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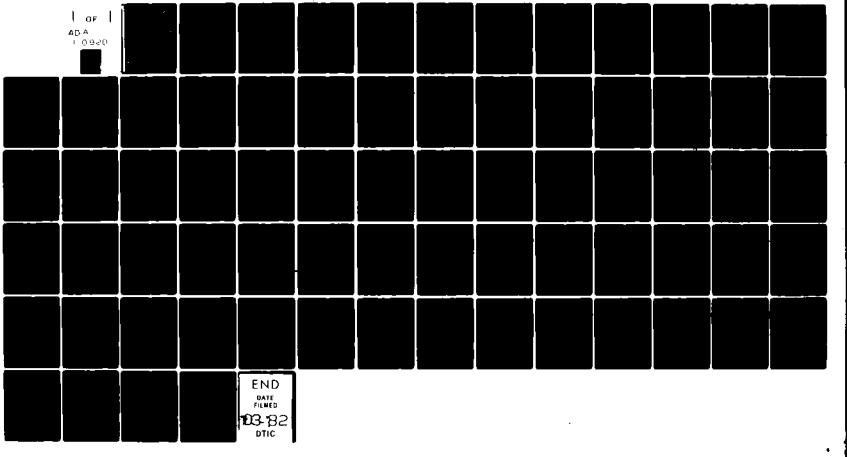
ADAM - AN ADA BASED LANGUAGE FOR MULTI-PROCESSING.(U)
JUL 81 D C LUCKHAM, H J LARSEN, D R STEVENSON MDA903-80-C-0159
UNCLASSIFIED STAN-CS-81-867 NL



July 1981

Report. No. STAN-CS-81-867

ADAM - An Ada based Language for Multi-Processing

by

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Research sponsored by

Defense Advanced Research Projects Agency

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ADAM
An Ada based Language for Multi-processing

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Abstract:

Adam is an experimental language derived from Ada. It was developed to facilitate study of issues in Ada implementation. The two primary objectives which motivated the development of Adam were: to program supervisory packages for multitask scheduling, and to formulate algorithms for compilation of Ada tasking.

Adam is a subset of the sequential program constructs of Ada combined with a set of parallel processing constructs which are lower level than Ada tasking. In addition, Adam places strong restrictions on sharing of global objects between processes. Import declarations and propagate declarations are included.

A compiler has been implemented in Maclisp on a DEC PDP-10. It produces assembly code for a PDP-10. It supports separate compilation, generics, exceptions, and parallel processes.

Algorithms translating Ada tasking into Adam parallel processing have been developed and implemented. An experimental compiler for most of the final Ada language design, including task types and task rendezvous constructs, based on the Adam compiler, is presently available on PDP-10's. This compiler uses a procedure call implementation of task rendezvous, but will be used to develop and study alternate implementations.

This research was supported by the Advanced Research Projects Agency of the Department of Defense under Contract MDA 903-80-C-0159.

CONTENTS

1. INTRODUCTION.

Adam is an experimental multiprocessing language based on Ada. It consists of a large subset of the non-tasking constructs of the Ada language [6], augmented by some simple primitive constructs for scheduling and parallelism. The sequential subset includes Ada packages, generic units, and exceptions; the omissions have mainly to do with numeric types.

Adam is intended to remain as close as possible to the final Ada language design while facilitating:
(i) construction of schedulers and runtime supervisors for multitask programs intended to run on either single or multiple processor hardware,
(ii) formulation of translation algorithms for Ada tasking, and for other high level parallel constructs, and
(iii) specification of parallel programs.

The additional constructs for parallelism are lower level than Ada tasking. These constructs include (1) units, called processes, which may execute in parallel, (2) constructs for communication among processes, specifically scheduled modules, which are packages that schedule access to their visible procedures, and (3) the predefined types *Locks*, *Process Names*, and *Condition Variables*. Some of these constructs are related to concepts in Concurrent Pascal [1] and Modula [13]. In every case, their compilation is well understood.

The reader might well ask why we feel it is necessary to deviate from Ada.

Goal (i) is motivated by the prediction that users of Ada tasking (or indeed any high level multiprocessing language) will need to modify "standard" runtime scheduling and supervisory packages to suit their own needs. (The reader who doubts this should consider, e.g., the design philosophy changes that took place between references [1] and [2]. Certainly, if one man can go through such changes, how widely might two men, an implementor and a user, disagree on the necessary language constructs for scheduling and their implementation? There are many other publications discussing this problem, e.g., [5] and [9].) It is therefore necessary to study the structure of runtime supervisors and to develop languages that facilitate their construction.

Why not use Ada? Most supervisory packages can be written in Ada provided the programmer obeys a very strict discipline in coding critical regions, and is content to simulate low level protection with high level constructs. Some simple additions to Ada might help. Adam attempts to alleviate some of the burdensome discipline by introducing the *scheduled module* and *reserve* constructs, and also provides the very low level scheduling objects, *Locks* and *Process Names*.

Additional problems arise in writing a supervisor in Ada if it is itself a parallel program (as might well be the case in a multiprocessor system, or indeed must be so if it uses interrupts). This requires coding a "subsupervisor" which in turn would provide scheduling for tasks in the main supervisor. But the Ada task rendezvous semantics ([6], 9.5) implies a very rigid scheduling algorithm. So tasks in the supervisor have to have a special

semantics (e.g., as interrupt entry procedures, [6], 13.5.1). In Adam parallelism is expressed by the process construct, the semantics of which do not imply any particular scheduling. Also, because process names are objects in Adam, a subsupervisor may be easily coded to schedule the processes in the main supervisor. (c.f., discussion of programming process scheduling in [5].)

Goal (ii) became a concern during the study of the preliminary Ada tasking design. It very soon became clear that the informal semantics of task rendezvous given in the preliminary Ada Rationale was by no means the only viable method of implementation. Indeed, translation algorithms for high level parallelism based on CSP [4] or similar concepts appear to require formulation and analysis. A promising approach is to implement these algorithms at a very high level, i.e., as translations from Ada to an existing high level parallel language. This should result in (a) precise definition of translation algorithms, (e.g., as input/output relations between Ada source and programs in the target language), and (b) the possibility of formalizing correctness of the tasking translation algorithms.

To do this, the semantics of parallelism in the target language has to be already well understood. Existing languages with clearly defined parallelism included Concurrent Pascal and Modula. So the parallelism in Adam is closely related to processes in these two languages.

Goal (iii) is concerned with the accurate description of parallel programs. How should a programmer document (by comments, formal specifications, or whatever) the intended behaviour of an Ada program, especially one containing packages or tasks? What descriptive facilities should the language provide, what restrictions should be enforced? This is an area of research that is relevant to such immediate questions as how to teach Ada and how to develop standards of documentation for Ada. (Some of these questions are being studied separately, e.g., in [8], [10] or [11].) There are also many possible longer term consequences; these might include techniques for formal verification and automatic generation of programs from their specifications.

One immediate reason for considering goal (iii) in the Adam design is to ensure that the translations of Ada tasking conform to a structure and discipline which makes them easy to specify and analyse. Since the translation algorithms are themselves defined in terms of input/output relations between Ada and Adam, this clearly affects the formulation and study of their correctness.

The crucial question is exactly how much weight to give goal (iii) in the design decisions, particularly when it appears to conflict with the goal of useability. In Adam we chose a form of parallel processes such that all interactions between processes can be deduced from their declarations and instances. To do this requires changing the visibility rules of Ada. In Ada these rules permit undeclared use of global objects, e.g. between tasks, in packages, or in exception handlers, which makes any attempt at precise documentation difficult. Their generality (or permissiveness) is a pitfall to the uninitiated and an area where good programming practice should be developed and taught. Here, Adam simply enforces restrictions that prevent processes from communicating (i.e., influencing each others computations) in arbitrary ways.

The discipline enforced by Adam includes: (a) restricting the visibility rules of Ada, (b)

limiting the interactions among processes and requiring that such interaction be explicitly declared in process specifications, (c) requiring import declarations to specify the use of global units in modules, and (d) requiring propagate declarations to specify the exceptions propagated by a unit.

The Adam restrictions can in fact be followed in Ada by disciplined programming; but the programmer will have to invent his own commentary to specify what he is doing, and his own methods of checking that he does it. On the issue of useability, the value of these restrictions in terms of whether they help or hinder current programming techniques remains to be studied.

We can report the following progress:

An Adam compiler has been running on DEC PDP-10 computers since June 1980. This compiler is implemented in Maclisp and generates PDP-10 assembly language. The compiler provides a small set of commands permitting users to manipulate library files for separate compilation. Runtime supervisor packages have been written in Adam, compiled, and now form part of our Ada runtime environment (an example is given in Appendix F). So far, these supervisors schedule processes on a single CPU; multiprocessor supervisors have not yet been constructed. A discussion of experience in transporting the compiler and environment is given in section 9, and a short description of the compiler facilities is in Appendix H.

Three algorithms for translating Ada task types and tasking constructs into the lower level Adam processing have been defined; an example is given in Appendix G, a description of the algorithms is given in [12], and a detailed report is forthcoming. One of these translation algorithms has been implemented in the compiler (as a subfunction of the static semantic checking). Many examples of Ada tasking programs have been compiled and run using separately compiled I/O and supervisor packages; the compiler has been used in teaching courses on Ada programming. Implementation of the other translation algorithms is in progress, and experiments comparing their runtime characteristics are planned.

1.1 Notation and Conventions.

This report is addressed to readers who already have some familiarity with the Ada reference manual [6]. The notation and formatting conventions of Ada are adopted with a few changes. This report describes those constructs of Adam that are not in Ada. Constructs common to both languages are only listed. Description of constructs is by an informal general format and examples; BNF syntax is given in Appendix A.

In both general formats and BNF the following notation is used.

Square brackets, [ ], indicate an optional construct. Curly brackets, { }, indicate zero or more repetitions of a construct.

Terminology. Modules and processes are called *units*. Nongeneric declarations are often called *actual*. Variables and actual modules are called *objects*. Elements declared in the

specification - or visible - part of a module are said to be *exported* by the module. Elements declared in the body of a module are said to be *encapsulated* by the module.

2. OVERVIEW OF Adam.

Adam consists of a large subset of the non-tasking constructs of the Ada language [6], augmented by some simple primitive constructs for scheduling and parallelism. This section presents a brief overview of the scheduling and parallel features together with the rationale for them. Syntax and examples are given in later sections.

2.1 Types for Scheduling.

The type differences between Ada and Adam are described in Section 3. The type facilities in Adam are not as rich as Ada, the general philosophy being not to include facilities that are not essential to studying the construction of multiprocess programs.

However, Adam includes some new types that are important in writing schedulers and process supervisors.

(i) *Locks*. Variables of type Lock provide a low-level facility for programming critical regions.

(ii) *Process Names*. Processnames provide a means of refering to the process (or thread of control) currently executing an instruction. This facility is important in programming scheduling of shared variables (or any interaction between processes), supervision of resources, and message-passing operations.

(iii) *Conditions*. Condition variables provide a fifo queue of process names.

2.2 Exceptions.

Exception handling and propagation is the same as Ada except that there is no direct propagation of exceptions between processes. In addition, all exceptions propagated from units must be declared in the specification part of the unit by means of propagate declarations (this can be practiced in Ada using the comment facility - see [8]).

Propagate declarations ensure that a calling unit will not receive any "surprise" errors. Their use permits compiletime checking (a) that the propagate declarations are consistent with the set of exceptions raised but not handled in the unit body, and (b) that exceptions are not propagated outside of the scope of their declaration, a somewhat ambiguous

situation permitted in Ada. The use of propagate declarations in a method of specifying programs with exceptions is described in [10].

2.3 Modules.

Modules in Adam correspond to packages in Ada. They provide facilities for encapsulation or abstraction. In addition Adam provides special modules:

(i) *Device modules*: Devices are intended for interfacing with hardware. Devices may contain machine coded operations and interrupts.

(ii) *Schedulers*: Schedulers are used to encapsulate scheduling and synchronization operations.

(iii) *Scheduled modules* (and devices): units for commmunication between processes. A scheduled module is simply a module containing a scheduler; its visible operations are associated with scheduler operations by scheduling declarations. Details are in Section 6.

Generic modules are declared and instantiated as in Ada.

2.4 Processes.

Processes are program units which may be initiated and run in parallel. The major difference from Ada tasks is that the constructs for communication between processes are essentially lower level than the Ada Rendezvous, and are more restricted.

Processes communicate by operating on scheduled modules. These modules are called communication channels and are declared by means of a **channels** declaration in the specification part of process declarations. The *Monitor* construct of Concurrent Pascal [1] and the *mailbox concept* of Gypsy [3] are examples of scheduled modules.

There are no means of communication among processes, other than channels; in particular, processes do not import values (see 2.5), may not reference external values, and do not have exports.

Execution of a process is begun by means of the **initiate** statement. Multiple initiations of a process are permitted; each initiation results in a new copy of the process. Initiation is the only operation on processes. A process terminates when it reaches the end of its body. A scope may be left only when all dependent processes have terminated (see 7.3).

Processes may be generic (but may have only type and in parameters). A generic process may be instantiated to an actual process.

The choice of communication constructs in Adam has several consequences and implications. First, the Ada rendezvous constructs, including entry procedures and **accept** and **select** statements, are omitted. Second, all communication among processes in a system can be determined from the specification parts of the process declarations. (In

Ada the bodies of consumer tasks must be examined to determine which service tasks they communicate with.) It is expected that this will be of some advantage in developing specifications for multiprocess systems. Third, the Adam programmer has to construct schedulers which determine interaction with the runtime supervisor in a multiprocess system. This may be burdensome for high level parallel processing applications, but should be close to the kind of programming required in constructing embedded computer systems. For high level multiprocessing it is expected that standard library communication modules with underlying supervision will be available in a separately compiled units. Fourth, Ada multitasking systems can be translated into Adam multiprocessing [12]. Different translation algorithms exist, each having advantages in runtime efficiency depending on the system to be translated, the facilities exported by the runtime supervisor, and the hardware.

