

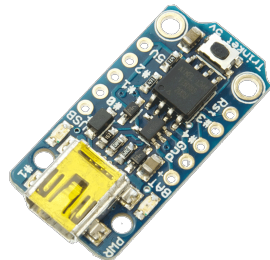
# Rizzly: Event Driven Microcontroller Programming

Urs Fässler

Saturday 17:40, H.2215, FOSDEM 2015

31.01.2015

- Micro Controller
  - no OS
  - no dynamic memory
  - Interrupts
- Event Driven Programming
  - every software that interacts with the “real world”
  - Source of Event is Interrupt or Callback
  - Inversion of Control[2]
  - Frameworks, Graphical Tools, Code Generators
  - Qt (on big Machine)

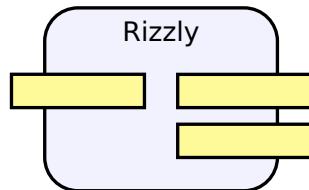


[1]

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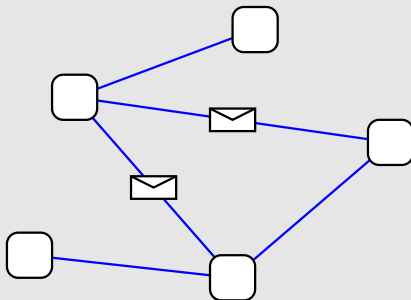
- 8 Bit
- 4-20 MHz
- $\geq$  128 Byte RAM
- $\geq$  2 KiB ROM
- no OS, no Memory Allocation
- whole Program and Environment is known at compile time

- Event Driven Programming Language
- for the smallest Micro Controllers
  - very static generated code
- high code re-usability
  - high machine abstraction
  - Templates
  - Compile Time Function Evaluation



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- Event handling is based on the Atom-Model
  - Communication only by Events (Messages)
  - Transmission needs time
  - Execution/Handling does not need time
  - Component/Node can only be activated by Event
  - Application is distributed system



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- basic number data type is an integer range type
  - $R\{\text{from}, \text{to}\}$
  - mathematical model: the type of the result of an operation is as big as needed → no overflow or implicit cast

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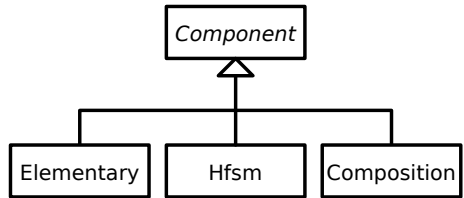
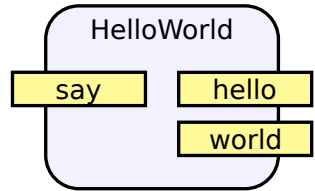
└ Rizzly

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- strict Language
  - Compiler understands Model
  - Compiler sees whole program
- better optimization (e.g. eliminate not reachable states in hfsm)
- static Code (no function pointer, no dynamic)

# Component

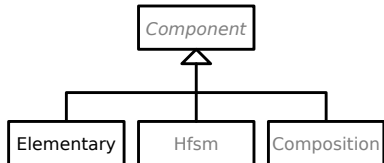
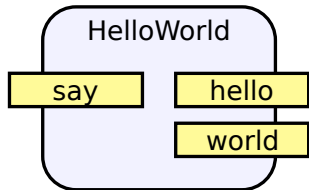
- Slots are Input Interface
- Signals are Output Interface
- only method to communicate
- contains a state
- there is no main ...
- different implementations





# Elementary

```
HelloWorld = Elementary  
  first : Boolean = True;  
  
  hello : signal();  
  world : signal();  
  
  say : slot()  
    if first then  
      hello();  
    else  
      world();  
    end  
    first := not first;  
end  
end
```

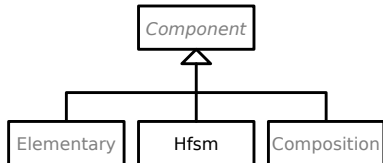
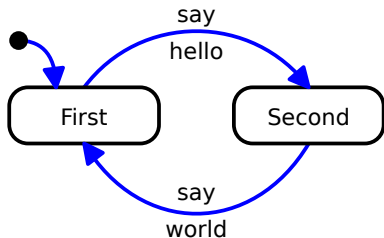


# Hierarchical Finite State Machine

```
HelloWorld = Hfsm
hello : signal();
world : signal();
say   : slot();

state(First)
  First : state;
  Second : state;

  First to Second by say() do
    hello();
  end
  Second to First by say() do
    world();
  end
end
end
```



# Composition

OneToThree = **Composition**

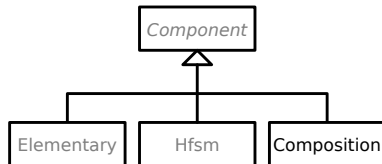
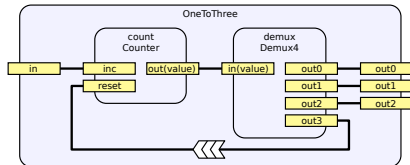
```
out0 : signal();  
out1 : signal();  
out2 : signal();  
in   : slot();
```

```
count : Counter{0};  
demux  : Demux4;
```

```
in -> count.inc;  
count.out -> demux.in;  
demux.out3 >> count.reset;
```

```
demux.out0 -> out0;  
demux.out1 -> out1;  
demux.out2 -> out2;
```

