Software Development with Real-Time Workshop Embedded Coder

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Who are we - Thales UK Operations in Defence

- 2nd largest defence systems contractor in the UK
- Operates at 3 levels in the UK market
  - Prime contractor
  - Sub-system integrator – where we take responsibility for integrating complete sub-systems for a platform
  - Sub-system supplier – where we will offer in competition world class technology and/or products
- Building on our core systems integration capability
- Growing CLS (Customer Logistic Support) business
Where are we – Thales Missile Electronics

- TME: Basingstoke
- Single Integrated Site
  - On-site manufacturing
  - Laboratories
  - Environmental test facilities
  - 240 staff
What do we do

Weapon Systems

Safety & Arming Units; Hard Target Fuzes
Proximity Fuzes / Target Detection Devices
Multimode Seekers & Sensors

Battlefield Systems

Battlefield Target Identification, UAS Sensors & Payloads

Systems, Technologies & Products

ILS, CLS, Rad Haz
Consultancy, Telemetry & Weapon
Range Support, Research, Security
Scanner

Consultancy

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Why do we want to use Model-Based Design

- Save money!
  - Reduce coding effort and timescales
  - Reduce introduction of errors – reduced risk
- Reduce the need for documentation
  - Requirements - DOORS
  - Design specifications – lost in translation!!
    - The model is the design – graphical solution but well documented
Why do we want to use Model-Based Design

- Rapid prototyping
  - Early checking of software on target - timing/resources
    - Functional correctness of algorithms
    - Determine run-time and memory requirements
  - Design decisions on target hardware
    - Put on eval boards quickly to confirm following
      - 16-bit or 32-bit
      - Floating or fixed point?
      - Memory – internal/external?
      - FPGA required?
Why do we want to use Model-Based Design

- More efficient use of resources
  - Modelling engineers concentrate on creating the model and supporting real-world environments
  - Embedded engineers concentrate on processor scheduling and I/O to the rest of the physical system
    - The model plugs into the embedded software harness
  - Uptake of Model-Based Design could lead to less distinction between the two disciplines
    - Increased labour flexibility – common toolsets
    - Hybrid engineers!!
    - Broader understanding of design and implementation
TME approach to Model-Based Design was not to use it in the harness

- Decision at the start of the pilot project was the model was to plug into a hand-coded scheduler/harness
- C coding was used for all software programming of the target resources
- Model could be taken from the Simulink “real-world” environment and C code generated
  - Some processor I/O simulation in real-world environment where required
Two projects used MBD

P1: Data processing for a single channel pulsed proximity sensor + timing algorithm
- TME designed custom hardware for TDP
- Software developed for 2 x dual-core 16-bit fixed-point DSPs
  - Serial and parallel I/O required with DMA
  - FPGA + analogue front-end

P2: Control algorithms for a gimbal assembly with mounted pulsed laser and PIR dual mode sensing
- COTS hardware with 4 x floating-point DSPs
- Single DSP used to run model
  - Parallel I/O
  - FPGA – gateway to rest of the system
- Vendor board support library
Where did we use Model-Based Design: P1

- Create representative simulator
- Historic Information
- Use measured results

Data saved as .mat file

**Simulator**

This represents a delay between the pulse transmit and the start of the sampling frame. You could add other noise sources in the calculation.

- Tx pulse with noise
- Rx pulse with noise & range law

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Where did we use Model-Based Design: P1

- Cut for target build
- Simulated data loaded into RAM read out of memory
- Models for Dual-Core DSP

Shared data defined at this level only. If data is shared, it must be both the coreA and coreB models, otherwise a build on

Optimisations turned on for full speed in dep_000

Conditional execution of coreA and coreB controlled by

The custom code blocks in coreA and coreB ensure that
of the application executes on the right core. Main and this is
code on both cores. The build environment ensures no false
data integrity when sharing between the two cores. Sh
Where did we use Model-Based Design: P1

Simple Ideology

Generic scheduler with I/O for processor family

TME Custom Hardware
Where did we use Model-Based Design: P2

- Simulation
  - Real-world model in Simulink
    - Several modes required
    - Single mode simulation model optimal—time/cost vs payback
  - Gimbal model developed in ProE
Where did we use Model-Based Design: P2

- Inputs derived from real-world model
- Model evaluated on hardware and compared against simulation for timing & correctness – it does what it says on the can
Where did we use Model-Based Design: P2

- State-machine implemented in state-flow
- Modes/States picked from original simulink model
Where did we use Model-Based Design: P2

Gimbal State Controller

- ControllingGimbal
  - [PostType > 6]
  - [feedbackStatusFlags.commandType = 0]
  - [feedbackStatusFlags.validState = 1]
  - feedbackStatusFlags.cmdValid = 1
  - feedbackStatusFlags.cmdType = 0