2.5 Program Units, Visibility and Imports.

The visibility rules of Adam differ from those of Ada. The motivation for the difference is to ensure that all interactions between processes are deducible from the process declarations. There are two changes from Ada. First, the visibility of outside objects within a process, (i.e., the Adam version of a task) is restricted to be exactly the scheduled modules declared as communication channels of the process. No other outside objects may be mentioned within a process. Second, all outside objects mentioned inside a module must be declared as *imports* of the module. As a consequence of these two changes, all objects by means of which processes may be able to influence each others' computations can be enumerated by taking the transitive closure of the channels, their imports, imports of imports, and so on.

It remains to motivate the definition of *object*. The elements out of which Adam programs are constructed are declarations (of types and subtypes, variables, constants, subprograms, modules, and processes) and statements.

The elements that may be used to communicate are those that have accessible values or states that may vary during a computation, i.e., *variables* and *actual modules*. These we define to be *objects*.

Elements that are purely definitional in nature and do not have states are type, subtype and generic unit declarations. (*Note:* Adam visibility rules for generic units ensure that they are purely definitional.) These cannot be used to communicate when shared between processes, and their visibility is exactly as in Ada.

Processes have states but their states are not accessible by other units. The only action that can be performed on a process is initiation. The only manner in which an external unit may effect the state of an initiated process is to operate on a channel shared with the process. So the visibility of processes is also unrestricted.

Finally, the treatment of subprograms results from a compromise with useability considerations. A subprogram declaration is definitional unless there are global objects. We could require imports declarations on subprograms, in which case their visibility need not

be restricted. However, the introduction of modules into a programming language appears to change the role of subprograms from basic unit (as in Pascal) to small subunit of a module. The unencapsulated subprogram becomes a rarity. But in its new role as building block of modules, it is normal for a subprogram to import the local data of a module body. So imports declarations would then be part of most subprograms. But the imports declarations on subprograms internal to a module body are invisible outside the body and no longer contribute to the specification of outer systems of processes. So instead of requiring imports declarations on subprograms, we have restricted the visibility of subprograms (which is what seems to be happening naturally anyway).

We may now summarize the visibility rules of Adam for units.

Declarations that are always visible within a unit if they are visible at the point of declaration of that unit are:
(i) type declarations (including the constants of an enumeration type),
(ii) constants,
(iii) generic unit declarations,
(iv) processes,
(v) exception declarations.
(vi) predefined system modules (e.g., process supervisor - 2.6.1).

Declarations that are not visible unless explicitly imported into a unit:
(i) variable declarations,
(ii) nongeneric module declarations (including instantiations of generic modules).

Note: Thus, outside unencapsulated subprograms are never visible inside units.

Channels
The channels declaration of a process permits an actual scheduled module to be visible inside a process body. This is the only kind of external object that can be made visible inside a process.

Imports
Import declarations can appear only in nongeneric modules. Such declarations permit a list of outside objects to be visible inside a module specification or a module body. If a module declaration mentions external objects, those objects must be declared as imports.
In the case of an instantiation of a generic module, those generic parameters that are objects are imports. A separate imports declaration is omitted. (See Section 8.3.)
Note: A generic module may not have imports.

Notes:

1. In defining those objects whose importation must be declared, there are two possible approaches. Make every identifier an object, as in Euclid. This is very simple but leads to lengthy and irrelevant imports lists containing many "objects" that cannot possibly be used to communicate between parallel computations. Alternatively, define as objects exactly those elements that a process may be able to use to influence another's computation. This requires more complex visibility rules and forces the programmer to think, but leads to more relevant lists of imports. We take the second approach.

2. Construction of the transitive closure of channels lists and imports lists is easily automated and may prove useful in checking for some common errors.

3. Ada with clauses function as imports declarations between separately compiled units.

4. Essentially, the stricter visibility rules enforce a discipline in Adam that can be practiced in Ada.

2.6 Adam Runtime Environment

2.6.1 Process Supervisor.

One of the design goals of Adam is to provide a language for writing process scheduling, often called *supervision* here. Consequently, the semantics of the basic multiprocessing constructs of Adam do not assume calls on an underlying supervisor.

However, it is important to define a minimal expected interface of operations to be provided by most supervisors. This facilitates programming scheduling of processes (since scheduling often involves supervisor calls) and substitution of new *supervisors* into *multiprocess programs.*

The Adam compiler assumes the presence of a predefined *scheduled module*, *supervisor*, that implements a set of visible standard procedures for activating and suspending processes:

```
procedure SUSPEND;
procedure ACTIVATE (P : PROCESSNAME);
procedure SWITCH   (P : PROCESSNAME);
procedure START    (D : INIT_DATA);
procedure FINISH;
```

(The types PROCESSNAME and INIT_DATA (process initialization data) are discussed in Section 3.6.) The supervisor procedure START is called when an **initiate** statement is executed; it sets up the proper entries in the supervisor tables and activates the process. When a process has reached the end of its body, the *supervisor procedure* FINISH is called. A call to SUSPEND results in the suspension of the calling process and (normally) the running of another process in its place. The procedure ACTIVATE reactivates a process after suspension. The procedure SWITCH causes a context switch from the calling process to process P, i.e. suspends the calling process and activates P. Examples of these supervisor procedures are given in Appendix F.

We assume that any Adam *environment* contains a predefined supervisor (cf. Appendix F). Calls to START and FINISH are generated by the compiler; these procedures have to be present in every supervisor. The other standard supervisor procedures are most often called directly by scheduling *procedures in user programs.* However, when processes are

nested the compiler may also have to generate calls to SUSPEND and ACTIVATE, e.g. for synchronizing termination of outer and inner process.

The interface of standard supervisor procedures is all the compiler knows about supervision. It is thus easy to substitute a user-written supervisor that conforms with the interface for the standard one and have it used in the compilation of multiprocess programs. A pragma, SUPERVISOR, notifies the compiler to substitute calls to procedures of the same name from a new module for calls to the standard supervisor procedures. For instance, the pragma,

```
pragma SUPERVISOR (M);
```

where M is a module name, will result in the replacement of all calls to ACTIVATE by calls to M.ACTIVATE in the compilation, and similarly for the other expected procedures in the supervisor interface. (Obviously, the supervisor pragma has to appear in the program text before any calls to supervisor procedures are to be compiled.)

A user-supplied supervisor may be more sophisticated and implement additional procedures. For instance, the supervisor presented in Appendix F supports multiprocessing on a one-processor installation; a supervisor for programs intended to run on multiprocessor hardware must deal with additional problems like possible time races. On the other hand, in some applications, e.g., where processors are dedicated to single processes, the user-supplied supervisor may be trivial and provide only the START and FINISH procedures.

2.6.2 Input-Output.

The Adam runtime environment also includes a predefined module for input and output to files and terminals. The module provides an implementation of the standard package for I/O as defined in Section 14 of the Ada Reference Manual [6].

3. TYPES AND DECLARATIONS.

3.1 Object Declarations.

In Adam objects are declared as in Ada:

```
identifier-list : [constant] type [:= expression];
```

3.2 Types and Subtypes.

The type structure of Adam is derived from that of Ada with the following major differences and restrictions. Range constraints must be static. There is only one integer type. Float, and fixed types are not implemented. There are no type conversions.

For the syntax of type definitions refer to Appendix A.

3.3 Predefined Types.

The predefined type identifiers of Adam include the following subset of the predefined Ada language environment:

```
type INTEGER is implementation_defined;
type NATURAL is INTEGER range 1 .. INTEGER'LAST;
type BOOLEAN is (FALSE,TRUE);

type CHARACTER is (NUL,...,'a',...,'~');
type STRING    is array (NATURAL range <>) of CHARACTER;
```

3.4 Types for Scheduling.

In addition to the standard Ada types listed above, the following new types are implemented in Adam. Variables of these types are intended to facilitate the writing of scheduling and synchronization.

3.4.1 Locks.

Variables of type LOCK are used to implement primitive mutual exclusion. For purposes of description, locks may be thought of as being in one of two states, ON and OFF. There are three procedures that may be applied to locks :

TEST_SET (L: in out LOCK; B: out BOOLEAN)	- gains exclusive access to L; if L is OFF changes L to ON and sets B to TRUE, else sets B to FALSE.
SET (L : in out LOCK)	- busy waits until L is OFF, then gains exclusive access to L and changes the state to ON.
RESET (L : out LOCK)	- gains exclusive access to L, then changes state of L from ON to OFF.

These are the only operations that may be applied to locks.

Example 3-2: The ‹body› is protected by L from simultaneous execution.

```
L : LOCK;              -- variable L is declared to be a lock with initial state OFF.
begin
    SET(L);            -- busy wait to gain access to L and <body>.
    <body>
    RESET(L);          -- reset L so next user may gain access.
end;
```

3.4.2 Processnames.

Values of type PROCESSNAME are created by the initiate statement. These values are distinct. This is the only way that processnames can be created. The only permissable operations are assignment, equality, and selection using MYNAME which returns the name of the thread of control executing the call to MYNAME.

The type PROCESSNAME also includes a constant, null, which is not associated with any process.

3.4.3 Conditions.

Values of type CONDITION are a FIFO queue of processnames. Variables of type CONDITION are called condition variables.

The operations on condition variables are as follows. All of these operations are indivisible (e.g., a possible implementation of indivisibility is to protect operations on each variable of type condition by disabling interrupts and locking the operations).

Selectors and constructors:

```
function EMPTY (CV : CONDITION) return BOOLEAN
    -- returns TRUE if the queue of CV is empty; initial value is TRUE.

procedure INSERT (CV : in out CONDITION; P : PROCESSNAME)
    -- inserts P on the queue of CV;
    -- raises CONDITION_QUEUE_FULL exception if the queue of CV is full.

procedure REMOVE (CV : in out CONDITION; P : out PROCESSNAME)
    -- removes the first processname from the queue of CV and returns it as the
    -- value of P;
    -- raises CONDITION_QUEUE_EMPTY exception if the queue of CV is empty.
```

Example 3-3: Two synchronization operations coded using condition variables.

The following two procedures are typical operations used to implement schedulers for modules in a multiprocessor environment. They include both decisions to queue (or dequeue) processes and calls to the process supervisor. They are, in turn, protected by locks.

```
procedure WAITFOR (CV : in out CONDITION; CVL : in out LOCK) is
                -- tests some condition followed by a queuing operation and a
                -- supervisor call if the test is FALSE.
                -- CVL should be a unique lock protecting all operations on CV.
begin
   SET (CVL);
   if <some-condition> then
      INSERT (CV, MYNAME());
      RESET (CVL);
      SUSPEND;
   else
      RESET (CVL);
   end if;
end;

procedure SIGNAL (CV : in out CONDITION; CVL : in out LOCK) is
                -- removes the first processname from the queue CV (if nonempty) and
                -- activates it. CVL is a unique lock protecting all operations on CV.
   P : PROCESSNAME;
begin
   SET (CVL);
   if  <some-condition> and not EMPTY (CV) then
      REMOVE (CV, P);
      RESET (CVL);
      ACTIVATE (P);
   else
      RESET (CVL);
   end if;
end;
```

Another example of use of condition variables is given in Section 7.6, Example 7-4.

3.5 Machine Dependent Types.

The initiate statement interfaces with the runtime supervisor by passing a record of information about the initiated process. The structure of this record is implementation dependent. For our PDP-10 implementation it has the form:

```
type INIT_DATA is
    record
        PNAME     : PROCESSNAME;
        CODESTART : ADDRESS;
        STKSTART  : ADDRESS;
        PRIORITY  : PRIORITY;
    end record;
```

4. STATEMENTS.

The statement syntax of Adam is taken from that of Ada with some minor differences and additions. All of the sequential statements of Ada are provided.

Since the multitasking in Adam differs from that of Ada there are no delay, abort, select, accept, or terminate statements in Adam.

4.1 Reserve Statement.

The **reserve** statement is used to reserve a scheduled module. It allows a process to perform a sequence of operations on the module without any intervening operations by another process on the same module. It is intended for use when the number of operations is determinable only at runtime.

The form of a **reserve** statement is:

```
reserve scheduled-module-name do
    statement-list
end reserve;
```

Example 4-1: Printing a file of arbitrary length.

```
reserve LPT_DRIVER do
    loop
        ...                              -- get next line of file
        LPT_DRIVER.PRINT (...);          -- print it on the line printer
    end loop;
end reserve;
```

The compilation of **reserve** statements using the REQUEST and RELEASE operations of the module's scheduler is described in Section 6.3.2.

4.2 Initiate Statement.

The **initiate** statement is used to cause a process to begin its execution. The general form of the statement is:

```
initiate list-of-process-names;
```

A process may be initiated any number of times, with each initiation causing a new copy of the process to begin execution.

5. SUBPROGRAMS.

A subprogram is either a procedure or function as in Ada. Adam includes the generic facility of Ada.

The main differences from Ada are required declarations in the specification part of a subprogram declaration. The new required declarations specify exceptions, and scheduling.

(1) If the subprogram is part of a scheduled module, it may be linked to procedures of a scheduler by a scheduling declaration - see Section 6.3.1.

(2) All exceptions that may be propagated by the subprogram must be named in a propagate declaration. Such a declaration must be within the scope of the exception.

The form for a subprogram declaration is:

```
subprogram-declaration ::=
      subprogram-header;
    | generic-subprogram-declaration        -- as in Ada
    | generic-subprogram-instantiation      -- as in Ada

subprogram-header ::=
      function designator [formal-part] return subtype-indication
    | procedure identifier [formal-part]
    | interrupt identifier called from number
```

The form for a subprogram body is:

```
subprogram-body ::=
    subprogram-header is
        specification-part
        declarative-part
    begin
        statement-list
    [exception
        {exception-handler}]
    end [designator];


specification-part ::=
    [propagate-declaration]
    [scheduling (scheduling-item, scheduling-item);]
```

where:

propagate declaration - propagate list of exception names;
scheduling-item is either a procedure call or else null; (see section 6.3.1).