**end**



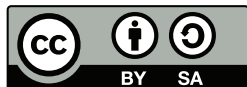
- method to access io, catch interrupts (see appendix)
- ~~llvm/gcc for Code generation~~
  - best is to stick with C code generation since there exists probably for every micro controller a C compiler
- IDE Integration
- ... and a lot more

# Thank you

→ Rizzly

- Event-Driven
- Micro Controller

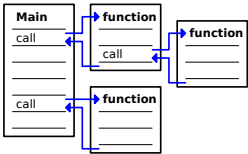
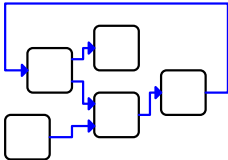
- [urs@bitzgi.ch](mailto:urs@bitzgi.ch)
- [gitorious.org/rizzly](https://gitorious.org/rizzly)



Exclusive external Content



# Imperative ↔ Event Driven

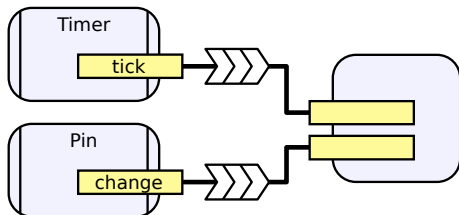
	Imperative	Event Driven
Contrololle	Program	Environment
Program flow	linear	non-linear
program is	calculating	waiting
run time	short	long
parallel	no	yes
coupling	strong	weak
	 <p>The diagram illustrates a linear flow in imperative programming. It starts with a 'Main' box containing 'call' and two empty lines. Two arrows point from 'Main' to two separate 'function' boxes. Each 'function' box contains 'call' and two empty lines. An arrow points from the top 'function' box to a third 'function' box on the right, which also contains 'call' and two empty lines. This represents a sequential, linear execution path.</p>	 <p>The diagram illustrates a non-linear flow in event-driven programming. It shows a central box with two arrows pointing to two separate boxes above and below it. From the top box, an arrow points to a box on the right. From the bottom box, an arrow points to a box on the right. From the top-right box, an arrow points to a box on the far right. From the bottom-right box, an arrow points to the same box on the far right. Additionally, a long arrow at the top points from the far right box back to the top box, creating a loop. This represents a non-linear, event-driven execution path.</p>

# TODO: access Hardware / Interrupts

```
Timer = Elementary
  tick = signal();

  reload      : Register{R{0,255}, 2048, 0, 8, MAP11};

  interrupt{INTERRUPT_TIMER}
    // clear interrupt flag
    reload := ...;
    tick();
  end
end
```







## Rizzly2[width=8cm]

└─ TODO

└─

TODO: access Hardware / Interrupts

```
Timer = Elementary
tick = signal();

reload    : Register(R(0,255), 2048, 0, 0, MAP1);

Interrupt(INTERUPT_TIMER)
// clear interrupt flag
reload := ...;
tick();
end
end
```

interrupt is a (special) event handler for interrupts. The template argument could be the interrupt number or the address where the interrupt function has to be placed.

2015-02-08

Rizzly2[width=8cm]

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└─

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// clear interrupt flag
reload := ...;
tick();
end
end

```

The component is no longer pure since she can send event without an activation as also since she changes the environment without sending an event. As this violates the model, we need queues to connect such components. To keep an application “clean”, impure components should be used carefully and only on the top layer.

2015-02-08

Rizzly2[width=8cm]

└─  
  └─  
    └─  
      └─

└─  
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└─  
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      └─

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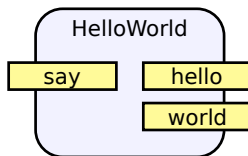
reload   : Register(R(0,255), 2048, 0, 0, MAP1);

Interrupt(INTERUPT_TIMER)
// clear interrupt flag
reload := ...;
tick();
end
end
```

As it is not yet possible to access hardware, some glue code is needed.

## Main (Glue Code)

```
ISR(INT0_vect){
    inst_say();
}
void inst_hello(){
    LED_HELLO = 1;
}
void inst_world(){
    LED_WORLD = 1;
}
void main(){
    ...
    inst__construct();
    ...
}
```



## Generated Header

```
extern void inst__construct();
extern void inst__destruct();
extern void inst_say();
// void inst_hello();
// void inst_world();
```

# Templates

```
Point{T: Type{Integer}} = Record  
  x : T;  
  y : T;  
end
```

```
max{N: R{0,100}} = function(x: R{0,100}):R{0,N}  
  if x > N then  
    return N;  
  else  
    return x;  
  end  
end
```

```
a : Point{R{-10,10}};  
y := max{80}( 42 );
```

# Compile-time function evaluation

```
lookuptable : const = calcTable(57);

calcTable = function(n: R{0,100}): Array{10,R{0,100}}
  res : Array{10,R{0,100}};
  i   : R{0,11} = 0;
  while1 i < 11 do
    idx : R{0,10} = R{0,10}(i);
    res[idx] := idx * n / 10;
    i := idx + 1;
  end
  return res;
end
```

---

<sup>1</sup>foreach loop is coming

[1] Adafruit trinket.

URL: <http://www.tandyonline.co.uk/adafruit-trinket-mini-microcontroller-5v.html>.

[2] Wikipedia.

Inversion of control — wikipedia, die freie enzyklopädie, 2013.  
[Online; Stand 11. November 2014].

URL: [http://de.wikipedia.org/w/index.php?title=Inversion\\_of\\_Control&oldid=125646165](http://de.wikipedia.org/w/index.php?title=Inversion_of_Control&oldid=125646165).