RTI Shapes Demo

A Demonstration of RTI Data Distribution Service

User's Manual

Version 2.0

The Global Leader in DDS

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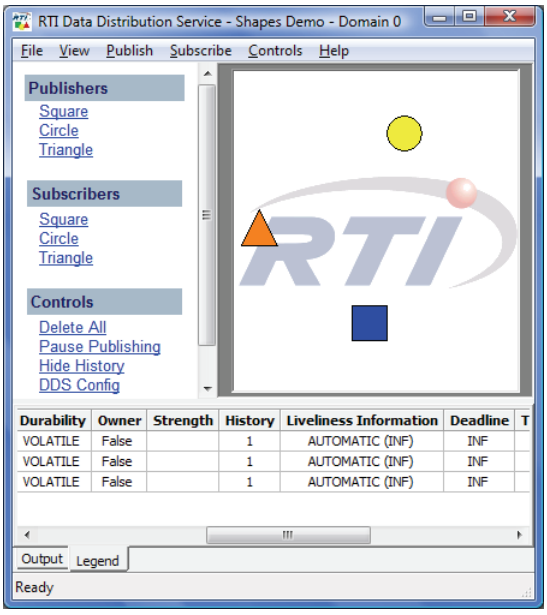
Chapter 1 Introduction

Welcome to the *RTI Shapes Demo*! This demonstration application is a self-contained introduction to the elegance and power of publish-subscribe networking. It goes beyond simple publishing and subscribing, however. This demo will also give you a glimpse of the goals and capabilities of RTI's implementation of the Object Management Group (OMG) Data Distribution Service (DDS) standard. This DDS standard is the first standard directly addressing the challenge of extremely-high-performance distributed networking. As you will see, the DDS standard offers flexibility, performance, and reliability well beyond other networking technologies.

RTI Data Distribution Service and the OMG DDS standard offer flexible and fine-grain control over Quality of Service (QoS) parameters. No one application can showcase all the supported QoS parameters. *RTI Shapes Demo* is intended to provide you with an abbreviated introduction to OMG DDS concepts; it covers a small subset of the many QoS parameters available in *RTI Data Distribution Service*.



RTI Shapes Demo publishes and subscribes to (writes and reads) colored moving shapes, which are displayed in the demo's window. Each copy of *RTI Shapes Demo* can simultaneously publish and subscribe to many topics (shapes).

1.1 Guide to this Document

This document will guide you through the demonstration, the middleware, and the underlying principles.

- Goals of the Demonstration (Section 1.2) below outlines the concepts and goals of this demonstration.
- Chapter 2: Background Information provides an overview of publish-subscribe and other communication paradigms. It also provides an overview of the DDS standard and its key concepts.
- Chapter 3: Installing and Using the Demo details the features of the demonstration application.
- Chapter 4: Examples jumps right into using the application and playing with examples. Feel free to start here if you are familiar with publish-subscribe networking.
- Chapter 5: About Real-Time Innovations (RTI) describes RTI products and where to seek further information.
- Appendix A explains how to run from the command line.
- Appendix B provides instructions for running a dynamic-library version of *RTI Shapes Demo*.
- Appendix C contains a few troubleshooting hints.

1.2 Goals of the Demonstration

There is no teacher like experience. Playing with this demonstration will give you a first-hand introduction to the key concepts behind the DDS standard. These include:

- **Anonymous publish-subscribe**

  Applications communicating over publish subscribe networks do not need to know the source or destination of the data. This loosely-coupled design simplifies (or eliminates) configuration, eases fault tolerance, and boosts performance.

- **Dynamic discovery**

  With publish subscribe, applications simply ask for the information they need and provide the information they have. The middleware does the hard task of

finding the information and delivering it where it needs to go. There is no (or minimal) configuration; each node can simply join or leave the network at any time.

- **Failover**

  The DDS standard supports the concept of "ownership"; a publisher can own the responsibility for providing data to the network. Ownership makes failover simple; if the owner fails, a backup owner can instantly take over responsibility

- **Failure notification**

  The DDS standard is designed for the real world. In the case of failure, e.g., the violation of a deadline or the termination of service, interested applications are immediately notified.

- **DDS advanced concepts**

  If you are interested in exploring the demo more extensively, this document also briefly illustrates additional use cases such as content-filtered topics, reliability, durability and time-based filtering.