5.1 Propagate Declarations.

Propagate declarations specify which of the declared exceptions may be raised and propagated by a subprogram. The others clause may be used in one propagate declaration to refer to all unnamed exceptions that may be propagated.

Propagate declarations may be annotated, and thus may be used to specify not only the exceptions that may be propagated, but also the conditions under which propagation of exceptions will occur.

Example 5-1: Subprogram specifications with propagate declarations with annotation.

In the procedure SEARCH, when propagation of the exception, NOT_FOUND, occurs, it is specified that the key, X, is not in array A. This illustrates a use of exceptions to break the normal output specification of a procedure into cases.

```
type NARRAY is array (1 .. N) of INTEGER;
. . . . .
NOT_FOUND: exception;

procedure SEARCH (N, X : INTEGER; A : NARRAY; I : out INTEGER) is
   propagate NOT_FOUND; -- 1 <= J <= N  =>  X /= A(J);
         -- annotation states a property of parameter values when propagation occurs.
   -- exit 1 <= I <= N and X = A(I);
         -- exit comment specifies parameter values on normal exit from Search.
begin
         . . . .
   raise NOT_FOUND;
         . . . .
end;
```

5.2 Interrupt Procedures.

Interrupts are special procedures that are called directly from the hardware. Interrupt procedures can occur only in device modules (cf. Section 6.2). Interrupt procedures may not be generic and may not have parameters; they may have global variables.

6. MODULES.

Module declarations in Adam are the same as for Ada packages except:
(i) Global objects in generic module declarations are not permitted.
(ii) Declaration of global objects imported into nongeneric modules is required.
(iii) Declaration of exceptions that may be propagated is required.

(iv) Scheduling declarations are used in a scheduled module body to associate visible operations with scheduling operations.

(v) Different kinds of modules can be defined:

module	- basic module declaration,
device	- bodies of devices may contain machine code and interrupts,
scheduler	- provides procedures for scheduling,
scheduled module	- a module containing a scheduler; this is the program unit for communication between processes.

Separate compilation of module specification and body is supported. The general format for module declarations is:

```
[generic generic parameter list]
module M is
     [imports (imports list);]
     exception declarations          -- declaration of those exceptions propagated
                                     -- by the procedures and functions if they
                                     -- are not already declared;
     type declarations               -- including private types,
     procedure specifications        -- the visible procedures and functions are
     function specifications         -- called the module operations,
     module specifications

[private . . .]                      -- private part
end [M];
     . . .
module body M is
     [imports (imports list);]       -- encapsulated imports, see Section 8
     type declarations
     variable declarations
     other declarations              -- must include the bodies of all operations
                                     -- and modules specified in the visible part
end [M];
```

Note:

An imports list is a list of variables and actual modules. Each import must be visible at the point of declaration. It is then imported or made visible inside the declaration. Each imported variable has a mode in, out, or in out), and each imported module has the nature module). See Section 8.

Example 6-1: Adam version of the visible part of the ON_STACKS example from the Ada Reference Manual [6], p. 12-5. Some annotations are included.

```
generic
   SIZE : INTEGER;
   type ELEM is private;
 --entry SIZE > 0;                   -- assertion on generic parameters.
module ON_STACKS is
```

```
    type STACK is private;
    OVERFLOW, UNDERFLOW : exception; -- visibility of exceptions is the same as
                                     -- the module declaration.
    procedure PUSH (S: in out STACK; E: in  ELEM);
       propagate OVERFLOW; -- full(S);

    procedure POP  (S: in out STACK; E: out ELEM);
       propagate UNDERFLOW; -- empty(S);

    -- comments specifying visible operations PUSH and POP, and full and empty.

private
     type STACK is
       . . .
end ON_STACKS;
```

Note: The formal annotation of modules is currently a topic of research. A discussion of annotation of Ada packages can be found in [11].

6.1 Schedulers.

Schedulers are intended to encapsulate both the synchronization and protection for scheduled modules shared between processes. Schedulers implement (a) the scheduling procedures for entry to, and exit from module operations, (b) procedures REQUEST and RELEASE (for the **reserve** statement), and (c) procedures for synchronization between module operations. Scheduler procedure declarations follow the normal format for procedures (Section 5), except they may not contain scheduling declarations; REQUEST and RELEASE do not have parameters.

A nongeneric declaration of a scheduler must be in the body of a scheduled module. Conversely, a scheduled module must contain exactly one scheduler. Generic schedulers may appear in any declarative part. An instance of a scheduler may be declared only in the body of a scheduled module.

Example 6-2: A common format for scheduler declarations within scheduled modules is:

```
scheduled module M is
    . . . .                          -- specification part of M,
end M;

scheduled module body M is
    . . . . .                        -- local variables of M,
  scheduler SCHED is                 -- scheduler for M.
      imports(list of local variables of M);
      procedure REQUEST;             -- REQUEST and RELEASE are procedures
      procedure RELEASE;             -- used for scheduling reserve (Sec. 6.3.2),
      procedure ENTER ( . . . );     -- ENTER, LEAVE, DELAY, ... are other
      procedure LEAVE ( . . . );     -- scheduling procedures exported by SCHED
      procedure DELAY ( . . . );
  end SCHED;
```

```
. . . . .                          -- body of M with scheduling declarations
                                   -- (see Section 6.3.1) for each of the visible
                                   -- operations of M.
                                   -- body of SCHED.
end M;
```

6.2 Devices.

Device modules are the only program units that may contain machine code and interrupt procedures. They are intended to encapsulate the machine-dependent parts of a system. Devices may be generic if they do not contain interrupts.

6.2.1 Machine code.

Machine code is inserted into a program through the use of an aggregate as in Ada. (An example is given in Appendix F.) Unlike Ada, both machine code and Adam statements may appear in the same subprogram.

6.2.2 Interrupts.

Interrupt procedures are declared by:

```
interrupt P called from number is
   . . .                           -- procedure body as in 5.3
```

Notes:
1. Interrupt procedures may not be generic.
2. Interrupts may not have parameters, but may reference global variables. See example 6-5, Section 6.5.
3. A separately compiled device which has an interrupt procedure in its body must contain a subprogram header for that procedure in its private part.

Remark: Specifications for interrupt procedures are certainly inadequate. For example, it would be useful to be able to name a procedure that must be called before the interrupt can be enabled and which will resume whenever the interrupt is disabled.

6.3 Scheduled Modules.

A scheduled module is a module whose visible operations are scheduled by a scheduler local to its body. Scheduling of operations is declared by scheduling declarations. If a scheduled module is named in a reserve statment, then the scheduler for the module must provide REQUEST and RELEASE procedures.

6.3.1 Scheduling Declarations.

Let p be an operation of a scheduled module. A scheduling declaration for p has the format,

```
procedure P (parameter list) is
   . . .
   [scheduling (scheduling list);]
   . . .
```

where
scheduling list has the form: p1(L1), p2(L2)
and each pi is either a visible procedure of the local scheduler or else is null.
p1 - scheduling before entry to p,
p2 - scheduling on exit from p,
Li - parameter lists.

The effect of a scheduling declaration for a procedure P in a module with a scheduler S is that the body of P, is compiled as

```
S.p1(L1);              -- omitted if p1(L1) is null.
<body of P>
S.p2(L2);              -- omitted if p2(L2) is null.
```

Notes:
1. Within the body of a scheduled module with scheduler, S, calls to a scheduler procedure, p, are stated in the usual format, S.p, unless they are in the scope of a "use S" clause.
2. Scheduling declarations permit specification of *"before" and "after" scheduling. The* set of scheduling declarations specifies explicitly the scheduling of entrance to and exit from the boundary of the scheduled module.
3. Internal synchronization between module operations cannot be declared by this mechanism. For this, one must still use calls to scheduler procedures.

6.3.2 Reserve Statements.

Let M be a scheduled module with scheduler S.

```
reserve M do statement-list end reserve;
```

is compiled as

```
S.REQUEST;
statement-list
S.RELEASE;
```

If REQUEST and RELEASE are not supplied by the scheduler, attempts to compile reserve statements for the module will result in an error message.

6.3.3 Exceptions in Scheduled Modules.

If an exception which is unhandled reaches the outer level of a scheduled operation the operation's exit procedure is run before the exception is propagated out of the operation.

6.4 Instantiation.

Instances of generic modules are declared as in Ada:

```
module M is new N(L);
```

where N is a generic module and L is a list of actual generic parameters. Similarly for scheduler and scheduled module. Each new instance of a generic scheduled module or device has a new instance of the local scheduler.

6.5 Examples.

Example 6-3: Buffer module. A buffer is a typical example of a scheduled module. We give first a very simple version; the example is presented in two stages, first the top level structure showing the scheduling, then the implementation of the scheduler.

```
generic
   BOUND : INTEGER;
scheduler BUFFER_SCHED is
   procedure FOO_1;                  -- first scheduler operation,
   procedure FOO_2;                  -- second scheduler operation,
   procedure FOO_3;                  -- third scheduler operation.
end BUFFER_SCHED;

generic
   type ITEM is private;
   SIZE : INTEGER;
scheduled module BUFFER is
   procedure READ  (X: out ITEM);
   procedure WRITE (Y: in  ITEM);
end BUFFER;

scheduled module body BUFFER is
      . . . .                        -- declaration of local variables of BUFFER,
   scheduler SCHED is new BUFFER_SCHED (SIZE); -- declaration of scheduler,

   procedure READ (X : out ITEM) is
      scheduling (FOO_1, FOO_3);     -- scheduling for READ - see below,
      . . . .

   procedure WRITE (Y : in ITEM) is
      scheduling(FOO_2, FOO_3);      -- scheduling for WRITE - see below,
      . . . . .
```

```
end BUFFER;

scheduled module  BIG_BUFFER is new BUFFER (CHARACTER, 120);
                                        -- declaration of an instance of BUFFER.
```

The declaration of BIG_BUFFER will result in the declaration of a new scheduler that is an instance of BUFFER_SCHED. The scheduler for BIG_BUFFER is not named, but conceptually its declaration is:

```
    scheduler BIG_BUFFER_SCHED is new BUFFER_SCHED (120);
```

The effect of the scheduling declarations in BUFFER is that calls to BIG_BUFFER will be compiled as,

```
BIG_BUFFER_SCHED.FOO_1;          BIG_BUFFER_SCHED.FOO_2;
BIG_BUFFER.READ (X);             BIG_BUFFER.WRITE (Y);
BIG_BUFFER_SCHED.FOO_3;          BIG_BUFFER_SCHED.FOO_3;
```

Example 6-4: Implementation of BUFFER_SCHED.

```
scheduler body BUFFER_SCHED is

   PROTECT : LOCK;                  -- local variables of scheduler
   COUNT   : INTEGER range 0 .. BOUND := 0;
   INUSE   : BOOLEAN := FALSE;
   READQ   : CONDITION;             -- queue for readers
   WRITEQ  : CONDITION;             -- queue for writers

   procedure FOO_1 is               -- schedules entry to READ,
   begin
         SET (PROTECT);             -- wait to gain exclusive access,
         if COUNT = 0 or INUSE then -- BUFFER is empty or in use,
              INSERT (READQ, MYNAME());  -- place reader on queue,
              RESET (PROTECT);      -- release BUFFER_SCHED (note 2 below),
              SUSPEND;              -- supervisor call to suspend caller,
         else
              INUSE := TRUE;        -- prepare to enter free BUFFER,
         end if;
         COUNT := COUNT - 1;        -- reduce no. of items in BUFFER,
         RESET (PROTECT);           -- release BUFFER_SCHED.
   end FOO_1;

   procedure FOO_2 is               -- schedules entry to WRITE,
   begin
```

```
        SET (PROTECT);              -- wait to gain exclusive access,
        if COUNT = BOUND or INUSE then -- BUFFER is full or in use,
           INSERT (WRITEQ, MYNAME()); -- place writer on queue,
           RESET (PROTECT);         -- release BUFFER_SCHED (see note 2 below)
           SUSPEND;                 -- supervisor call to suspend caller,
        else
           INUSE := TRUE;           -- prepare to enter free BUFFER,
        end if;
        COUNT := COUNT + 1;         -- increase no. of items in BUFFER,
        RESET (PROTECT);            -- release BUFFER_SCHED.
    end FOO_2;

    procedure FOO_3 is              -- schedules exit from READ and WRITE,
       P : PROCESSNAME;
    begin
        SET (PROTECT);              -- wait to gain exclusive access,
        if COUNT > 0 and not EMPTY (READQ) then
           REMOVE (READQ, P);
           ACTIVATE (P);            -- supervisor call to activate a reader
        elseif COUNT < BOUND and not EMPTY (WRITEQ) then
           REMOVE (WRITEQ, P);
           ACTIVATE (P);            -- supervisor call to activate a writer
        else
           INUSE := FALSE;          -- else BUFFER is free
           RESET (PROTECT);
        end if;
    end FOO_3;

begin
   RESET (PROTECT);
end BUFFER_SCHED;
```

Notes:

1. All procedures of BUFFER_SCHED are protected by the same lock, PROTECT. Only one thread of control, P say, can have access to BUFFER_SCHED at any time. Processes busy wait to enter BUFFER_SCHED. The implementation of waiting in SET is not required to be fair, and this could cause a process to be starved.
2. Each BUFFER_SCHED procedure calls the supervisor. PROTECT is reset before calls to SUSPEND. In a multiprocessor system this means an ACTIVATE (P) might be executed (by another thread of control) in FOO_3 before SUSPEND is executed by p itself in FOO_1 or FOO_2. This will not cause blocking only if the supervisor can remember an ACTIVATE that arrives ahead of the matching SUSPEND.

An alternative design of supervisor calls is to permit locks as parameters of ACTIVATE and SUSPEND, and require these procedures to reset the lock.

3. Operations of the scheduler, BUFFER_SCHED, and BUFFER may execute simultaneously. However the very simple scheduling in BUFFER_SCHED makes BUFFER a critical region also. It is a simple exercise to change BUFFER_SCHED so that Read and Write operations may execute simultaneously in BUFFER.

