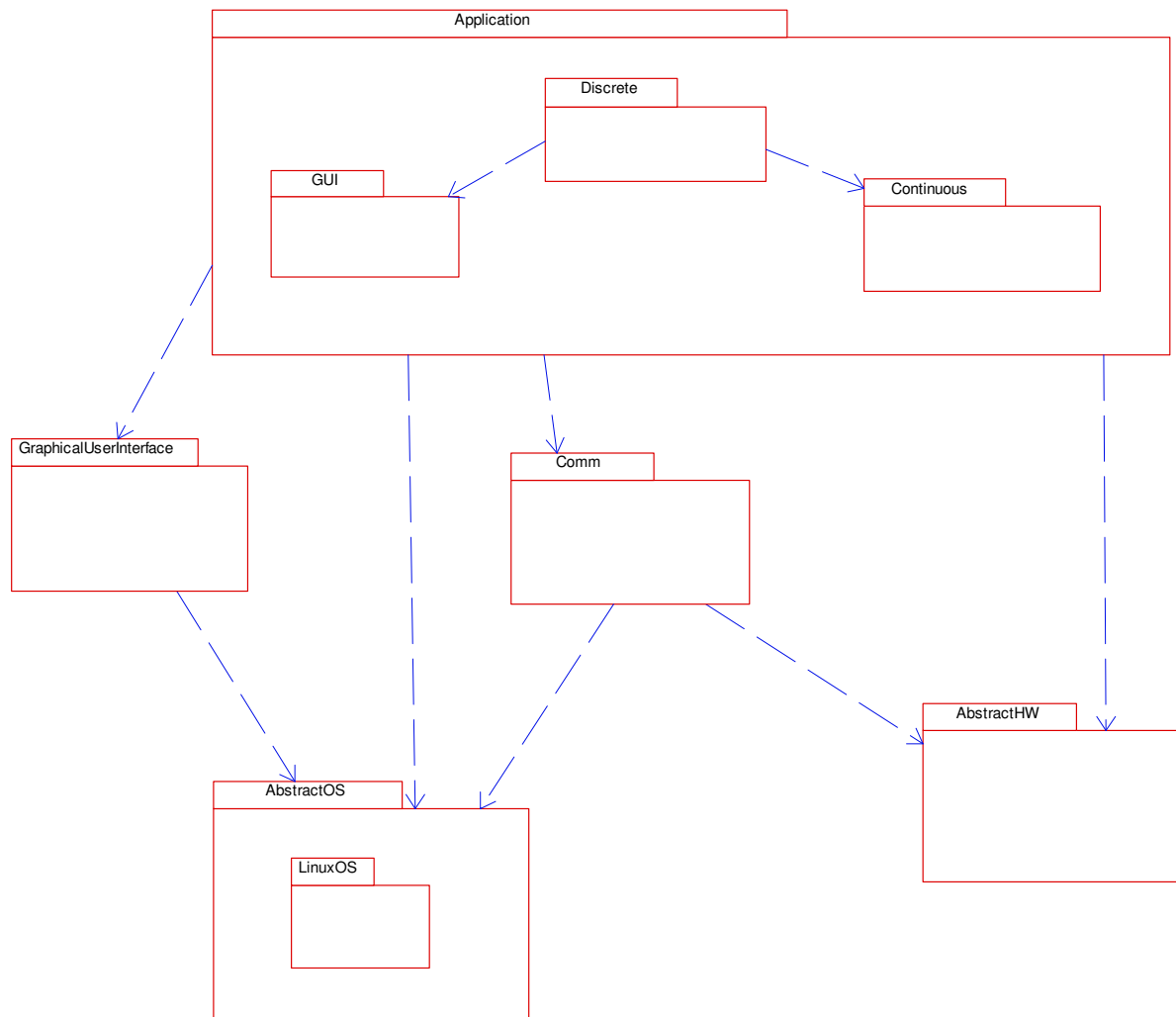


Figure 1 Five layered architecture for logical view

The architecture divides the application into five abstraction layers:

Applications – Business Logic

GUI – Graphical User Interface

Communication – Communication protocols

Abstract OS – OS specific methods

Abstract Hardware – Encapsulated hardware interfaces

Each abstraction layer is a logical layer representing a well defined domain. Dividing the system into several layers ensures high cohesion for each domain and low coupling between the domains. This simplifies the process of modifying our design or extending it.

5.2 Architecturally significant design packages

The implementation will be explained on a design package basis.

5.2.1 Continuous Package

The continuous package contains all classes to run in the real-time part of the system. This package must respond to events and supply the hardware outputs with real-time data. This is done with stringent requirements to jitter and latency.

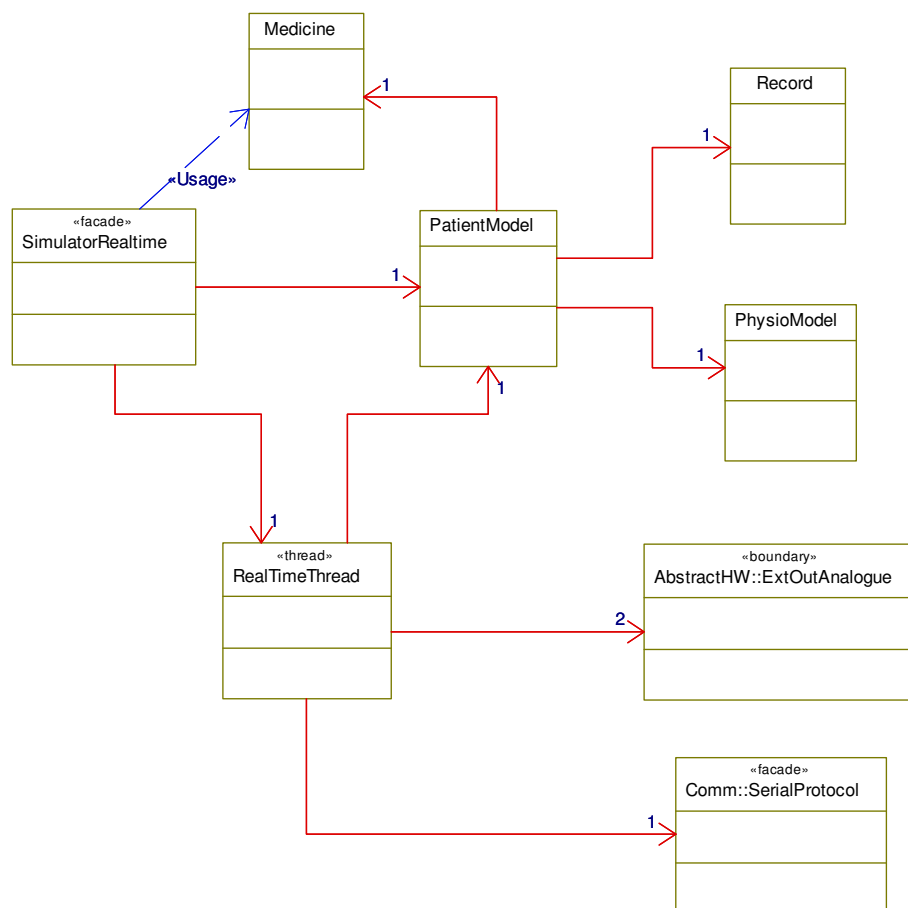


Figure 2 Major Classes in Continuous Package

The *SimulatorRealTime* class provides a façade towards the discrete system. It provides a uniform interface that hides all the underlying logic.

The center of the continuous package is the *PatientModel* class. The patient model emulates a patient, thus it emulates the patients' subsystems, such as heart, lungs etc.

The *PatientModel* uses:

- *Record*, that provides ECG data and signal annotations.
- *PhysioModel*, that provides filters to calculate physiological data based on the record data, medicine and user input (from the discrete system)
- *Medicine*, that provides information about the current medicine injection

The *RealTimeThread* handles the real-time analogue and digital signals. Originally created by the *SimulatorRealTime*, this thread acquires data from the *PatientModel* and outputs its result to the abstracted hardware outputs.

The *ExtOutAnalogue* class wraps the interface to the D/A converter devices and provides

each of the two D/A channels as separate objects to the *RealTimeThread*.

The *SerialProtocol* adds a simple protocol to the raw simulator data provided, before transmitting it using the abstracted serial port hardware (*ExtOutSerial*). Figure 3 explains this in detail. This figure also shows how *Medicine* actually abstracts a physical interface to an injection pump unit.

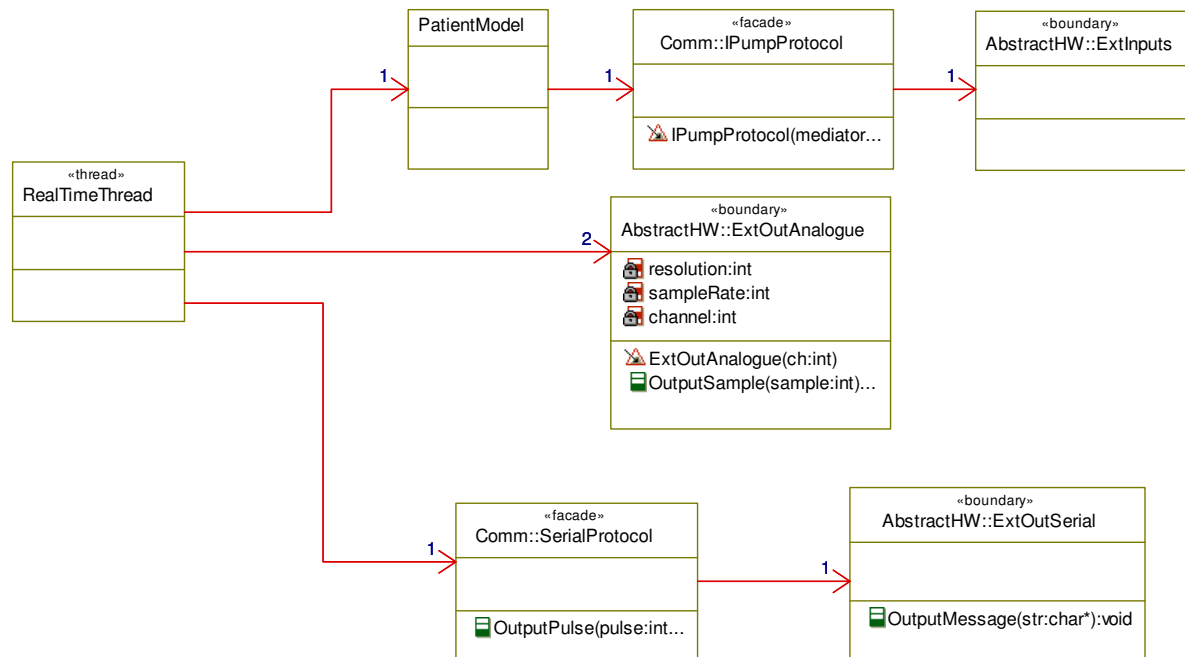


Figure 3 Boundary Classes for RealTimeThread

It has been chosen to implement the collection of record samples in the *PatientModel* using the **Iterator Pattern** (Figure 4). Compared to the original GOF presentation, *PatientModel* is the Client, *Record* is the Aggregator and *RecordIterator* is the actual iterator. Using this pattern we can let the *PatientModel* iterate through the records without actually knowing anything about them. This makes the system insensitive to changes in the record. The iterator is implemented as an external iterator, as the iteration is controlled from *PatientModel*.

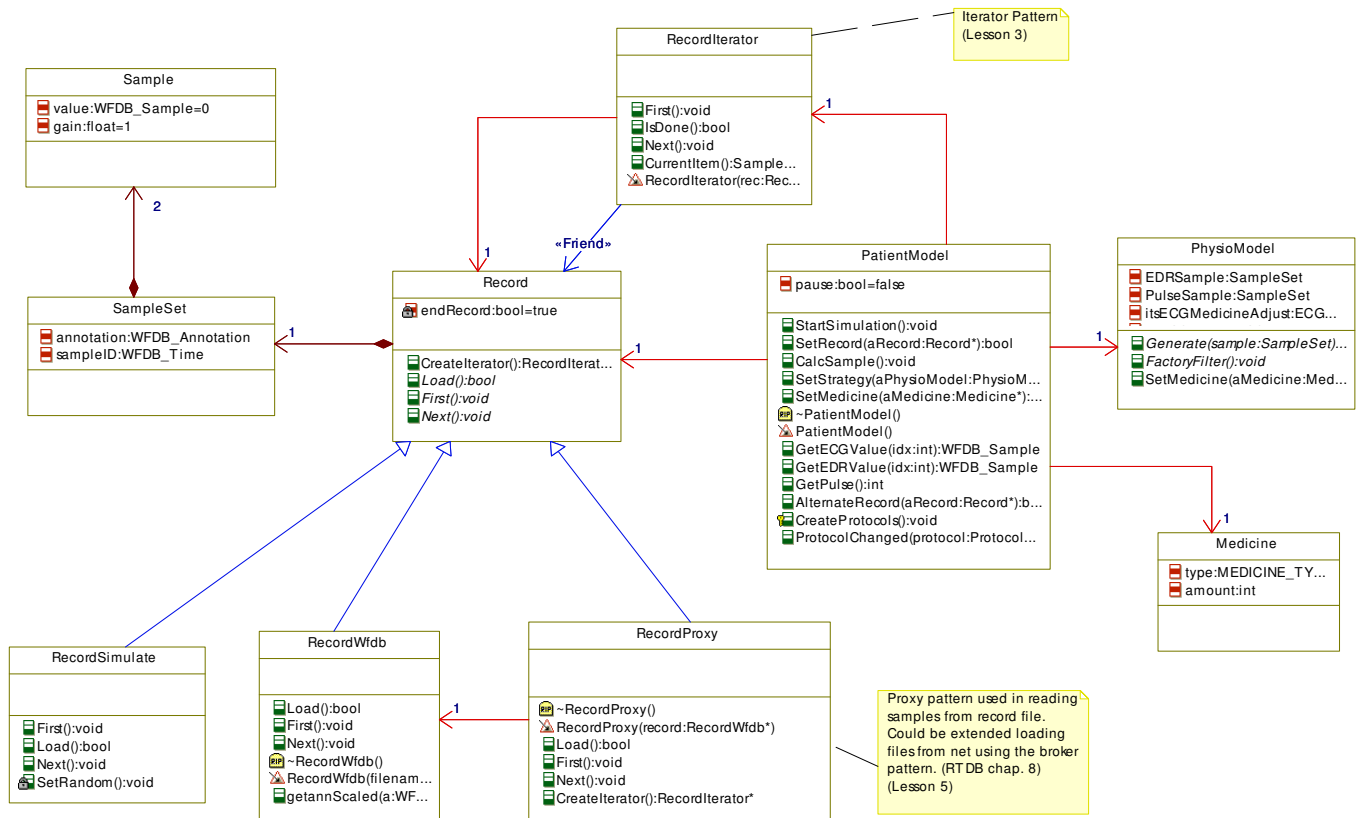


Figure 4 Proxy and Iterator Pattern used to access Records from the PatientModel

The *PatientModel* is implemented similar to the **Mediator pattern**. The *PatientModel* acts as a mediator between the *Record*, the *PhysioModel* and the *Medicine* classes. These classes do not interact directly; rather information is passed among them by means of the mediator class. The mediator promotes loose coupling between its clients and centralizes control of these. The result, again, is a much more rugged design, that is easier to test and maintain. The implementation is not strict to the GOF implementation, where we have the Mediator and Colleague super classes. In a future implementation that includes an infusion pump, it would be natural to let the medicine be a concreteColleague², now being able to notify the Mediator of changes in medicine.

The *Record* inherits to three children: *RecordSimulate*, *RecordWfdb* and *RecordProxy*. *RecordSimulate* generates random sample values for simulation. *RecordWfdb* acquires samples from the WFDB record specified in the scenario. Finally, *RecordProxy* implements the **Proxy Pattern** to give us a proxy for future interfaces such as access to remote data or access to new data sources. The default implementation of the proxy calls the *RecordWfdb* methods directly

² [1] page 276

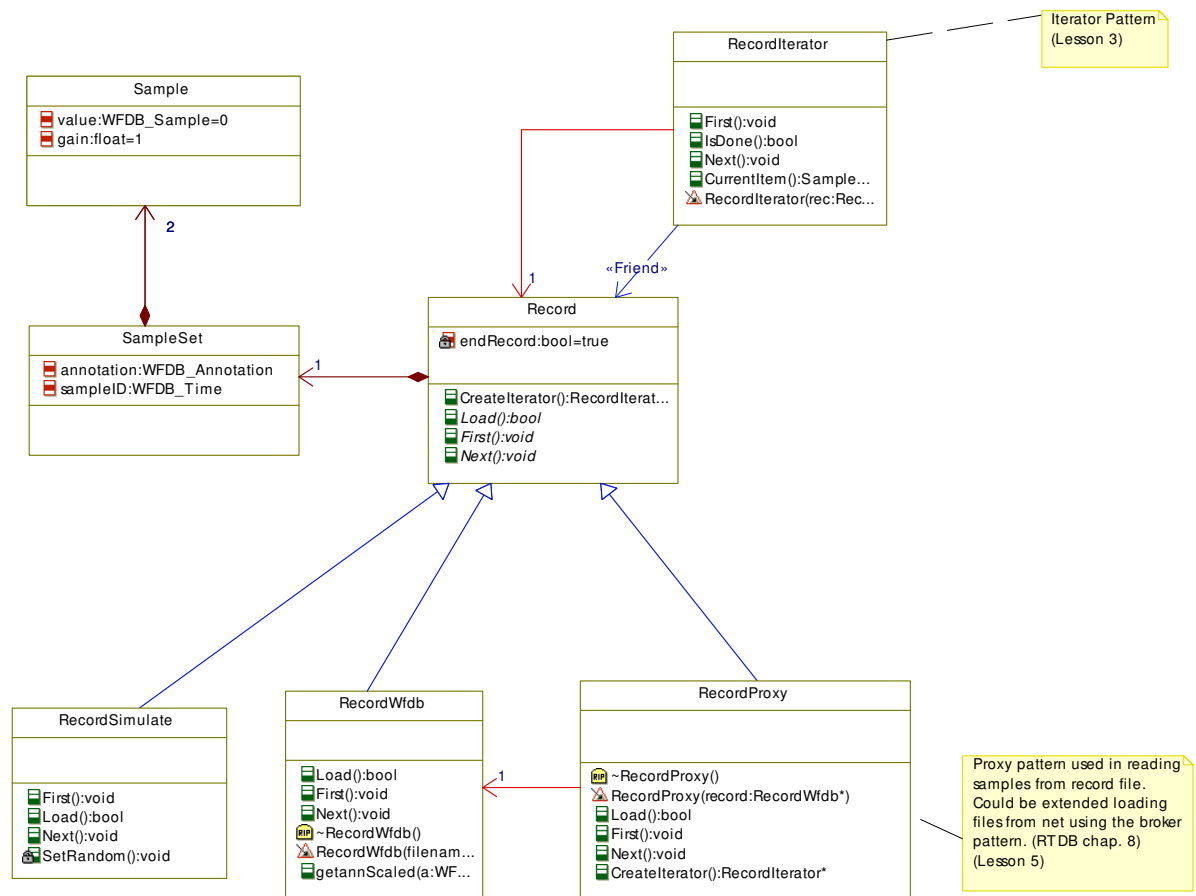


Figure 5 Record and Iterator

Each *Record* object has a sample set. The sample set contains

SampleID – A sequential sample index

Annotation – Annotation text for the current sample index

Value[1..*] – Data sample. Sample time is aligned

Gain[1..*] – Gain of the corresponding sample

One sample is read at a time from *RecordWfdb* or the other classes that inherit from *Record*. This is done in the “next” method, called by the iterator.

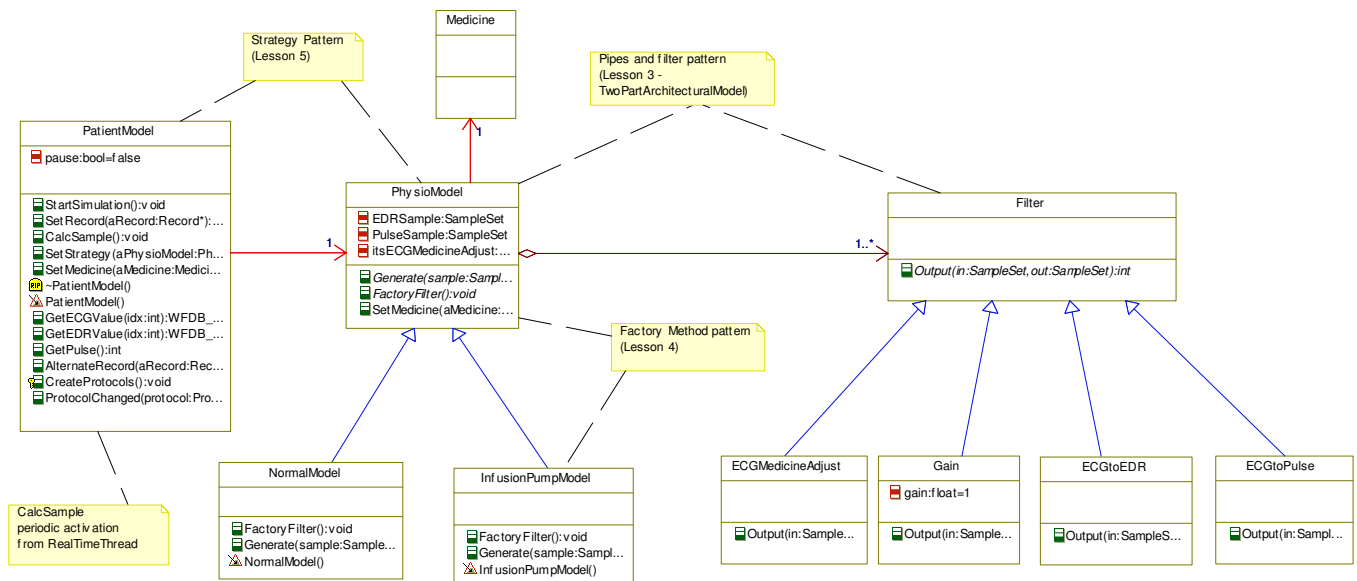


Figure 6 Strategy, Filter and Pipes Pattern used for PhysioModel

The *PhysioModel* is build using a **Strategy Pattern**. The *PatientModel* provides a `SetStrategy` method to set the *PhysioModel* strategy to either *NormalModel* or *InfusionPumpModel*. This corresponds to the use case scenarios described in 4.2.