- MovingToLOS
  - [PostType = 6]
  - [feedbackStatusFlags.commandType = 0]
  - [feedbackStatusFlags.validState = 1]
  - feedbackStatusFlags.cmdValid = 1

- GimbalStateController
  - [PostType = 6]
  - [feedbackStatusFlags.commandType = 0]
  - [feedbackStatusFlags.validState = 1]
  - feedbackStatusFlags.cmdValid = 1

- InitialPosition
  - [PostType = 6]
  - [feedbackStatusFlags.commandType = 0]
  - [feedbackStatusFlags.validState = 1]

- TargetTracking
  - [PostType = 6]
  - [feedbackStatusFlags.commandType = 0]
  - [feedbackStatusFlags.validState = 1]

- ReturningToPosition
  - [PostType = 6]
  - [feedbackStatusFlags.commandType = 0]
  - [feedbackStatusFlags.validState = 1]

Key:
- 1 = MoveToLOS
- 2 = ReturnToPosition
- 3 = TrackTarget
- 4 = FrameTarget
- 5 = MoveToGimbalAngle

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What benefits were seen

- **Re-use of simulation data**
  - Same stimuli used for model verification on hardware
  - Easy/fast capture of test stimuli for model from real-world model
  - Cross referencing simulation and hardware model versions

- **Rapid prototyping possible**
  - Extensive use of low cost microprocessor evaluation boards prior to making hardware decisions
  - Evaluate model and hardware it is to run on
  - Timing analysis/profiling – can the model run fast enough on hardware
  - Optimise parts of model if necessary
What benefits were seen

- **Reduced specification writing**
  - No need for lengthy detailed design specs
    - Well documented model with graphical flow can yield almost as much detail as a written specification – can do this in the model
    - Well organised model with several tiers can clearly show model hierarchy (with adequate labelling)
    - Software interface documentation still required

- **Rapid response to change/additions to requirements**
  - New model sections rapidly integrated and tested on hardware
    - Maximise use of existing architecture – greater visibility with graphical model
What benefits were seen

- Powerful linkage between model and software run on the hardware established
  - During integration can return easily to model for debug
    - Simulink display facilities allow easy visibility for rapid debug
    - Still use microprocessor development environment
      - Breakpoints
      - Memory/register contents
      - Execution time
  - Can aid debug of third party sub-systems

- No perceivable increase in development time during the learning curve period
  - Scheduler required significant development time
  - This needs to be done anyway
What benefits were seen

- Ability to review model with third party
  - TME program management team
  - Customer
  - Other team project members
  - Internal review processes
Where to start!!!

- No prior experience of Simulink or Stateflow
  - Mathworks training courses only in 2005
- How to architecture the model for simulation
- Limited experience of house keeping activities for code generation from a Simulink model
  - Template Make Files
  - Low level understanding of compiler options
  - Code and data placement in memory
What difficulties did/do we experience?

- Pressures to deliver on a live project
  - Learning curve to go up

- Debugging the model
  - Setting breakpoints in the model
  - Is it Simulink or the target environment
  - Program flow through the model
    - Graphical interpretation of execution order
    - Program control sometime difficult to understand
    - In-built debugger hard to drive – lack of training/experience?
What difficulties did/do we experience

- How to configure a model for multiple developers
  - TME uses SourceSafe for software
  - How do we handle multiple developers on a single model for configuration and integration – even for desktop development
    - More acute for embedded applications
Where do we go now

- Demonstrate significant reductions in timescales for model based development
  - Acceptance by program managers and company hierarchy only if visible savings

- Define a company process for model based design involving code generation
  - Record current knowledge so not lost!
  - Iterative/learning process

- Use on more projects
  - Increase expertise in model based design across the company product range and staff – where applicable
Where do we go now

- MISRA compliant hand/model generated code
  - Future products expected to require safety related software
  - Increase documentation within the models
- Make use of linkage with DOORS
  - For bigger programs
  - Simplify requirements and compliance management
- Make more use of in-built Simulink reporting tools to better describe model – the model is the specification
Conclusions so far

- No perceived increase in development time/cost in early programs
  - Savings masked by other activities that are also on the learning curve – e.g. new processor
- If it happens in the model it will happen on the target
- Re-use of simulation data allows early evaluation of algorithms/models on target resources
- Model-Based Design very flexible and responsive to change (for example dual vs. single core)
Conclusions so far

- Still work to do to define a process
  - Iterative activity to get to a process that works
  - Flexible process to cater for desktop and embedded applications
- MathWorks pilot support throughout - Excellent!
Similar pilot study evaluating Model-Based Design carried out at a Thales sister company in Belfast

Automatically generated fixed point code ran 30% faster than the hand written fixed point code