Chapter 2 Background Information

This section provides an overview of existing middleware communication paradigms, including publish-subscribe, along with details of the OMG DDS standard.

If you are already familiar with this information, you can go directly to Chapter 3: Installing and Using the Demo.

2.1 Communication Models in Networking Middleware

Software applications are becoming increasingly distributed. A node in a distributed application must find the right data, know where to send it, and deliver it to the right place at the right time. Simplifying access to this data would enable a whole new class of distributed applications. The challenge, especially in embedded and real-time networks, is to quickly find and disseminate information to many nodes.

Three major middleware communication paradigms have emerged to meet this need: client-server, message passing, and publish-subscribe.

Client-server is fundamentally a many-to-one design that works well for systems with centralized information, such as databases, transaction processing systems, and central file servers. However, if multiple nodes generate information, client-server architectures require that all the information be sent to the server for later redistribution to the clients, resulting in inefficient client-to-client communication. The central server is a potential bottleneck and single-point of failure. It also adds an unknown delay (and therefore indeterminism) to the system, because the receiving client does not know when it has a message waiting.

Message-passing architectures work by implementing queues of messages. Processes can create queues, send messages, and service messages that arrive. This extends the

many-to-one client-server design to a more distributed topology. Message passing allows direct peer-to-peer connection; it is much easier to exchange information between many nodes in the system with a simple messaging design. However, the message-passing architecture does not support a data-centric model. Applications have to find data indirectly by targeting specific sources (e.g., by process ID or "channel" or queue name) on specific nodes. So, this architecture doesn't address how applications know where a process/channel is, what happens if that process/channel doesn't exist, etc. The application must determine where to get data, where to send it, and when to perform the transaction. In the message-passing architecture, there is a model of the means to transfer data but no real model of the data itself.

Publish-subscribe adds a data model to messaging. Publish-subscribe nodes simply "publish" information they have and "subscribe" to data they need. Messages logically pass directly between the communicating nodes. The fundamental communications model implies both discovery (i.e. what data should be sent) and delivery (i.e. when and where to send the data). This design mirrors time-critical information delivery systems in everyday life (e.g. television, radio, magazines and newspapers). Publish-subscribe systems are good at distributing large quantities of time-critical information quickly, even in the presence of unreliable delivery mechanisms.

Publish-subscribe architectures map well to the real-time communications challenge. Finding the right data is straight forward; nodes just declare their interest once and the system delivers it. Sending the data at the right time is also natural; publishers send data when the data is available. Publish-subscribe can be efficient because the data flows directly from source to destination without requiring intermediate servers. Multiple sources and destinations are easily defined within the model, making redundancy and fault tolerance natural. Finally, the intent declaration process provides an opportunity to specify per-data-stream Quality of Service (QoS), requirements. Properly implemented, publish-subscribe middleware delivers the right data to the right place at the right time.

In summary, client-server middleware is best for centralized data designs and for systems that are naturally service oriented, such as file servers and transaction systems. Client-server middleware is not the best choice in systems that entail many, often-poorly-defined data paths. Message passing, with "send that there" semantics, map well to systems with clear, simple dataflow needs. Message passing middleware is better than client-server middleware at free-form data sharing, but still require the application to discover where data resides. Publish-subscribe, by providing both discovery and messaging, implements a data centric information distribution system. Nodes communicate simply by sending the data they have and asking for the data they need.

2.2 The DDS Model

The Object Management Group (OMG) Data Distribution Service (DDS) standard is the first comprehensive specification available for "publish-subscribe" data-centric designs. The DDS publish-subscribe model connects anonymous information producers (publishers) with information consumers (subscribers). The overall distributed application is composed of processes called "participants," each running in a separate address space, possibly on different computers. A participant may simultaneously publish and subscribe to typed data-streams identified by names called "Topics." The interface allows publishers and subscribers to present type-safe API interfaces to the application.

The DDS standard defines a communications relationship between publishers and subscribers. The communications are decoupled in space (nodes can be anywhere), time (delivery may be immediately after publication or later), and flow (delivery may be reliably made at controlled bandwidth). To increase scalability, topics may contain multiple independent data channels identified by "keys." This allows nodes to subscribe to many, possibly thousands, of similar data streams with a single subscription. When the data arrives, the middleware can sort it by the key and deliver it for efficient processing.