Example 6-5: Simple device module using interrupts.

The following example demonstrates the use of interrupts and scheduling in device modules. The device module Line_Out is to be used for sending a line of output to a device, such as a line printer, which is initiated by receipt of the first character of the line and which will generate an interrupt when it is ready to accept each succeeding character. A user of the device does a call to the procedure Send. If the device is already in use, the caller will be put on a wait queue and suspended. The body of the Send procedure performs the initial output to the device and then suspends the calling process via a call to the scheduler procedure Await. The interrupt procedure within the device module performs the output of the remaining characters in the line and activates the calling process upon completion of the IO. Upon leaving the module, the awakened caller checks if other processes have been suspended awaiting access to the device and activates the first process on the wait queue.

```
scheduled device LINE_OUT is
    LINE_LENGTH : constant INTEGER := 80;

    subtype CHAR_POSITION is INTEGER range 1 .. LINE_LENGTH;
    type    LINE is array ( 1 .. LINE_LENGTH ) of CHARACTER;
    type    RESULT is ( OK, ERR );

    procedure SEND (L : in LINE; R : out RESULT);

end;

scheduled device body LINE_OUT is

    subtype IO_RESULT is INTEGER range 1 .. 2;-- 1 for error,2 for ok

    LINE_STORE    : LINE;
    CURRENT_CHAR  : CHAR_POSITION := 1;
    DEVICE_STATUS : IO_RESULT;

    scheduler LINE_SCHED is
        procedure ENTER;
        procedure AWAIT;
        procedure LEAVE;
        procedure LEAVE_INTERRUPT;
    end LINE_SCHED;


    procedure INITIALIZE_DEVICE (C: in CHARACTER; IR :out IO_RESULT ) is
        machine code  . . .        -- machine code procedure to send a
                                   -- character to the device; see appendix F.
    end INITIALIZE_DEVICE;

    procedure TERMINATE_DEVICE  is
        machine code  . . . -- machine code to tell device to stop interrupting
    end TERMINATE_DEVICE;

    procedure SEND (L : in LINE; R : out RESULT) is
        scheduling (ENTER, LEAVE);
    begin
        LINE_STORE := L;
        CURRENT_CHAR := 1;
```

```
    INITIALIZE_DEVICE (LINE_STORE(CURRENT_CHAR), DEVICE_STATUS);
    if DEVICE_STATUS = 1 then
        R := ERR;
    else
        LINE_SCHED.AWAIT;
        if DEVICE_STATUS = 1 then
            R := ERR;
        else
            R := OK;
        end if;
    end if;
end SEND;

interrupt OUT_CHAR called from 0016 is
    scheduling (null, LEAVE_INTERRUPT);
begin
    CURRENT_CHAR := CURRENT_CHAR + 1;
    INITIALIZE_DEVICE (LINE_STORE(CURRENT_CHAR), DEVICE_STATUS);
    if DEVICE_STATUS = 1 or CURRENT_CHAR = LINE_LENGTH then
        TERMINATE_DEVICE;
    end if;
end OUT_CHAR;

--the scheduler procedures insure mutual exclusion on the send procedure
--and provide synchronization between SEND and the interrupt

scheduler body LINE_SCHED is
    imports (CURRENT_CHAR, DEVICE_STATUS : in );


    SCHED_LOCK : LOCK;
    BUSY       : BOOLEAN := FALSE;
    WAIT_QUEUE : CONDITION;
    USER       : PROCESSNAME;

    procedure ENTER is
    begin
        SET (SCHED_LOCK);
        if BUSY then
            INSERT (WAIT_QUEUE, MYNAME());
            RESET (SCHED_LOCK);
            SUSPEND;
        else
            BUSY := TRUE;
            RESET (SCHED_LOCK);
        end if;
    end ENTER;

    procedure AWAIT is
    begin
        SET (SCHED_LOCK);
        USER := MYNAME();
        SUSPEND;
        RESET (SCHED_LOCK);
    end AWAIT;
```

```
            procedure LEAVE  is
                NEXT : PROCESSNAME;
            begin
                SET (SCHED_LOCK);
                if not EMPTY (WAIT_QUEUE) then
                    REMOVE (WAIT_QUEUE, NEXT);
                    ACTIVATE (NEXT);
                else
                    BUSY := FALSE;
                end if;
                RESET (SCHED_LOCK);
            end LEAVE;

            procedure LEAVE_INTERRUPT is
            begin
                SET (SCHED_LOCK);
                if DEVICE_STATUS = 1 or CURRENT_CHAR = LINE_LENGTH then
                    ACTIVATE (USER);
                end if;
                RESET (SCHED_LOCK);
            end LEAVE_INTERRUPT;

        begin
            RESET (SCHED_LOCK);
        end LINE_SCHED;

    end LINE_OUT;
```

7. PROCESSES.

Processes are program units which may be initiated and run in parallel. Processes communicate by operating on scheduled modules. These modules are called communication channels and are declared in the specification part of process declarations. Channels are the only means of communication among processes. Processes may not import objects and objects declared within processes may not be imported by other units. Processes may be generic (but may have only type and in parameters). Channel parameters (scheduled modules) may also be generic.

The general format for a process declaration is:

```
[generic
   generic process parameter list]
process p [is
   channels channels list;
end [p]];
```

A process body has the form:

```
process body p is
        declarative part
begin
        statement-list
end [p];
```

where:
(a) generic process parameter list has the form,
    list of generic type and in parameters; channels generic_channels_list;
(b) generic_channels_list is a list of declarations of the form,

```
m is n(L) [restricted (operations list)]
```

- where n is a generic scheduled module, L is a list each member of which is in the preceding list of generic type and in parameters. n(L) must be an instance of n obtained by replacing the generic formal parameters of n by generic formal type and in parameters of process p. Any actual module substituted for m in an instance of p must be an instance of n with the same parameters as those substituted for corresponding members of L. (See Examples 7-2, 7-3, and Section 7.4.)

(c) channels list has members of the form

```
m[restricted (operations list)]
```

- where m is an actual scheduled module.
(d) operations list - a list of visible operations of a module.

Notes:
1. Optional clauses of the form, restricted (operations_list), in a channels declaration restrict the operations on the channel which can be performed by the process.
2. Processes are an encapsulation unit; they have some important differences from modules:
   (a) channels declarations provide the only form of importation.
   (b) Processes cannot propagate exceptions.
   (c) generic parameters can only be type or in parameters.
3. A generic process declaration may have actual channel parameters (perhaps in addition to generic channel parameters).

7.1 Channels Declarations and Use Clauses.

The channels declaration may also include a use clause containing some of the names of the scheduled modules in the channels list. This avoids duplication of channels and use declarations.

Examples.

Example 7-1: Nongeneric Process.

```
type BLOCK is . . .
type LINE  is . . .
scheduled device LPT is
     procedure WRITE_LINE (L : LINE);
        . . .
end LPT;

scheduled module DISKFILE is
     procedure READ_BLOCK (B : out BLOCK);
        . . .
end DISKFILE;

process FILE_PRINT is
     channels use LPT, DISKFILE;
end FILE_PRINT;


process body FILE_PRINT is
     type LINE_STORE is array(1 .. C) of LINE;
     procedure BLOCK_TO_LINES (B : BLOCK; A : out LINE_STORE) is
           . . .                          -- transfers a block to a line store.
     end BLOCK_TO_LINES;

     BUF :  LINE_STORE;
     BLOC : BLOCK;

begin
     READ_BLOCK (BLOC);                   -- read into BLOC from DISKFILE.
     BLOCK_TO_LINES (BLOC, BUF);          -- transfer BLOC to BUF.
     reserve LPT do                       -- reserve LPT
         for i in 1 .. C loop
               WRITE_LINE (BUF(i));       -- write onto LPT
         end loop;
     end reserve;
end FILE_PRINT;
```

Example 7-2: Generic process with generic channels.

```
generic
     type T is private;
     SIZE : INTEGER;
scheduled module BUFFER is
     procedure READ  (X: out T);
     procedure WRITE (Y: in  T);
        . . .
end BUFFER;

generic
     type ITEM is private;
```

```
      LENGTH : INTEGER;
      channels A is BUFFER (ITEM, LENGTH) restricted (READ),
                B is BUFFER (ITEM, LENGTH) restricted (WRITE);
process TRANSFER;
                                    -- instances of TRANSFER must have channels
                                    -- that are instances of BUFFER with the same
                                    -- pair of actual generic parameters.
process body TRANSFER is
    C : ITEM;
begin
   loop
      A.READ  (C);
      B.WRITE (C);
   end loop;
end TRANSFER;
```

7.2 Initiation of Processes.

Processes are initiated by the initiate statement:

```
initiate process-list;
```

where process-list is a list of previously declared actual processes.

A process may be initiated more than once; each time a new activation of execution of the process body occurs. Previously initiated instances of a process are not effected by later initiations, except in as much as the instances share channels.

Initiate statements compile as a sequence of calls to the supervisor procedure, START (one call for each process in process list).

7.3 Termination of Processes.

The visibility and declaration rules of Adam establish a similar dependency relation for processes as exists for tasks in Ada [6, pg. 9-5]. Processes depend on subprograms, blocks, or processes within which they are initiated. Termination of a process occurs when the process execution reaches the end of its body and all dependent processes, if any, have terminated. Termination of a process compiles as a call to the supervisor procedure FINISH.

The dependency relationship of a process to a subprogram, block, or process imposes significant requirements on the techniques used to implement scope exit in Adam. Each unit which may have dependent processes must have an associated count or list of its nonterminated dependent proceses, in order to detect satisfaction of the exit condition. Only when the count reaches zero, or the list is empty, may the subprogram return, the block be left, or the process terminate. However, the scope exit problem in Adam is much less complicated and requires less runtime mechanism than is needed for scope exit in

Ada. Because Adam has no analogue of the terminate alternative of Ada and processes do not have visible operations, the only manner in which a process can terminate is by reaching the end of its body, either normally or by means of an exception. Once the end of its body has been reached, no further activity occurs in the process. The semantics of terminate in Ada requires that a dependent task inform the unit on which it depends when it selects a terminate alternative. This information could be exchanged either by decrementing a count or removing an object from a list as in Adam. However, in Ada the dependent task may have to change its terminate vote because of a call to an entry in the select statement containing the terminate. This communication of state information among scopes and their dependent tasks must be carefully implemented to insure absence of race and deadlock conditions and requires a considerably more sophisitcated task supervisor.

7.4 Instantiation of Processes.

Instances of generic processes are created as follows:

```
process P is new Q(L; channels M);
```

where
L is a list of actual compiletime generic parameters,
M is a list of actual channels.

Rules for matching actual and formal generic parameters in instantiation of a generic process extend the Ada *rules for generic instantiation [6, 12.3]. Scheduled modules* match generic formal channel parameters. The actual channel must be an instance of the formal channel obtained by replacing its generic formal parameters by actual generic parameters of the process instance. Thus, above, each member of M must be an instance of the corresponding generic channel with the members of L indicated in the declaration of Q.

Example 7-3. We continue with the previous example: correct and incorrect instantiations of the process, Transfer.

```
scheduled module BUF1 is new BUFFER (APPLES, 120);
scheduled module BUF2 is new BUFFER (APPLES, 120);
scheduled module BUF3 is new BUFFER (ORANGES, 120);

process T1 is new TRANSFER (APPLES, 120; channels BUF1, BUF2);
          -- This is a proper instance of TRANSFER,

process T2 is new TRANSFER (APPLES, 120; channels BUF1, BUF3);
          -- This is an improper instance of TRANSFER, since the declaration of
          -- TRANSFER requires that the generic parameters in the declaration of
          -- BUF3 be the same as those in the declaration of T2, namely, APPLES, 120.
```

8. VISIBILITY RULES and IMPORTS.

The visibility rules of Adam are those of Ada with the following restrictions placed on the visibility of subprograms and objects within units. Outer declarations of objects are not visible within modules unless explicitly imported by an imports declaration. Outer declarations of objects are not visible within processes, except those scheduled modules declared by a channels declaration. There are no restrictions on the visibility of objects within subprograms. Outer subprograms that are not exported from a module are not visible in units.

These restrictions ensure that all objects shared among processes can be enumerated from channels and imports declarations. The correctness of these declarations can be checked.

8.1 Visible Declarations.

Declarations that are always visible within the body of a unit if they are visible at the point of declaration of that unit are the following:
(i) type declarations (including the constants of an enumeration type),
(ii) constants,
(iii) generic unit declarations,
(iv) exception declarations.
(v) processes,
(vi) predefined system modules (e.g., Supervisor).

8.2 Declarations Requiring Importation.

The following declarations must be imported in order to be visible within a module:
(i) variable declarations,
(ii) nongeneric module declarations (including instantiations of generic modules).

8.3 Imports.

Declarations requiring importation can be explicitly imported into a nongeneric module specification or body by an imports declaration of the form:

imports (imports list);

where

imports list ::= import-item {; import-item}
import-item ::= [use] identifier-list : import-kind
import-kind ::= in | out | in out | module

Imports are declared as part of the specification or body of a nongeneric module (see

formats, Section 6). Any external object that is mentioned syntactically in a module must be declared in its imports.

Imports declared in the specification of a module are also imported into the body; repetition of the imports declaration in the body is not required. However, a module body may have additional imports that are not declared in the module specification.

Note: Generic module declarations may not have imports.

8.3.1 Redundant Imports Declarations

Some parts of Ada and Adam declarations already perform the function of declaring imports. In these cases a separate imports declaration is unnecessary:

1. Objects listed in a with clause are imports.

2. When a generic module is instantiated, those generic parameters that are objects are imports of the actual instantiation.

8.3.2 Using Imports.

To avoid duplication of imports and use lists, a use declaration may appear within an imports list (see syntax above).

Examples.