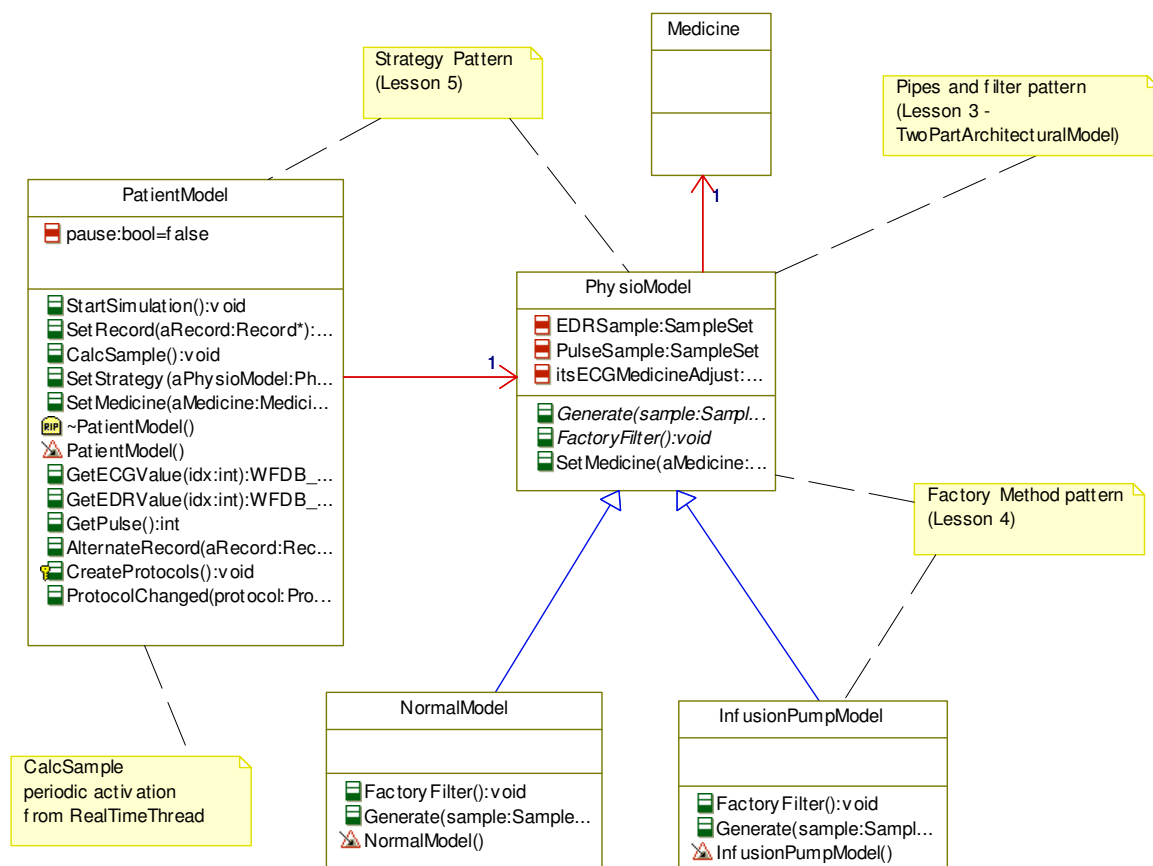


Figure 7 Strategy for PatientModel

The *PhysioModel* uses a collection of filters with a uniform interface, thus making it possible

to connect any two filters in series. This is also known as the **Filters & Pipes Pattern**.

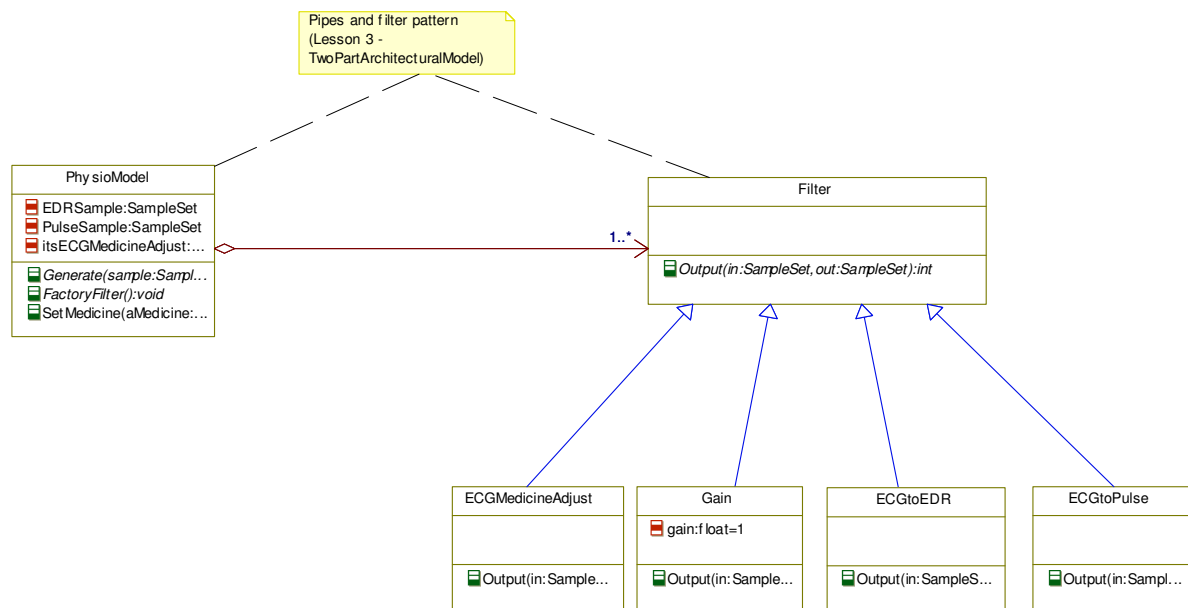


Figure 8 Filter Pattern for PhysioModel

The combination of these two patterns is typical for a two-part architecture. The discrete system³ chooses a strategy which is then passed from the discrete system to the continuous system, where it is executed.

The classes inherited from *PhysioModel* uses a **Factory Method Pattern** to create filter objects according to the chosen strategy. The “Generate” method implements the actual filter chain.

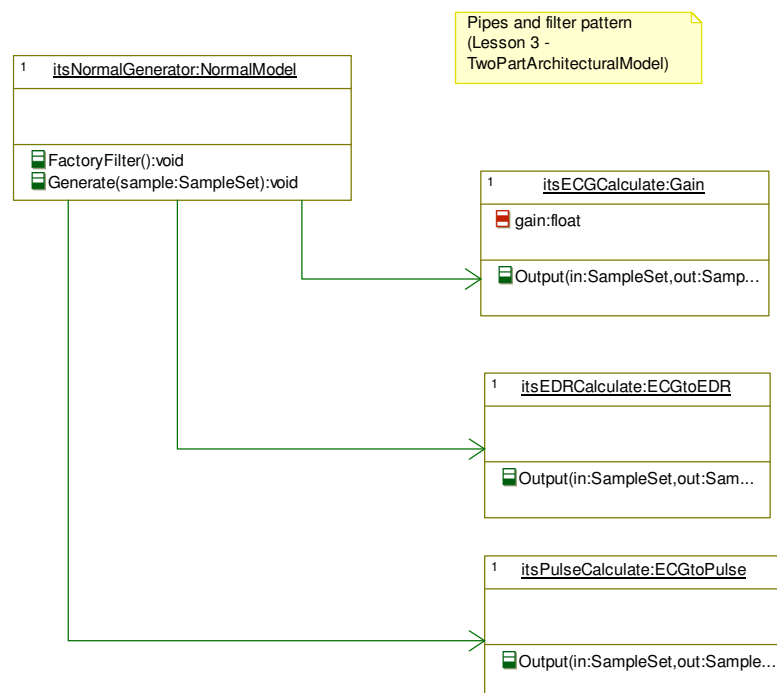


Figure 9 NormalGenerator using filters to generate signals

³ Designing Event-Controlled Continuous Processing Systems, page 8

To provide a uniform interface between the discrete- and the continuous parts of the patient simulator, it has been chosen to wrap the discrete sub system with a **Façade Pattern**. This provides a single class for the real-time part to interface to, thus lowering the coupling between the two sub-systems. As seen in Figure 1, the façade wraps *Record*, *PhysioModel* and their relatives. Another job for the façade is to instantiate all its private classes.

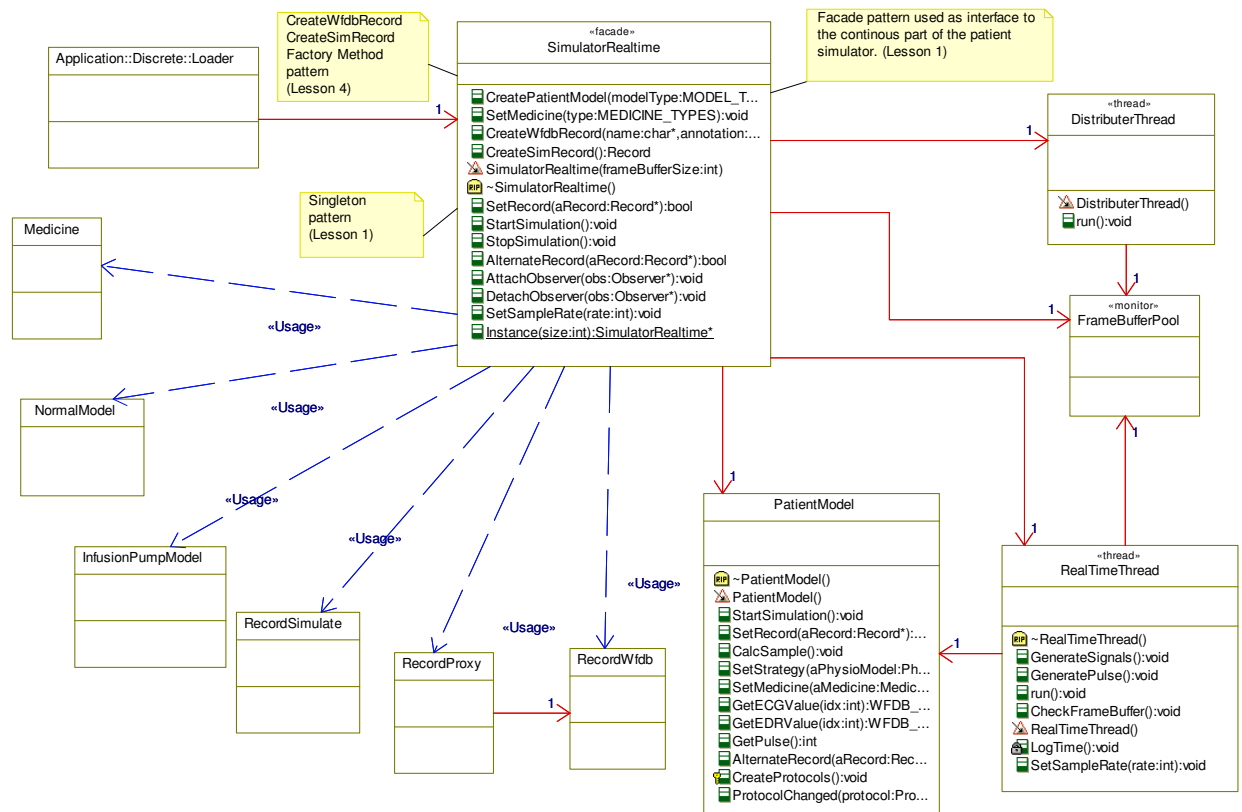


Figure 10 Façade Pattern used for interface to the Continuous Package

5.2.2 Discrete Package

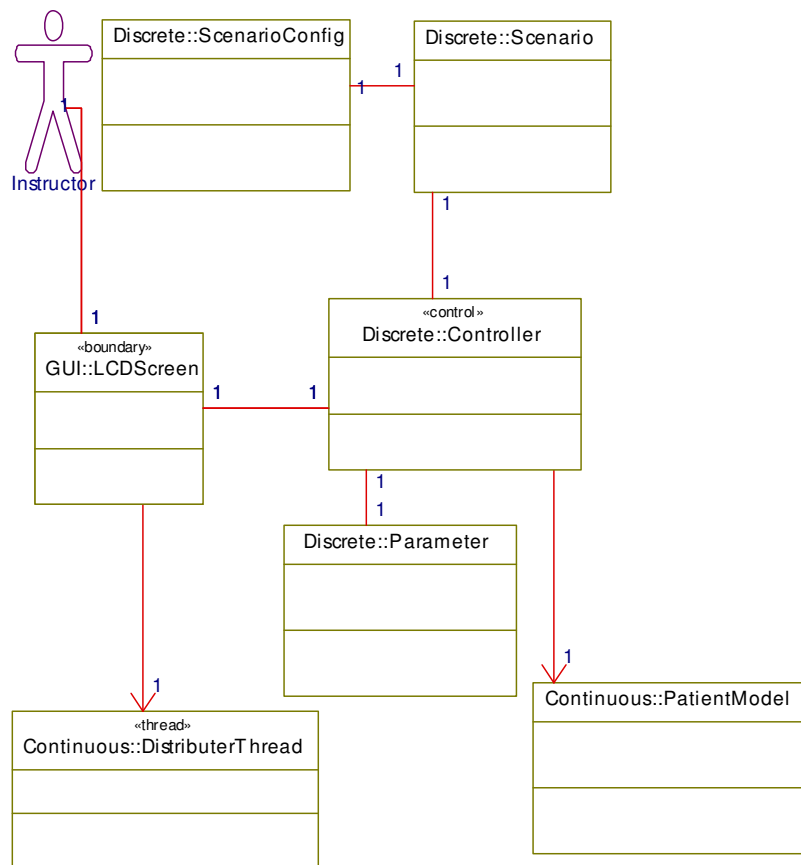


Figure 11 Application model for discrete package

To loosen the coupling between our UI and controller, we have implemented the **Command Pattern**. The command pattern is used to execute requested commands from the UI, on our continuous system via callbacks. We have 2 types of command pattern, one command pattern is used to change parameters (the Parameter class), based on user import, things such as, rate, gain and what record to read. The other one is described later on. See Figure 12.

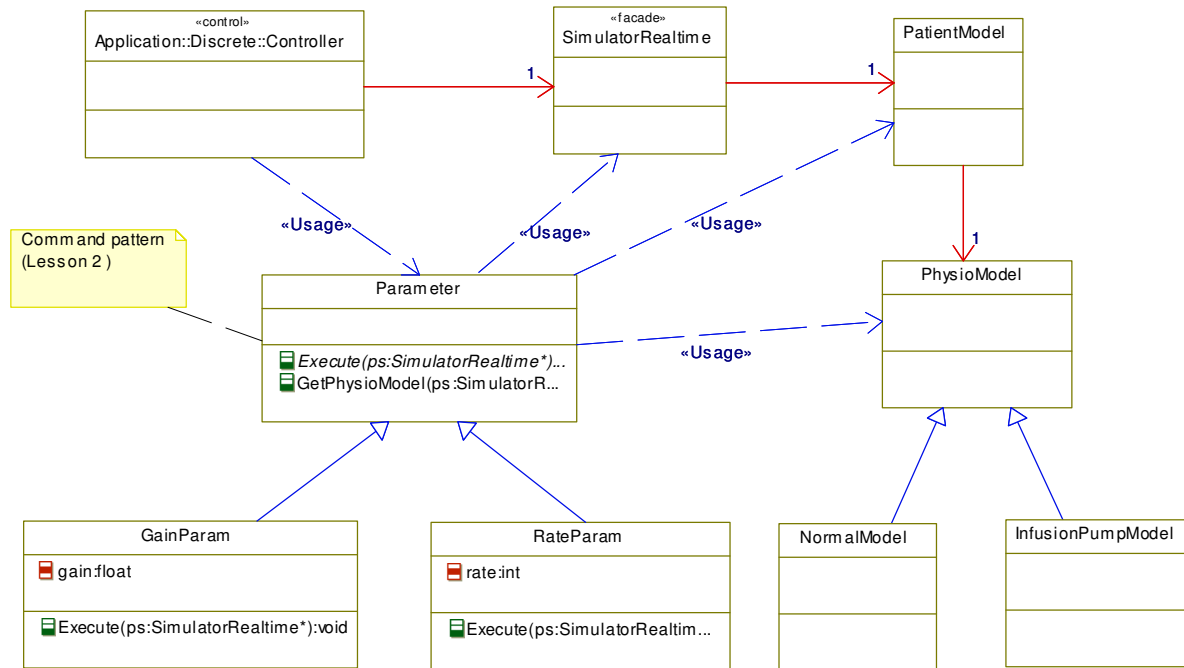


Figure 12 Command pattern used to set parameters in real-time simulator

To transfer information to our UI, we have implemented **Observer Pattern**, which with help of the Distributor Thread is used to distribute information in our discrete system.

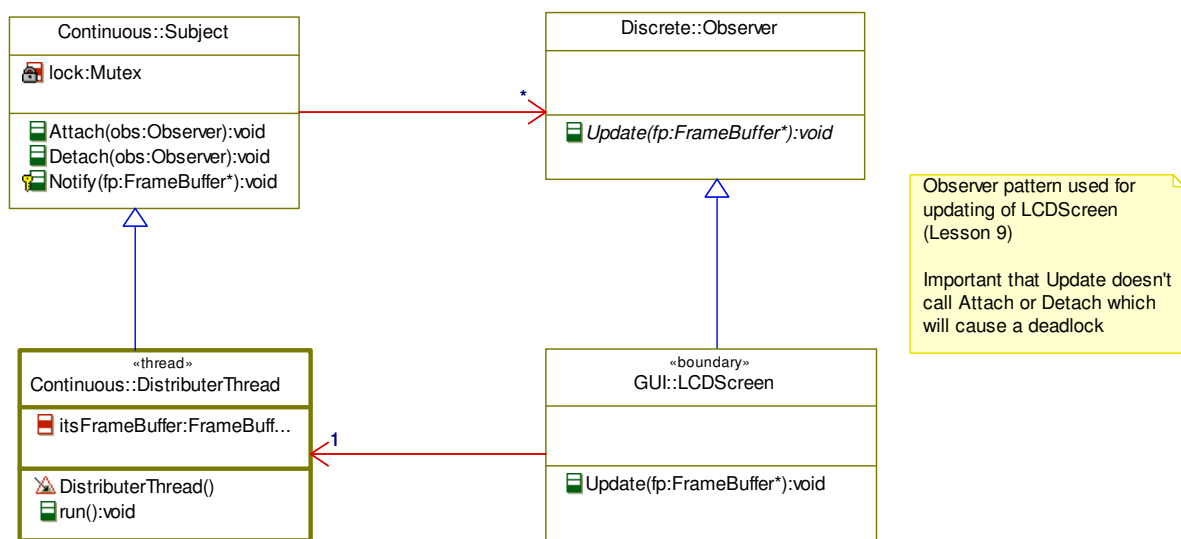


Figure 13 Observer pattern used to notify GUI with new frame buffer

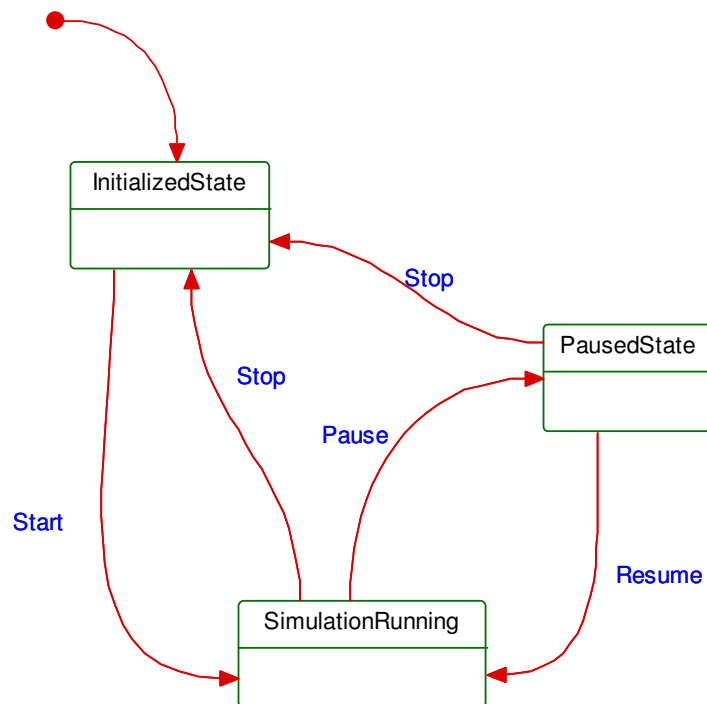


Figure 14 State chart for SapienApplication controller

To control Continuous system, we have implemented a **state pattern** in the presentation layer. This pattern allow us to control the continuous system, by changing state based on user input, and reflect it into our continues system. This is a how we initialize, start, pause, resume and stop our system based on user input.