The DDS standard is fundamentally designed to work over unreliable transports, such as UDP or wireless networks. No facilities require central servers or special nodes. Efficient, direct, peer-to-peer communications, or even multicasting, can implement every part of the model.

2.2.1 Quality of Service

Fine control over Quality of Service (QoS) is perhaps the most important feature of the DDS standard. Each publisher-subscriber pair can establish independent QoS agreements. Thus, DDS designs can support extremely complex, flexible data-flow requirements.

QoS parameters control virtually every aspect of the DDS model and the underlying communications mechanisms. Many QoS parameters are implemented as "contracts" between publishers and subscribers; publishers offer and subscribers request levels of service. The middleware is responsible for determining if the offer can satisfy the request, thereby establishing the communication or indicating an incompatibility error. Ensuring that participants meet the level-of-service contracts guarantees predictable operation. More information about some important QoS parameters is presented below.

Deadline Periodic publishers can indicate the speed at which they can publish by offering guaranteed update deadlines. By setting a deadline, a compliant publisher promises to send a new update at a minimum rate. Subscribers may then request data at that or any slower rate.

Reliability Publishers may offer levels of reliability, parameterized by the number of past issues they can store for the purpose of retrying transmissions. Subscribers may then request differing levels of reliable delivery, ranging from fast-but-unreliable "best effort" to highly reliable in-order delivery. This provides per-data-stream reliability control.

Strength The middleware can automatically arbitrate between multiple publishers of the same topic with a parameter called "strength." Subscribers receive from the strongest active publisher. This provides automatic failover; if a strong publisher fails, all subscribers immediately receive updates from the backup (weaker) publisher.

Durability Publishers can declare "durability," a parameter that determines how long previously published data is saved. Late-joining subscribers to durable publications can then be updated with past values.

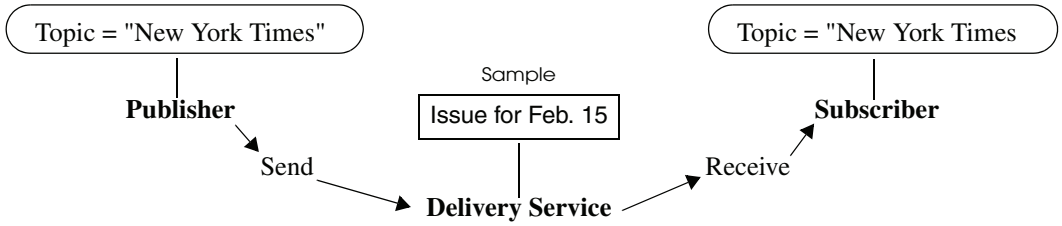
Other QoS parameters control when the middleware detects nodes that have failed, suggest latency budgets, set delivery order, attach user data, prioritize messages, set resource utilization limits, partition the system into namespaces, and more. The DDS QoS facilities offer unprecedented flexibility and communications control.

2.3 Publish-Subscribe Simple Analogy

The publish-subscribe communications model is analogous to that of magazine or newspaper publications and subscriptions. Think of a publication as a newspaper such as New York Times®. The Topic is the name of the periodical ("New York Times"). The type specifies the format of the information (weekly printed magazine or daily newspaper). The user data is the contents (text and graphics) of each sample (weekly or daily issues). The middleware is the distribution service (US Postal service or a paper delivery service) that delivers the reading material from where it is created (a printing house) to the individual subscribers (people's homes). This analogy is illustrated in Figure 2.1.

Note that by subscribing to a publication, subscribers are requesting current and future samples of that publication, so that as new samples are published, they are delivered without having to submit another request for data.

Figure 2.1 **Publish-Subscribe Example**



The publish-subscribe model is analogous to publishing magazines or newspapers. The Publisher sends samples of a particular Topic to all Subscribers of that Topic. With the New York Times®, the Topic would be "New York Times." The sample consists of the data (articles and pictures) sent to all Subscribers daily or weekly. The middleware (RTI Data Distribution Service) is the distribution channel: all of the planes, trucks, and people who distribute issues to the Subscribers.

In this example, Quality of Service (QoS) parameters can be linked to delivery requirements; deliver only the Sunday edition, the paper must be delivered by 7:00am; the paper must be in the mailbox or on the porch, etc. QoS parameters specify where, how, and when the data is to be delivered, controlling not only transport-level delivery properties, but also application-level concepts of fault tolerance, ordering, and reliability.