Example 8-1: Imports and using imports.

```
module A is                              -- declaration of actual module A
    procedure P ( . . .);
      . . .
end A;

module body B is
    imports (A: module);                 --A is now visible in body of B.

      procedure C ( . . .) is
      begin
              . . .
              A.P ( . . .);
              . . .
      end C;
end B;
```

```
module body D is
    imports (use A: module);          --A is both visible and used in body of D.

        procedure E ( . . .) is
        begin
              . . .
              P ( . . .);             -- call to A.P
              . . .
        end E;
end D;
```

Example 8-2: Visibility of generics and instances.

```
generic  . . .
module STACK is
    procedure PUSH (. . .);
    . . .
end STACK;

module body CATALOGUE is
    . . .
    module GLOBAL_STACK is new STACK ( . . .);
                              -- generic STACK is visible in the body of CATALOGUE.
    . . .
    module SYMBOL_TABLE is
        imports (use GLOBAL_STACK: module);
                              -- nongeneric GLOBAL_STACK must be imported
        module LOCAL_STACK is new STACK ( . . .);
                              -- generic STACK is visible.
        . . .
        PUSH ( . . .);        -- GLOBAL_STACK. PUSH ( . . .).
        LOCAL_STACK. PUSH ( . . .);
        . . .
    end SYMBOL_TABLE;
    . . .
end CATALOGUE;
```

8.3.3 Encapsulated Imports.

Modules may be encapsulated by an enclosing module and exported by the outer module. In this case, the declaration within the body of the encapsulating module may have imports of local objects that are not visible in the exported specifications. These are called *encapsulated* imports. Modules may be used to encapsulate and hide imports from outside users. Thus careful modularization should result in only essential objects appearing in imports lists.

Example 8-3: Encapsulation of imports. The FILE_TEMPLATE module body has two imports local to DISKFILES. These imports are implementation details encapsulated in the body of DISKFILES and not declared in the specification of FILE_TEMPLATE.

```
module DISKFILE is              -- DISKFILE exports FILE_TEMPLATE.

    scheduled module FILE_TEMPLATE is
            . . .               -- no imports are declared in specification
    end FILE_TEMPLATE;          -- of FILE_TEMPLATE.
      . . .
end DISKFILE;

module body DISKFILE is         -- body of FILE_TEMPLATE is local to DISKFILE.

    module FILE_MANAGER is      -- FILE_MANAGER is encapsulated by DISKFILE.
            . . .
    end FILE_MANAGER;

    device DISK is              -- DISK is encapsulated by DISKFILE.
            . . .
    end DISK;

    module body FILE_TEMPLATE is
        imports(use FILE_MANAGER, DISK : module);
                                -- both imports are local to DISKFILE.
            . . .
    end FILE_TEMPLATE;

end DISKFILE;
```

9. CONCLUSIONS.

Although our use of Adam in pursuing the goals which motivated development of the language is not complete, our experience has led us to several conclusions which will be useful in our continued experimentation with Adam and Ada. We hope these results will assist others who are involved in similar efforts and may be considering similar techniques.

9.1 Writing Supervisors.

A supervisor for scheduling processes on a single PDP-10 processor has been written in Adam, compiled, and is part of the runtime environment. It is used by Adam programs with processes and Ada programs with tasks. Two versions are currently in use; one interfaces with the SU-AI WAITS operating system and the other is for use with TOPS-20. Appendix F gives a simplified version of the WAITS supervisor.

Supervisors so far constructed fit very naturally into the structure of a scheduled device module encapsulating both interrupts and machine code. First, it turns out that the standard procedures, ACTIVATE (P : PROCESSNAME), . . . , require only the simple "before

and after" protection provided by Adam scheduling declarations. Second, the encapsulation of protection in a separate scheduler subunit and the use of scheduling declarations improves the structure of the supervisor; the scheduling is much easier to understand than if each subprogram body contains protection, scheduling and computation all mixed together. This is true even in cases where the scheduler operations are trivial (e.g., simply disabling and enabling interrupts). For example, in Appendix F two of the standard supervisor procedures have null scheduling on exit. If these declarations were absent the reader might well consider the omission of enabling interrupts on exit from these procedures to be an error. Thirdly, it has been possible so far to encapsulate all machine language procedures (for switching contexts on the CPU and enabling and disabling interrupts) in a single subdevice such as CPU in Appendix F. (In fact, the two versions of the supervisor for WAITS and TOPS-20 differ only in the CPU subdevice.) In addition, process names have provided an adequate means of refering to threads of control in user-defined process scheduling and in interaction between such scheduling and the supervisor.

Further development is being undertaken to determine the extent to which the scheduled device structure suffices as a paradigm for more sophisticated supervisors and other varieties of resource scheduling systems. A first step in this work is to extend the current existing supervisor to provide facilities necessary for implementation of the Ada **terminate** alternative, the **abort** statement, and the FAILURE exception. We also intend to develop supervisors for more varied and complicated applications, including large system control, realtime interrupt driven processing, device handling, and multiple CPU interfacing. By considering a broad class of supervisor implementations, we hope to demonstrate the utility of Adam constructs or, perhaps, to discover generalizations of the Adam notions which will better meet the requirements for scheduling programs.

9.2 Transporting the Adam Compiler and Runtime Environment.

Our experience in transporting the Adam compiler to different operating systems has demonstrated the utility of providing a simple module interface between the compiler and the runtime system. The only changes to the compiler which were required in moving from the WAITS to TOPS-20 systems involved changes in file naming for I/O and interrupt initialization code. All other operating system differences were absorbed by the supervisor written in Adam and, as mentioned above, the changes needed in the supervisor were confined to a single local device.

9.3 Translating Ada Multitasking.

In extending the Adam compiler to support Ada multitasking, we have used Adam as an intermediate target language. This use results essentially in a translation of Ada tasking into the lower level multiprocessing facilities of Adam. The development of this translation proceeded in two stages. First, for each Ada tasking construct we defined Adam text corresponding to the semantics of the construct and utilizing the scheduling features of Adam. Thus, the translation algorithm is defined by a mapping between Ada source and

Adam target programs; an example of this mapping is given in Appendix G. The second step in the translation was to augment the semantic processing phase of the compiler with MACLISP routines which replace abstract syntax tree nodes for Ada multitasking constructs with the corresponding Adam trees. Thus, though the algorithms for translating Ada multitasking were defined by correspondences between Ada and Adam program text, the implementation is by tree surgery on the parsed form of Ada programs. The actual text translation could be constructed by applying a pretty printer to the Adam syntax tree after completion of the compiler's semantic phase.

Our experience in using Adam as a target language for implementing Ada multitasking has led us to several conclusions, which are given below.

9.3.1 Advantages of Using a High Level Target Language

The main advantages were reliability and ease of implementation; others include clarity and understandability of the translator.

We found that using Adam to specify the translation of Ada multitasking was an excellent technique for quickly producing a reliable implementation. Errors in the definition of Ada/Adam correspondence were easily identified and corrected by analyzing the proposed Adam text; we are certain that these errors would not have been so easily detected if it we had decided to hand generate and analyze sample assembly code. In fact, we were able to give quite short and convincing informal proofs that the Adam translations were semantically equivalent to the corresponding constructs of Ada. (Because adequate proof methods for the semantic correctness of parallel programs have not yet been developed, use of informal arguments is the best step towards verification of tasking translators that can be expected at the moment.)

Starting with the compiler for the parallel constructs of Adam, we implemented the tree transformations required for a substantial subset of Ada multitasking, including task types, rendezvous, select, conditional entry call, and a simplified abort statement (no abortion of dependent tasks) in a short time. Less than two man months were expended in writing and debugging the MACLISP code which was added to the compiler. Relatively few difficulties arose during the translation implementation and those that did were generally resolved at the level of the Adam text. The transforming operations basically emit a subtree of an Adam program, utilizing the context of the Ada abstract syntax tree. When a problem was encountered in the implementation, it was possible to identify the Adam source which was needed in the tree, to compile and dump the syntax tree for that Adam program, and then simply to write the (correct) constructor for that tree. We anticipate that the advantages of using Adam in our initial implementation of Ada tasking will carry over to the alternative implementations currently underway.

9.3.2 Using Ada as a Target for Translating Ada

One might ask whether the same advantages of using a high level language for the target

of the multitasking translation would not have accrued if a pure subset of Ada had been used. For those parts of the translation specification which describe only sequential operations, Ada would certainly suffice, since sequential Adam is sequential Ada. However, one would still have to deal with describing concurrency by using a restricted target subset of Ada. The target, of course, could not utilize any form of rendezvous. One could restrict the usage of tasks to only those with no entries, eliminate select and accept statements, and have all inter-task communication be carried out by operations on shared data structures (packages) for which one had explicitly written the exclusion and synchronization mechanisms. However, in such an Ada system, the problems of interfacing to a supervisor and of naming tasks would still be present. Furthermore, the discipline of scheduling the visible operations of the shared data structures would have to be carefully followed. In such a system in Ada, it would not be possible to determine from their visible parts which packages were shared by tasks (and hence had scheduling) and which packages were not. Clearly, solution of these problems was a primary factor in developing many of the constructs of Adam, and, hence, specifying the multitasking translation is much more easy and clear in Adam.

9.3.3 Multiprocessors and Optimization

We believe that use of an intermediate Adam transformation to implement Ada multitasking will expedite research into multiprocessor implementations and optimization techniques. The translation algorithms we currently use separate all scheduling operations and rendezvous code from the thread of control of a task. By such a breakdown it will be easier to identify computations which may be truly carried out in parallel and to isolate the critical sections and synchronizations required for multiprocessor environments. Also, it is relatively easy to identify, as an optimization, those tasks which may be compiled as static rather than active structures.

9.3.4 Disadvantages of the Translation Technique

The use of Adam in developing the tasking translation algorithms has had some drawbacks. First, strong typing was occasionally very annoying and cumbersome. For example, in a message passing implementation of rendezvous, it is necessary to declare complicated variant record types in which the variant parts are lists of the parameters of the task entries. In a directly compiled implementation the manipulation of the parameters could be handled without the type definitions. A second difficulty encountered was due to some mismatch between the Adam constructs and the desired translated semantics. For example, the task type construct for tasks with entries is not readily translatable into Adam. The actual implementation of task types required modifying the code generator of our Adam compiler to permit creation of copies of scheduled module local data (almost like including a module type). Most of the mismatch problems occurred because much of the Adam design was based on Preliminary Ada and was maintained although the tasking was siginificantly revised in final Ada.

9.3.5 Future Research

Our experience thus far has not been sufficient to allow us to draw conclusions about a number of questions associated with the multitasking translation. We have not been able to evaluate the compilation overhead and implemention efficiency of translating the internal form as compared to directly checking semantics and generating assembly code for the tasking constructs. Our experiments with modifying and replacing supervisors have been limited, and have not yet included supervisors and tasking for multiprocessor systems. The use of the multitasking translation for specification and verification of Ada task systems, including proof of equivalence of an Ada program and its corresponding Adam program, has not progressed much beyond the concept stage. These questions, and many other related issues, are the objects of ongoing research.

Acknowledgment:

The authors wish to thank Anthony Garagaro for many helpful comments on an earlier draft of this paper.

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APPENDIX A : SYNTAX.

Notation:

Reserved words are in boldface. Square brackets, [ ], indicate an optional construct. Curly brackets, { }, indicate zero or more repetitions of a construct. To indicate one or more repetitions we use { }+. The bar, |, is used to indicate alternation in the right-hand-side of a production. Any nonterminal of the form xxx-name is syntactically the same as name.

compilation ::= {compilation-unit}

compilation-unit ::=
    context-specification module-specification;
  | context-specification generic-module-declaration
  | context-specification module-body
  | context-specification subprogram-body

context-specification ::= {with-clause [use-clause]}

with-clause ::= **with** unit-name {, unit-name};

DECLARATIONS.

declarative-part ::=
    {declarative-item} {representation-specification} {program-component}

declarative-item ::= declaration | use-clause

program-component ::= body | module-declaration

body ::= subprogram-body | module-body | process-body

declaration ::=
    object-declaration | type-declaration
  | subtype-declaration | subprogram-declaration
  | module-declaration | process-declaration
  | exception-declaration | renaming-declaration

use-clause ::= **use** module-name {, module-name};

object-declaration ::=
    identifier-list : [**constant**] subtype-indication [:= expression];
  | identifier-list : [**constant**] array-type-definition [:= expression];

identifier-list ::= *identifier* {, *identifier*}

exception-declaration ::= identifier-list : **exception**

renaming-declaration ::=
    identifier : type-mark **renames** name;
  | identifier : **exception renames** name;
  | module-nature *identifier* ***renames*** *name*;

TYPES.

type-declaration ::=
    type identifier **is** type-definition;
  | *incomplete-type-declaration*;

type-definition ::=
    enumeration-type-definition | array-type-definition
  | *record-type-definition* | access-type-definition
  | private-type-definition

subtype-declaration ::=
    subtype identifier **is** subtype-indication;

subtype-indication ::= type-mark [constraint]

type-mark ::= type-name | subtype-name

constraint ::= range-constraint | index-constraint

range-constraint ::= **range** range
range ::= simple-expression .. simple-expression

index-constraint ::= (discrete-range {, discrete-range})
discrete-range ::= [type-mark **range**] range

enumeration-type-definition ::= (enumeration-literal {, enumeration-literal})

enumeration-literal ::= identifier | character-literal

chararacter-literal ::= ' character '

record-type-definition ::=
    record
      component-list
    end record

component-list ::=
    {component-declaration}+

component-declaration ::=
    identifier-list : subtype-indication [:= expression];
  | identifier-list : *array-type-definition* [:= *expression*];

array-type-definition ::=
    array (index {, index}) **of** subtype-indication
  | **array** index-constraint **of** subtype-indication

index ::= type-mark **range** <>

access-type-definition ::= **access** subtype-indication

incomplete-type-declaration ::= **type** identifier ;

private-type-definition ::= **[limited] private**

representation-specification ::= address-specification

address-specification ::=
    for identifier **use at** expression;

EXPRESSIONS.

