

OSADL Fieldbus Framework Meeting



SPS/IPC/Drives 2008
2008-11-26, 9:30 - 13:00 MEZ

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Agenda

- 10:00 - 11:00 Presentations I: Technology
 - Aims of the Fieldbus Framework Project (R. Schwebel, M. Kremer)
 - Current State of Prototypes: 3S, Pengutronix (R. Schwebel)
 - User Expectations (Plenum Discussion)
- 11:00 - 11:30 Coffee Break
- 11:30 - 12:00 Presentations II: Administrative Aspects
 - Legal Status of Userspace Drivers (C. Emde)
 - Business Plan Draft (R. Schwebel)
- 12:00 - 13:00 Panel Discussion
 - Commitments
 - Definition of a Roadmap
 - Assignment of Tasks



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Aims of the Fieldbus Framework Project

- How does non-Industrial networking work these days?

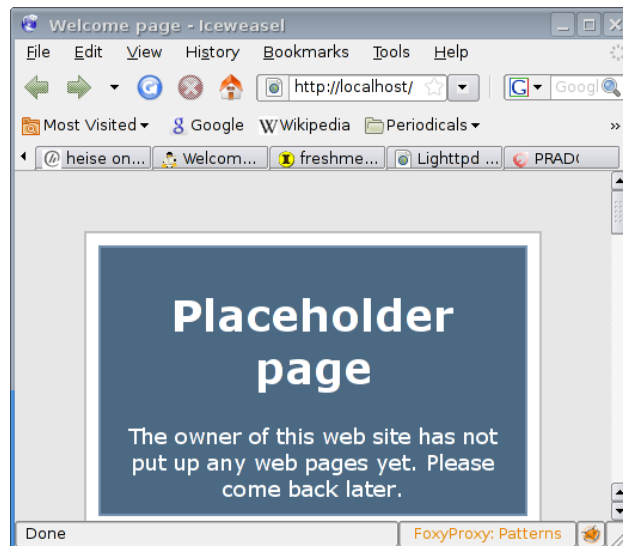
```
root@thebe:~# ifup eth0
root@thebe:~# apt-get install lighttpd
Reading package lists... Done
Building dependency tree
Reading state information... Done
The following NEW packages will be installed:
  lighttpd
0 upgraded, 1 newly installed, 0 to remove and 552 not
  upgraded.
Need to get 360kB of archives.
After this operation, 979kB of additional disk space will be
  used.
Do you want to continue [Y/n]? y
Get:1 http://debian.tu-bs.de testing/main lighttpd 1.4.19-5
  [308kB]
Fetched 360kB in 0s (431kB/s)
Selecting previously deselected package lighttpd.
Unpacking lighttpd (from ../lighttpd_1.4.19-5_i386.deb) ...
Setting up lighttpd (1.4.19-5) ...
Starting web server: lighttpd.
root@thebe:~#
```



Aims of the Fieldbus Framework Project

- How does non-Industrial networking work like these days?

```
root@thebe:~# ifup eth0  
root@thebe:~# apt-get install lighttpd
```



- Industrial Networking should be That Simple (TM)!

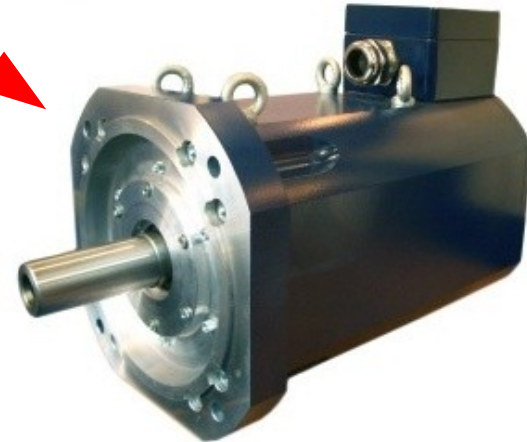


Which Problem are we Trying to Solve?

- Tell hardware what to do:

motionController
current_speed : int desired_speed : int
getCurrentSpeed() : void setDesiredSpeed() : void

„Rot at e!“



(Obviously, this needs realtime behaviour, the device needs to be told when and how, but we leave these boring details out for now ...)