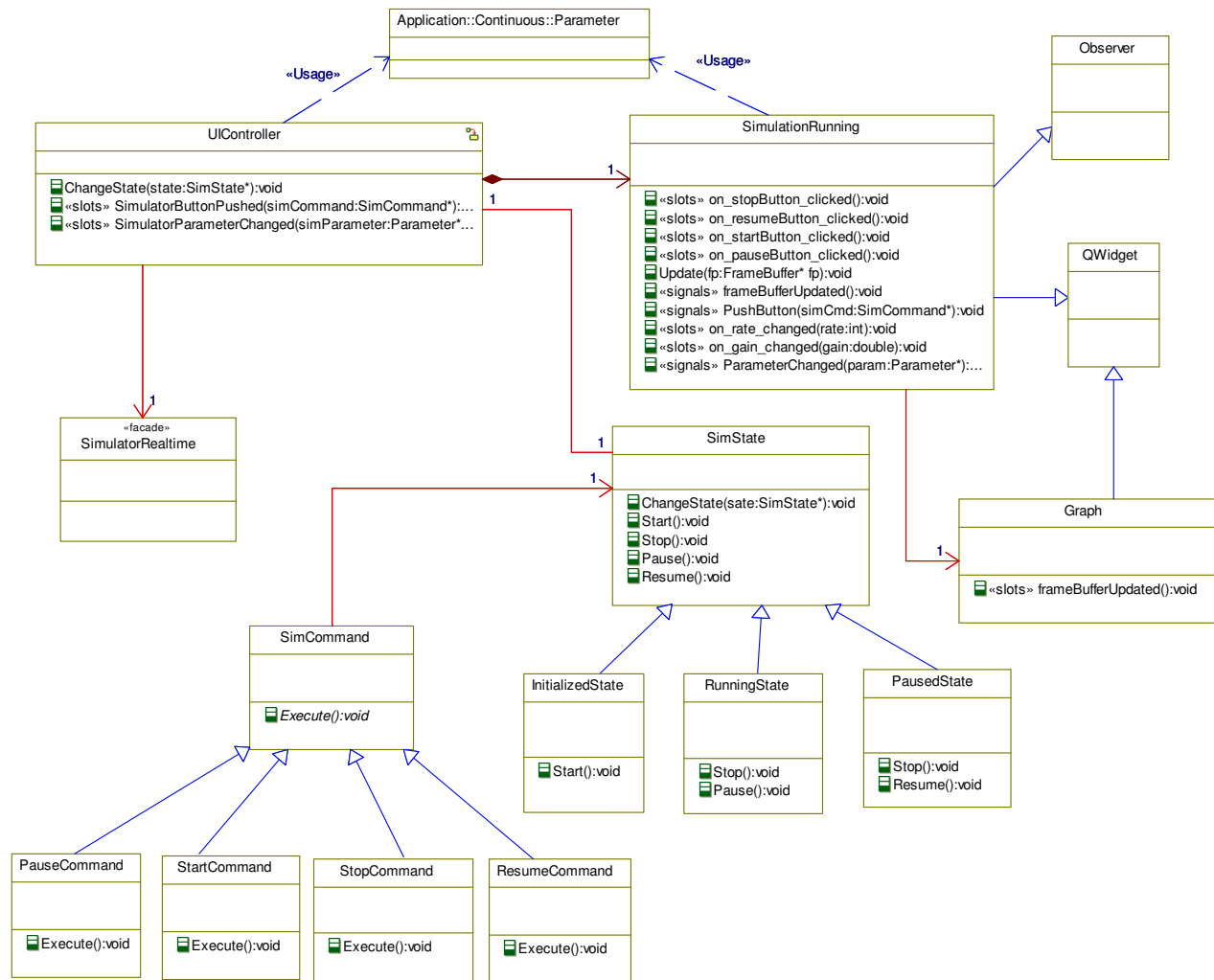


Figure 15 Command, State and Observer pattern used to design SapienApplication (Controller)

As written before we have implemented **Command pattern** to loosen the coupling between our UI and controller. The **SimCommand** is used to transfer actions from the UI to our state pattern (**SimState**), controlling state based on user input. The **SimulationRunning** class functions as a subject in our **Observer Pattern**, and transfer information from our continuous system into our UI. The state pattern as mentioned before, control the current state of our continuous system, based on user input from the UI.

5.2.3 Communication Package

The *SerialProtocol* class is provided for creating data packages according to the description in 3.3.1. Integrity check and re-transmission is handled in the abstracted hardware layer, *ExtOutSerial*.

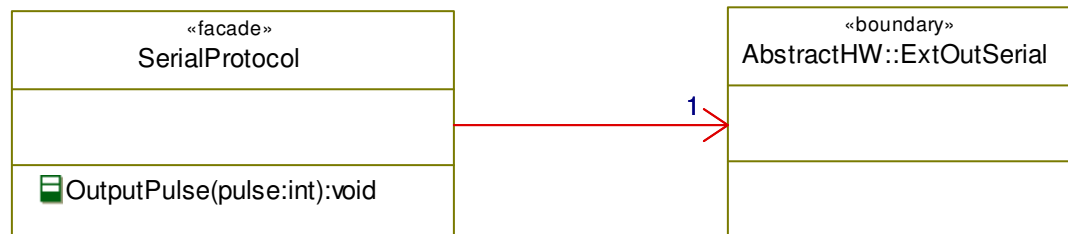


Figure 16 Communication package Serial protocol

The current design of the *PatientModel* uses a Mediator-pattern-like structure. The next version of the Sapien 190 will support interfacing to an IPUMP. Modifying the *PatientModel* design to use the GOF **Mediator Pattern**, will allow the infusion pump to notify the *PatientModel* when new medicine is injected.

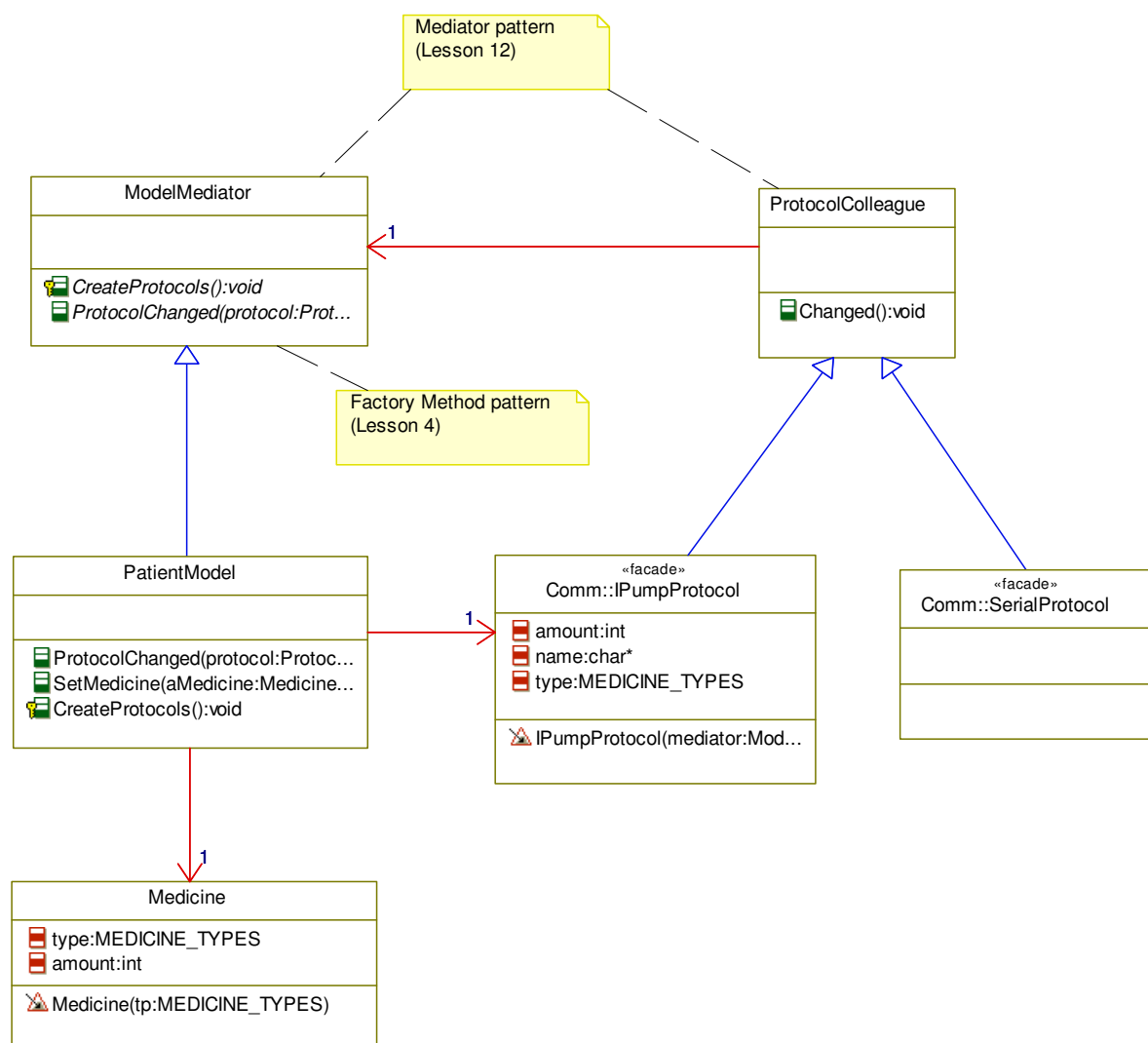


Figure 17 Mediator pattern used to update PatientModel with external input from protocols

The implementation will work like this: When new medicine is injected, that is a data package is received (see 3.3.2), the *IPumpProtocol* will call its inherited *Changed()* method. The *Changed()* method will then call *PatientModel::ProtocolChanged()*, to notify the *PatientModel* that something changed in the *IPumpProtocol*.

The *PatientModel* should then get the new medicine type and amount from the *IPumpProtocol* and create a new corresponding *Medicine* object.

This way, the mediator will decouple the *IPumpProtocol* and the *Medicine* classes and mediate the IPUMP inputs into new *Medicine* objects.

Getter and setter methods are not shown in Figure 17.

5.2.4 AbstractHW Package

The *ExtOutSerial* wraps the serial port interface. The intention is to use a “tty”⁴ device. These do not provide means for transmission integrity check and re-transmission. This will have to be implemented in the *ExtOutSerial* class.

The *ExtOutAnalogue* class provides a façade to the abstracted analogue output. Two D/A channels are provided in the hardware. A **Singleton Pattern** has been implemented to limit the number of *Dac* objects to one for each channel. The *_instance* attribute is an array two elements, one for each D/A channel. Thread protection has been added to ensure that two threads cannot access a *Dac* objects simultaneously.

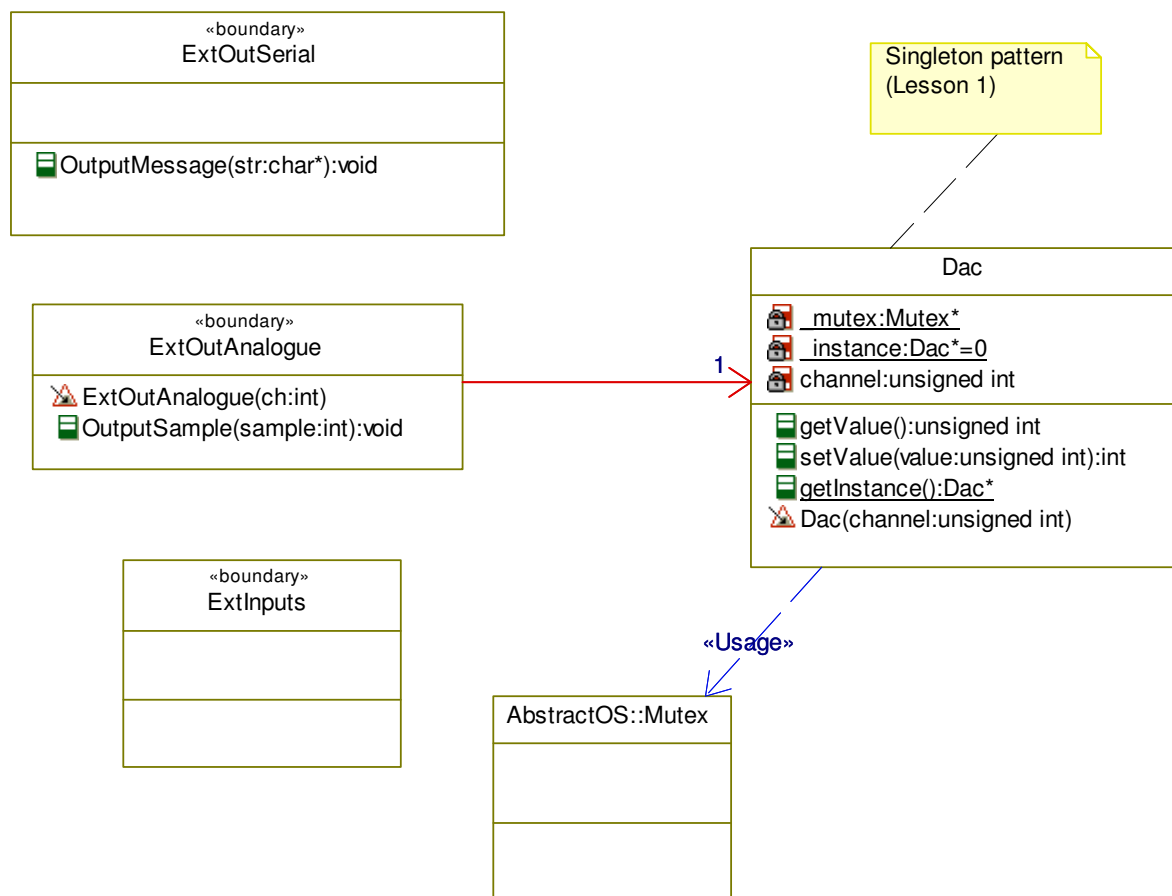


Figure 18 Hardware Abstraction using singletons for Dac abstraction

⁴ <http://www.linuxjournal.com/article/5896>

5.2.5 Application Helper Classes

To improve the design a number of helper classes have been created.

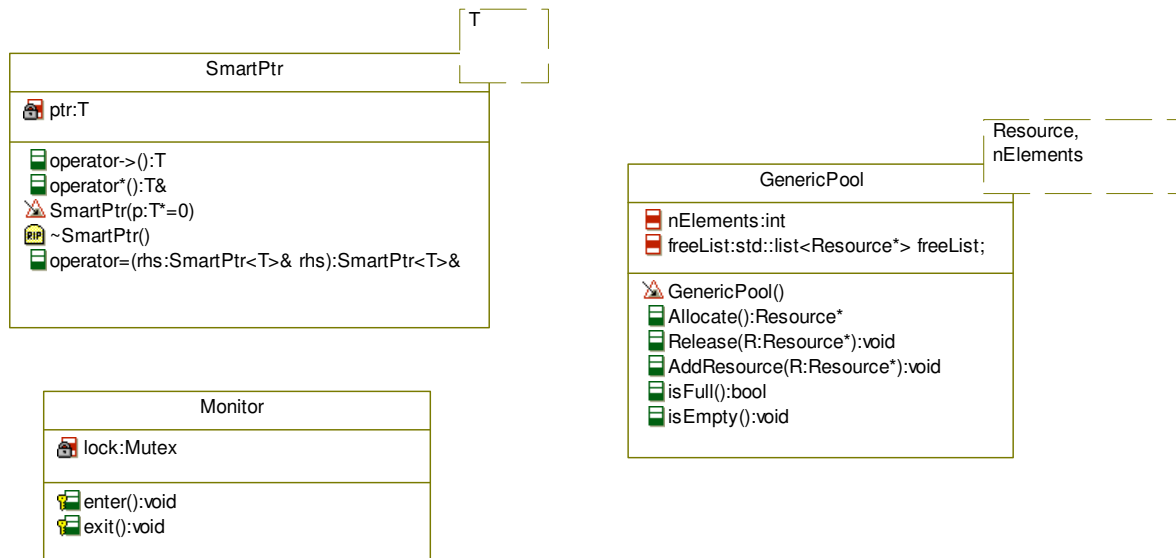


Figure 19 Application Helper classes

The *SmartPtr* class wraps a normal c-pointer. The constructor creates an object and the destructor deletes it, which is the smart thing about this pointer type. The “->” and “*” operators are overloaded, so that the smart pointers can be worked on like ordinary pointers. The *SmartPtr* class uses a **template pattern** that allows it to be used for pointers of different object types. The function of the *SmartPtr* class is very similar to that of the C++ standard library class “auto_ptr”⁵.

A *SmartPtr* is used for creation of the *PatientModel* object, when the Test Model button is pressed in the GUI.

The *Monitor* class is used to implement the **Monitor Pattern**. It is used to synchronize access to a shared resource and is basically just a wrapped c-mutex. It is used for the *PatientModel* and the *FrameBufferPool*. The *FrameBufferPool* is accessed by both the Distributer- and RealTime threads. The *Monitor* Class inherits its methods “enter()” and “exit()” to *FrameBufferPool*, who uses them for allocation and release of the pool resource.

The *GenericPool* class implements the memory pattern called **Pool Allocation Pattern**. This pattern allocates a pool of objects at startup. These objects can be requested from the pool and released to it at run-time. The static memory allocation is faster than dynamic allocation at run-time. The *GenericPool* class is used by the *FrameBufferPool* to store frame buffer objects.

⁵ <http://ootips.org/yonat/4dev/smart-pointers.html>

5.3 Use case realizations

This section describes the design of the uses cases that have been implemented so far. Refer to the Sapien 190 Requirement Specification [8] for use case details. The description uses the flow of the use case.

5.3.1 Use case #1: Execute and Control Simulation scenarios

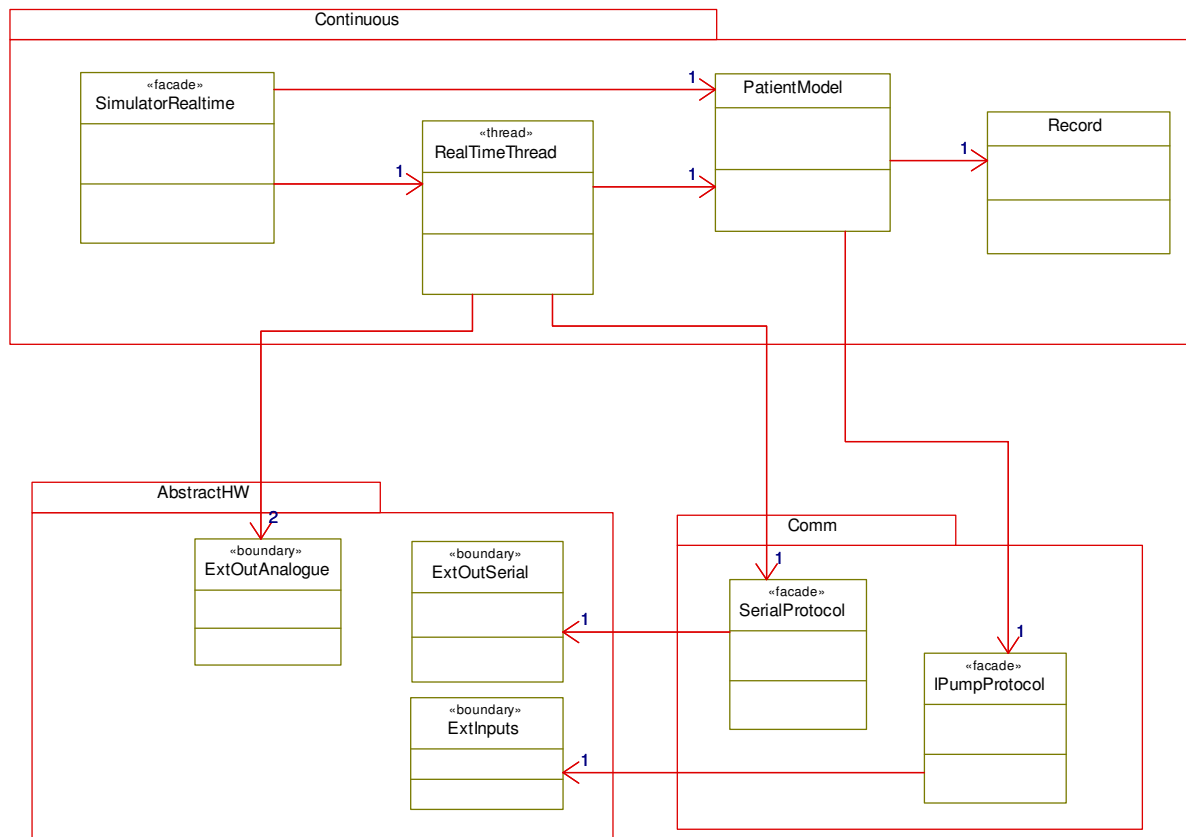


Figure 20 Logical view for use case #1 Execute and Control Simulation

This use case is activated when the simulation has been started by the user. It therefore works in the continuous domain, rather than the discrete.

The design description is based on a simulation made in the Rhapsody tool.

Test setup in Rhapsody for #UC 1 continuous package SimulatorRealtime

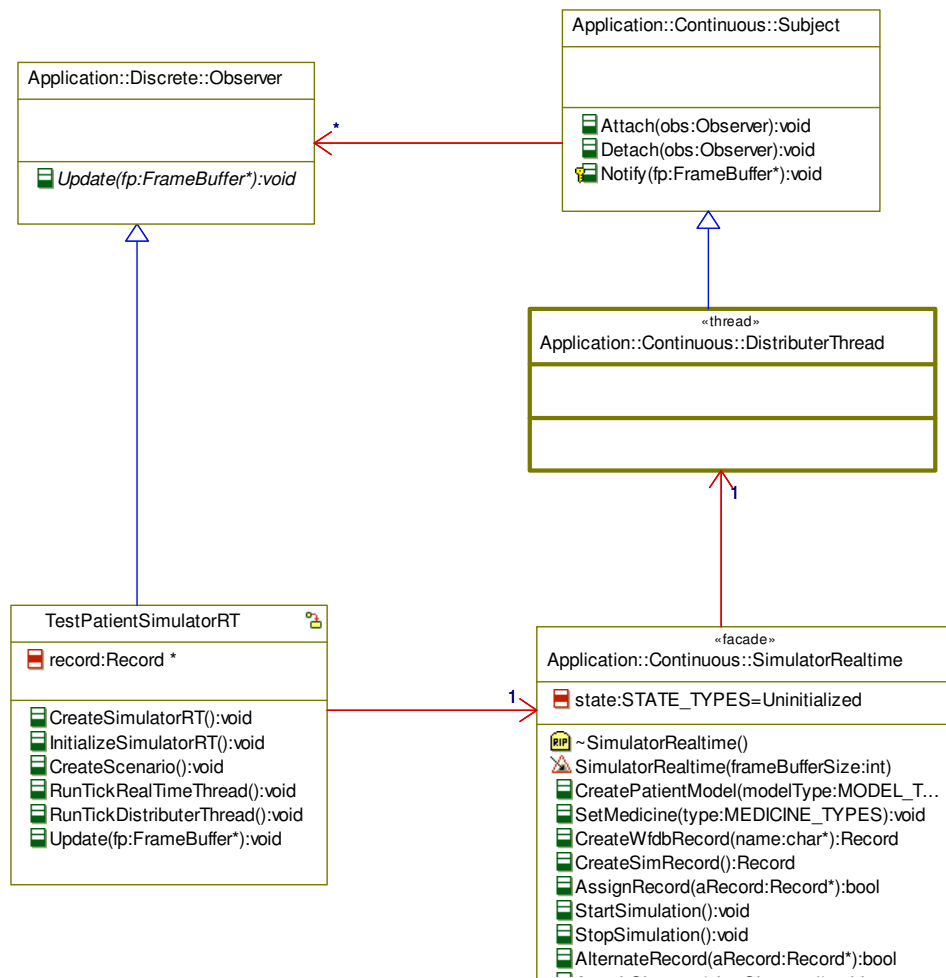


Figure 21 Test setup for UC#1 – test setup in Rhapsody only

The test is created in the *TestPatientSimulatorRT* class. This class creates all objects and implements an observer pattern.

The observer pattern is used to monitor the results of the *SimulatorRealtime*.

The test itself is created as a state machine in the Rhapsody tool (Figure 22).