expression-list ::= expression {, expression}

expression ::= relation {logical-operator relation}

relation ::= simple-expression {relational-operator simple-expression}

simple-expression ::= *[unary-operator] term {adding-operator term}*

term ::= factor {multiplying-operator factor}

factor ::= primary {** primary}

primary ::= literal | aggregate | name | function-call | (expression) | allocator

logical-operator ::= **and | or | xor | and then | or else**

relational-operator ::= = | /= | < | <= | > | >=

adding-operator ::= + | -

multiplying-operator ::= * | / | **mod**

unary-operator ::= + | - | **not**

literal ::= number | enumeration-literal | character-string | **null**

aggregate ::=
[type-mark'] (component-association {, component-association})

component-association ::= [choice {| choice} =>] expression

choice ::= simple-expression | range | **others**

allocator ::= **new** type-mark [(expression)] | **new** type-mark aggregate

function-call ::= function-name (expression-list) | function-name ()

name ::= *identifier* | indexed-component | selected-component | attribute

indexed-component ::= *name* (expression-list)

selected-component ::= *name.identifier* | *name.all*

attribute ::= name'identifier

identifier ::= letter { letter | digit | underscore }

number ::= digit {digit}

character-string ::= "{character}"

STATEMENTS.

statement-list ::= statement {statement}

statement ::= {label} simple-statement | {label} compound-statement

simple-statement ::=
assignment-statement | exit-statement
| return-statement | goto-statement
| raise-statement | procedure-call

```
   |  code-statement
   |  initiate-statement     | null;

compound-statement ::=
      if-statement           | case-statement
   |  loop-statement          | block
   |  reserve-statement
label  ::= <<identifier>>


assignment-statement  ::=  name := expression;

exit-statement ::=  exit [identifier] [when expression];

return-statement::=   return [expression];

goto-statement  ::=  goto identifier;

raise-statement  ::=  raise [exception-name];

procedure-call ::=   procedure-name [ ( expression-list ) ];

code-statement ::=  aggregate

initiate-statement ::=   initiate process-name {, process-name};

if-statement ::=
      if expression then
            statement-list
      {elsif expression then
            statement-list }
      [else
            statement-list ]
      end if;


loop-statement  ::=  [identifier:] [iteration-clause] basic-loop

iteration-clause  ::=
      while expression
   |  for identifier in [reverse] range

basic-loop  ::=
      loop
            statement-list
      end loop;

case-statement ::=
      case expression is
         { when choice {| choice}  => statement-list }+
      end case;


block ::=
```

```
      [identifier:]
      [declare
            declarative-part]
      begin
            statement-list
      [exception
            {exception-handler}]
      end;


exception-handler ::=
      when exception-choice {| exception-choice} =>
            statement-list

exception-choice ::= exception-name | others


reserve-statement ::=
      reserve module-name do
            statement-list
      end reserve;
```

SUBPROGRAMS.

```
subprogram-declaration ::=
      subprogram-header;
  |   generic-subprogram-declaration
  |   generic-subprogram-instantiation


subprogram-body ::=
      subprogram-header is
            specification-part
            declarative-part
      begin
            statement-list
      [exception
            {exception-handler}]
      end [designator];



subprogram-header ::=
      function designator [formal-part] return subtype-indication
  |   procedure identifier [formal-part]
  |   interrupt identifier called from number


designator ::= identifier | character-string
```

formal-part ::=
    (parameter-declaration {; parameter-declaration})

parameter-declaration ::=
    identifier-list : mode subtype-indication

mode ::= [**in**] | **out** | **in out**

specification-part ::=
    [propagate-declaration]
    [**scheduling** (*scheduling-item, scheduling-item*);]

imports-list ::= **imports** (import-item {; import-item});

import-item ::= [**use**] identifier-list : *import-kind*

import-kind ::= **in** | **out** | **in out** | **module**

propagate-declaration ::= **propagate** *identifier-list*;

scheduling-item ::= identifier [(expression-list)] | **null**

generic-subprogram-declaration ::= generic-part subprogram-header;
generic-part ::= **generic** {generic-formal-parameter}

generic-formal-parameter ::=
    parameter-declaration;
  | **with** subprogram-header;
  | **type** identifier **is** private-type-definition;

generic-subprogram-instantiation ::=
    procedure identifier **is** generic-instantiation;
  | **function** designator **is** generic-instantiation;

generic-instantiation ::= **new** identifier [(expression-list)]

MODULES.

module-declaration ::=
    module-specification;
  | generic-module-declaration
  | generic-module-instantiation

module-specification ::=
    module-nature identifier **is**
        [import-list]
        {declarative-item}
    [**private**
        {declarative-item}
        {representation-specification}]
    end [identifier]

generic-module-declaration ::= **generic-part** **module-specification**;

generic-module-instantiation ::=
    module-nature identifier **is** **generic-instantiation**;

module-body ::=
    module-nature **body** identifier **is**
        [import-list]
        declarative-part
    [**begin**
        statement-list
    [**exception**
        {exception-handler}]]
    end [identifier];

module-nature ::=
    scheduler | **device** | **module** | **scheduled device**
  | **scheduled module**

PROCESSES.

process-declaration ::=
    process-specification
  | *generic-process-declaration*
  | generic-process-instantiation;

process-specification ::=
    process identifier [**is**
        [**channels** actual-channel {, actual-channel};]
    end];

generic-process-declaration ::= **process-generic-part** **process-specification**

generic-process-instantiation ::=
    process identifier **is** **new** *identifier* [(*instantiation-actuals*)];

process-body ::=
    process body identifier is

```
        declarative-part
    begin
        statement-list
    [exception
        {exception-handler}]
    end [identifier];


actual-channel ::= identifier [restricted ( identifier-list )]


process-generic-part ::=
    generic [ {process-generic-parameter}
        [channels generic-channel {, generic-channel};] ]

process-generic-parameter ::=
    identifier-list : [in] type-mark;
  | type identifier is private-type-definition;

generic-channel ::=
    identifier is module-name [(expression-list)]
        [restricted ( identifier-list )]


instantiation-actuals ::=
    expression-list
  | channels-list
  | expression-list; channels-list

channels-list ::= channels identifier-list
```

APPENDIX B: RESERVED WORDS.

and	**for**	**new**	**reserve**
array	**from**	**not**	**restricted**
at	**function**	**null**	**return**
			reverse
begin	**generic**	**of**	
body	**goto**	**or**	**scheduled**
		others	**scheduler**
called	**if**	**out**	**scheduling**
case	**imports**		**subtype**
channels	**in**	**pragma**	
constant	**initiate**	**private**	**then**
	interrupt	**procedure**	**to**
declare	**is**	**process**	**type**
device		**program**	
do	**limit**	**propagate**	**use**
	loop		
else		**raise**	**when**
elsif	**mod**	**range**	**while**
end	**module**	**record**	**with**
exit		**renames**	
exception		**requires**	**xor**

APPENDIX C: LIST OF PRAGMAS.

```
pragma INCLUDE (file name)
pragma PRIORITY (number between 0 and 10)
pragma SUPERVISOR (module name)          - explained in Section 2.8
pragma MAIN                              - specify main program
```

APPENDIX D: PREDEFINED ATTRIBUTES.

Attributes of any object:

ADDRESS	X'ADDRESS returns an integer corresponding to the location of the first storage cell of X.

Attributes of any type or subtype:

SIZE	T'SIZE gives the number of storage units used to represent the type.

Attributes of any scalar type or subtype:

FIRST	T'FIRST returns the minimum value in the range of T.
LAST	T'LAST returns the maximum value in the range of T.

Attributes of any discrete type or subtype T:

POS(X)	Returns an integer which is the ordinal position of X in the type T.
VAL(I)	Returns the enumeration value occupying the Ith position in T.

Attributes of any array object or array type with specified bounds:

FIRST	Returns the value in the first index which is the lower bound of that index.
FIRST(i)	Same as FIRST for the ith index.
LAST	Upper bound for the first index.
LAST(i)	Same as LAST for the ith index.
LENGTH	Number of elements in the first dimension.
LENGTH(i)	Same as LENGTH for the ith dimension.

APPENDIX E: PREDEFINED EXCEPTIONS.

Exception Name	When Raised
CONSTRAINT_ERROR	When exceeding the declared range of a variable, or when an index value is outside the range specified for an array, or when dereferencing an access variable that has the value null
STORAGE_ERROR	When all free storage in the heap is used up.
CONDITION_QUEUE_FULL	When attempting to insert into a full condition queue
CONDITION_QUEUE_EMPTY	When attempting to remove from an empty condition queue

APPENDIX F: A STANDARD SUPERVISOR.