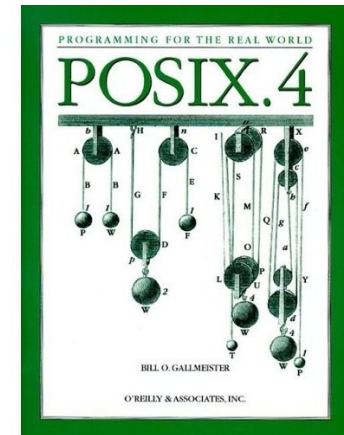
What we have these days instead is ...

1. ... no modern APIs (object dictionary is no IT interface!)
2. ... no language independence
3. ... no clear layering (in code, not in marketing slides)
4. ... no public review of stack code
5. ... no vendor independence
6. ... no bus independence
7. ... no market independence



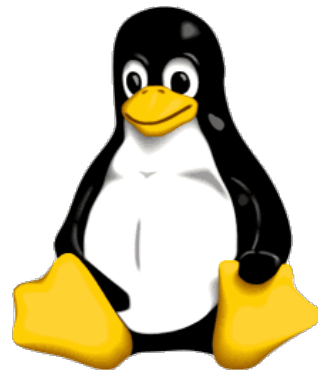
Design Goal 1: Modern APIs

- Think POSIX
- Respect the last 15 years of Linux Development
- Object Oriented Design
- Multi Instance



```
motionController
current_speed : int
desired_speed : int

getCurrentSpeed() : void
setDesiredSpeed() : void
```



Design Goal 2: Language Independence

- No constraints to programming language:

C, C++, Java, C#, IEC-61131, Python, Ruby, ... ergo: C with Wrappers

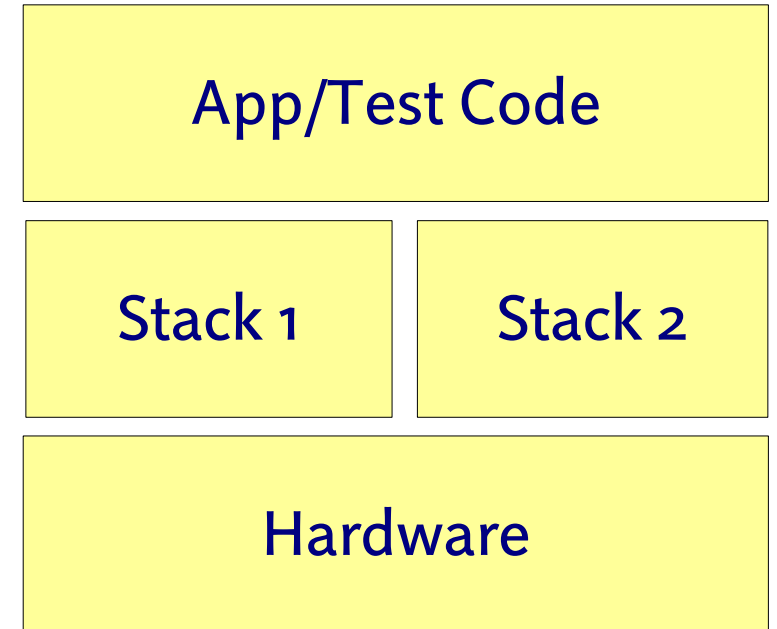
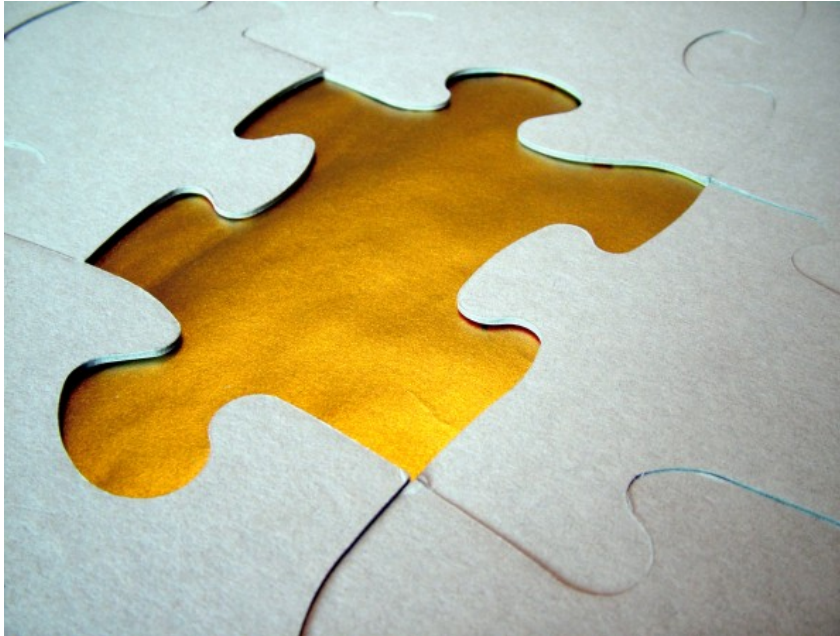
- Must run on low-ressource systems:

H720x (70 MHz ARM); Blackfin (no mmu)



Design Goal 3: Clear Layering

- Well Defined Interfaces

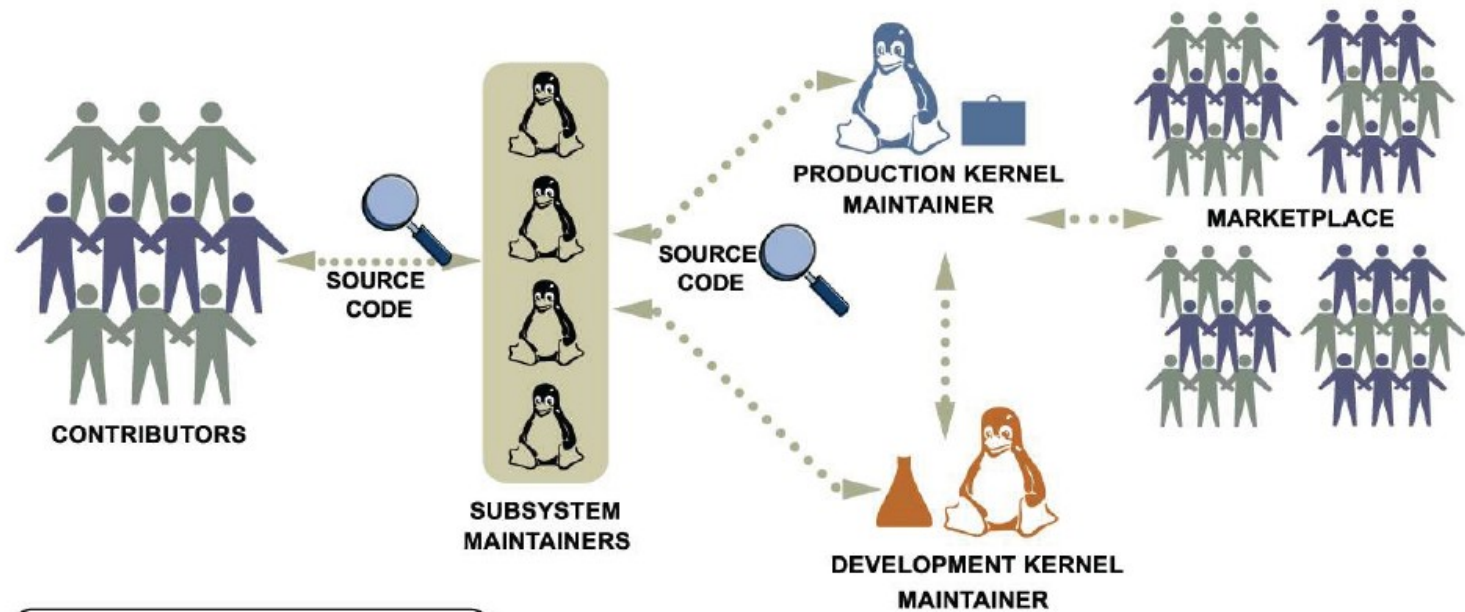



- Testability / Certification
- Clean, Layered Stack Design
- Plugin Concept (Proprietary / OSS) - „Buy & Play“