2.4 Publish-Subscribe Complex Analogy

Above, we drew an analogy between publish-subscribe and a newspaper delivery system. That is, of course, an oversimplification. Complex systems have complex data-delivery requirements. DDS is perhaps more like a picture-in-picture-in-picture super-television system, with each super-TV set capable of displaying dozens or even thousands of simultaneous channels. Super-TV sets can optionally be broadcast stations; each can publish hundreds of channels from locally mounted cameras to all other interested sets. Any set can add new pictures by subscribing to any channel at any time.

Each of these sets can also be outfitted with cameras and act as a transmitting station. TV sets publish many channels, and may add new outgoing channels at any time. Each communications channel, indeed each publisher-subscriber pair, can agree on reliability, bandwidth, and history-storage parameters, so the pictures may update at different rates and record outgoing streams to accommodate new subscribers.

These super-TV sets can also join or leave the network, intentionally or not, at any time. If and when they leave or fail, backup TV set-transmitters will take over their picture streams so no channels ever go blank.

That would be quite a system! It is only an analogy, but we hope this gives you some idea of the enormity of the real-time communications challenge. It also outlines the power of publish-subscribe: as you will see, DDS provides simple parameters to permit all these scenarios with a remarkably simple and intuitive model.

2.5 Publish-Subscribe Example Application

An air traffic control system provides a more realistic example application. An air traffic control system monitors and directs all flights over an entire continent. The data distributed in such a system is in the form of aircraft tracks, which provides positional information (e.g., course, speed, etc.) about an airplane. Components of an air traffic control system would include radar systems, airplanes and air traffic control centers that provide current flight status information through real-time displays.

Managing correct distribution of data in such a system is complex. Each radar system can track many different airplanes, and each airplane may be tracked by more than one radar system. Real-time access to this information is needed for displays at air-traffic control centers so that air traffic controllers can make informed decisions. Air traffic controllers in the north-east may only want aircraft track information in their area, so only a subset of data needs to be provide to them. Based on current local conditions (e.g. air traffic, weather, etc.) air traffic controllers may issue flight plan updates back to airplanes in order to rout around inclement weather and other airplanes. Though airplanes do not need flight plans from all other air planes, it would be useful to have information about planes in the immediate vicinity.

Defining the air traffic control system in terms of publishers, subscribers and QoS parameters reveals that DDS is a natural fit to address this data distribution problem. Each radar system can be thought of as a publisher that publishes the "tracks" topic which describes an airplane's positional information. Each airplane that the radar system is tracking can be thought of as an "instance" of the "track topic. The real-time controller displays are both subscribers that subscriber to the "tracks" topic and publishers that publish "flight plant" topic updates back to the specific airplane. QoS parameters can be used to manage and control deterministic behaviors and fault tolerance capabilities of the system.

Chapter 3 Installing and Using the Demo

3.1 Installation

❑ **On Linux Systems**

The distribution is packaged in a **.tar.gz** file. Unpack it as described below. You do not need to be logged in as root during installation.

1. Create a directory for *RTI Shapes Demo*.
2. Move the downloaded file into your newly created directory.
3. Extract the distribution from the uncompressed files. For example:

```
> tar xvzf RTI_ShapesDemo-<version>.tar.gz
```

❑ **On Windows Systems**

Simply double-click the downloaded file to run the installer.

If you run the installer as Administrator and you want to install *RTI Shapes Demo* for all users, they will need to create their own configuration files by selecting: **Start, Programs, RTI, RTI Shapes Demo <*version*>, Create Configuration File**.

3.2 Running RTI Shapes Demo

You can run *RTI Shapes Demo* on a single computer or on multiple workstations connected via Ethernet. Both Windows and Linux operating systems are supported.

You can start multiple copies of the demo on as many computers as you would like. By default, the demo discovers other demo applications using multicast, loopback, or shared memory. The discovery mechanism is fully configurable.

