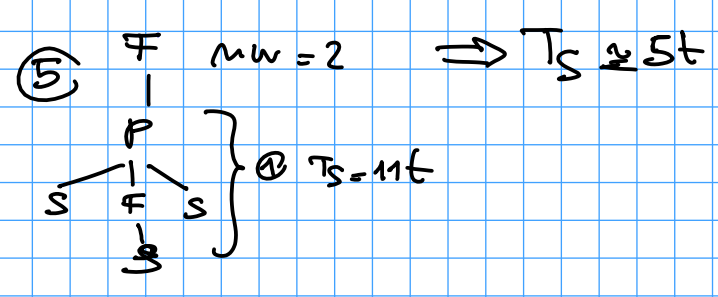
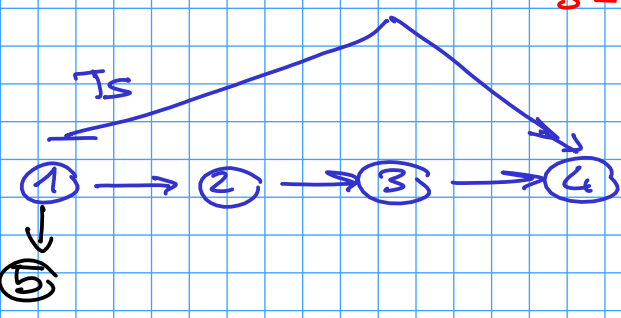
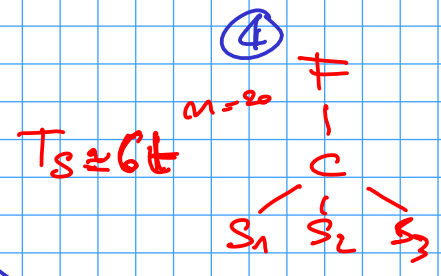
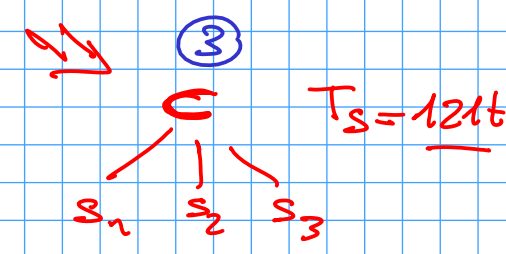
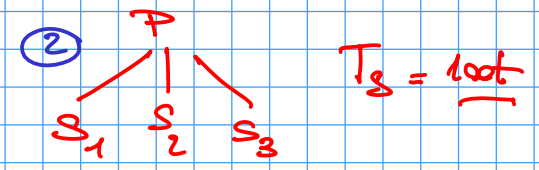


$T_S = \max \left\{ 10t, \frac{100t}{10}, 11t \right\} = 11t$



Behavioral Skeletons

Concerns (for programming)

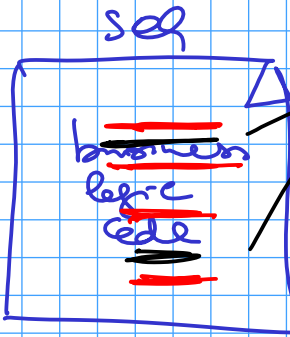
MAIN: Performance (T_{goal})

POWER: watts

battery →
cots →

FAULT TOLERANCE
("RESILIENCE")