Design Goal 4: Peer Review

LINUX KERNEL DEVELOPMENT PROCESS



 Ongoing peer review of code
Continuously available online
for public review

© 2003 Open Source Development Labs



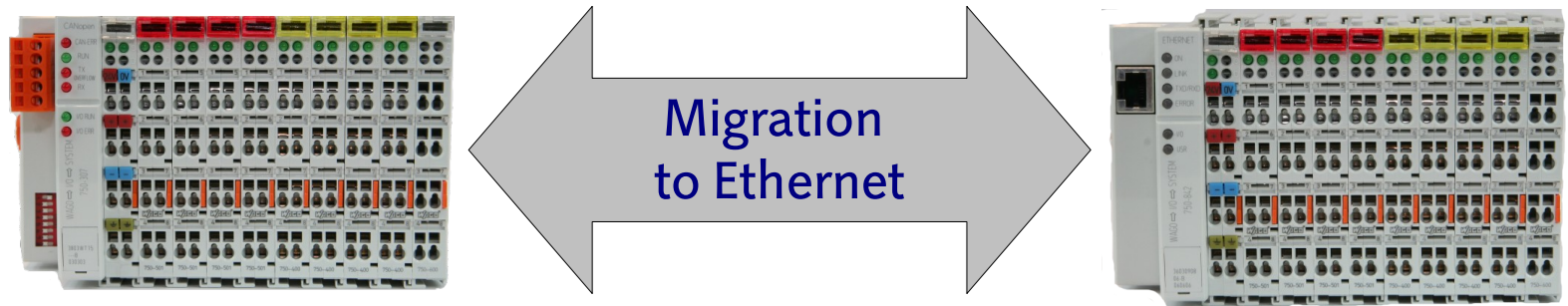
Design Goal 5: Vendor Independence

- Strategic Arguments:
 - Escape one-way vendor lock-ins by migrating to service & support business models
 - „Best Source“ strategy: optimal mix of open and closed source
 - Linux makes independence of a single processor manufacturer possible
 - Linux makes independence of operating system vendors possible



Design Goal 6: Bus Independence

- Unified Framework for All Fieldbus Technologies



Or:

- Several Fieldbuses in One System (i.e. local I/O + Fieldbus I/O)
- Box with local I/Os (GPIO, SoC integrated ADC/DAC)



Design Goal 7: Market Independence

- We must match to as many markets' demands as possible:
 - Automation (PLC: read inputs - calculate - write outputs - cycle)
 - Measurement (bus sends data packets, stream away; sync reqs)
 - Automotive (self defined protocols)
 - Embedded (local I/Os, no fieldbus at all)



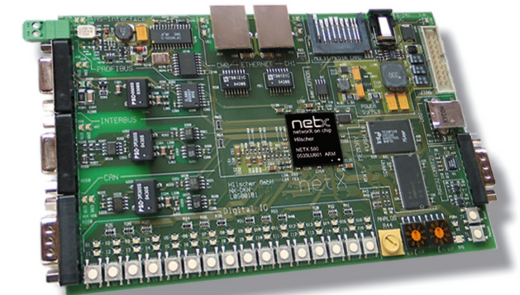
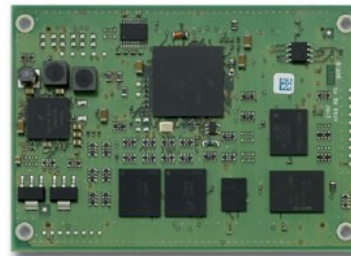
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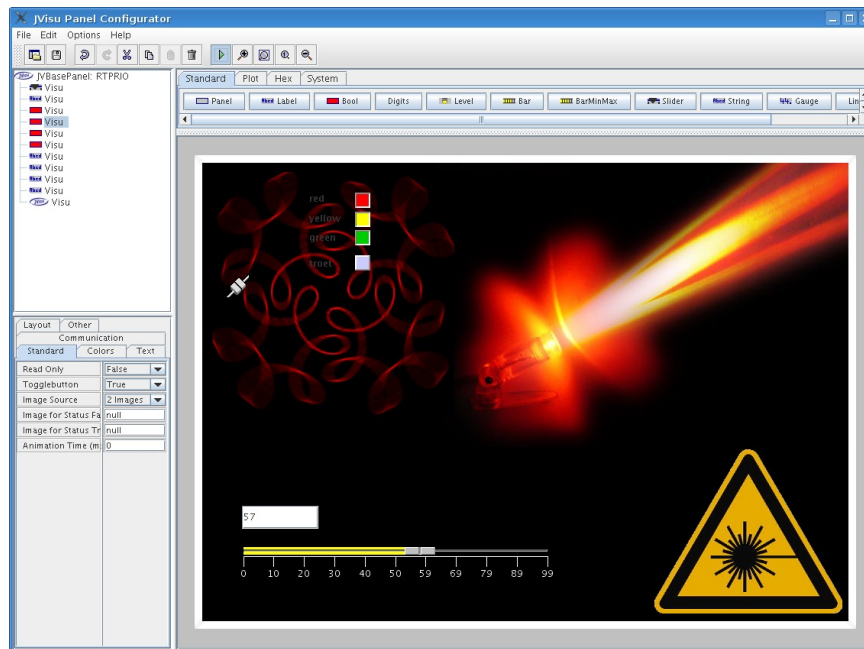
Current State of Prototype at Pengutronix