❑ **On Linux systems**

Enter the following command to run the installer (where *<arch>* is the architecture for your *RTI Shapes Demo* installation; for example, i86Linux2.6gcc4.1.1):

```
> <install directory>/bin/<arch>/rtishapesdemo
```

❑ **On Windows systems**

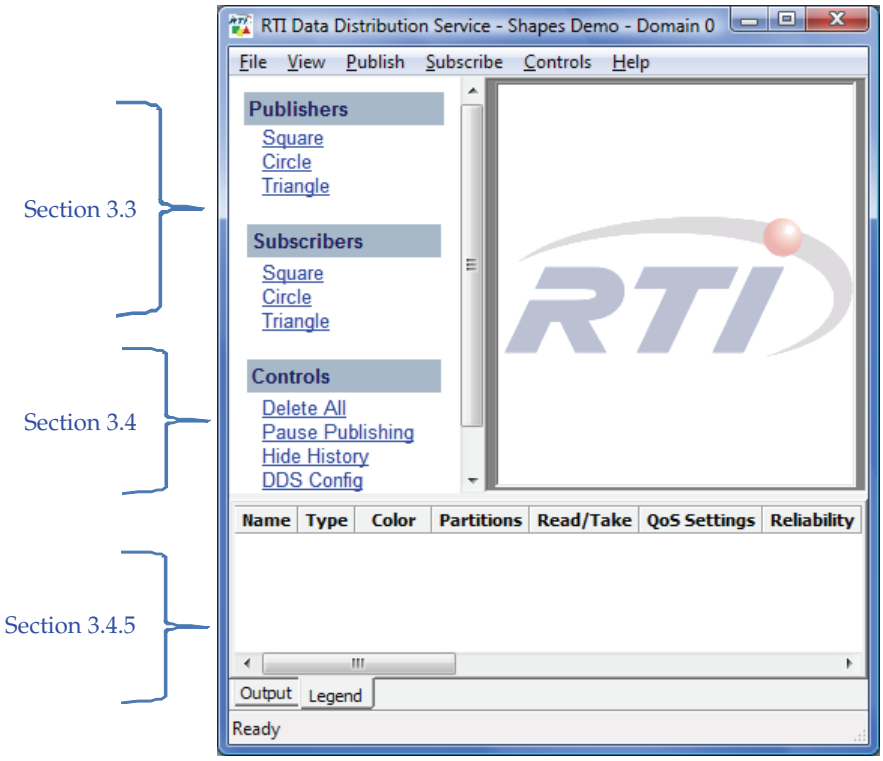
From the Start menu, select **Programs, RTI, RTI Shapes Demo *<version>*, RTI Shapes Demo**.

To start from the command-line, see Appendix A: Running from the Command Line.

Note: *RTI Shapes Demo* is distributed in two versions: static and dynamic. This document refers to the static version unless otherwise noted. To run the dynamic version of *RTI Shapes Demo*, see Appendix B: Using the Dynamic Version.

When *RTI Shapes Demo* starts, you should see a window like that in Figure 3.1.

Figure 3.1 **RTI Shapes Demo—Initial View**

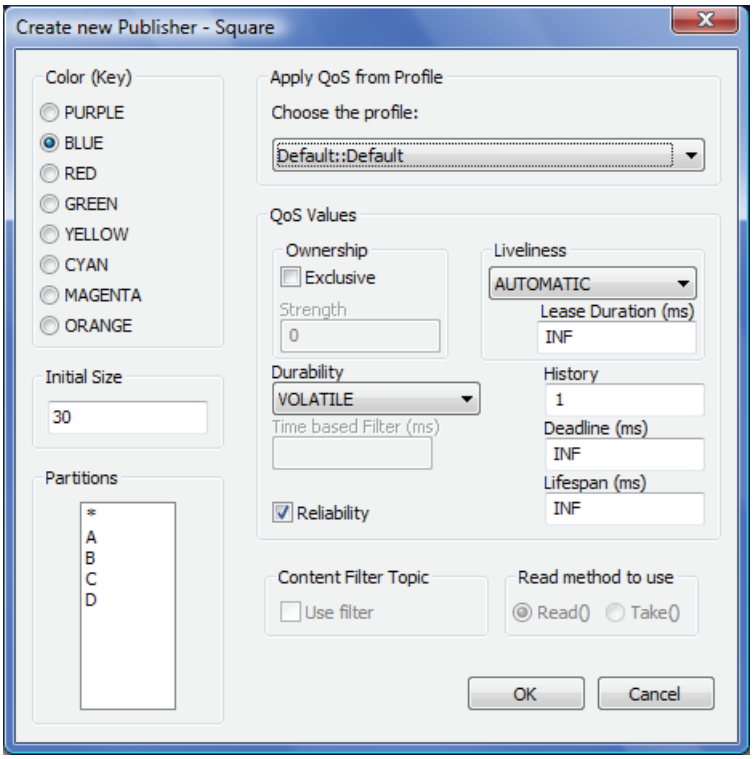


3.3 Publisher and Subscriber Task Panes

DDS applications publish (write) and subscribe to (read) Topics. A Topic has a name and a type; the type defines the structure of the data.

