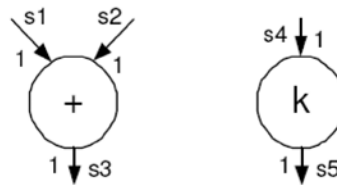


2. **A traffic-light controller.** Construct an Esterel program that controls a traffic light at the intersection of a busy highway and a farm road according to the following specifications:
- Normally, the highway light is green.
 - If a sensor detects a car on the farm road:
 - The highway light turns yellow then red.
 - The farm road light then turns green until there are no cars or after a long timeout.
 - Then, the farm road light turns yellow then red, and the highway light returns to green.
 - The program accepts as inputs the car sensor C , a short timeout signal S , and a long timeout signal L .
 - The program outputs are a timer start signal R , and the colors of the highway and farm road lights HG , HY , HR , FG , FY , and FR .
3. **An infinite impulse response filter.** We want use a dataflow model to express an infinite impulse response (IIR) system and represent the resulting model within the Tagged Signal Model framework. In particular, we use the two processes (actors) shown below, where $+$ is an adder and k multiplies the input signal by a constant.



Given the following denotational description of the filter

$$y_i = x_i + k \cdot y_{i-1},$$

where x is the input sequence of samples and y is the output sequence of samples,

- Describe the set of values V that you are going to use. Write a possible input signal x . Describe all possible behaviors of the processes $+$ and k .
 - Using interconnection processes, the two processes $+$ and k defined above and the operation of projection, build an IIR first-order filter with input x and output y .
 - Describe now the IIR first-order filter without using the projection operator. How many signals does the resulting process have? Describe the set of tags and all the signals of the process.
4. **Automobile engine control.** The following task model represents an example of an engine control application. WCET is the worst-case execution time of each task, periods and WCETs are in ms, and a lower priority index indicates a higher priority. The system consists of Periodic (P) and Sporadic (S) tasks. Sporadic tasks are executed at every revolution of the engine crankshaft (period T) or at the half revolution ($T/2$).
- Modern automobile engines are typically operated at around 2000–3000 revolutions-per-minute (rpm) (33–50 Hz) when cruising, with a minimum (idle) speed around 750–900 rpm (12.5–15 Hz), and an upper limit anywhere from 4500 to 10,000 rpm (75–166 Hz) for a road car or nearly 20,000 rpm for racing engines such as those in Formula 1 cars (currently limited to 18,000 rpm)¹.

¹ Wikipedia

Task	Period	Priority	WCET	Per/Spor
τ_1	T/2	1	0.2	S
τ_2	T	2	0.3	S
τ_3	4	3	0.04	P
τ_4	T	4	0.15	S
τ_5	T	5	0.1	S
τ_6	T	6	0.01	S
τ_7	1000	7	1.5	P
τ_8	1000	8	5	P
τ_9	50	9	1	P
τ_{10}	12	10	0.82	P
τ_{11}	100	11	9.85	P
τ_{12}	1000	12	150	P
τ_{13}	1000	13	100	P
τ_{14}	1000	14	110	P
τ_{15}	1000	15	120	P
τ_{16}	1000	16	131	P

- a) Write a program (or Excel script) for computing the worst-case response time of all tasks given the engine speed in rpm. Provide the results for 3000 rpm.
- b) Assume the WCETs of all sporadic tasks are doubled. What is the maximum rpm for which all tasks terminate before their next instance (i.e. they are schedulable, assuming that their deadline is $D=T$)? At 6000 rpm, what is the maximum WCET of τ_1 that still guarantees schedulability if all WCETs of the sporadic tasks (except τ_1) are doubled?