- Industrial I/O has some history in our projects (see next slide ...)
- We are „Embedded People“, not „Automation People“ (but some of our customers are)
- Our customers have Embedded Systems which need to interact with their environment



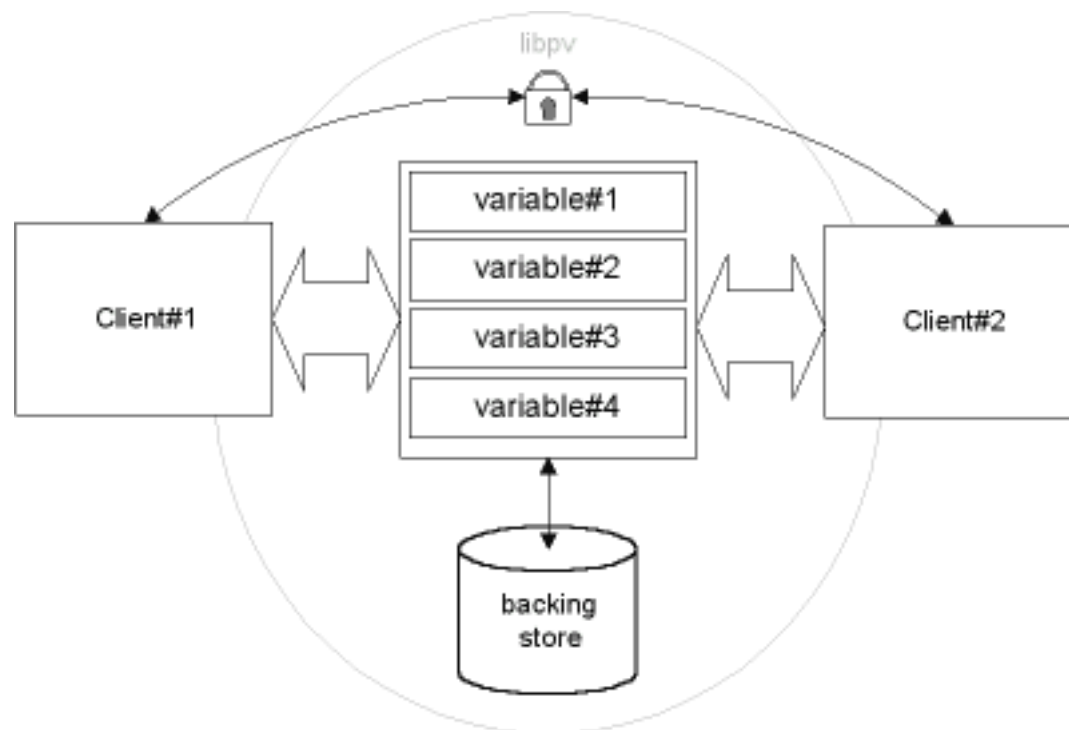
History @PTX: JVisu

- Process Data first came up in our project around 2003
- No fieldbus involved - first project was about ultrasound measurement
- First experiments with JVisu (Gleixner), but it was necessary to compile software on the backend side for process data integration