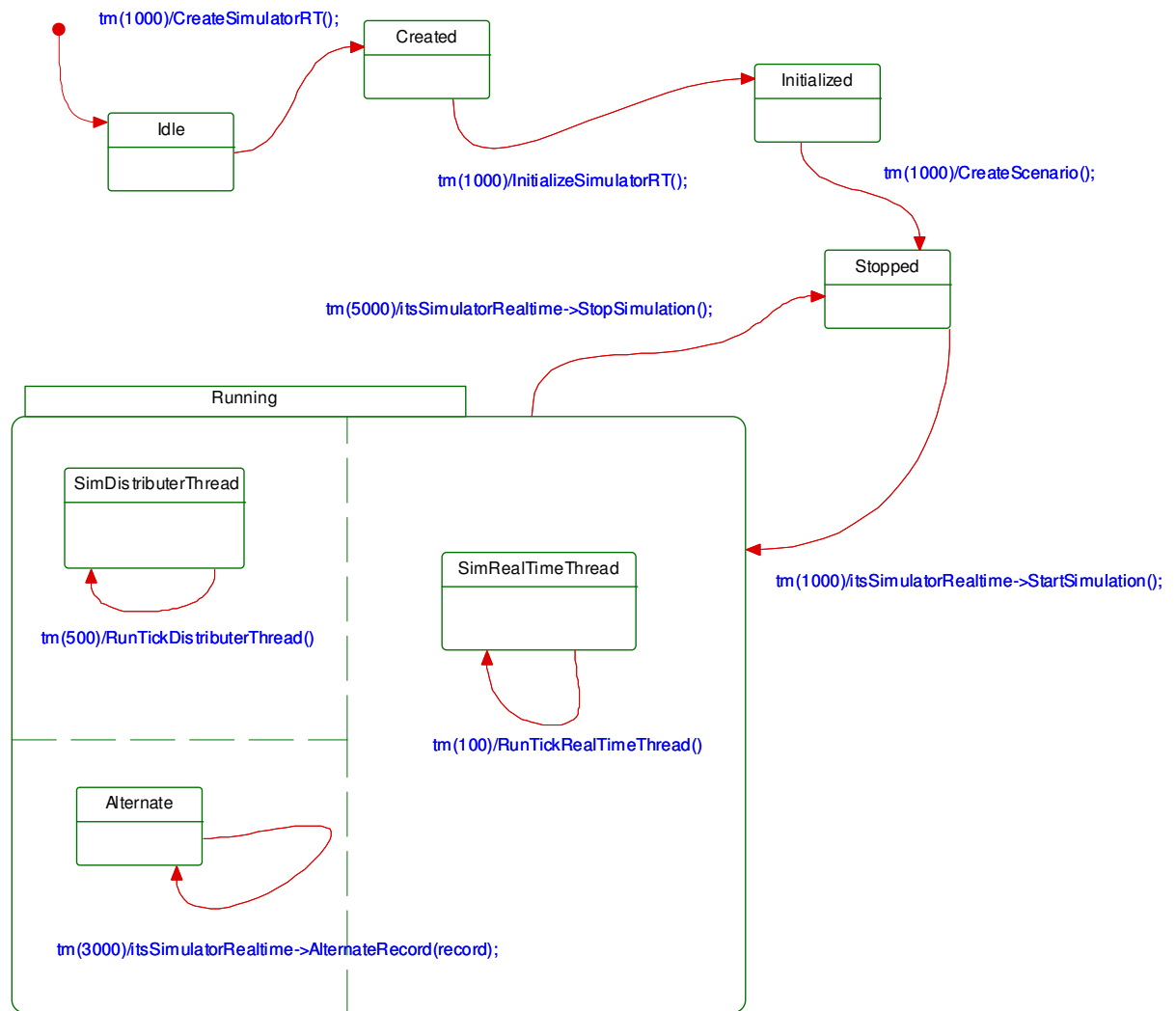


Figure 22 State machine test of UC#1 including simulation of Threads in Rhapsody

As shown in the state chart, the test is run like this:

- After 1000 ms, the SimulatorRT is created.
- After another 1000 ms, the SimulatorRT is initialized.
- After another 1000 ms, a scenario is created.
- After another 1000 ms, the simulation is started and the three “threads” are running.

When the simulator is running, the three threads are scheduled by a timer:

- For every 100 ms the RealTime “thread” is invoked.
- For every 500 ms the Distributer “thread” is invoked
- For every 3000 ms the AlternateRecord “thread” is invoked.

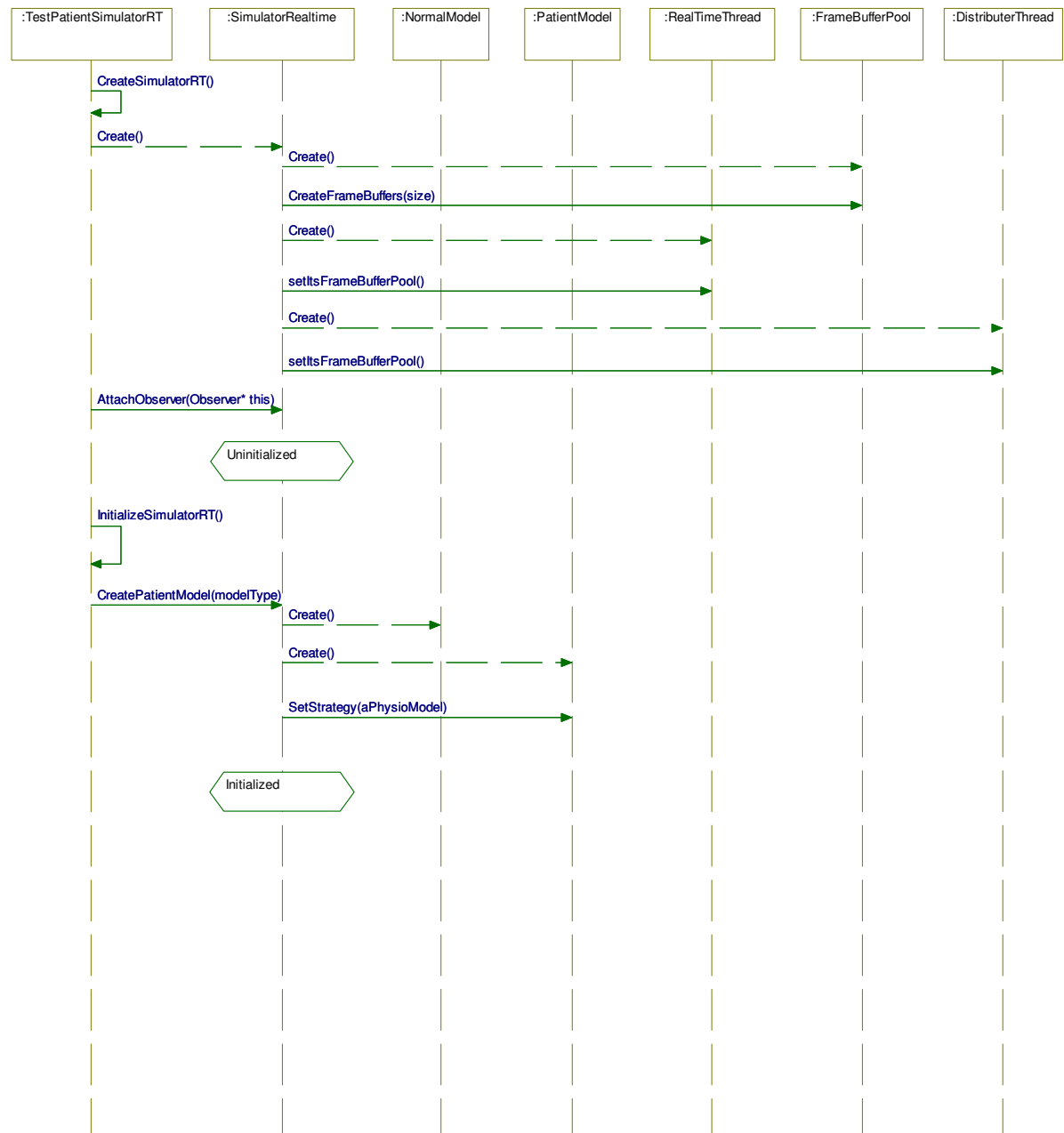


Figure 23 Sequence Diagram: Create Realtime Simulator

Figure 23 describes the creation of the simulator objects. Note how the patient model strategy is set during the patient model creation.


```
void TestPatientSimulatorRT::CreateSimulatorRT() {
    itsSimulatorRealtime = new SimulatorRealtime(5);
    itsSimulatorRealtime->AttachObserver(this);
}

SimulatorRealtime::SimulatorRealtime(int frameBufferSize) :
state(Uninitialized)
{
    itsPatientModel = NULL;
    itsFrameBufferPool = new FrameBufferPool();
    itsFrameBufferPool->CreateFrameBuffers(frameBufferSize);
    itsRealTimeThread = new RealTimeThread();
    itsRealTimeThread->setItsFrameBufferPool(itsFrameBufferPool);
    itsDistributerThread = new DistributerThread();
    itsDistributerThread->setItsFrameBufferPool(itsFrameBufferPool);
}
```

```
void TestPatientSimulatorRT::InitializeSimulatorRT() {
    itsSimulatorRealtime->CreatePatientModel(SimulatorRealtime::Normal);
}

void SimulatorRealtime::CreatePatientModel(const
SimulatorRealtime::MODEL_TYPES& modelType) {
    if (state != Running)
    {
        if (itsPatientModel != NULL) delete itsPatientModel;
        setItsPatientModel(new PatientModel());

        switch (modelType)
        {
            case Normal:
                itsPatientModel->SetStrategy(new NormalModel());
                break;
            case InfusionPump:
                itsPatientModel->SetStrategy(new InfusionPumpModel());
                break;
        };

        state = Initialized;
    }
}
```

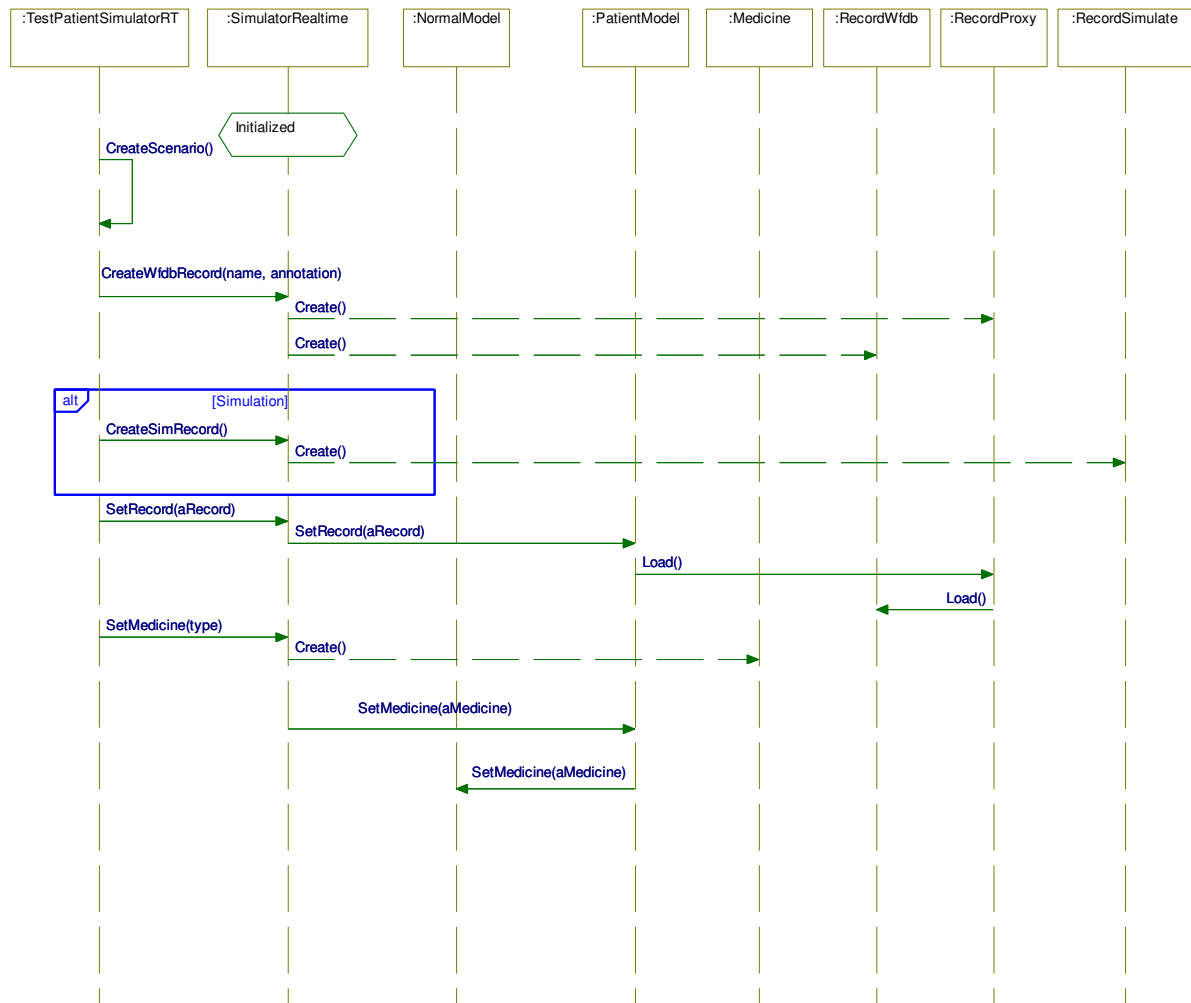


Figure 24 Sequence Diagram: Create WFDB or Simulation Record and Set Medicine

```
void TestPatientSimulatorRT::CreateScenario() {
    GainParam gainParam;
#ifdef _LINUX
    record = itsSimulatorRealtime->CreateWfdbSimRecord("100s", "atr");
#else
    record = itsSimulatorRealtime->CreateSimRecord();
#endif
    itsSimulatorRealtime->SetRecord(record);
    itsSimulatorRealtime->SetMedicine(SimulatorRealtime::Morphine);
    gainParam.setGain(0.50);
    gainParam.Execute(itsSimulatorRealtime);
}

Record* SimulatorRealtime::CreateWfdbRecord(char* name, char* annotation) {
    return new RecordProxy(new RecordWfdb(name, annotation));
}

bool SimulatorRealtime::SetRecord(Record* aRecord) {
    if (itsPatientModel != NULL)
    {
        state = Stopped;
        return itsPatientModel->SetRecord(aRecord);
    }
    return false;
}

void SimulatorRealtime::SetMedicine(const
SimulatorRealtime::MEDICINE_TYPES& type) {
    if (itsPatientModel != NULL)
        itsPatientModel->SetMedicine(new Medicine(type));
}
```

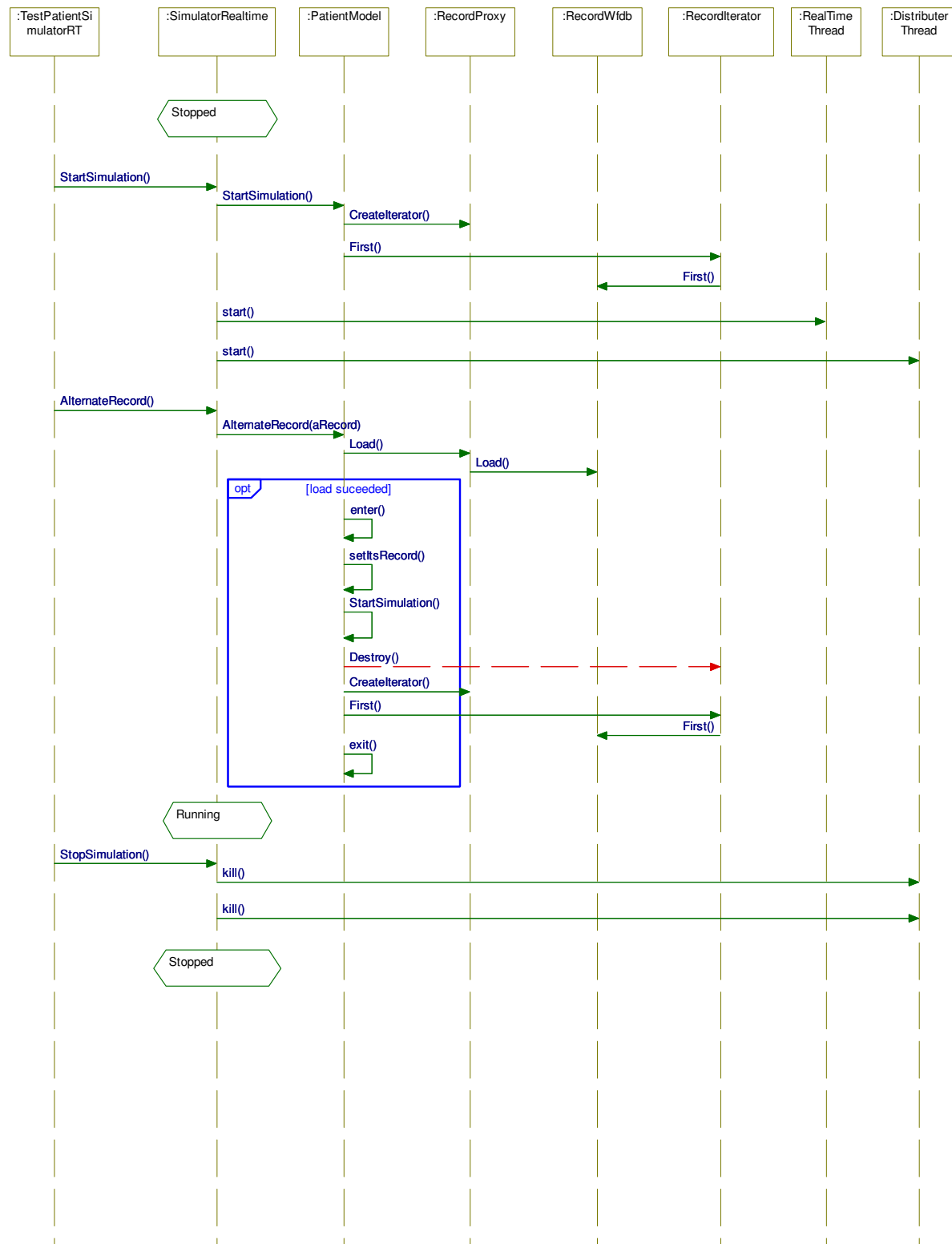


Figure 25 Sequence Diagram: Start Realtime Simulation

```
void SimulatorRealtime::StartSimulation() {
    if ( ((state == Initialized) || (state == Stopped)) &&
        (itsPatientModel != NULL) )
    {
        itsPatientModel->StartSimulation();
        itsRealTimeThread->setItsPatientModel(itsPatientModel);
        itsDistributerThread->start();
        itsRealTimeThread->start();
        state = Running;
    }
}

void PatientModel::StartSimulation() {
    if (itsRecord != NULL)
    {
        if (itsRecordIterator != NULL) delete itsRecordIterator;
        setItsRecordIterator(itsRecord->CreateIterator());
        itsRecordIterator->First();
    }
}

bool PatientModel::AlternateRecord(Record* aRecord) {
    if (aRecord->Load()) {
        enter();
        setItsRecord(aRecord);
        StartSimulation();
        exit();
        return true;
    }
    return false;
}

void SimulatorRealtime::StopSimulation() {
    if (itsPatientModel != NULL)
    {
        if (state == Running)
        {
            itsDistributerThread->kill();
            itsRealTimeThread->kill();
        }
        state = Stopped;
    }
}
```

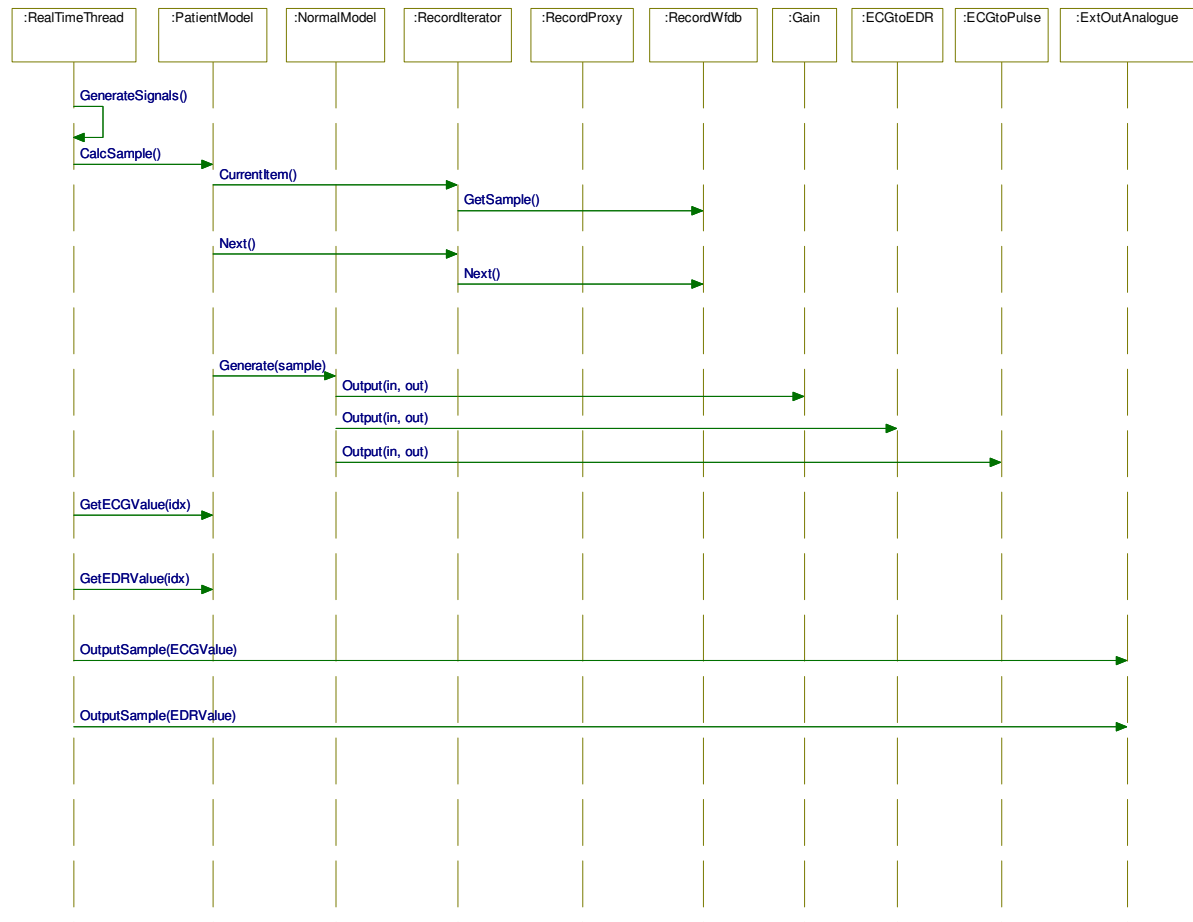


Figure 26 Sequence Diagram: RealTime thread GenerateSignals

```

// RealTimeThread.cpp
void RealTimeThread::GenerateSignals() {
    itsPatientModel->CalcSample();
    WFDB_Sample e0 = itsPatientModel->GetECGValue(0);
    WFDB_Sample r0 = itsPatientModel->GetEDRValue(0);
    itsExtOutAnalogue[0]->OutputSample(e0);
    itsExtOutAnalogue[1]->OutputSample(r0);
    if (itsFrameBuffer != NULL)
        itsFrameBuffer->Insert(e0);
}
  