This appendix presents a simplified version of the process supervisor that we have been using in our implementation of Adam on SAIL WAITS. Processes are given a fixed size time slice and are preempted if they exceed their time slice. Scheduling within a priority level is round-robin. The WAITS operating system provides timer interrupts to implement the timing. The priority of a process may be specified by a pragma.

```
scheduled device SUPERVISOR is
    type INIT_DATA is limited private;

    subtype TICK_COUNT is INTEGER range 0 .. INTEGER'LAST;
    subtype PRIORITY   is INTEGER range 0 .. 10;
    subtype ADDRESS    is INTEGER range 0 .. 2 ** 18 - 1;
    procedure SUSPEND;
    procedure ACTIVATE (P : PROCESSNAME);
    procedure SWITCH (P : PROCESSNAME);
    procedure START  (D : INIT_DATA);
    procedure FINISH;
    procedure DELAY_FOR (I : TICK_COUNT);

private
    type INIT_DATA is
        record
            PNAME     : PROCESSNAME;
            CODESTART : ADDRESS;
            STKSTART  : ADDRESS;
            PRIORITY  : PRIORITY;
        end record;

    interrupt TIMER_INTERRUPT called from 0;

end SUPERVISOR;


with  DEC10_INSTRUCTIONS;
scheduled device body SUPERVISOR is

-- DEC10_INSTRUCTIONS is a package which defines the formats for inserting
-- machine code.

    MAX_PROCESSES : constant INTEGER := 40;
    subtype PT_INDEX  is  INTEGER range 0 .. MAX_PROCESSES;

    NO_PROCESS : constant PT_INDEX := 0;

    type PROCESS_STATUS is (RUN, READY, BLOCKED);

    type QHEADER is
        record
            FIRST : PT_INDEX;
            LAST  : PT_INDEX;
        end record;
```

```
    type READYQS is
        array (PRIORITY) of QHEADER;

    type REGISTER_SET is
        array (0 ..15) of INTEGER;

    type PROCESS_DATA is
        record
            NAME        : PROCESSNAME;
            STATUS      : PROCESS_STATUS;
            PC          : ADDRESS;
            REG         : REGISTER_SET;
            PRIORITY    : PRIORITY;
            DELAY_TIME  : TICK_COUNT;
            NEXT, PRIOR : PT_INDEX;
        end record;

    PT : array (PT_INDEX range 1 .. MAX_PROCESSES) of PROCESS_DATA;

    MAIN_PROGRAM : constant PT_INDEX := 1;
    RUNNING : PT_INDEX := MAIN_PROGRAM;- table index of the currently running
                                       -- process
    FREE    : PT_INDEX := 2;

    READYQ : READYQS;
    DELAYQ : QHEADER;

    BLOCKED_COUNT : INTEGER := 0;     -- count of number of blocked processes

    TICK_LENGTH : constant INTEGER := 6;     -- = 6/60 of a second
    TIME_SLICE  : constant TICK_COUNT := 10;-- = 10 * TICK_LENGTH = 1 second

    RUNNERS_TICKS : TICK_COUNT := 0;
    SP  : constant INTEGER := 14;     -- register which points to stack frame
    TOP : constant INTEGER := 15;

    MAIN_PRIORITY : PRIORITY;         -- priority of the main program

    for MAIN_PRIORITY use at "PRITYT";--this representation specification
                                      --is known at link time

scheduler S is
    procedure ENTER;
    procedure LEAVE;
    pragma INLINE (ENTER, LEAVE);
end S;



module Q is

    procedure INSERT (Q : in out QHEADER;  I : PT_INDEX);
    procedure REMOVE (Q : in out QHEADER;  I : in out PT_INDEX);
```

```
    procedure DELETE (Q : in out QHEADER;  i : PT_INDEX);
    function  EMPTY  (Q : QHEADER) return BOOLEAN;
    pragma INLINE (EMPTY);

    procedure INSERT (A : in out READYQS;  i : PT_INDEX);
    procedure REMOVE (A : in out READYQS;  i : in out PT_INDEX);
    procedure DELETE (A : in out READYQS;  i : PT_INDEX);
    function  EMPTY  (A : READYQS) return BOOLEAN;
    function  FIRST  (A : READYQS) return PT_INDEX;
    pragma INLINE (EMPTY, DELETE, INSERT);
end Q;


device CPU is
  -- machine dependent code
    procedure IDLE;
    procedure START_PROCESS (D : PROCESS_DATA);
    procedure SAVE_CONTEXT  (D : in out PROCESS_DATA);
    procedure DISABLE;
    procedure ENABLE;
    pragma INLINE (ENABLE, DISABLE);

    procedure STARTUP      (D : PROCESS_DATA);
    procedure SAVE_STATE   (D : in out PROCESS_DATA);
end CPU;


function NAME_TO_INDEX (P : PROCESSNAME) return PT_INDEX is
    -- convert a processname into a table index
begin
    if P /= null then
        for i in PT_INDEX'FIRST + 1 .. PT_INDEX'LAST loop
            if PT(i).NAME = P then
                return i;
            end if;
        end loop;
    end if;
    return NO_PROCESS;
end NAME_TO_INDEX;


procedure UNBLOCK (i : PT_INDEX) is
    PCB : PROCESS_DATA renames PT(i);
begin
    if PCB.DELAY_TIME > 0 then
        Q.DELETE (DELAYQ, i);
        PCB.DELAY_TIME := 0;
    end if;
end;


procedure DO_SUSPEND is
begin
```

```
        CPU.SAVE_CONTEXT (PT(RUNNING));
        PT(RUNNING).STATUS := BLOCKED;
        BLOCKED_COUNT := BLOCKED_COUNT + 1;

        if Q.EMPTY (READYQ) then
            CPU.IDLE;
        else
            Q.REMOVE (READYQ, RUNNING);
            PT(RUNNING).STATUS := RUN;
            CPU.START_PROCESS (PT(RUNNING));
        end if;
    end DO_SUSPEND;


    procedure START (D : INIT_DATA) is
        scheduling (ENTER, LEAVE);
        i : PT_INDEX;
    begin
        if FREE = NO_PROCESS then
            raise STORAGE_ERROR;
        else
            i := FREE;    FREE := PT(FREE).NEXT;

            PT(i) := (NAME          => D.PNAME,
                      STATUS        => READY,
                      PC            => D.CODESTART,
                      REG           => (SP => D.STKSTART, others => 0),
                      PRIORITY      => D.PRIORITY,
                      DELAY_TIME    => 0,
                      NEXT | PRIOR  => NO_PROCESS);

            Q.INSERT (READYQ, i);
        end if;
    end START;


    procedure FINISH is
        scheduling (ENTER, null);
    begin
        PT(RUNNING).NEXT := FREE;    FREE := RUNNING;
        PT(RUNNING).NAME := null;
        if Q.EMPTY (READYQ) then
            CPU.IDLE;
        else
            Q.REMOVE (READYQ, RUNNING);
            PT(RUNNING).STATUS := RUN;
            CPU.START_PROCESS (PT(RUNNING));
        end if;
    end FINISH;


    procedure ACTIVATE (P : PROCESSNAME) is
        scheduling (ENTER, LEAVE);
```

```
    i : constant PT_INDEX := NAME_TO_INDEX (P);
begin
    if i /= NO_PROCESS and then PT(i).STATUS = BLOCKED then
        UNBLOCK (i);
        BLOCKED_COUNT := BLOCKED_COUNT + 1;
        Q.INSERT (READYQ, i);
        PT(i).STATUS := READY;
    end if;
end ACTIVATE;


procedure SUSPEND is
    scheduling (ENTER, null);
begin
    DO_SUSPEND;
end SUSPEND;


procedure SWITCH (P : PROCESSNAME) is
    scheduling (ENTER, LEAVE);
    i : constant PT_INDEX := NAME_TO_INDEX (P);

    procedure DO_SAVE (D : in out PROCESS_DATA) is
    begin
        CPU.SAVE_CONTEXT (D);
    end;
begin
    if i /= NO_PROCESS and then PT(i).STATUS /= RUN then
        DO_SAVE (PT(RUNNING));
        PT(RUNNING).STATUS := BLOCKED;
        RUNNING := i;
        if PT(i).STATUS = READY then
            Q.DELETE (READYQ, i);
            BLOCKED_COUNT := BLOCKED_COUNT + 1;
        else
            UNBLOCK (i);
        end if;
        PT(i).STATUS := RUN;
        CPU.START_PROCESS (PT(i));
    end if;
end SWITCH;


procedure DELAY_FOR (I : TICK_COUNT) is
    scheduling (ENTER, LEAVE);
begin
    if I > 0 then
        Q.INSERT (DELAYQ, RUNNING);
        PT(RUNNING).DELAY_TIME := I;
        DO_SUSPEND;
    end if;
end;
```

```
module body Q is

    function EMPTY (Q : QHEADER) return Boolean is
    begin
        return Q.FIRST = NO_PROCESS;
    end;


    procedure INSERT (Q : in out QHEADER;  i : PT_INDEX) is
    begin
        PT(i).PRIOR := NO_PROCESS;
        if Q.FIRST = NO_PROCESS then
            Q.FIRST := i;   PT(i).NEXT := NO_PROCESS;
        else
            PT(Q.LAST).PRIOR := i;     PT(i).NEXT := Q.LAST;
        end if;
        Q.LAST := i;
    end;


    procedure DELETE (Q :  in out QHEADER;  i : PT_INDEX) is
        PCB : PROCESS_DATA renames PT(i);
    begin
        if i = Q.FIRST then
            Q.FIRST := PCB.PRIOR;
            if Q.FIRST /= NO_PROCESS then
                PT(Q.FIRST).NEXT := NO_PROCESS;
            end if;
        elsif i = Q.LAST then
            Q.LAST := PCB.NEXT;
            if Q.LAST /= NO_PROCESS then
                PT(Q.LAST).PRIOR := NO_PROCESS;
            end if;
        else
            PT(PCB.PRIOR).NEXT := PCB.NEXT;
            PT(PCB.NEXT).PRIOR := PCB.PRIOR;
        end if;
    end;


    procedure REMOVE (Q : in out QHEADER;  i : in out PT_INDEX) is
    begin
        i := Q.FIRST;
        Q.FIRST := PT(i).PRIOR;
        if Q.FIRST /= NO_PROCESS then
            PT(Q.FIRST).NEXT := NO_PROCESS;
        end if;
    end;


    procedure DELETE (A : in out READYQS;  i : PT_INDEX) is
    begin
        Q.DELETE (READYQ(PT(i).PRIORITY), i);
    end;
```

```
    procedure INSERT (A : in out READYQS;  i : PT_INDEX) is
    begin
        Q.INSERT (READYQ(PT(i).PRIORITY), i);
    end;


    function  EMPTY  (A : READYQS) return BOOLEAN is
    begin
        return Q.FIRST (A) = NO_PROCESS;
    end;


    procedure REMOVE (A : in out READYQS;  i : in out PT_INDEX) is
    begin
        for j in reverse PRIORITY'FIRST .. PRIORITY'LAST loop
            if not Q.EMPTY (READYQ(j)) then
                Q.REMOVE (READYQ(j), i);
                exit;
            end if;
        end loop;
    end;


    function  FIRST  (A : READYQS) return PT_INDEX is
    begin
        for j in reverse PRIORITY'FIRST .. PRIORITY'LAST loop
            if not Q.EMPTY (READYQ(j)) then
                return READYQ(j).FIRST;
            end if;
        end loop;
        return NO_PROCESS;
    end;
end Q;


device body CPU is
    use DEC10_INSTRUCTIONS;
    use REGISTERS;


    procedure DISABLE  is
    begin
        UUO'(INTMSK, (LITERAL, 0));
    end;


    procedure ENABLE  is
    begin
        UUO'(INTMSK, (LITERAL, -1));
    end;
```

```
procedure STOP  is
begin
    FAIL_INSERTION'(TEXT => "EXIT");
end;


procedure SLEEP  is
    -- this procedure is called when there are only blocked processes
begin
    loop
        ENABLE;
        R1 := 1;
        UUO'(SLEEP, 1, (QUOTED, ""));          -- sleep for 1 second
        DISABLE;
        if not Q.EMPTY(READYQ) then
            Q.REMOVE (READYQ, RUNNING);
            PT(RUNNING).STATUS := RUN;
            CPU.START_PROCESS (PT(RUNNING));
        end if;
    end loop;
end;


procedure IDLE  is
    -- this procedure is called when there are no ready processes to run
begin
    RUNNING := NO_PROCESS;

    if BLOCKED_COUNT = 0 then
        STOP;
    else
        SLEEP;
    end if;
end;


procedure SAVE_STATE  (D : in out PROCESS_DATA) is
    -- this procedure is called when a process is preempted during a timer
    -- interrupt
    SAIL_REG_SAVE : REGISTER_SET;
    SAIL_PC_SAVE  : INTEGER;
    for SAIL_REG_SAVE use at 16;
    for SAIL_PC_SAVE use at 87;
begin
    D.REG := SAIL_REG_SAVE;
    DEC10'(HRRZ, 1, (ADDRESS, SAIL_PC_SAVE));
    D.PC := R1;
end;


procedure STARTUP (D : PROCESS_DATA) is
begin
    CPU.DISABLE;
    UUO'(OP => DEBREAK);
    CPU.START_PROCESS (D);
end;
```

```
    procedure START_PROCESS (D : PROCESS_DATA) is
    begin
        RUNNERS_TICKS := 0;
        R0 := D.PC;
        DEC10'(MOVEM, 0, (LABEL, "XFER", 1));
        DEC10'(MOVSI, 0, (ADDRESS, INTEGER'(D.REG)));
        DEC10'(BLT, 0, (REG, 15));
        UUO'(INTDEJ, (LABEL, "XFER", 0));
        FAIL_LABEL'("XFER", (VALUE, -1));
        DIRECTIVE'(BLOCK, (VALUE, 1));
    end;


    procedure SAVE_CONTEXT (D : in out PROCESS_DATA) is
        -- this procedure must be called 3 dynamic links away from the
        -- stack frame of the caller of the kernel
    begin
        DEC10'(HLRZ, 1, (INDEX, 0, 14))-- get caller's saved return address
        DEC10'(HLRZ, 1, (INDEX, 0, 1))-- by following dynamic links
        DEC10'(HRRZ, 0, (INDEX, 0, 1));
        D.PC := R0;
        DEC10'(HLRZ, 0, (INDEX, 0, 1))-- get caller's dynamic link
        D.REG(SP) := R0;
        D.REG(TOP) := R1 - 1;          -- save caller's top of stack pointer
    end;
end CPU;



procedure DO_WAKEUPS is
    i : PT_INDEX := DELAYQ.FIRST;    j : PT_INDEX;
begin
    while i /= NO_PROCESS loop
        declare PCB : PROCESS_DATA renames PT(i); begin

            PCB.DELAY_TIME := PCB.DELAY_TIME - 1;
            if PCB.DELAY_TIME <= 0 then
                j := i;    i := PCB.PRIOR;
                Q.DELETE (DELAYQ, j);
                Q.INSERT (READYQ, j);
                BLOCKED_COUNT := BLOCKED_TIME - 1;
            else
                i := PCB.PRIOR;
            end if;
        end;
    end loop;
end;



interrupt TIMER_INTERRUPT called from 0 is
    i : PT_INDEX;
begin
    DO_WAKEUPS;

    if RUNNING /= NO_PROCESS then
```

```
            RUNNERS_TICKS := RUNNERS_TICKS + 1;
            if not Q.EMPTY(READYQ) and then
                (RUNNERS_TICKS > TIME_SLICE or
                PT(Q.FIRST(READYQ)).PRIORITY > PT(RUNNING).PRIORITY) then
                CPU.SAVE_STATE (PT(RUNNING));
                PT(RUNNING).STATUS := READY;
                Q.REMOVE(READYQ, 1);
                Q.INSERT(READYQ, RUNNING);
                RUNNING := 1;
                PT(1).STATUS := RUN;
                CPU.STARTUP (PT(1));
            end if;
        end if;
    end TIMER_INTERRUPT;


    scheduler body S is

        procedure ENTER is
        begin
            CPU.DISABLE;
        end;

        procedure LEAVE is
        begin
            CPU.ENABLE;
        end;
    end S;


    begin
        PT(MAIN_PROGRAM) := (NAME          => PROCESSNAME'(1),
                             STATUS        => RUN,
                             PC            => 0,
                             REG           => (others => 0),
                             PRIORITY      => MAIN_PRIORITY,
                             DELAY_TIME    => 0,
                             NEXT | PRIOR  => NO_PROCESS);

        for i in PRIORITY loop
            READYQ(i).FIRST := NO_PROCESS;
        end loop;

        DELAYQ.FIRST := NO_PROCESS;

        for i in PT_INDEX'FIRST + 2 .. PT_INDEX'LAST - 1 loop
            PT(i).NEXT := i + 1;
            PT(i).NAME := null;
        end loop;
        PT(PT_INDEX'LAST).NEXT := NO_PROCESS;
        PT(PT_INDEX'LAST).NAME := null;
        CPU.ENABLE;
        UUO'(CLKINT, (VALUE, TICK_LENGTH));          -- enable timer interrupts
    end SUPERVISOR;
```

APPENDIX G: ADA MULTITASKING TRANSLATION EXAMPLE.

This appendix presents an example of techniques used in translating the multitasking constructs of Ada into Adam. Various algorithms for such translation are being developed and are described in detail in [9].

Tasking in Ada provides a very general, expressive, and elegant means of designing parallel systems. However, because of their generality, the high level tasking constructs of Ada pose a significant challenge for language implementers. Much concern has been expressed about the efficiency and even possibility of implementing the full multitasking capabilities of Ada. The multiprocessing constructs of Adam, on the other hand, are much lower level than those of Ada and create no major compilation difficulty. Hence, by developing implementations of Ada tasking in Adam the problem a Ada multitasking may be readily identified and studied. Automation of the algorithms will permit testing and comparing performance of implementations which use different execution, scheduling, and resource allocation schemes. Also, the algorithms may be used with the existing Adam compiler to produce a two-step compiler for Ada tasking.

The essential step of the translation algorithms is to transform the components of an Ada multitasking system into corresponding elements of an Adam system. Any Ada task which does not have visible entries is transformed into an Adam process. Ada tasks with entries, which we term "service tasks", are translated into both a process and a scheduled module in Adam. This division of the service task into two parts separates the truly independent thread of control of the task from the synchronization and inter-task communication functions of the task.