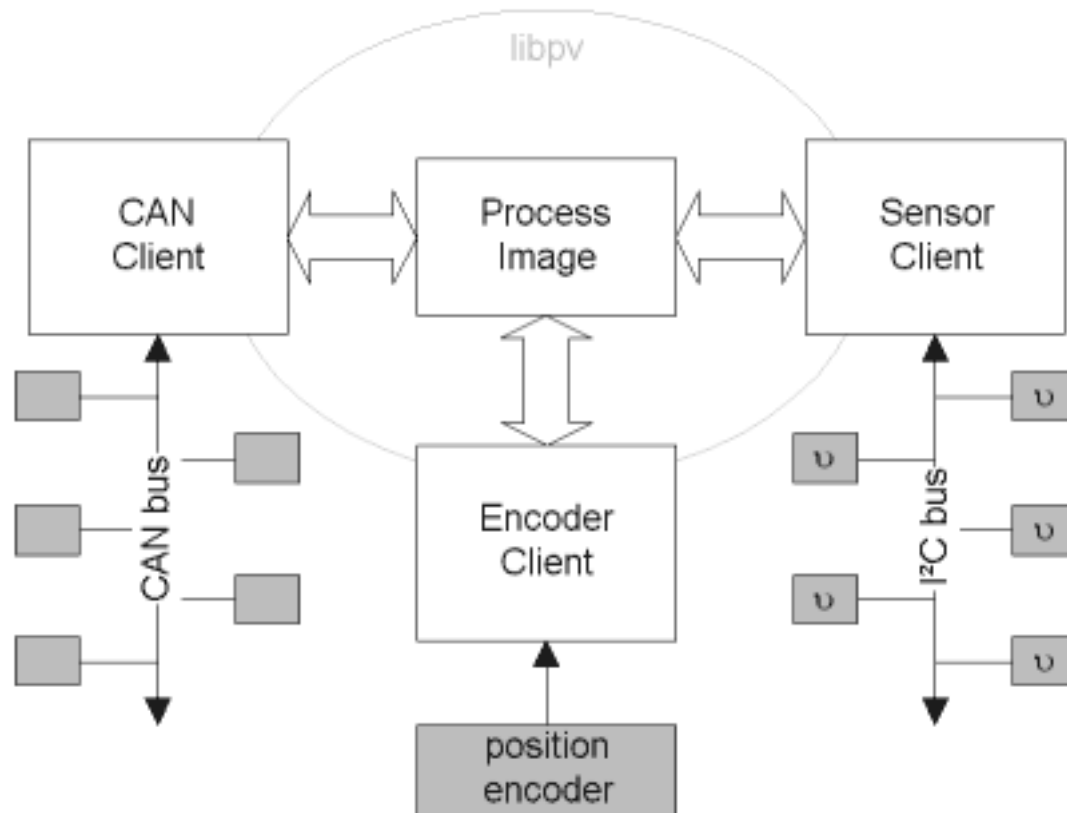
History @PTX: libpv-1.x

- During our projects, an Open Source library has grown up to access shared process data:



History @PTX: libpv-1.x

- libpv-1.x is used in more complex scenarios today (autonomous measurement robots, data loggers, heat pumps ...)



Problems with libpv-1.x

- We didn't care about the „where do the data come from“ question
- Centralized locking: race free, but slow
- No mapping layer, variables have to be referenced by name
- **We started searching for alternatives in 2006...**



Ptolemy II



Ptolemy II:

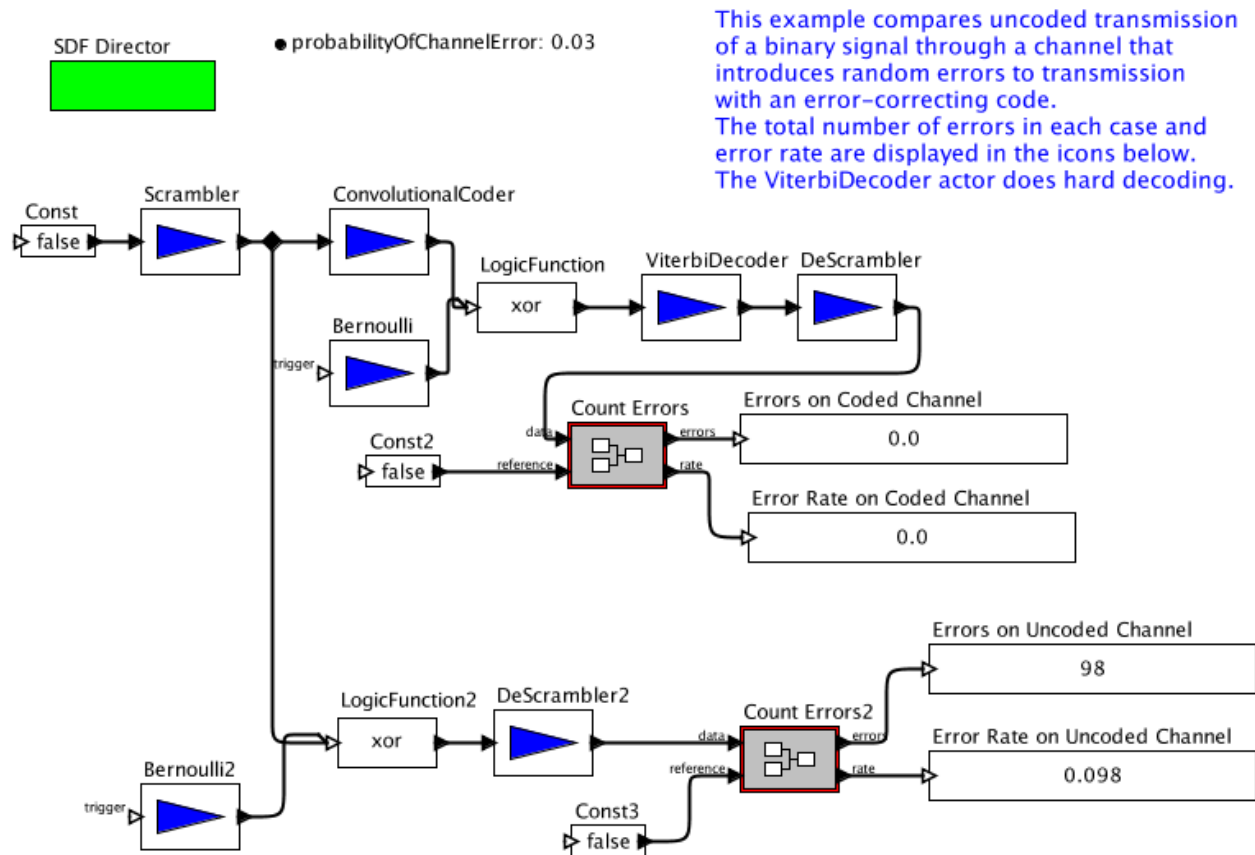
- „Heterogeneous Hierarchical Modeling“
- „The Ptolemy project studies modeling, simulation, and design of concurrent, real-time, embedded systems“

(<http://ptolemy.eecs.berkeley.edu>)

- Model Based Design:
 - Hierarchical Topology Models
 - Several „Domains of Execution“ - Semantics
- The Ptolemy II project has provided the theoretical background for almost all modern realtime control systems & modeling tools



Ptolemy II: „Actor Based Design“



This example compares uncoded transmission of a binary signal through a channel that introduces random errors to transmission with an error-correcting code. The total number of errors in each case and error rate are displayed in the icons below. The ViterbiDecoder actor does hard decoding.

Authors: Ye Zhou and Edward A. Lee

Go Pause Resume Stop



History @PTX: libpv-2.x

- Based on Ptolemy II, we started a prototype implementation
- Actor Based, no execution semantics in the actors
- Fully object oriented, but written in C
- The „network“ is the process image (with persistence)
- Connection == Mapping (actor code only knows it's local variables)
- Actor code is without semantics:
 - „PLC Director“ possible (static schedule: read/process/write)
 - Fully asynchronous event system possible
 - Lockless / Locking variants (independend of actor implementation)
 - Bridging to other modeling tools (LabVIEW, Matlab/Simulink)



Roadmap (Draft)

- Phase I:
 - Definition & Implementation of an Infrastructure Library
 - Merger of the 3S / Homag / Pengutronix Prototypes
 - Proof of Concept, based on selected & simple Use Cases
 - Milestone: Library Release 1.0 (for testing purposes)
- Phase II:
 - Call for Stack Implementation
 - Refactoring of the Infrastructure based on Feedback
- Phase III:
 - Graphical Configuration Tool for Mapping Layer



Thank you for listening! Questions ... ?