RTI Shapes Demo can publish and subscribe to three Topics: Square, Circle, and Triangle.

Clicking one of these options will open a dialog which allows you to set the QoS for the publisher/subscriber. The same dialog is used for creating a publisher and a subscriber:



3.3.1 Color

Color is selectable only when creating a publisher. You can use color to represent different instances of the same topic (shape).

The Color (key) area is grayed out for subscribers. The subscriber of a topic will receive all data sent on all instances of the topic.

A shape's color is used as a *key*—simply a way to distinguish between data for multiple instances of the same shape (topic). Data that belongs to the same instance in the topic (shape) will have the same key (color).

3.3.2 Initial Size

The “initial size” field allows you to control how big the shape is.

3.3.3 Partitions

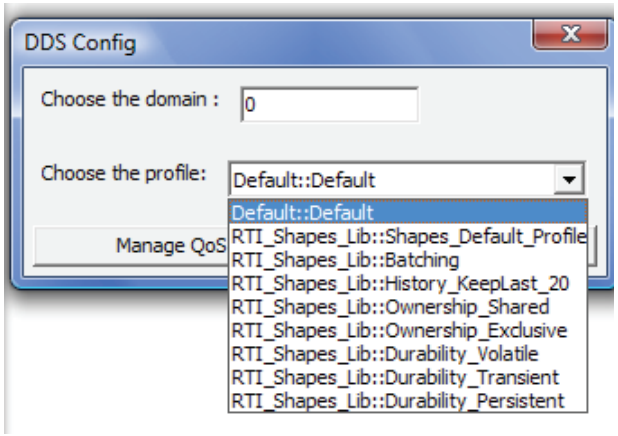
You can use partitions to dynamically isolate and group publishers and subscribers. If a publisher has a partition, then only subscribers with that same partition will receive data from that publisher.

The demo supports four partitions: A, B, C, and D. Partitions support regular expressions, so a publisher with a wildcard (*) partition will match subscribers with partitions A, B, C, and D.

A publisher with no partition (the default case) will not be matched with a subscriber that does have a partition. That is, "no partition" is *not* the same thing as a wild card (*) partition.

3.3.4 Apply QoS from Profile

The drop-down listbox allows you to choose a QoS profile that has been pre-loaded from an XML file using the DDS Dialog Box as explained in Section 3.2.4.



If the listbox contains only **Default::Default**, it means you haven't specified any XML files via the DDS Config dialog (see Section 3.4.4). In this case, **Default::Default** will result in all default QoS settings, as described in the *RTI Data Distribution Service* documentation.

A profile contains the QoS values that will be used for the DDS objects created by the demo. All QoS values not specified in the selected profile will use the default DDS values. Any QoS settings that you make in the Create New Publisher/Subscriber dialog take precedence over the values in the selected profile. (See Setting QoS Values (Section 3.3.5).)

RTI Shapes Demo includes an XML file, **RTI_SHAPES_DEMO_QOS_PROFILES.xml**, which includes these profiles:

- **Default::Default**—This profile means you want to use whichever profile in the XML file is marked as the default (with <qos_profile name="x" is_default_qos="true">). In **RTI_SHAPES_DEMO_QOS_PROFILE.xml**, the default profile is **RTI_Shapes_Lib::Shapes_Default_Profile**.
- **RTI_Shapes_Lib::Shapes_Default_Profile**—This profile sets the *DataWriter's* **autodispose_unregistered_instances**[1] to false and the *DataReader's* History **depth** to keep the last 6 samples.
- **RTI_Shapes_Lib::Batching**—This profile enables best-effort communication in the *DataWriter* and keeps the last 10 samples. It also enables batching with a maximum flush delay of 1 second and allows an unlimited number of bytes to be batched for up to 10 samples.
- **RTI_Shapes_Lib::History_KeepLast20**—This profile sets the *DataReader's* History QoS to keep the last 20 samples.