```

```
// PatientModel.cpp
void PatientModel::CalcSample() {
    if (itsRecordIterator != NULL)
    {
        enter(); // Enter Monitor (Lock resource)
        itsSampleSet = itsRecordIterator->CurrentItem();
        if (itsRecordIterator->IsDone())
            itsRecordIterator->First();
        else
            itsRecordIterator->Next();

        if (itsPhysioModel != NULL)
            itsPhysioModel->Generate(*itsSampleSet);
        exit(); // Exit Monitor (Free resource)
    }
}
```

```
// NormalModel.cpp
void NormalModel::Generate(SampleSet& sample) {
    itsGain.Output(sample, ECGSample);
    itsECGtoEDR.Output(ECGSample, EDRSample);
    itsECGtoPulse.Output(ECGSample, PulseSample);
}
```

5.3.2 Use case #3. Adjust Scenario Parameters realization

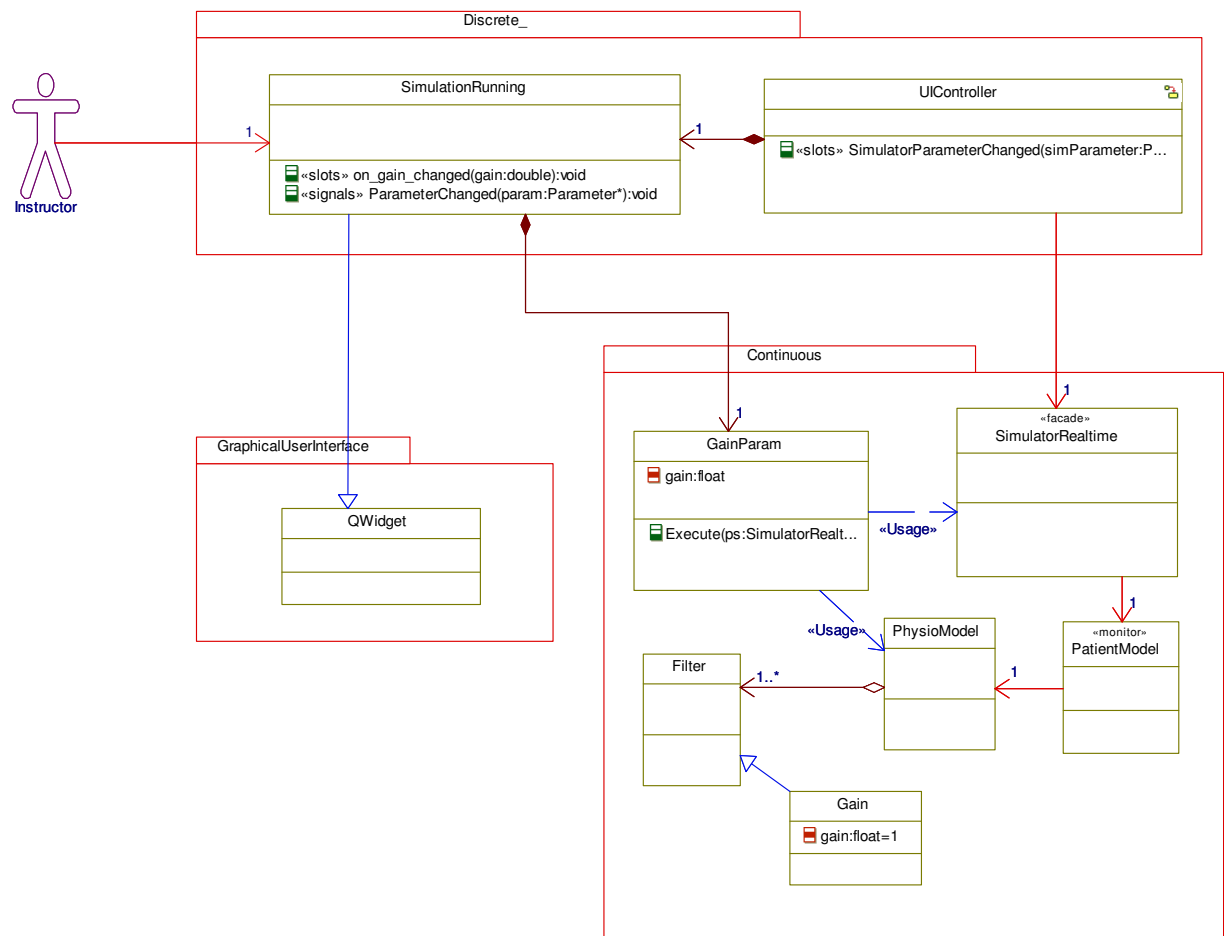


Figure 27 Actor, Classes and packages involved in use case

Change in the UI is returned to the UIController via callbacks. In QT callbacks are introduced with help of two types of functions.

- Signals
- Slots

Signals make the class function like a subjects in Observer Pattern, where the signal functions are a function which can be fired. The subscriber of a subject needs to have slot function for incoming callback. Whenever the UIcontroller receive a parameter change, it receives it as an object, using the command pattern, and execute the functionality on the simulation object.

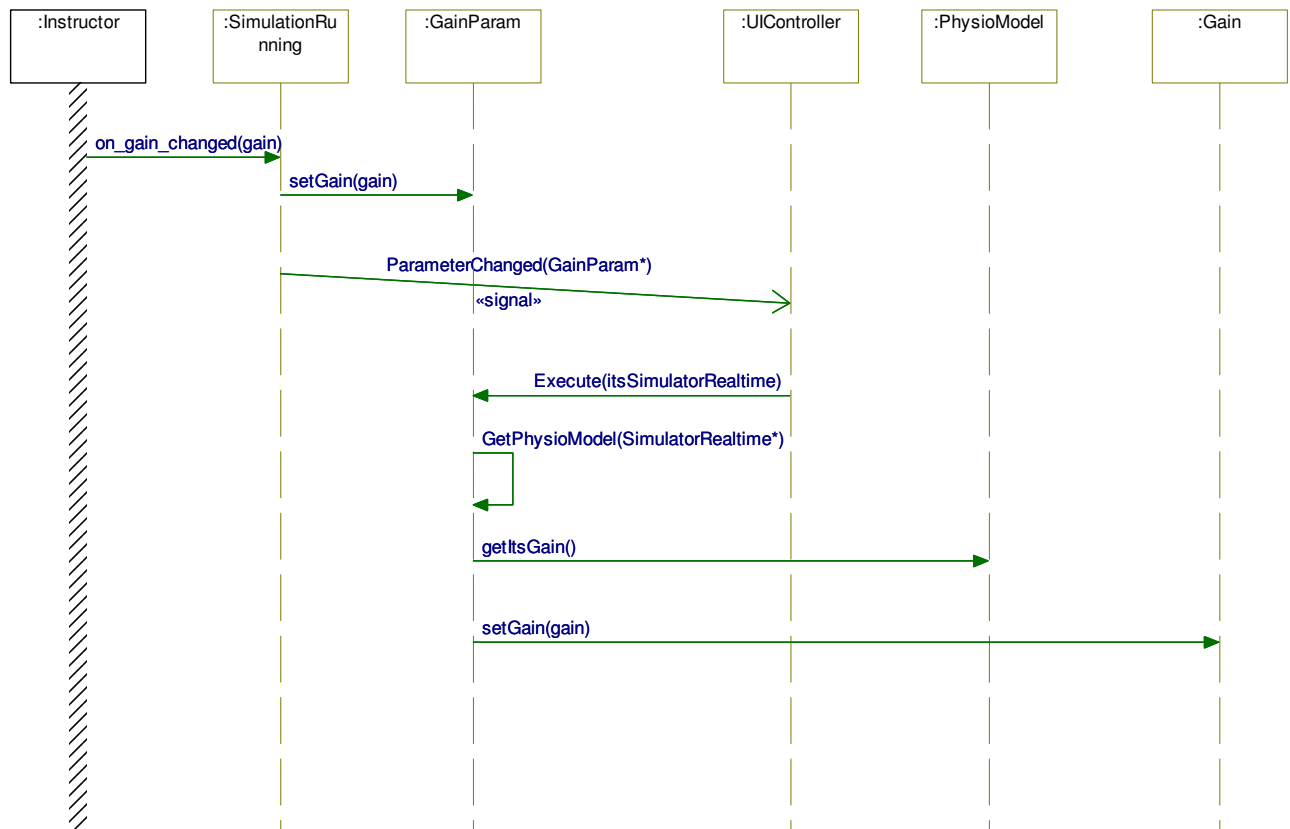


Figure 28 Scenario for instructor adjusting gain parameter

```

class SimulationRunning : public QWidget, public Observer {
    Q_OBJECT

private:
    Ui::SimulationRunning *ui;
    GainParam gainParam;

private slots:
    void on_gain_changed(double);

signals:
    void ParameterChanged(Parameter*);
};

void SimulationRunning::on_gain_changed(double gain)
{
    gainParam.setGain((float)gain);
    emit ParameterChanged(&gainParam);
}
  
```

```
class UIController : public QObject
{
    Q_OBJECT
public:
    explicit UIController(QObject *parent = 0);

    SimulatorRealtime* GetSimulatorRealtime();
    void ChangeState(SimState*);
    void start();

private:
    SimulationRunning sim;
    SimState *simState;
    SimulatorRealtime *itsSimulatorRealtime;

public slots:
    void SimulatorButtonPushed(SimCommand*);
    void SimulatorParameterChanged(Parameter*);

signals:
};

UIController::UIController(QObject *parent) :
    QObject(parent)
{
    connect(&sim, SIGNAL(ParameterChanged(Parameter*)), this,
            SLOT(SimulatorParameterChanged(Parameter*)),
            Qt::QueuedConnection);

    // Create the SimulatorRelatim system and configurate
    itsSimulatorRealtime = SimulatorRealtime::Instance(50);
    itsSimulatorRealtime->AttachObserver(&sim);

    this->simState = SimState::GetInstance();
    this->simState->SetSapientApplication(this);
}

void UIController::SimulatorParameterChanged(Parameter * simParameter)
{
    simParameter->Execute(itsSimulatorRealtime);
}
```

6. PROCESS/TASK VIEW

This chapter describes the view of threads for the real-time part of Sapien 190. It contains an overview of the different threads in the architecture and synchronization used between them. In this chapter task and threads will have the same meaning and threads will be used in the text and UML diagrams.

There is included a Rate Monotonic Analysis (RMA) for the utilization of threads based on the calculation of utilization bounds including analysis of blocking threads.

Finally an analysis is included for the utilization of updating the ECG graph on the LCD display.

6.1 Process/task overview

In the below class diagram is illustrated threads in the Sapient 190 architecture.

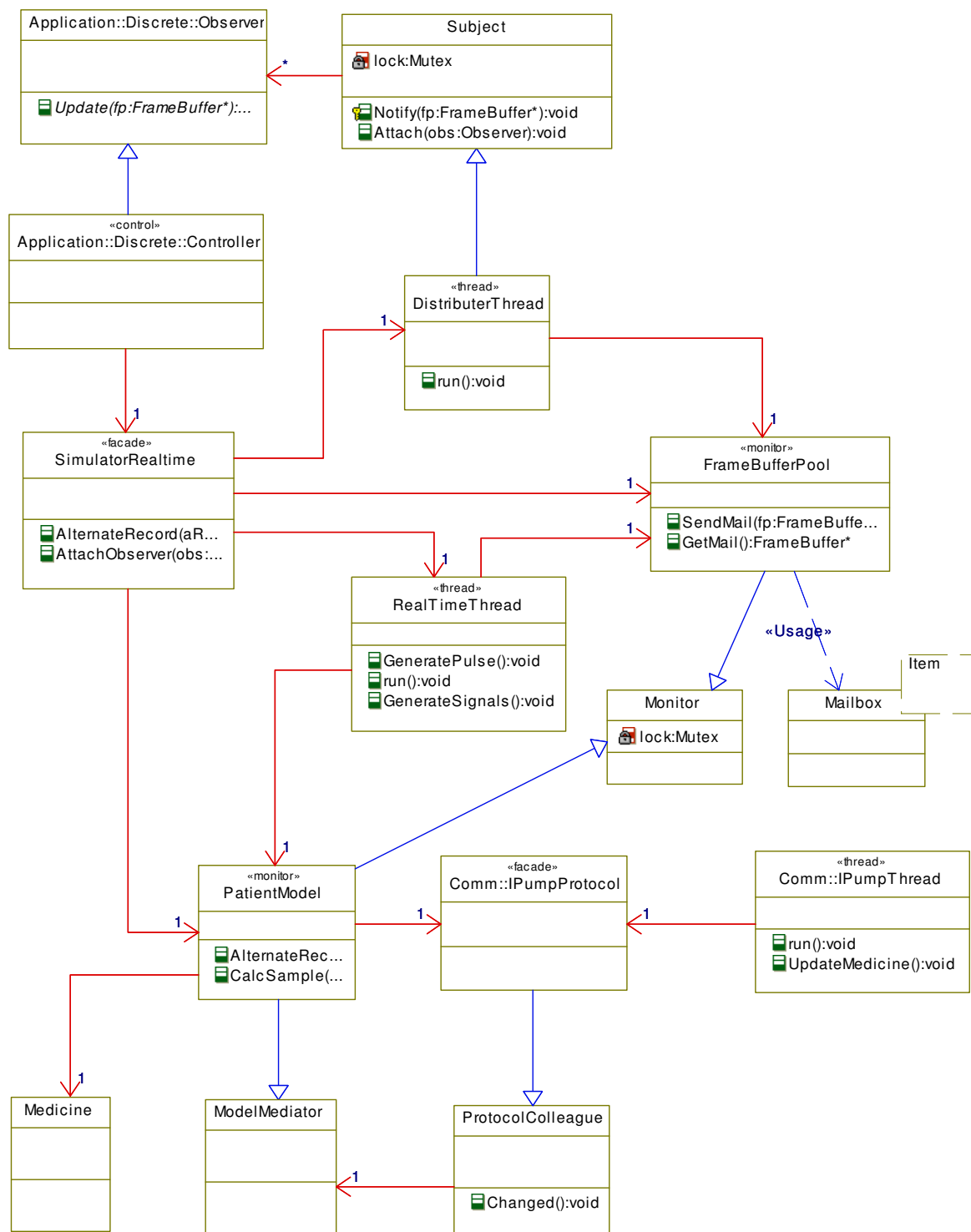


Figure 29 Overview of all threads for the Sapien 190 design

The following threads will be running in Sapien 190 patient simulator:

Controller:

The controller will be part of the discrete package that contains the state machine to control the continuous part of the two layered model. States will be controlled from the main GUI thread (Qt) of the Sapien 190 and therefore synchronization is needed between controller and other continuous parts of the system.

RealTimeThread:

This thread is the essential thread of the systems that is periodic with the sample rate and is responsible for generating signals and outputs them to the environment.

DistributerThread:

This thread is used to collect a buffer of samples that is updated to the observers that in this case will be the controller part of the GUI thread. This thread is periodic with the sample rate times the number of samples in the frame buffer.

IpumpThread:

This thread is used to handle PDU messages received from the IPUMP and updating the medicine volume. PDU messages are received with a rate of 1 sec.

6.1.1 Synchronization between threads

The controller class from the discrete part of the system will interact with the DistributerThread where the observer pattern has been used to update the GUI with frames of samples. A mutex has been added to this observer pattern to ensure synchronization between the controller thread and the DistributerThread. This synchronization will ensure that Attach is not called the same time as Notify, meaning that new observes are not allowed to be added or deleted at the same time we are updating the observes.

The RealTimeThread generates samples and collects a number of samples before a new frame buffer are sent to the DistributerThread by using a mailbox (SendMail and GetMail). The FrameBufferPool is implemented as monitor to ensure synchronization between the RealTimeThread and DistributerThreads when they request the pool of free frame buffers. This part will be explained in details in chapter 6.4.

Synchronization between the IpumpThread and RealTimeThread is not yet finalized since this part is still in the design phase. It could be done by adding a monitor or mutex to the mediator pattern to ensure that the medicine class is updated and access exclusively between the two threads.

6.2 Process/task implementation

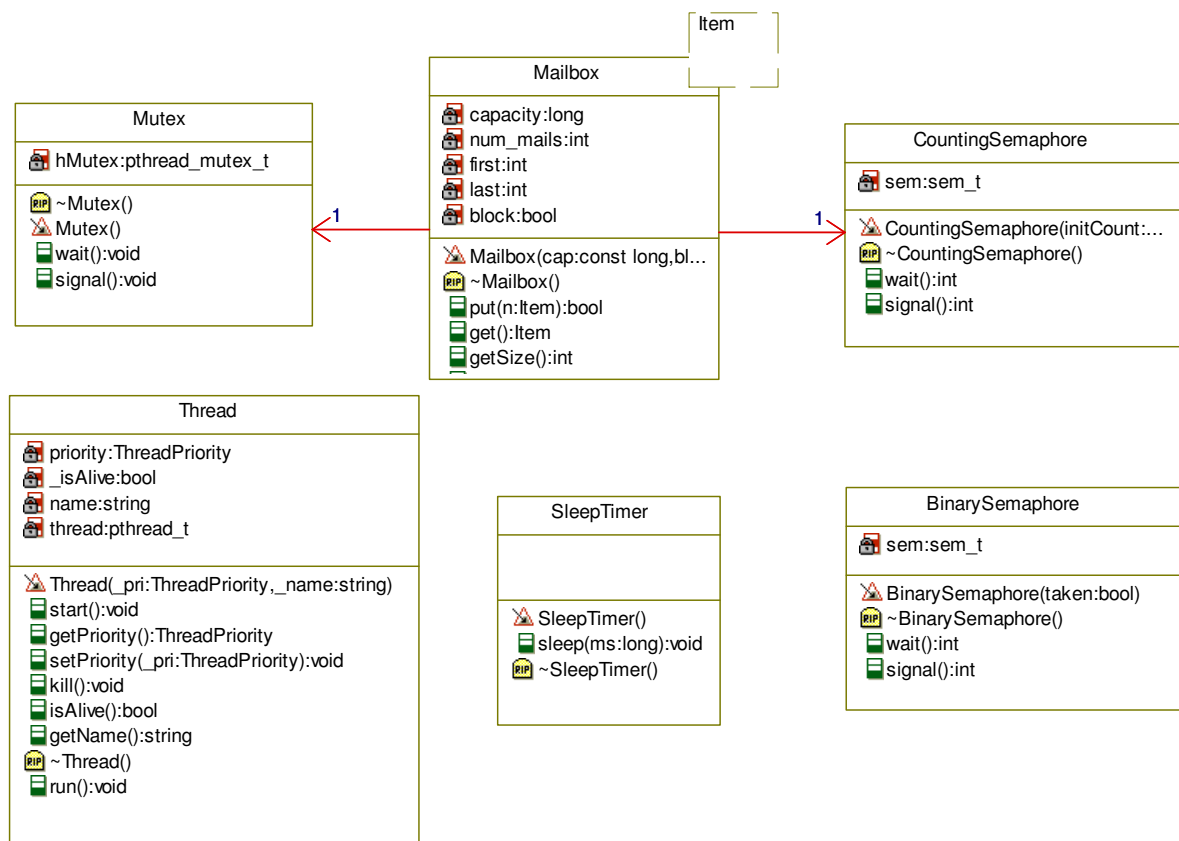


Figure 30 Abstract OS (Linux)

The operating system is encapsulated in the classes displayed above. The specification of this operating system is to be found in [10]. These classes are implemented in two versions. The first is to be used for simulation and test in Rhapsody. The second is implemented as an abstraction of the posix thread API used on Linux.

The mailbox is implemented by use of a mutex to ensure synchronization between put and get and a semaphore where the caller will be waiting if the mailbox is empty. Thread, Mutex and Semaphore is implemented by using the POSIX pthread, mutex and semaphore API for Linux.

6.3 Process/task communication and synchronization

A monitor is implemented using a mutex to implement the enter and exit functions of the monitor. The monitor is used by the PatientModel and FrameBufferPool as illustrated in class diagram Figure 29.

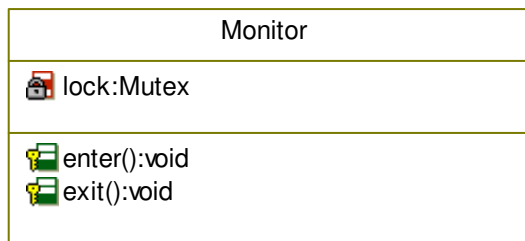


Figure 31 Monitor implemented using mutex

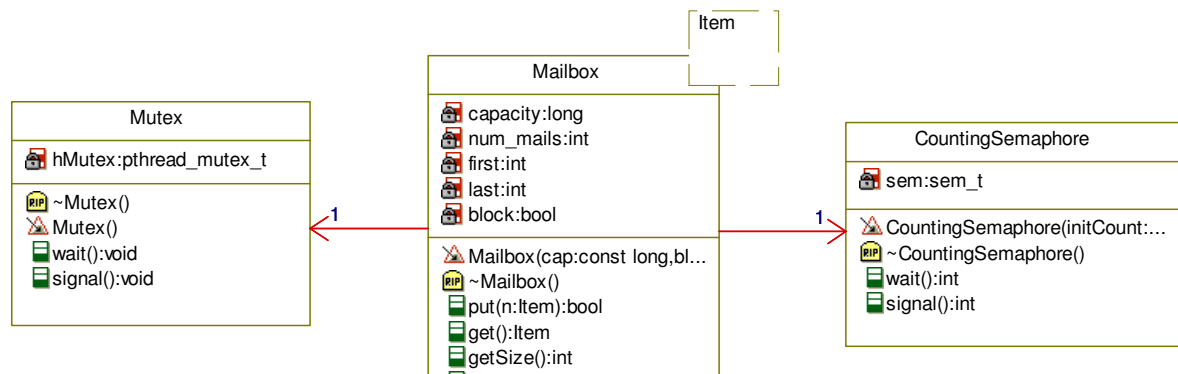


Figure 32 Mailbox implementation for Linux

The mailbox is implemented for the linux version using a buffer, mutex and counting semaphore. The mailbox can be used as a blocking or non blocking mailbox.