SECURITY

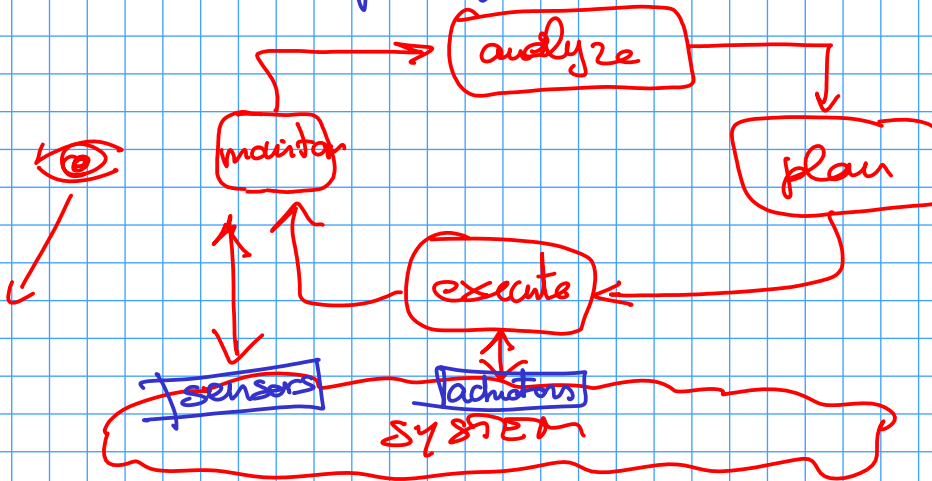


deal with
non functional
concerns

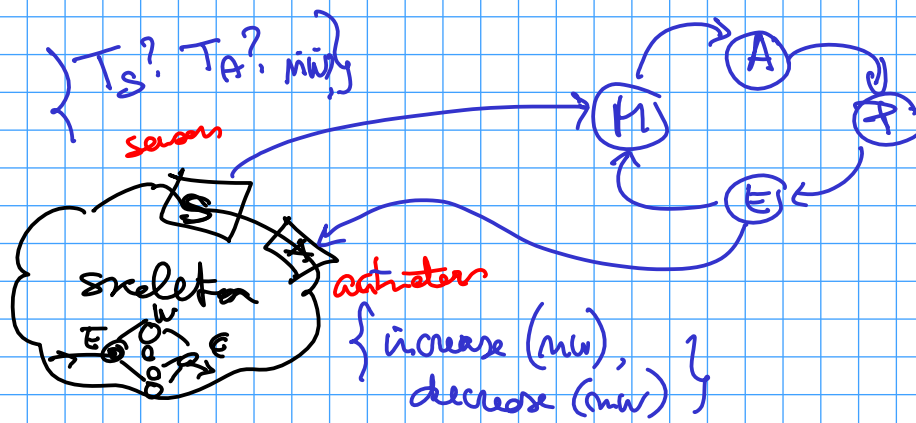
code to exploit
parallelism

Autonomic computing

autonomic control
loop



self*



Abstract "engine"

↑

{rules}

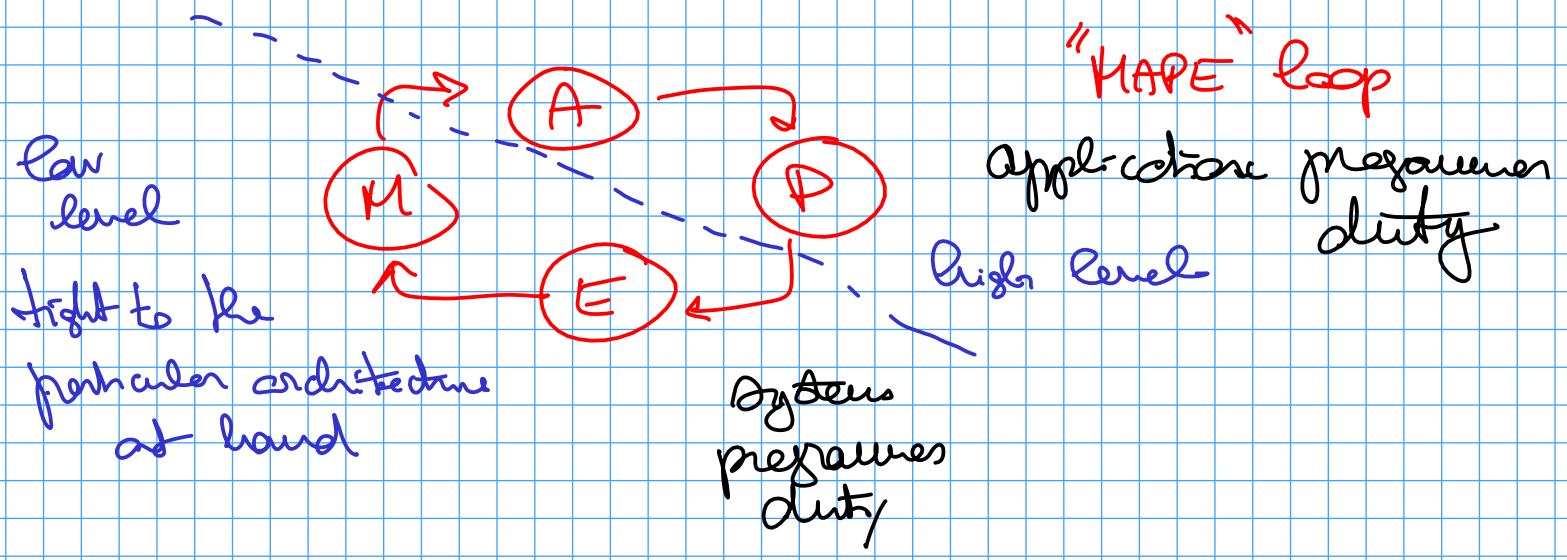
managing a particular functional concern