1. See "Dispose vs. Unregister:" on page 3-15.

- **RTI_Shapes_Lib::Ownership_Shared**—This profile sets Ownership to SHARED and Durability to TRANSIENT with direct communication to true for both the *DataReader* and the *DataWriter*. Both the *DataReader's* and the *DataWriter's* Liveliness is set to AUTOMATIC with a lease duration of 1 second. The *DataReader* has a History depth of 100 samples and is set to RELIABLE.
- **RTI_Shapes_Lib::Ownership_Exclusive**—This profile sets Ownership to EXCLUSIVE for both the *DataReader* and the *DataWriter*. The *DataWriter's* Ownership Strength is set to 4.
- **RTI_Shapes_Lib::Durability_Volatile**—This profile sets Ownership to VOLATILE and History of 100 samples for both the *DataReader* and the *DataWriter*. The *DataReader* is set to be RELIABLE.
- **RTI_Shapes_Lib::Durability_Transient**—This profile sets Ownership to TRANSIENT for both the *DataReader* and the *DataWriter*.
- **RTI_Shapes_Lib::Durability_Persistent**—This profile sets Ownership to PERSISTENT for both the *DataReader* and the *DataWriter*.

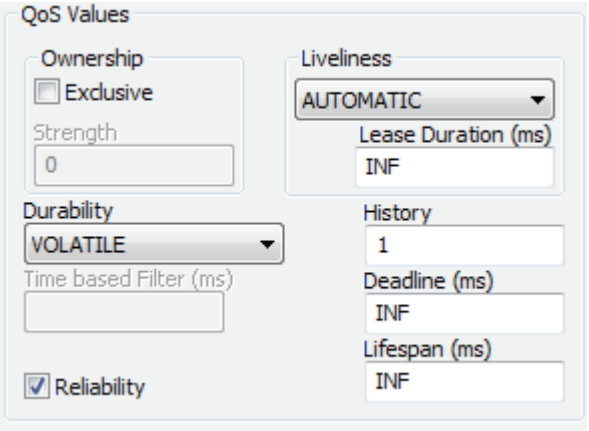
You will find **RTI_SHAPES_DEMO_QOS_PROFILES.xml** in the ***<RTI Shapes Demo installation directory>*** or **My Documents\RTI\RTI Shapes Demo <*version*>**, depending on your operating system.

If you open **RTI_SHAPES_DEMO_QOS_PROFILES.xml**, you can see that the profiles shipped with this demo have the property **base_name**, which points to another profile. That means that the profile will use all the QoS settings of the profile pointed by **base_name**, plus the QoS settings explicitly specified. If a property is specified both in the base profile and in the current profile, the one in the current one is used.

3.3.5 Setting QoS Values

You can control the QoS values for the publisher and subscriber in two ways.

1. You can modify the QoS values in a profile and then apply that profile as described in Section 3.3.4.
2. You can explicitly set some QoS values directly in the Create New Publisher/Subscriber dialog, as seen in this screenshot and described below. Values set in the dialog override values in the profile.



3.3.5.1 Exclusive Ownership and Strength

Ownership determines whether or not the instance (specified by color) of the Topic is exclusively owned by one publisher—that is, if multiple publishers of Red Squares can send data to this instance at the same time or not.

If the "Exclusive" checkbox is selected for a publisher, the Strength box will become available for input. The publisher with the highest Ownership Strength number is the only publisher that can write data to this instance.

If the "Exclusive" checkbox is selected for a subscriber, it means that the subscriber only wants data from one publisher—the one with the highest ownership strength.

The publisher and subscriber must use the same setting, so either check this box for both, or leave it unchecked for both. Otherwise, their QoS are incompatible and the publisher and subscriber will not communicate.

3.3.5.2 Durability

Durability controls whether the publisher will store the data that it sends, so that it can be sent to new subscribers that join the system later. The possible settings for this QoS are:

- **VOLATILE** (Default) Data samples are not stored.
- **TRANSIENT** *RTI Data Distribution Service* will attempt to store samples in memory. The data will survive the DataWriter.
- **TRANSIENT_LOCAL** *RTI Data Distribution Service* will attempt to store samples in memory. The data will not survive the *DataWriter*.
- **PERSISTENT** *RTI Data Distribution Service* will store previously published samples in permanent storage, like a disk. The data will survive the *DataWriter*.