6.4 Process group 1 - DistributerThread and RealTimeThread

In this chapter we will describe in details how the interaction between DistributerThread and the RealTimeThread is performed.

6.4.1 Process communication in group 1

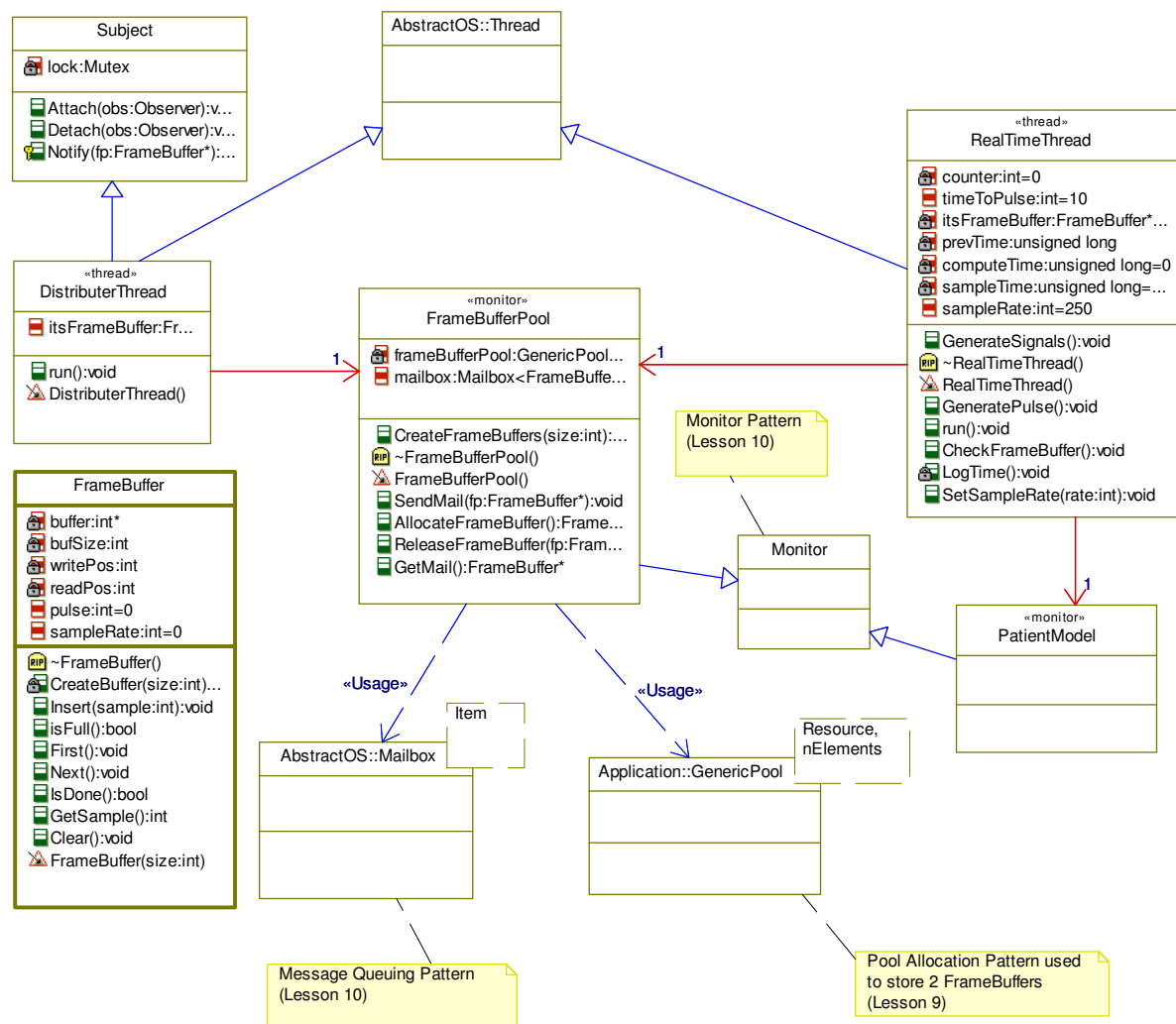


Figure 33 Process view for Distributer and RealTime threads and mechanism for synchronization

The essential process groups for Sapien 190 are the `DistributerThread` and `RealTimeThread`. These threads exchange frame buffers with samples by use of a Mailbox implemented according to the Message Queuing Pattern. This pattern uses asynchronous communication between the two threads. A pointer to the frame buffer is passed through the mailbox by use of the methods `SendMail` and `GetMail`. `GetMail` will be blocking if there is no new frame buffers in the mailbox letting the `DistributerThread` being blocked. The pointer reference to the frame buffer is exchanged between the two threads to minimize copy of data.

The `FrameBufferPool` is implemented according to the Pool Allocation Pattern. This approach saves allocation of a new frame buffer from the heap every time the `RealTimeThread` will be filling the next buffer with samples. There is only allocated 2 frame buffers in the pool since the `DistributerThread` needs to distribute the newest samples to the waveform graph. In case it cannot follow the speed of updating the graph if the sampling rate is too high samples will automatically be skipped.

The monitor is used by the `FrameBufferPool` to synchronize allocation and release of `FrameBuffer`'s to the `GenericPool`. The `FrameBuffer` contains a number of samples, pulse and sample rate all information used to be updated on the GUI. The `FrameBuffer` contains information that is send to the GUI controller using the observer pattern.

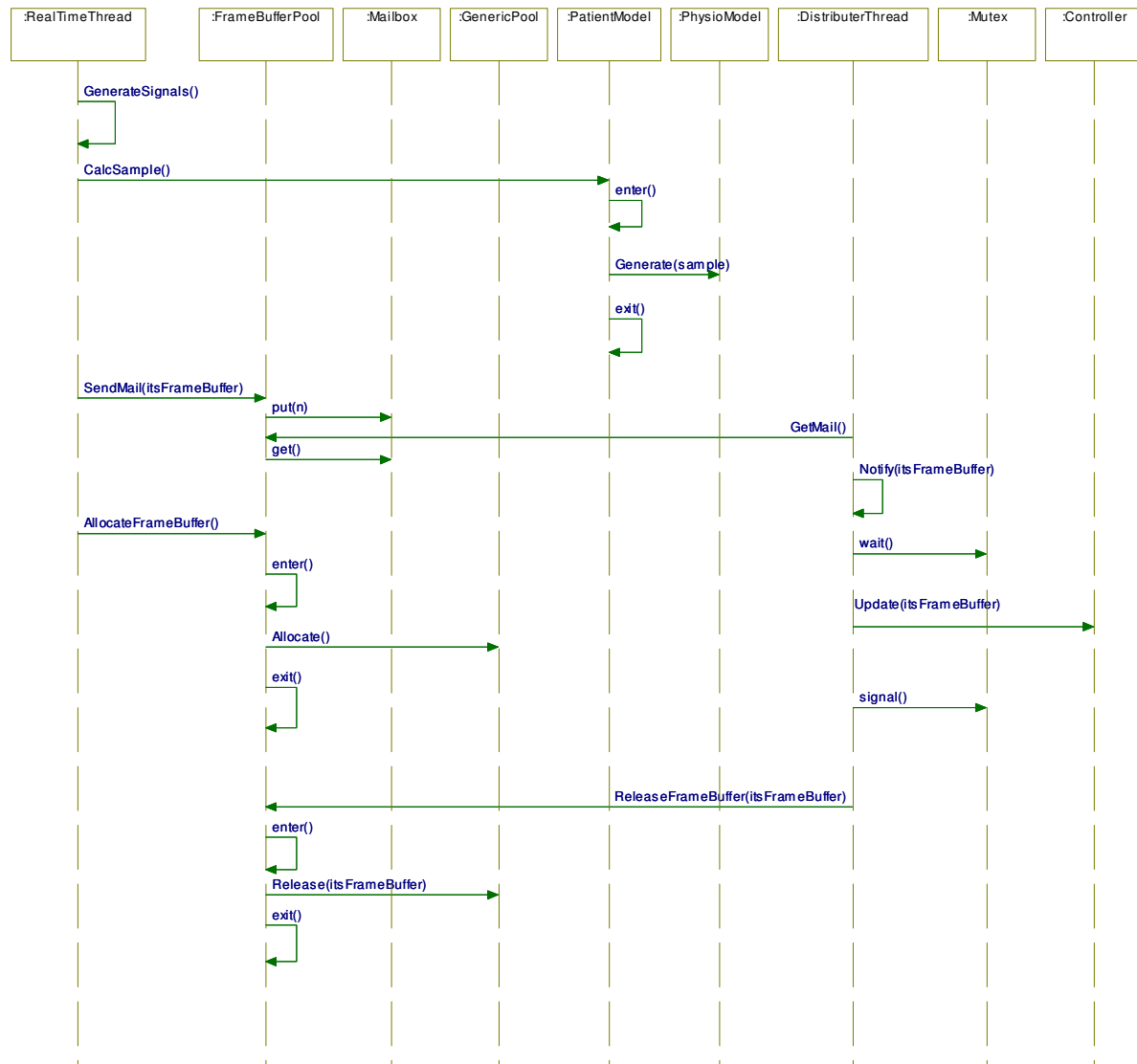


Figure 34 Synchronization between threads

The sequence diagram above illustrates part of a scenario where the RealTimeThread is calculating a new sample. When the Generate method is called in the PatientModel the enter and exit monitor functions are called to ensure that the GUI is not at the same time altering the record currently used to generate samples of the ECG, EDR and pulse signals.

When a frame buffer is filled with samples the RealTimeThread sends a filled FrameBuffer to the DistributerThread by calling the SendMail method in the FrameBufferPool that puts the pointer of the FrameBuffer in the Mailbox. The filled FrameBuffer is collected by the DistributerThread by calling the GetMail method that will be blocking in the get call to the Mailbox if it is empty.

A mutex internal in the Distributer thread is used to synchronize updating the UI controller class in case a call to Attach or Detach in the observer class is invoked at the same time. A monitor is also used by the FrameBufferPool to synchronize calling the methods Allocate and Release in the GenericPool.

6.4.2 Distributer thread

The distributer thread separates updating the GUI with information of the continuous part of the system and is active as long the discrete system is in the running state. It is activated for every update of the frame buffer that contains a configured number of samples. Every time the DistributerThread notifies the observers a lock (Mutex) is used to ensure mutual access to the list of observers.

```
void DistributerThread::run() {
    while(isAlive()){
        itsFrameBuffer = itsFrameBufferPool->GetMail();
        if (itsFrameBuffer != NULL) Notify(itsFrameBuffer);
        itsFrameBufferPool->ReleaseFrameBuffer(itsFrameBuffer);
    }
}
```

```
void Subject::Notify(FrameBuffer* fp) {
    lock.wait();
    std::list<Observer*>::const_iterator iter;
    iter = itsObserver.begin();
    while (iter != itsObserver.end()){
        Observer *pObserver = *iter;
        pObserver->Update(fp);
        iter++;
    }
    lock.signal();
}
```

6.4.3 Real-time thread

The real-time thread is a periodic thread that is executed every sample period running with the default sample rate of 250 Hz. This thread reads samples from the patient record and generates the ECG, EDR and pulse samples that are send to the analogue and serial interfaces. It collects a number of ECG samples that is transmitted to the distributer thread to separate updating the waveform graph from the real-time part of the system. To compensate for the computing time of generating the signals we have added the method LogTime that measures the time it takes to execute the run loop of the RealTimeThread. This time is subtracted from the sampleTime and will be limited to this time. Meaning if the sampling rate is increased too high or the compute time takes a very long time this thread will be running all time.

```
void RealTimeThread::run() {
    while(isAlive()){
        usleep(sampleTime - computeTime);
        LogTime();
        GenerateSignals();
        counter++;
        if (counter > timeToPulse)
        {
            GeneratePulse();
            counter = 0;
        }
        CheckFrameBuffer();
        LogTime();
    }
    // Ensure that Distributer thread will die
    if ((itsFrameBuffer != NULL) && (itsFrameBufferPool != NULL))
        itsFrameBufferPool->SendMail(itsFrameBuffer);
}
```

6.5 Rate Monotonic Analysis (RMA) with Task Blocking

In this chapter an analysis of the scheduling of all threads are calculated. An excel sheet is attached with the project that can be used to calculate the RMA based on a number of parameters and measured Worst Case Execution (WCE) times.

Two questions are important for this analysis.

Will we be able to calculate and generate the EDR and ECG signals with the given sampling frequency (250 – 400 Hz)?

What is the best configuration of parameters (frame buffer size) for the RMA analysis being able to update the LCD display with the ECG or EDR signal waveforms?

Below is listed the internal and external events that is important for this analysis. Here we have the sample event that will be generated by the sampling frequency based on an internal timer. The pulse and frame buffer are updated every N_p or N_f samples given a periodicity that is in sync with the sample rate. The only external event is the PDU frame that is received from the IPUMP every second and will not be in sync with the sample rate.

Internal and external event list

#	Event Id	System response	Arrival Pattern	Event Source	Response time
1	Sample	Calculate and generate EDR and ECG signals	Frequency of 250 (Fs) max 400	Internal timer	Less than sample periode
2	Pulse	Calculate pulse every 50 (N_p) samples	F_s/N_p	Internal timer	Less than sample periode
3	PDU	Updates medicine information	Every second (F_i)	IPUMP	Less than ½ second
4	FrameBuffer	Updates signal graph on LCD display	Every 50 (N_f) samples (1/8 of LCD display in pixels)	Internal timer	Less than period updating framebuffer

A number of parameter has been identified to be important for the scheduling and calculation of utilization bounds of the RMA analysis. These parameters can be used to adjust the Sapien 190 thread scheduling in finding an optimized configuration being able to run the system without any missed deadlines.

RMA analysis with Task Blocking ($F_s = 250$ Hz)

Parameters identified from internal and external event list:

Time units		1000000	us per second
F_s	Sample frequency	250	Hz
N_p	Num samples for pulse calculation	10	Number
F_i	PDU frequency	1	Hz
N_f	Frame buffer size	50	Number

**$N_f > N_p$
 $T_i(3) > T_i(4)$**

The Rate Monotonic Scheduling (RMS) is used to schedule the threads as described in the previous chapter. There are assigned fixed priorities to all threads, they are all periodic tasks and the highest priority has been assigned to the thread with the shortest period.

The table below contains the fundament for calculating the RMA. The WCE times is only estimates based on a measurement made in the RealTimeThread run part.

#	Event Id	Arrival Period (T_i)	Action	Thread
1	Sample	4000	Run (GenerateSignals)	RealTimeThread
2	Pulse	40000	Run (GeneratePulse)	RealTimeThread
3	PDU	1000000	Run (UpdateMedicine)	IPumpThread
4	FrameBuffer	200000	Run (Notify)	DistributerThread

WCE Time (C_i)	Priority	Blocking Delays (B_i)	Blocking term ($B_{ti} = B_i/T_i$)	Deadline (D_i)
250	Very High	40	0.01	4000
50	Very High	0	0	4000
200	High	40	0.00004	10000
200	Medium	100000	0.5	200000

6.5.1 Calculation of Utilization Bound (250 Hz)

The RMA calculation is done using the steps and formulas presented in slides ThreadsAndSchedulability from Lesson 6.

- S1. Utotal – calculate the total utilization for all of the events
- S2. Btotal – calculate the blocking term
- S3. Ubound – calculate the utilization bound
- S4. UBtotal – compare total utilization (Utotal + Btotal) to the utilization bound (Ubound)

In the below calculation we can see that with a sample rate of 250 Hz we will be able to schedule the threads using a frame buffer of 50 samples. We can see that the calculated total utilization (UBtotal) is less than the utilization bound (Ubound).

Rate Monotonic Analysis with Task Blocking

(U = Utilization, UB = Utilization and Blocking, B = Blocking)

Utotal	sum (Ci/Ti)	0.06
Ubound	$n(2^{1/n} - 1)$	0.76
Btotal	max(Bti)	0.50
UBtotal	Utotal + Btotal	0.56

Ubound > UBtotal

6.5.2 Utilization Bound for the FrameBuffer event sequence (250 Hz)

In the next part we have added calculation of the utilization bound for the FrameBuffer event, since this is the part that is most complicated and critical for the scheduling updating the waveform graph. The FrameBuffer event is schedulable if the utialization bound calculated in step 3 is bigger than total effective utilization for the FrameBuffer event calculated in step 2.

Utilization bound for FrameBuffer (e4) valid as long $N_f > N_p$

<u>Step 1: Identify H</u>	<u>Step 2: Calculate f</u>
- Higher priority events - e1, e2, e3	
H1 = e3 $T_i \geq D_i(4)$	$f4 = \text{sum}(C_j/T_j) H_n + 1/T_i(4) (C_i(4) + B_i(4) + \text{sum}(C_k) H1$
Hn = e1, e2 $T_i < D_i(4)$	0.57

<u>Step 3: Utialization bound</u>
$u(n, di) = n((2^{*di})^{1/n} - 1) + 1 - di$ 0.83 $(0.5 < di \leq 1)$
$di = D_i(4) / T_i(4)$ 1.00 $(di < 0.5)$

<u>Step 4: Compare effective calculated utilization with bound</u>
Caluclate $f < Utializtion \text{ bound } (f4 < di \text{ or } u(n, di)$ TRUE

6.5.3 RMA calculation for 370 Hz

In the next calculation we can see that with a sample rate of 370 Hz we will not be able to schedule the threads using a frame buffer of 50 samples. All other parameters are the same as for 250 Hz.

Rate Monotonic Analysis with Task Blocking (370 Hz)

(U = Utilization, UB = Utilization and Blocking, B = Blocking)

Utotal	sum (Ci/Ti)	0.10
Ubound	$n(2^{1/n} - 1)$	0.76
Btotal	max(Bti)	0.74
UBtotal	Utotal + Btotal	0.84

Ubound > Ubttotal

Utilization bound for FrameBuffer (e4) valid as long $N_f > N_p$ (370 Hz)

Step 2: Calculate f

$$f_4 = \sum(C_j/T_j) | H_n + 1/T_i(4) (C_i(4) + B_i(4) + \sum(C_k) | H_1$$

0.84

Step 3: Utilization bound

$$u(n, d_i) = n((2^{d_i})^{1/n} - 1) + 1 - d_i \quad \mathbf{0.83} \quad (0.5 < d_i \leq 1)$$

$$d_i = D_i(4) / T_i(4) \quad \mathbf{1.00} \quad (d_i < 0.5)$$

Step 4: Compare effective calculated utilization with bound

Calculate $f < \text{Utilization bound}$ ($f_4 < d_i$ or $u(n, d_i)$) **FALSE**

7. DEPLOYMENT VIEW

7.1 System configurations overview

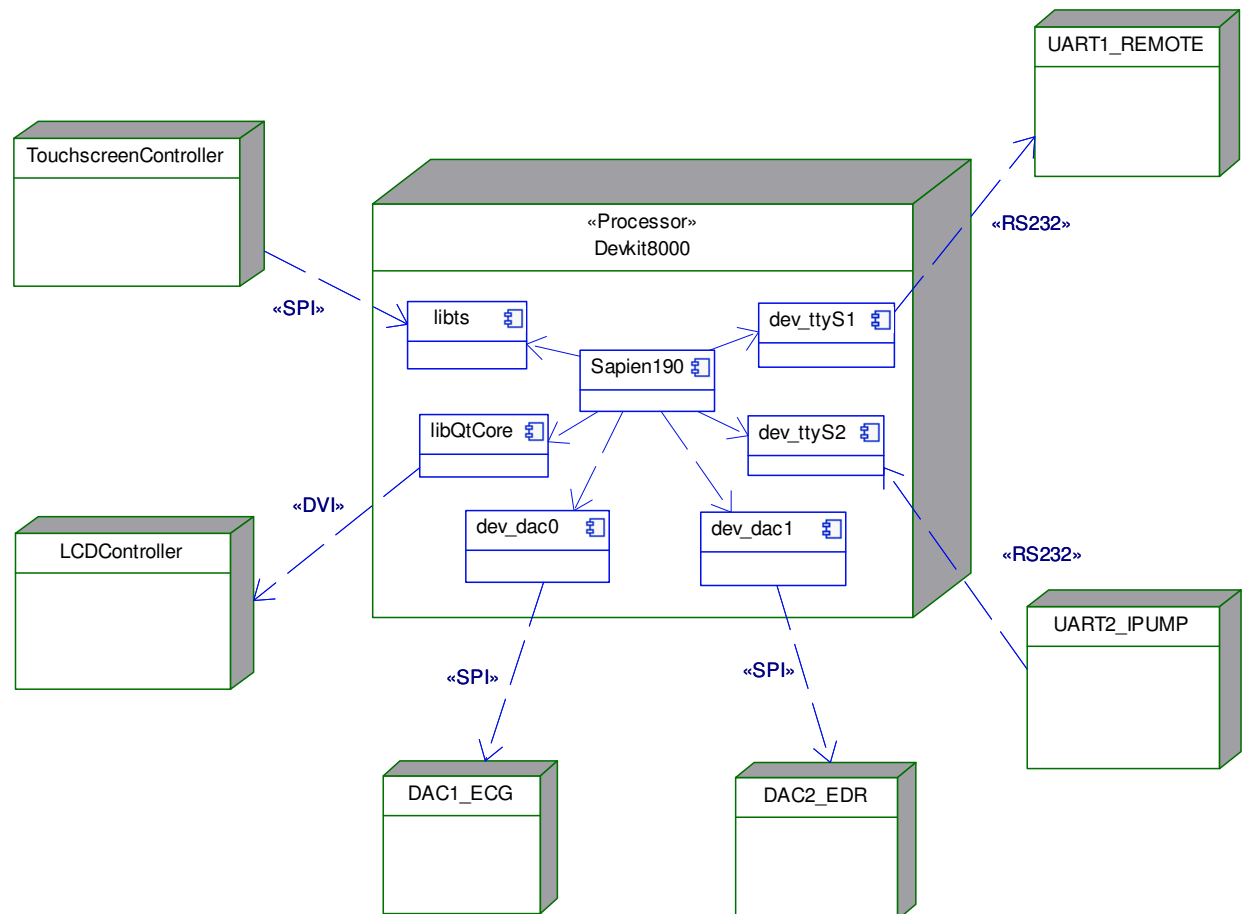


Figure 35 Essential HW nodes used from DevKit8000 used for Sapien190

On Figure 35 the deployment of our system is shown. The libts components contain driver information, which enable the Sapien190 to use the TouchScreenController. LibQtCore is used to communicate with our LCD controller, via DVI.