ECA rules Event Condition

When any of $\{T_A, T_s, T_w\}$ changes... then Action

(P1) IF $(T_A < T_s)$ && $(\frac{T_w}{m_w} > \max\{t_e, t_c\})$
 then increase (m_w) ;

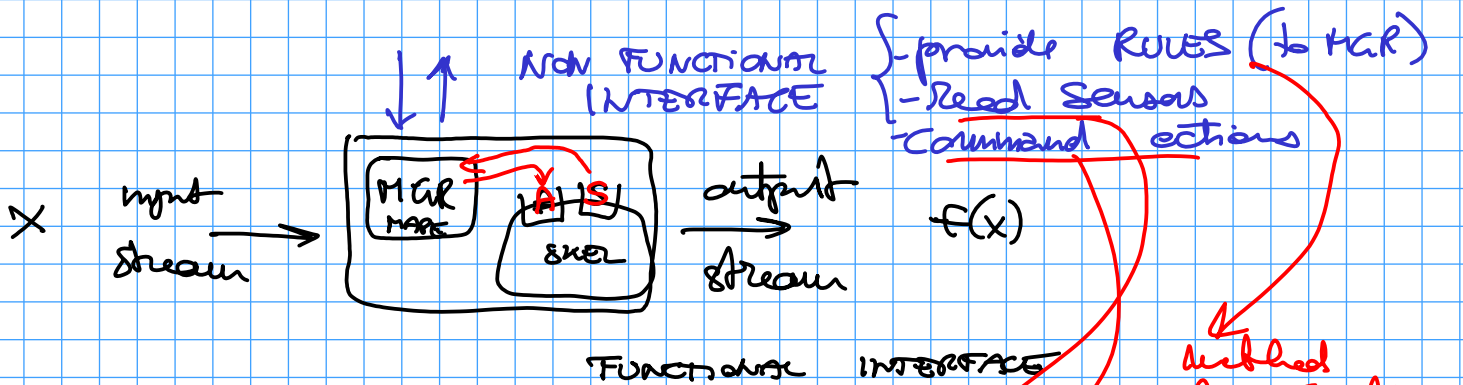
(P2) IF $(T_A >> T_s)$ then decrease (m_w) ;



