

# A Semantics of Communicating Reactive Objects with Timing

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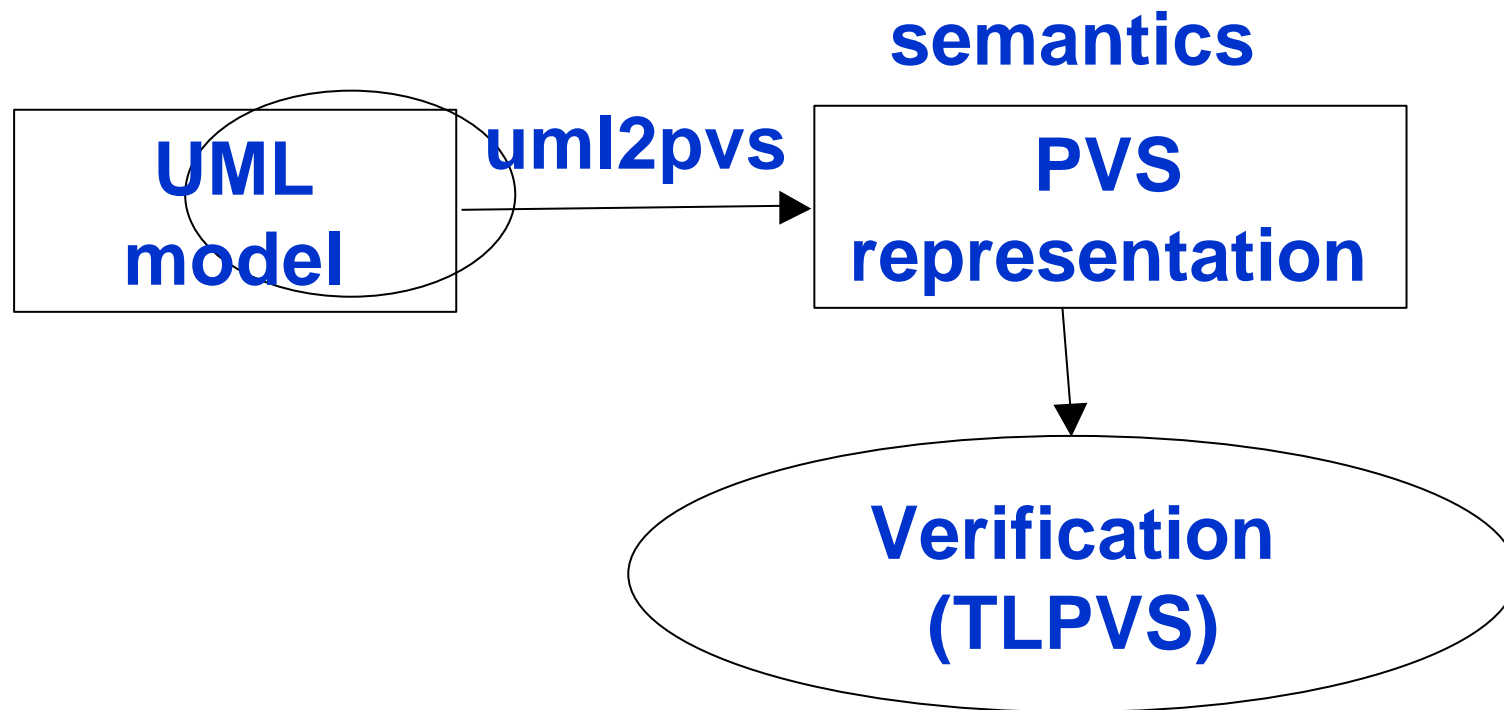
## OMEGA project:

### Correct Development of Real-Time Embedded Systems

#### Partners:

- Verimag, Grenoble, France
- OFFIS, Oldenburg, Germany
- CWI, Amsterdam, Netherlands
- CAU, Kiel, Germany
- KUN, Nijmegen, Netherlands
- WIS, Rehovot, Israel
- Industrial partners (IAI, EADS, NLR, FT)

**CAU, CWI, WIS and KUN collaborate on  
tool support for theorem proving in PVS**



- **Input: UML model expressed in OMEGA kernel language, i.e. class diagrams + state machines**

**This includes:**

- Asynchronous signals (and queues)
  - Synchronous operation calls
  - Active classes (thread of control)
  - Timing annotations
- **The semantics defines a Labelled Transition System (LTS) for the input model**
- **Verification: prove correctness properties (safety, liveness, timing) of execution traces (runs) of LTS**

**System behaviour is concurrent behaviour of all state machines of the objects in the system**

**Global step corresponds to:**

- **A state machine action of one of the objects (possibly involving other objects as well, e.g, for synchronous operation calls)**
- **The discarding of a signal by one of the objects**
- **A global time delay step (all other steps do not take time)**

## Main semantic issues discussed:

1. Meaning of **active objects** and thread of control
2. **Operations**: triggered vs primitive, and relation with control
3. **Signals**: handling of queues and relation with operations and control
4. **Timing**

## Not elaborated here:

- Object creation/destruction
- Generalization (inheritance)

# 1. Activity Groups

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Each object belongs to an **activity group** that has exactly one active object.

In every group exactly one object has **control**.

An object needs control to execute actions.

We have a “**run to completion**” semantics:

An object cannot loose control before it has reached a **stable** state (unless it calls a triggered operation of a group member).

- **Primitive operation:** result value is completed locally in one atomic step which includes assignment of result value to attribute of caller  
Decision: callee may be unstable or suspended
  
- **Triggered operation:**
  1. Synchronization of caller and callee
  2. Caller becomes suspended until return value is received
  3. Callee must be stable
  4. No re-entrance



## Control requirements and changes:

- **If caller and callee in same group:**  
control passed to callee,  
after return of result value, caller gets control back  
when callee has become stable
- **If caller and callee in different groups:**  
caller remains in control, callee must have control

**Note: control requirements and control changes are rather complex; challenge to represent this conveniently in PVS to enable verification**

### Signals:

- Each object has its own signal queue  
(alternative: each activity group has queue)
- An emitted signal is placed in the signal queue of the addressed object; no requirements on receiver.
- A signal can be accepted (i.e. trigger a transition) from the queue if object is stable and has control
- A signal can be discarded from the FIFO queue if the object is stable and has control, and the signal does not trigger a transition from the current state  
(if it is deferrable, it remains in the queue)

**Timing:** adding time is orthogonal to previous issues

We follow standard approach of **Timed Automata**:

- Every object has local clocks which it can read and reset; guards may depend on clock values
- Global delay steps
- Clock invariants on state machine locations

We allow the (global) passing of time in between the actions of a transition

- **Modeling of passing of control, in combination with operations and signals, in PVS revealed many ambiguities in the first OMEGA semantics and raised many new questions**
- **Adding time is orthogonal to the issues above**

## **Current work includes:**

- **Verification of industrial case studies in PVS**
- **Interpretation of OMEGA timing annotations**
- **Compositional semantics**