For converting our values into analog signal the system are using component dev_dac to communicate with our digital / analog converter.

7.2 System configurations

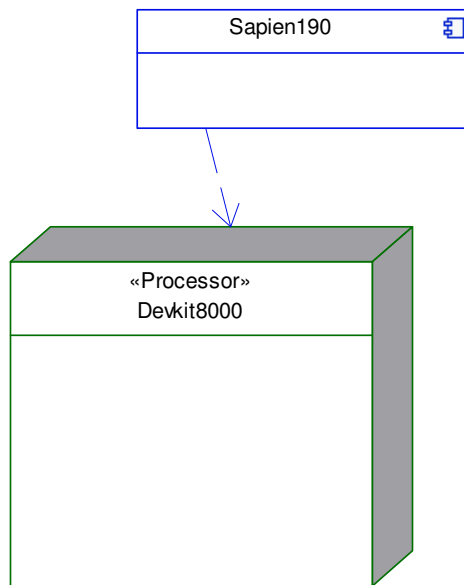


Figure 36 Sapien190 deployed on ARM Linux target platform

7.2.1 Configuration 1.

7.2.2 Configuration 2.

7.3 Node descriptions

7.3.1 Node 1. description

7.3.2 Node 2. description

8. IMPLEMENTATION VIEW

8.1 Overview

8.2 Component descriptions

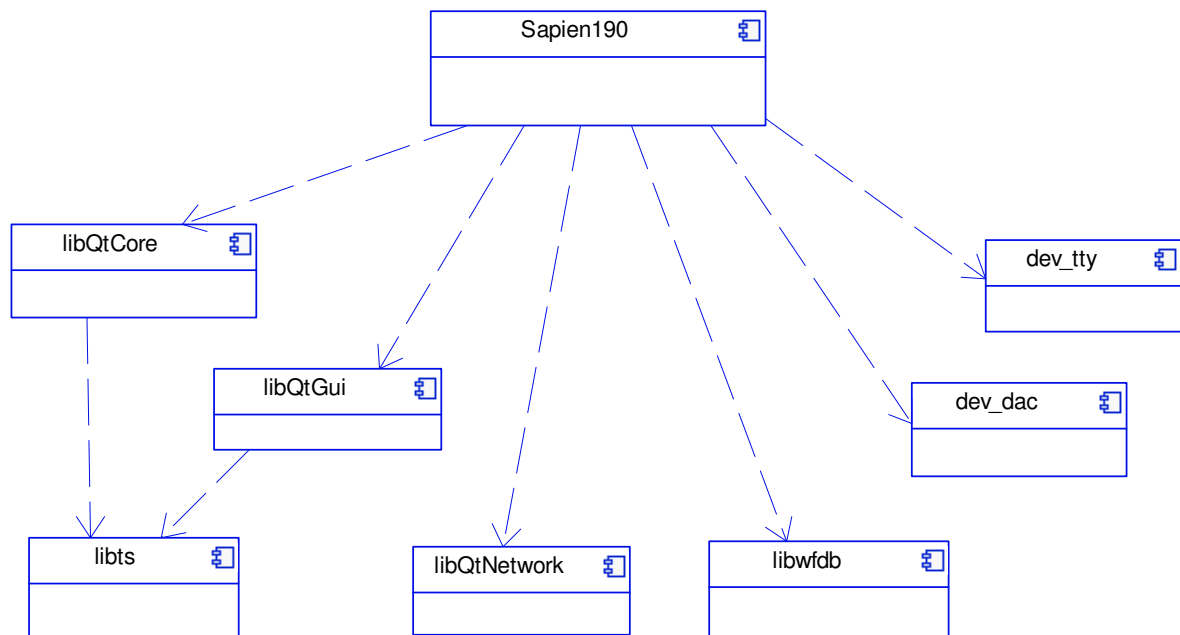


Figure 37 Component diagram for Sapien190 and libraries used from Qt and WFDB

8.2.1 Sapien190

Containing main program for Sapien190

8.2.2 libQtCore

LibQtCore is a component containing standard classes used when programming with the QT framework

8.2.3 libwfdb

Libwfdb provide drivers for reading all our patient records.

8.2.4 libts

Providing drivers to be able to display our user interface on the Devkit8000

8.2.5 dev_dac

Providing drivers to be able to write to the digital to analog converter

8.2.6 dev_tty

Drivers for writing to the serial port.

8.2.7 libQtGui

Providing a framework to draw and control the user interface of Sapien190

9. GENERAL DESIGN DECISIONS

9.1 Architectural goals and constraints

The architectural goals are to make the system modifiable and provide high performance. Since the system is a real time system, there are constraints on how modular system can be, since modular and performance work in the opposite direction. It should be easy to extend the system new types of medicine, different kind of inputs and output. The system should be encapsulated so it's easy to port the system to different platform.

9.2 Architectural patterns

Observer Pattern:

Observer pattern helps out with mass distribution of information in a system. If a number of processes are interested in the same information, observer pattern is the pattern to choose. In Sapien the observer pattern is used to distribute information generated by our simulation to the user interface. This a very common way to use observer pattern since it also notify the user interface when new data has arrived so it can be refreshed.

Five Layered Architecture:

Layered pattern organizes domains into a hierarchical organisation based their level of abstraction. The advance of layered architectural is that it make it easier to find relevant code, and make it easier to replace whole layers, for instance if you want to port the system to another device. There used open layered architectural so it's allowed to call more than one layer down.

9.3 General user interface design rules

9.4 Exception and error handling

There is no exception handling implemented, if something is going wrong, the functionality is wrapped, so the systems does not crash.

9.5 Implementation languages and tools

This section lists the chosen implementation language and tools with version numbers.

Implementation languages:

C++

Tools

Eclipse

TrollTech QT Creator

9.6 Implementation libraries

QT-Everywhere-4.6.1

wfdb

10. SIZE AND PERFORMANCE

11. QUALITY

This section describes the non-functional qualities of the system.

11.1 Operating Performance

The system has been designed to minimize bugs by applying GRASP⁶ principles such as “Low Coupling”, “High Cohesion”, “Information Expert” and other.

The design has not been tested heavily and may have memory leaks or other bugs that have not been identified yet.

The use of smart pointers is an effective way of minimizing memory leaks and stray pointers. Smart pointers have not been widely used, but should replace the existing pointers used in factories and similar places.

Another performance measure is the jitter of the D/A output. The design uses the D/A output a sink, that is sourced from the input records. That is, the output pulls data from the input. The input itself does not take initiative to source data to the output. This simple source-sink design protects against data contention and provides the lowest possible jitter as it is driven by the D/A output. Performance could be improved by

11.2 Quality Targets

Ex no unscheduled down-time

11.3 Extensibility

The software design allows the software to be extended with minimum effort and to keep domain specific code together. This satisfies the Open-Closed Principle⁷

11.3.1 Patient Model

The design is extensible to new data record sources. The *Record* class can use the *RecordProxy* to point a new source (Figure 5).

The *SampleSet* is not limited to use two samples per set as it is used at the moment.

Using the *RecordIterator* to acquire samples makes the *PatientModel* insensitive to changes in the *SampleSet* (Figure 4).

11.3.2 PhysioModel

The *PhysioModel* is build using a Strategy Pattern and supports extension of models by

⁶ Larman

⁷ <http://www.objectmentor.com/resources/articles/ocp.pdf>

adding new strategies (Figure 7).

Filters can be added or reused in the *PhysioModel* as the filters and pipes pattern is used (Figure 8). New filters inherit from the *Filter* class and are instantiated in the filter factory in the appropriate model (Figure 6).

11.3.3 DistributerThread

The *DistributerThread* uses an observer pattern to notify the *LCDScreen* of frame buffer updates.

The system can be extended with data processing- or other algorithms that subscribe to the frame buffer data, by implementing the “Update” method (Figure 13).

11.4 Portability

Care has been taken to create a design that wraps OS- and hardware specific code. The layered architecture encapsulates hardware/OS specific to increase portability.

11.4.1 Hardware

The hardware boundaries have been encapsulated in the *AbstractHW* package and contain (Figure 3):

- ExtInputs – Input from infusion pump
- ExtOutAnalogue – D/A outputs
- ExtOutSerial – Serial digital interface for transmitting pulse value

The abstraction provides a well-defined boundary to the hardware interfaces. Changing the hardware will only require changes in the *AbstractHW* implementation.

The LCD display and touch panel is not interfaced to directly, rather through the QT framework. The QT framework can be seen as an abstraction of the whole GUI.

The hardware abstraction is as such not an abstraction to the raw hardware, this is the job of a device driver. The abstraction is actually an interface to the resources provided by the operating system.

11.4.2 OS

Code specific to the operating system is placed in the *AbstractOS* package (and in the *AbstractHW* package, see 11.4.1).

The *AbstractOS* package currently holds an abstraction of the Posix library “pthread”. Porting the design to a different operating system will require an update of this class. OS specific classes are placed under *Sapien/os/* in the project file structure.

The QT framework provides an abstraction for the whole GUI. It is a cross-platform framework that allows the GUI design to be ported to several operating systems, such as Linux and Windows Embedded.

By using QT, we have made it easier to port the design to other operating systems, but performance in example a non-preemptive Linux version must be investigated.

11.4.3 Spoken Language

Currently, no measures have been taken to support multiple languages. This could however be implemented with an abstract factory pattern. The factory should create objects that use the proper text source (xml file or similar).

12. COMPILATION AND LINKING

This section describes the process of compiling and linking a program. This project has been developed using a number of different tools.

IBM Rhapsody has been used for UML modelling, simulation and testing. It has been used for automatic source code generation and compilation on windows using Cygwin and generating C++ source code classes for Linux.

Eclipse has been used on Ubutu Linux in WMware for implementation and testing of the WFDB interface and hardware interface to the DAC and serial ports.

Qt has been used on Ubutu Linux for the final application by integrating and compilation of the graphical user interface, UML model and interface implementation made in eclipse.

The ARM cross compiler has been used to compile eclipse and Qt projects for the target.

In the following chapters the above tools usages for compilation the software for the Sapien patient simulator to target (Devkit8000) is described.

12.1 Rhapsody modeling and testing

Rhapsody (version 7.5) has been used to create an UML model for the Sapien patient simulator that is used for test of the simulator model including generated C++ source code before compilation on Linux and Target. We have created test scenarios by use of the Rhapsody state diagrams and used them for testing the model by setting breakpoints in the states and made inspection of the state variables of the model by using the high level abstractions of that is possible with Rhapsody. This approach has reduced the development time in removing a lot of the manual C++ debugging and coding of the model. In this chapter we will describe how Rhasody has been configured for testing and code generation for Linux and Target.

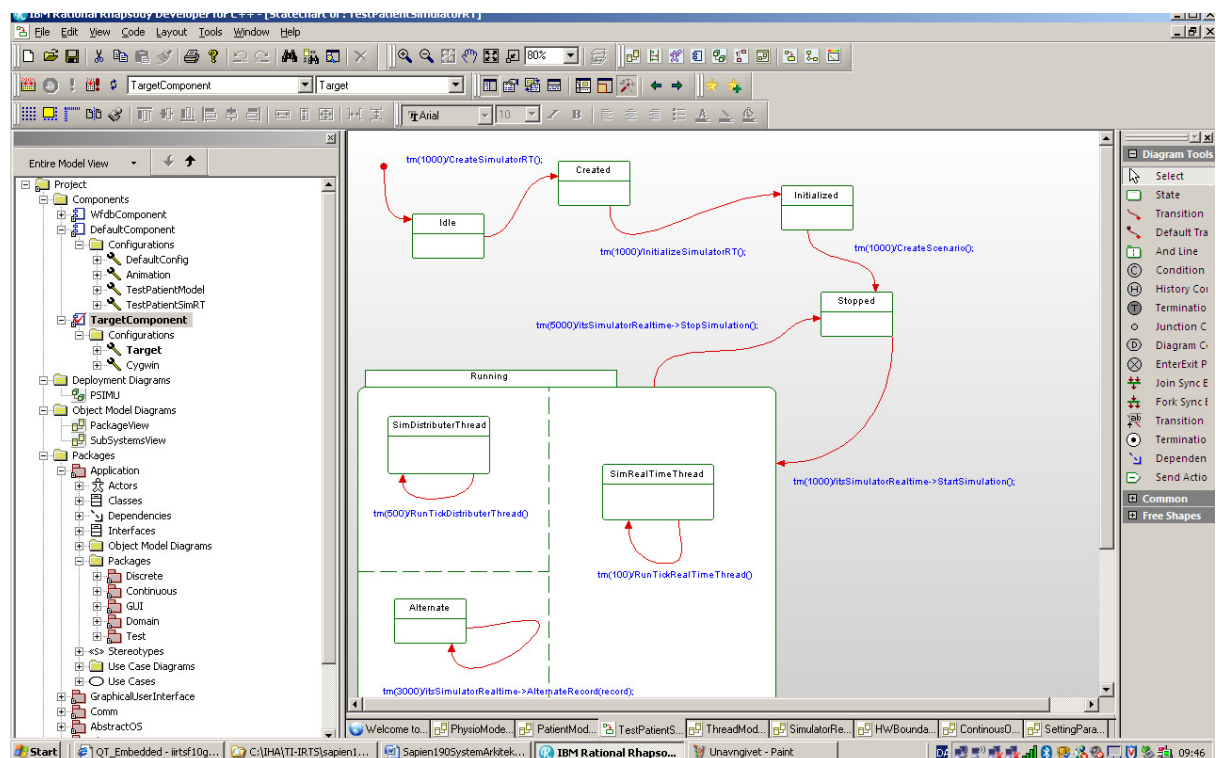


Figure 38 Rhapsody UML model for Sapien 190 used for simulation and test

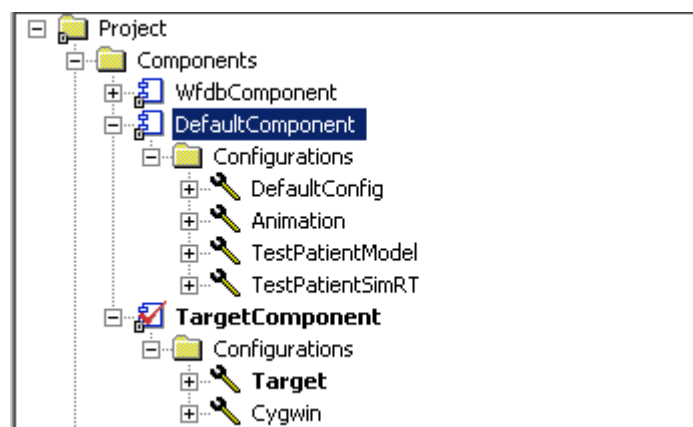


Figure 39 Rhapsody components for testing and source code generation

The figure above illustrates the components we have created for the Rhapsody project. The DefaultComponent and TargetComponent specifies the **scope** for classes for where

source code is generated. Classes used for test of the model are not in scope of the TargetComponent since this component contains classes that are part of the final product. Simulation and test on windows is done by using Cygwin this is done by selecting the DefaultConfig settings to Cygwin and specifying the wfdb headerfiles that we have used for the project:

DefaultConfig settings for windows simulation of DefaultComponent:

Standard Headers: wfdb/wfdb.h, math.h, wfdb/ecgcodes.h

Instrumentation Mode: None or Animation

Settings -> Environment: Cygwin

Rhapsody automatically generates the Makefile and compiles the generated source files in this configuration by using cygwin. We have made a configuration for each test scenario we have done in Rhapsody. (TestPatientModel, TestPatientSimRT)

TargetComponent is settings for generating source code for Linux and target:

Directory: C:\Ubuntu_share\sapient190\source\Sandbox\sapient_v1\cpy

Settings -> Environment: Environment

Here we have configured Rhapsody to generate the C++ source code directly to a sub directory of the Qt project that is compiled on Linux. We have shared a directory between the Windows and Linux platforms. The generated source classes is included in the Qt make project by using qmake.

12.2 Linux host Compilation-software

On the host Linux computer Qt and Eclipse must be installed. Qt has been used for the final product and Eclipse to test and develop parts of the Sapient software like hardware access and reading of WFDB records.

We have used the open source Qt Creator version 1.3.1 and the Qt SDK 2010.02 to be downloaded and installed from:

<http://qt.nokia.com/downloads>

We have used the open source Eclipse Galileo release to be downloaded and installed from:

<http://www.eclipse.org/cdt/downloads.php>

12.3 Linux Cross Compilation and linking process

The guide “Getting started with Qt” [9] describes how to install Qt on the Linux host which must be performed prior to the below steps. The following chapters describe how to cross compile the needed libraries for Qt and the WFDB library for the target Devkit8000 platform. For touch screen support see “Getting started with Qt”.

12.3.1 Qt Cross Compilation with qt-everywhere

This chapter describes how to download the embedded version of Qt that does not use the Linux X11 graphic library. It is therefore a suitable compact cross platform framework for the simulator platform where Devkit8000 is used for the first version of the product.

The following process describes how to configure Qt everywhere for compiling and linking a given program. Include a specification of special compiler and link switches.

This section is about how to modify qt-everywhere for cross compilation to target.

```
#
# qmake configuration for building for ARMv7 devices with arm-none-linux-gnueabi-g++
#

include(../common/g++.conf)
include(../common/linux.conf)
include(../common/qws.conf)

# modifications to g++.conf
QMAKE_CC = /opt/CodeSourcery/Sourcery_G++_Lite_2007q3/bin/arm-none-linux-gnueabi-gcc
QMAKE_CXX = /opt/CodeSourcery/Sourcery_G++_Lite_2007q3/bin/arm-none-linux-gnueabi-g++
QMAKE_LINK = /opt/CodeSourcery/Sourcery_G++_Lite_2007q3/bin/arm-none-linux-gnueabi-g++
QMAKE_LINK_SHLIB = /opt/CodeSourcery/Sourcery_G++_Lite_2007q3/bin/arm-none-linux-gnueabi-g++
QMAKE_CFLAGS += -O3 -march=armv7-a -mtune=cortex-a8 -mfp=neon -mfloat-abi=softfp
QMAKE_CXXFLAGS += -O3 -march=armv7-a -mtune=cortex-a8 -mfp=neon -mfloat-abi=softfp
#-mfp=vfp

# modifications to linux.conf
QMAKE_AR = /opt/CodeSourcery/Sourcery_G++_Lite_2007q3/bin/arm-none-linux-gnueabi-ar cqs
QMAKE_OBJCOPY = /opt/CodeSourcery/Sourcery_G++_Lite_2007q3/bin/arm-none-linux-gnueabi-objcopy
QMAKE_STRIP = /opt/CodeSourcery/Sourcery_G++_Lite_2007q3/bin/arm-none-linux-gnueabi-strip

QMAKE_INCDIR += /home/stud/tslib_arm/include
QMAKE_LIBDIR += /home/stud/tslib_arm/lib

load(qt_config)
```

Configure the libraries to use the linux-armv7-g++ configuration:

```
$ cd /home/stud/qt-everywhere-opensource-src-4.6.2
$ ./configure -embedded arm -xplatform qws/linux-armv7-g++ -qt-kbd-linuxinput -qt-
mouse- tslib -opensource -verbose -R /home/stud/tslib_arm/lib/
```

Make the libraries (Grab ...something, this takes several hours):

```
$ make
```

and install them:

```
$ make install
```

WFDB Installation and Cross Compilation

This chapter describes how to install the WFDB library from physionet.org and how to modify it for cross compilation to the ARM target running Linux. The WFDB library is an open source project used to read and manipulate patient records from the PhysioBank database. The host Linux platform must have installed the “arm-none-linux-gnueabi-gcc” prior to this installation.

First download the WFDB library from here:

<http://www.physionet.org/physiotools/wfdb.shtml#downloading>

Steps to install WFDB on the Linux host:

1. Install XView for Linux
\$ sudo apt-get install xviewg xviewg-dev
2. Unpack the downloaded wfdb.tar.gz
/home/stud\$ tar -xvf wfdb.tar.gz
3. Run configure in the wfdb directory
/home/stud/wfdb-10.5.1\$./configure
4. Build and make the wfdb library
/home/stud/wfdb-10.5.1\$ make
5. Install the wfdb library on Linux host
/home/stud/wfdb-10.5.1\$ sudo make install

Steps for cross compile of the WFDB library to target:

This part describes how create the libwfdb.so.10.5 library that must be copied to the target platform. Prior to this step the WFDB library must be installed on the Linux host see description above.

1. The first step is to copy the source library files to a new directory. Copy the lib directory from the wfdb-10.5.1 installation to a new directory named lib-arm.

```
/home/stud/wfdb-10.5.1/lib
```

Copy to

```
/home/stud/wfdb-10.5.1/lib-arm
```

2. Edit the Makefile manual in the new lib-arm directory, change the following lines to:

```
SRCDIR = "/home/stud/wfdb-10.5.1"
WFDBROOT = /home/stud/wfdb-arm
CC = arm-none-linux-gnueabi-gcc
BUILDLIB = arm-none-linux-gnueabi-gcc $(MFLAGS) -shared -Wl,-
soname,$(WFDBLIB_SONAME) $(LL) \
-o $(WFDBLIB)
```

These modification will now used the arm cross compiler (arm-none-linux-gnueabi-gcc) and install the WFDB header and library files in /home/stud/wfdb-arm

3. Make, Compile, link and install the wfdb library for arm target

```
/home/stud/wfdb-10.5.1/lib-arm $ make
```

```
/home/stud/wfdb-10.5.1/lib-arm $ make install
```

Ignore errors when “make install” is performed this is due to some files it tries to install on the Linux host that is not needed on target.

Steps for using the WFDB library in eclipse:

1. Change the eclipse application project to include wfdb:
/home/stud/wfdb-arm/include
2. Change the eclipse project to include the wfdb library and path:
-l wfdb
/home/stud/wfdb-arm/lib

Steps for using the WFDB library in Qt:

This step describes how to use the qt-everywhere version of qmake to generate the makefile for cross compilation to target. The following parameters to qmake must be added as described below.

These parameters adds information about the paths for find the wfdb header files and wfdb library. The below line also specifies to include the touch screen library (-lts) for the Devkit8000 platform.

```
/home/stud/qt-everywhere-opensource-src-4.6.1/bin/qmake LIBS+="-L/home/stud/wfdb-arm/lib -lts -lwfdb" DEFINES+=_LINUX DEFINES+=_USE_HW_DAC  
INCPATH+=/home/stud/wfdb-arm/include
```

If the _USE_HW_DAC is not specified a version will be compiled that just prints out record samples on the standard output. (Terminal output)

13. INSTALLATION AND EXECUTING

This section describes how to install the sapien190 software on the DevKit8000 target running Linux. We will describe how to install the needed libraries and the application program on target.