The example below presents the general form of translation for a very simple Ada task system, a buffer and two user tasks. In Ada, such a system might appear as follows:

```
task CHARACTER_BUFFER is
    entry PUT_CHAR (C : in  CHARACTER);
    entry GET_CHAR (C : out CHARACTER);
end CHARACTER_BUFFER;

task body CHARACTER_BUFFER is
    MAX     : constant INTEGER := 200;

    subtype BUFFER_POINTER is INTEGER range 0 .. MAX;

    BUFFER  : array(1 .. MAX) of CHARACTER;
    IN_PTR  : BUFFER_POINTER := 1;
    OUT_PTR : BUFFER_POINTER := 0;
begin
    loop
        select
            when IN_PTR /= OUT_PTR =>
                accept PUT_CHAR (C :in  CHARACTER) do
                    BUFFER(IN_PTR) := C;
                end PUT_CHAR;
                IN_PTR := IN_PTR mod MAX + 1;
```

```
                if OUT_PTR = 0 then
                    OUT_PTR := 1;
                end if;
        or
            when OUT_PTR =/ 0 =>
                accept GET_CHAR (C : out CHARACTER) do
                    C := BUFFER(OUT_PTR);
                end GET_CHAR;
                OUT_PTR := OUT_PTR mod MAX + 1;
                if OUT_PTR = IN_PTR then
                    OUT_PTR := 0; IN_PTR := 1;
                end if;
        end select;
    end loop;
end CHARACTER_BUFFER;

task PRODUCER;                      -- the body of PRODUCER contains calls to
                                    -- CHARACTER_BUFFER.PUT

task CONSUMER;                      -- the body of CONSUMER contains calls to
                                    -- CHARACTER_BUFFER.GET
```

One algorithm used for translation of Ada tasking uses procedure call to implement the user task/service task rendezvous. In this scheme, the calling task executes the body of the accept and awakens the service task at completion of the rendezvous to perform scheduling and internal actions.

```
scheduled module CHARACTER_BUFFER is
    procedure PUT_CHAR (C : in  CHARACTER);
    procedure GET_CHAR (C : out CHARACTER);
    procedure NEW_PROCESS_ENTRY;    -- this procedure corresponds to the separate
                                    -- thread of control of the service task
end CHARACTER_BUFFER;

scheduled module body CHARACTER_BUFFER is
    MAX      : constant INTEGER := 200;

    subtype BUFFER_POINTER is INTEGER range 0 .. MAX;

    BUFFER  : array(1 .. MAX) of CHARACTER;
    IN_PTR  : BUFFER_POINTER := 1;
    OUT_PTR : BUFFER_POINTER := 0;

    type ENTRY_NAME is (PUT_CHAR, GET_CHAR);
    subtype SYNCHRONIZATION_LEVEL is INTEGER range 1 .. 3;
    SL : SYNCHRONIZATION_LEVEL;     -- this variable is used to track which accept
                                    -- or select statement is being executed

    scheduler BUFFER_SCHED is
        imports (IN_PTR, OUT_PTR : in; SL : in out);
        procedure ENTER (E : in ENTRY_NAME);
        procedure COMMON_EXIT;
        procedure AWAIT;
    end BUFFER_SCHED;
```

```
procedure PUT_CHAR (C : in CHARACTER) is
    scheduling (ENTER (PUT_CHAR), COMMON_EXIT);
begin
    BUFFER(IN_PTR) := C;        -- executed by the calling process
end PUT_CHAR;

procedure GET_CHAR (C : out CHARACTER) is
    scheduling (ENTER (GET_CHAR), COMMON_EXIT);
begin
    C := BUFFER(OUT_PTR);       -- executed by the calling process
end GET_CHAR;

procedure NEW_PROCESS_ENTRY  is
begin
    loop                        -- executed by the thread of control of
                                -- the buffer
        SL := 1;
        BUFFER_SCHED.AWAIT;     -- schedule entry calls and suspend
                                -- until entry call is complete
        case SL is              -- current value of SL determines
                                -- which call was accepted
            when 2 => IN_PTR := IN_PTR mod MAX + 1;
                      if OUT_PTR = 0 then
                          OUT_PTR := 1;
                      end if;
            when 3 => OUT_PTR := OUT_PTR + 1;
                      if OUT_PTR = IN_PTR then
                          OUT_PTR := 0; IN_PTR := 1;
                      end if;
            when others => null;
        end case;
    end loop;
end NEW_PROCESS_ENTRY;

-- NOTE: the bodies of the visible procedures above contain the translation of
-- the Ada source statements; the scheduler procedures below contain the
-- implementation of scheduling and mutual exclusion for entry calls which would
-- be provided by the compiler in an implementation of Ada.

scheduler body BUFFER_SCHED is
    PROTECTION  : LOCK;         -- mutual exclusion in module scheduling
    BUSY        : BOOLEAN := TRUE;-- whether module is in use
    ENTRY_OPEN  : array(ENTRY_NAME) of BOOLEAN:  -- which entries open
    ENTRY_Q     : array(ENTRY_NAME) of CONDITION;-- queues for names
                                                 -- of calling processes
    BUFFER_NAME : PROCESSNAME;-- internal name for thread of control
                              -- of the buffer

    procedure ENTER (E : in ENTRY_NAME) is
    begin
        SET (PROTECTION);
        if BUSY or else not ENTRY_OPEN(E) then   -- module is in use
```

```
                INSERT (ENTRY_Q(E), MYNAME());  -- or guard is false
                RESET (PROTECTION);             -- so calling process
                SUSPEND;                        -- suspends itself
            else
                BUSY := TRUE;           -- call is accepted so set module
                RESET (PROTECTION);     -- in use
            end if;
            case E is
                when PUT_CHAR =>
                    SL := 2;        -- Put call is being accepted
                when GET_CHAR =>
                    SL := 3;        -- Get call is being accepted
            end case;
        end ENTER;

        procedure COMMON_EXIT is
        begin
            ACTIVATE (BUFFER_NAME);-- Activate thread of control of buffer
        end COMMON_EXIT;

        procedure AWAIT is
            NEXT : PROCESSNAME;
        begin
            SET (PROTECTION);       --wait for protection on scheduling
            BUFFER_NAME := MYNAME(); --setup internal name for buffer
            ENTRY_OPEN  := (IN_PTR /= OUT_PTR, OUT_PTR /= 0);
            BUSY := FALSE;          --anticipate module not busy
            for E in ENTRY_NAME'FIRST .. ENTRY_NAME'LAST loop
                if ENTRY_OPEN(E) and then not EMPTY (ENTRY_Q(E)) then
                    case E is
                        when PUT_CHAR =>
                            SL := 2;    -- Put call is being accepted
                        when GET_CHAR =>
                            SL := 3;    -- Get call is being accepted
                    end case;
                    REMOVE (ENTRY_Q(E), NEXT); --remove next caller from queue
                    BUSY := TRUE;  --set module is busy
                    ACTIVATE (NEXT); -- and activate
                    exit;
                end if;
            end loop;
            RESET (PROTECTION);     -- release scheduling protection
            SUSPEND;                -- and suspend
        end AWAIT;

    end BUFFER_SCHED;

end CHARACTER_BUFFER;

process NEW_PROCESS is              -- this process is the separate thread
```

```
                                        -- of control of the buffer
    channels CHARACTER_BUFFER;
end NEW_PROCESS;

process body NEW_PROCESS is
begin
    CHARACTER_BUFFER.NEW_PROCESS_ENTRY;
end NEW_PROCESS;


process PRODUCER is
    channels CHARACTER_BUFFER;      -- the body of PRODUCER contains calls to
                                    -- CHARACTER_BUFFER.PUT_CHAR
end PRODUCER;

process CONSUMER is
    channels CHARACTER_BUFFER;      -- the body of CONSUMER contains calls to
                                    -- CHARACTER_BUFFER.GET_CHAR
end CONSUMER;
```

Note that the scheduling used for calls to the CHARACTER_BUFFER will accept PUT's before GET's whenever the Buffer is not full. This selection scheme is consistent with the specification of Ada, which only requires that the choice among open alternatives be "performed arbitrarily". In general, however, identification of an optimal selection scheme depends on the global semantics of a program, so it is not possible to make such an identification in the syntax directed translation used with the Adam compiler. The method of selection implemented in Ada to Adam translation utilizes a pseudorandom number generator to make a choice among the open aternatives. Thus, the general implementation of select is random, which is also consistent with the Ada requirement for arbitrariness.

APPENDIX H: COMPILER COMMANDS.

This appendix briefly describes a compiler we have implememented for Adam. The compiler is written in Maclisp, runs on a PDP-10, and produces PDP-10 assembly language code. The compiler is interactive. It accepts commands from the terminal user to compile files, manipulate libraries, etc. It has three phases: a parser which constructs an abstract syntax tree, a phase which does static semantic checking, and a code generation phase. The parser is constructed by an SLR parser generation system.

The compiler supports the Ada separate compilation facility. A compilation consists of a library file and a set of compilation units. A compilation unit can be a module specification, module body, subprogram body, or module body subunit. The main program is designated by having a subprogram body compilation unit with the name MAIN, or by having a subprogram body compilation unit which has the pragma MAIN in its outermost declarative part. Compilation units can refer to units already in the library and the new units in a compilation will be added to the library or replace old units with the same name in the library. The compiler has commands to create libraries, open and close libraries, list the table of contents of libraries, etc.

1. Compiler Commands.

The compiler is invoked by typing:

```
r adam
```

The compiler prints a prompt and waits for a command to be typed.

A command to the compiler consists of a command name, or a command name followed by a list of arguments. All commands are terminated by a semicolon. Arguments are separated by commas. After a command has been executed another prompt is printed and another command can be typed.

When the compiler is initially invoked, all file operations will be defaulted to the job's current directory. The defaults for various kinds of file operations can be changed by the following commands.

`Alias <dir>;` - will change the default directory for all operations to `<dir>`.

`Input <dir>;` - will change the default directory for source program input to `<dir>`.

`Output <dir>;` - will change the default directory for any output which the compiler generates to `<dir>`.

`Libdir <dir>;` - will change the default directory for library related i/o to `<dir>`.

where <dir> has the form <directory-name> on TOPS-20 or p, pn on SAIL WAITS.

```
Quit;          - terminates the compiler.
Help;          - prints a list of the available commands.
```

2. Compiling a Source File.

Before any source file is compiled a library must be opened. See section on libraries for how to do this.

To compile a source file, which is in the file, name.ada, the command is:

```
Compile name;
```

This has the following effect. The file is opened and the program is parsed. If there is a syntax error the compiler returns to the command level. If there are no syntax errors the static semantic checking is done. If there are semantic errors, messages will be written to the terminal and also to a file called name.err. The compilation units in the source file will be inserted into the open library. If there are no semantic errors code generation is done. The compiler generates a file of Fail source code called name.fal.

To run a main program which is in the currently open library, the command is:

```
Execute main-program-name;
```

This command tests for completion of the the compilation tree rooted at the main program. If it is complete a do file is created with commands to link and run the program, the compiler terminates.

The command:

```
Compile;
```

will recompile the most recently compiled file from the current compilation session.

3. Separate compilation and libraries.

A library consists of a set of compilation units. The information recorded for a compilation unit in a library includes: Its name, the kind of unit it is, the name of the source file it came from, the name of the file to which code was generated for it, the time and date it was compiled, its with requirements of other units in the library, and a copy of the abstract syntax tree for the unit. For non-generic units an abstract syntax tree for the

specification part is kept. For generic units the abstract syntax tree for the entire unit is retained.

All library operations during a compilation session are done with respect to the currently open library.

Commands for libraries.

To create a new library the command is:

```
Create name;        -- this creates a file name.lib
                    -- in the default library directory
```

To open an existing library the command is:

```
Open name;          -- looks for name.lib in the default library
                    -- directory and opens it if found
```

To close the currently open library the command is:

```
Close;
```

A quit command will also close any open library.

To copy a library unit from some library to the currently open library the command is:

```
Copy libraryname.unitname;
```

Example:

```
Open mylib;         -- open an existing library
Copy io.tty_io;     -- copy a tty I/o module called tty_io from the
                    -- library io to the library mylib
```

The following commands can be applied to an open library.

```
Dir;                -- list the table of contents of the library
Tdir;               -- list times when units were compiled
Fdir;               -- list the files from which units came and were compiled into
Wdir;               -- list the 'with' requirements of the units in the library

Remove unitname;    -- remove the named unit from the library.
```

An example of a command sequence to create a library of utility modules:

```
.r adam
...                 -- compiler prints signon message and a prompt
-> create util;     -- create and open a new library named util.lib
-> compile util;    -- compiles a file of units from the source
                    -- file util.ada
                    -- generates code to a file named util.fal
Adding STACK to the library  -- compiler comments
Adding RAT_NUMBERS to the library
```

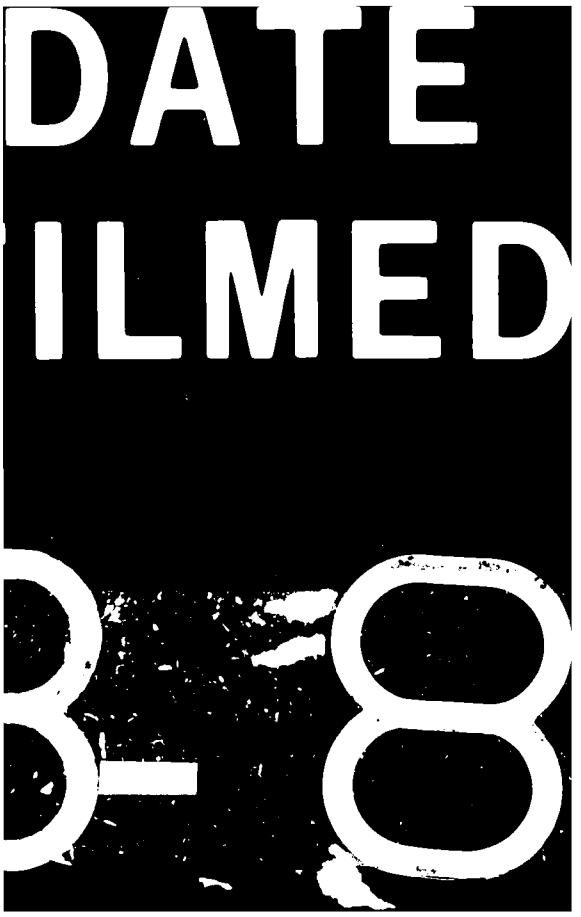
```
-> close;              -- close the library
-> quit;               -- terminate the compiler
```

At a later compilation session one can type:

```
...
-> open util;          -- open an existing library
-> dir;                -- see what's in it

module STACK ...
module RAT_NUMBERS ...

-> compile foo;        -- compile some file that uses units in the library
-> open mylib;         -- open some other library, closes util
-> compile bar;        -- compile some other file
-> quit;               -- close any open library and terminate
```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