EU Project → NOE CAREGRID (44 members) ↓

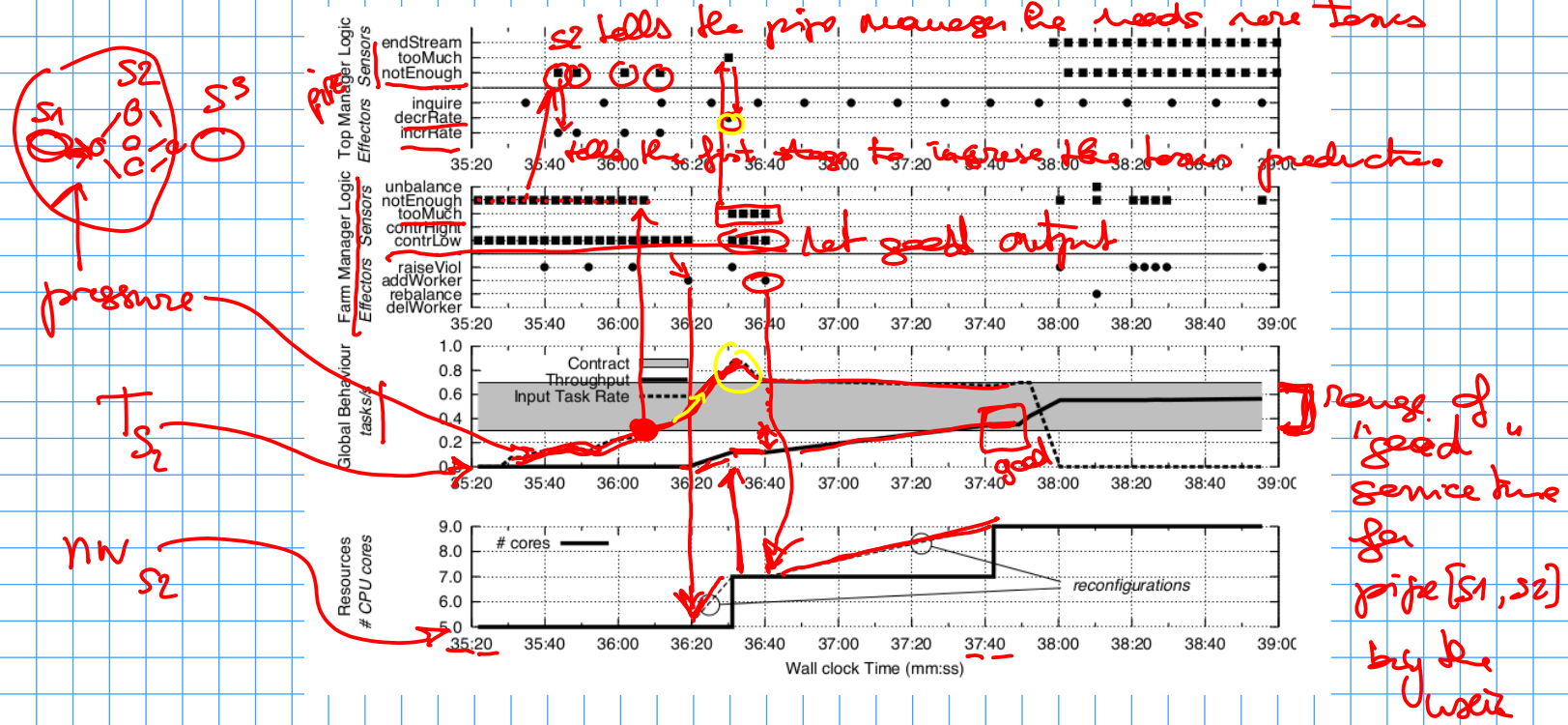
EU STREP
GRIDCOMP (9 members)

REACTIVE ← BEHAVIOURAL SKELETON CONCEPT
↓
BS on JAVA

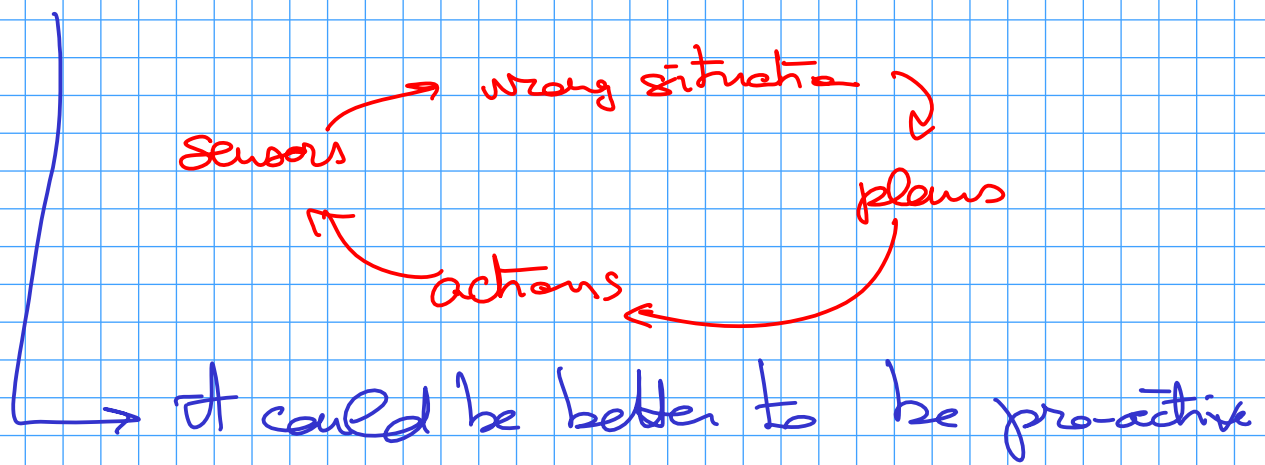


have to be exposed in such a way the component may be used within other components

disabled changing the "central program" of the skeleton (BS)



① the system is reactive



② single-concern