13.1 Installation

The sapien190 executable can be copied to the target by copy of the cross compiled binary executable program to the SD card or using Ethernet over an USB connection to the target.

Ethernet over USB to target

Configure Ethernet over USB after the USB wire is connected between host and target powered on with the target IP address of 10.9.8.2:

First configure the IP address of the Linux host:

```
$ ifconfig usb0 10.9.8.1/24 up
```

Use secure copy of binary cross compiled application to target in the default directory /home/root:

```
$ scp sapien190 root@10.9.8.2:
```

Copy of files using SD card:

Copy the sapien190 binary file to the SD card and insert it on the target. The SD card will automatically be mounted on the target at:

```
/media/mmcblk0p1/
```

13.2 Executing-hardware

To run sapien190 on the host development platform Qt and the WFDB library must be installed to start sapien190 enter the following command in Linux:

```
$/sapien190
```

To run Sapien190 on the target after installed:

```
$/sapien190 -qws
```

The driver for the Add-on board must be installed according to the description found here: <http://devkit8000addon.wikispaces.com/>

The Add-on board contains the following features:

- 8-Channel 12-bit A/D Converter with build-in programmable PGA
- 2-channel 12-bit D/A Converter
- 16 GPIO ports via the I2C Interface
- 8 GPIO ports directly mapped to the OMAP processor
- CPLD for future VHDL programs
- Flexible clock generator for the CPLD
- Additional LEDs for debugging
- 3 RS-232 Interfaces including

13.3 Executing-software

This chapter describes the needed libraries to be installed on target to run the Sapien190 patient simulator.

Installing Qt Everywhere on target by moving the cross compiled libraries and some

fonts to the DevKit8000 target.

Fonts: At least one font must be present on target to show text. Fonts can be found in `$HOME/qt-everywhere-opensource-src-4.6.1/lib/fonts` on the host and must be copied to `/usr/local/Trolltech/QtEmbedded-4.6.1-arm/lib/fonts/` on target (create the directories as necessary).

(At least) the below libraries must be copied from `$HOME/qt-everywhere-opensource-src-4.6.1/lib/` on host to `/usr/lib` on target:

- `libQtCore.so.4`
- `libQtGui.so.4`
- `libQtNetwork.so.4`

The wfdb library must be copied from host `/home/stud/wfdb-arm/lib/` on host to `/usr/lib` on target:

- `libwfdb.so.10`

The standard C++ library must be copied from host

`/opt/CodeSourcery/Sourcery_G++_Lite_2007q3/arm-none-linux-gnueabi/lib/` to `/usr/lib` on target:

- `libstdc++.so.6`

Install and enable the touch screen on Devkit8000 by following the steps in “Getting started with Qt” [9] and install the touch screen library as described below:

Copy the touch screen libraries from `/home/stud/tslib_arm/lib/` to `/usr/lib` on target and enable the touch on the DevKit8000:

- `libts-0.0.so.0`
- `libts.so`

Enable touch screen on DevKit8000:

```
$ chmod a+rw /dev/input/event2
$ export QWS_MOUSE_PROTO=Tslib:/dev/input/touchscreen0
```

Add the environment variable `QWS_MOUSE_PROTO` in the startup profile listed below.

```
/etc/profile
```

13.4 Execution-control (start, stop and restart)

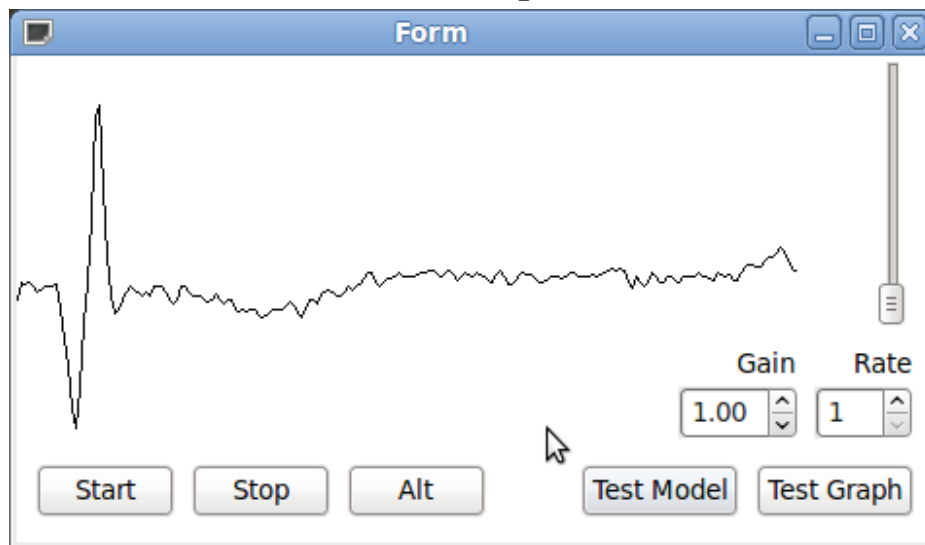


Figure 40 Sapien190 test version

The first version of the Sapien190 patient monitor is only able to start and stop playing a specific patient ECG record e0104 alternating with patient ECG record e0103. When test model or test graph is selected the contents of patient record files is printed on the display independent of the DAC signal outputs. The final prototype of the Sapien190 patient monitor is shown below. In this version the graph is updated simultaneously with output of the ECG signal on the analogue output. It is possible to alternate between patient records e0103 and e0104, when the simulation is running and setting gain and rate of replaying the patient record. Pause and resume buttons will temporary stop the simulation and continue from the point it was stopped.

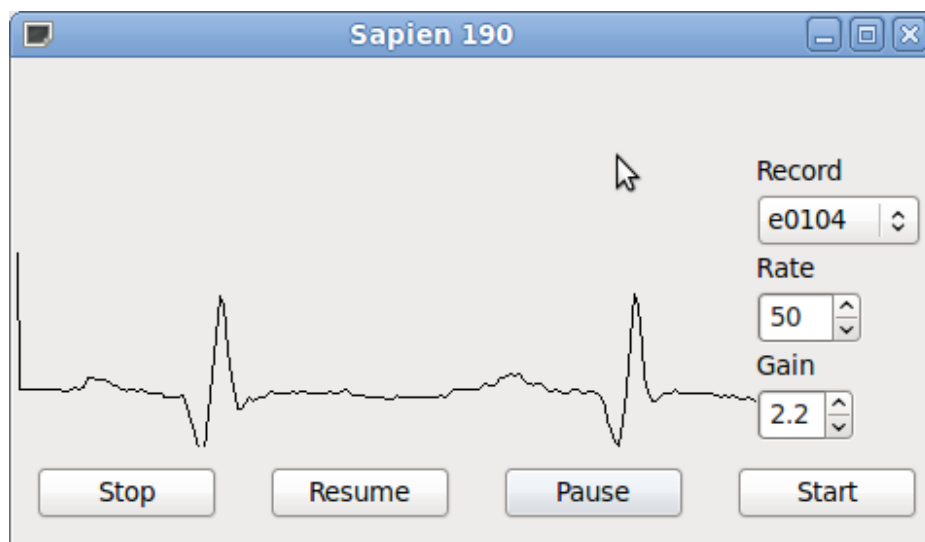


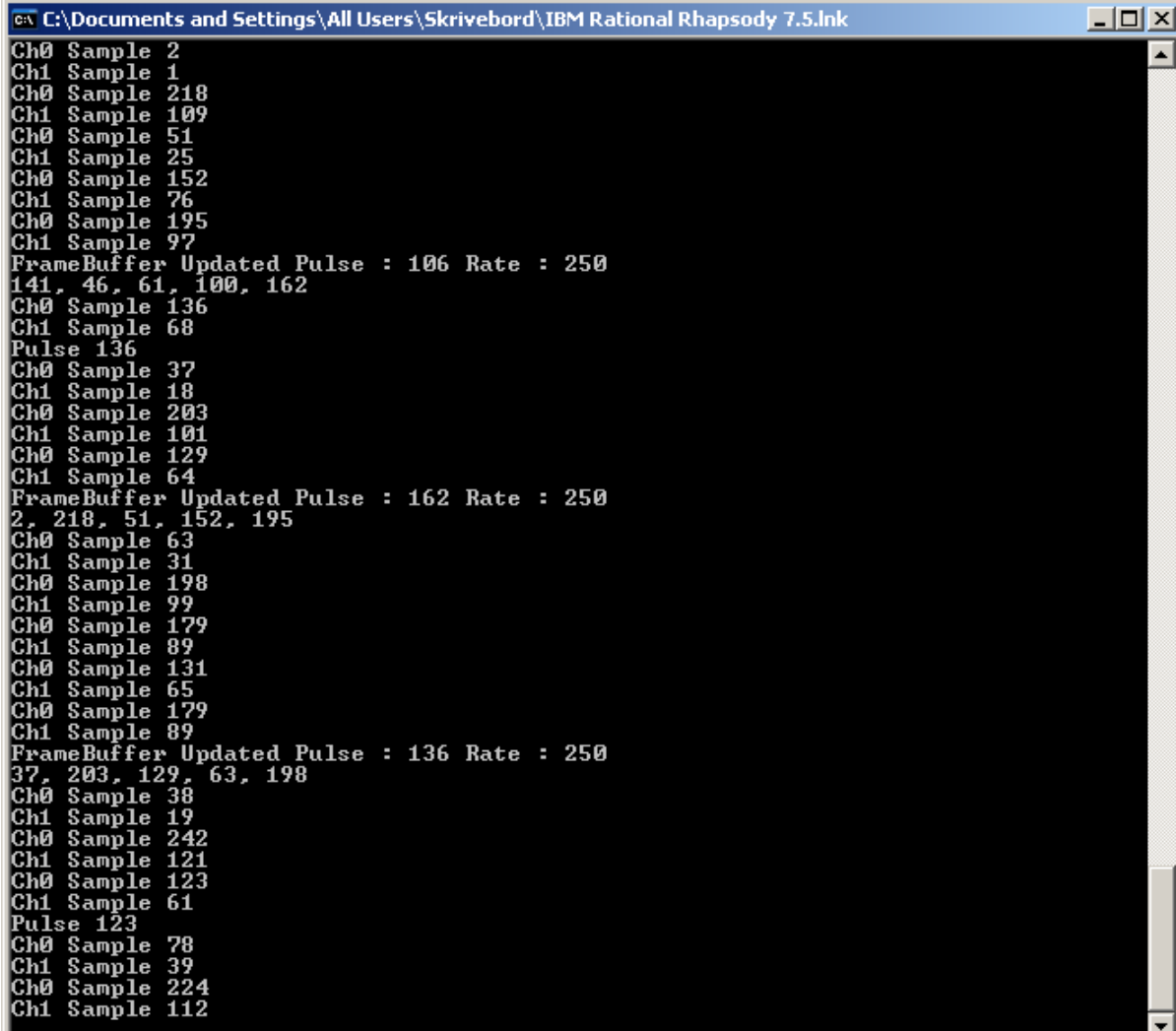
Figure 41 Sapien 190 Final prototype

13.5 Error messages

The current version will be displaying no error messages if as an example the patient record could not be found. The simulator will in this case just output zero voltages output for ECG and EDR signals.

14. APPENDICES

Test: Console output from test in Rhapsody



```
C:\Documents and Settings\All Users\Skrivebord\IBM Rational Rhapsody 7.5.lnk
Ch0 Sample 2
Ch1 Sample 1
Ch0 Sample 218
Ch1 Sample 109
Ch0 Sample 51
Ch1 Sample 25
Ch0 Sample 152
Ch1 Sample 76
Ch0 Sample 195
Ch1 Sample 97
FrameBuffer Updated Pulse : 106 Rate : 250
141, 46, 61, 100, 162
Ch0 Sample 136
Ch1 Sample 68
Pulse 136
Ch0 Sample 37
Ch1 Sample 18
Ch0 Sample 203
Ch1 Sample 101
Ch0 Sample 129
Ch1 Sample 64
FrameBuffer Updated Pulse : 162 Rate : 250
2, 218, 51, 152, 195
Ch0 Sample 63
Ch1 Sample 31
Ch0 Sample 198
Ch1 Sample 99
Ch0 Sample 179
Ch1 Sample 89
Ch0 Sample 131
Ch1 Sample 65
Ch0 Sample 179
Ch1 Sample 89
FrameBuffer Updated Pulse : 136 Rate : 250
37, 203, 129, 63, 198
Ch0 Sample 38
Ch1 Sample 19
Ch0 Sample 242
Ch1 Sample 121
Ch0 Sample 123
Ch1 Sample 61
Pulse 123
Ch0 Sample 78
Ch1 Sample 39
Ch0 Sample 224
Ch1 Sample 112
```

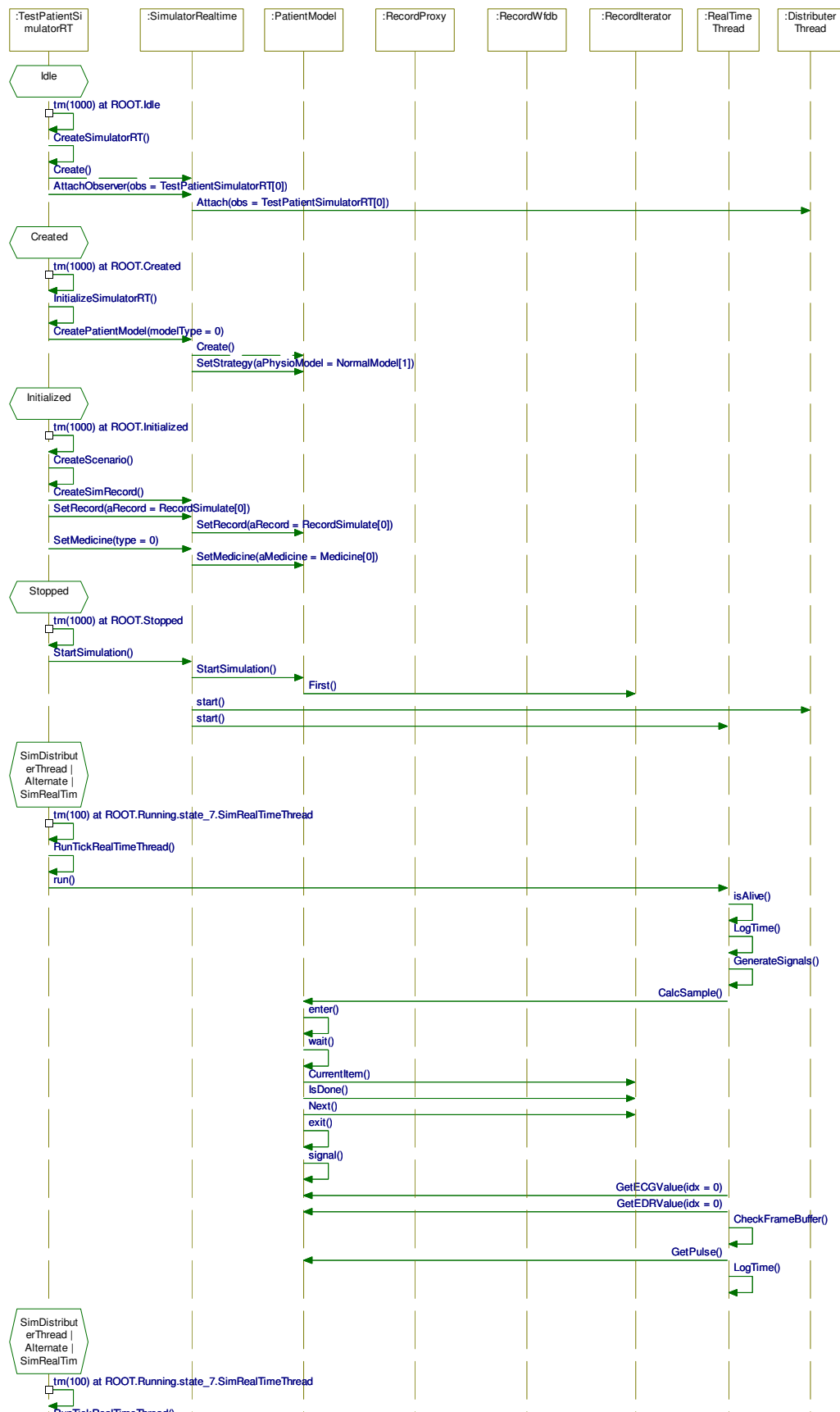


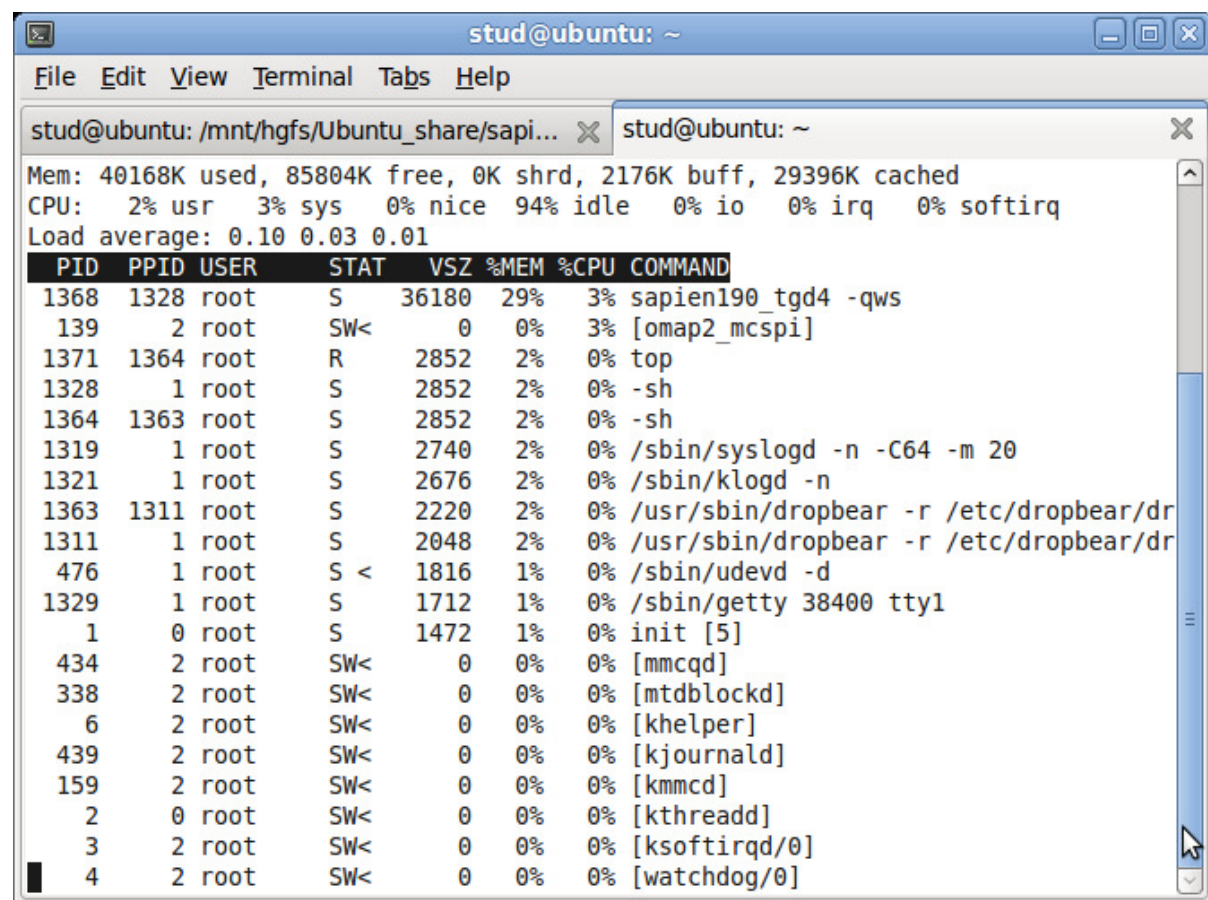
Figure 42 Animated Rhapsody of testing real-time simulator

Measurements: Compute Time for sample and graph on target

```

CTSample 153
Pulse 90
CTGraphUpdate 3357
CTSample 4089
CTSample 244
CTSample 305
CTSample 213
Kill Thread DistributerThread
Kill Thread RealTimeThread
CTSample 244
CTGraphUpdate 3784

```

**Figure 43 Memory and CPU usages on target**

Measurements: Compute Time for updating the ECG graph on target

CTGraphUpdate 3662
CTGraphUpdate 3479
CTGraphUpdate 2960
CTGraphUpdate 3113
CTGraphUpdate 3235
CTGraphUpdate 3112
CTGraphUpdate 3113
CTGraphUpdate 3204
CTGraphUpdate 3082
CTGraphUpdate 3113
CTGraphUpdate 3205
CTGraphUpdate 3052
CTGraphUpdate 3205
CTGraphUpdate 3235
CTGraphUpdate 3173
CTGraphUpdate 3113
CTGraphUpdate 3174
CTGraphUpdate 3205
CTGraphUpdate 3113
CTGraphUpdate 3113
CTGraphUpdate 3204
CTGraphUpdate 3144
CTGraphUpdate 3113
CTGraphUpdate 3174
CTGraphUpdate 3082
CTGraphUpdate 3112
CTGraphUpdate 3143
CTGraphUpdate 3235
CTGraphUpdate 3144
CTGraphUpdate 3174
CTGraphUpdate 3265
CTGraphUpdate 3143
CTGraphUpdate 3113
CTGraphUpdate 3205
CTGraphUpdate 3173
CTGraphUpdate 3083
CTGraphUpdate 3113
CTGraphUpdate 3204
CTGraphUpdate 3082
CTGraphUpdate 3082
CTGraphUpdate 3174
CTGraphUpdate 3113
CTGraphUpdate 3113
CTGraphUpdate 3265
CTGraphUpdate 3204
CTGraphUpdate 3296
CTGraphUpdate 3235
CTGraphUpdate 3327
CTGraphUpdate 3693

Measurements: Compute Time for calculate and generate new sample on target

CTSample 396
CTSample 213
CTSample 122
CTSample 153
CTSample 122
CTSample 458
CTSample 245
CTSample 244
CTSample 153
CTSample 122
CTSample 122
CTSample 152
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CTSample 336
CTSample 214
CTSample 213
CTSample 153
CTSample 122
CTSample 122
CTSample 2000
CTSample 214
CTSample 153
CTSample 122
CTSample 122
CTSample 122
CTSample 152
CTSample 152
CTSample 122
CTSample 122
CTSample 122