Which particular samples are stored depends on other QoS such as History (Section 3.3.5.6) and ResourceLimits.

If Durability is selected for a subscriber, the subscriber will ask the publisher to send all previously written data. All data in the publisher's history queue will be sent to the subscriber. To buffer this temporary high throughput, the subscriber should use a History value comparable to the publisher's.

The publisher and subscriber must use compatible settings, as described in Table 3.1.

Table 3.1 Valid Combinations of Durability

		Subscriber			
		VOLATILE	**TRANSIENT_ LOCAL**	**TRANSIENT**	**PERSISTENT**
Publisher	**VOLATILE**	✔	incompatible	incompatible	incompatible
	TRANSIENT_ LOCAL	✔	✔	incompatible	incompatible
	TRANSIENT	✔	✔	✔	incompatible
	PERSISTENT	✔	✔	✔	✔

Note: If you select Durability, you must also select Reliability (this applies to the publisher and subscriber).

3.3.5.3 Time-Based Filter

Time-Based Filter is only available when creating a subscriber. It is the minimum separation time (in milliseconds) that the subscriber wants between data updates. Any data arriving within this time interval will be discarded. Where possible, the publisher will not "publish" the data. Valid settings range from 0 to 31,536,000,000 ms (1 year).

The Time Based Filter value must be less than the Deadline value (Section 3.3.5.7).

3.3.5.4 Reliability

If Reliability is selected for a publisher (the default setting for a publisher), the publisher will attempt to deliver all data sent. If data has not been received by the subscriber due to a communication error, the middleware will retransmit the data.

If Reliability is not selected, the publisher will use best-effort communication and will not retransmit any missing data.

If Reliability is not selected for a subscriber (the default setting for a subscriber), the subscriber will not expect lost data to be resent.

If Reliability is selected for a subscriber, the subscriber expects all data updates reliably. It listens for "heartbeats" from the publisher and responds with either a positive acknowledgement to indicate data receipt or a negative acknowledgement to initiate retransmission of missing data.

The publisher and subscriber must use compatible settings, as described in Table 3.2.

Table 3.2 **Valid Combinations of Reliability**

		Subscriber	
		Reliability not selected (default) (BEST_EFFORT)	**Reliability selected (RELIABLE)**
Publisher	**Reliability not selected (default) (BEST_EFFORT)**	✔	incompatible
	Reliability selected (RELIABLE)	✔	✔

3.3.5.5 Liveliness and Lease Duration

Liveliness is used to detect the state of the publisher even when it is not actively sending data.

For a publisher, the Liveliness value is the maximum time interval within which a publisher will signal that it is active.

For a subscriber, the Liveliness value is the maximum time interval within which a subscriber expects to be notified that the publisher is alive.

A subscriber's Liveliness must be greater than or equal to the publisher's Liveliness.Valid settings range from 0 to 31,536,000,000 ms (1 year), or "INF" for infinity (the default).

3.3.5.6 History

History controls the amount of data that is kept in the send queue. This is normally used in connection with Durability and/or Reliability. If Durability is selected, then History determines how much previously sent data is sent to late-joining subscribers. Valid settings range from 0 to 100,000,000. The default is 1.

3.3.5.7 Deadline

For a publisher, the Deadline value is the time interval within which the publisher commits to updating data at least once, if not more frequently.

For a subscriber, the Deadline value is the maximum time interval between data updates that the subscriber expects from the publisher.

If a publisher fails to send a data update within the subscriber's requested Deadline interval, the subscriber will get a "deadline missed" notification.

Valid settings range from 1 ms to 1 year, or "INF" for infinity (the default).

A subscriber's Deadline value must be greater than or equal to the publisher's. A subscriber's deadline must also be >= its minimum separation (see Time-Based Filter (Section 3.3.5.3)).

3.3.5.8 Lifespan

Lifespan is only available when creating a publisher. The purpose of the Lifespan QoS is to avoid delivering stale data.

Each data sample written has an associated expiration time, beyond which the data should not be delivered. The middleware attaches timestamps to all data sent and received. The expiration time of each sample is computed by adding the specified Lifespan duration to the destination timestamp. When you specify a finite Lifespan, *RTI Data Distribution Service* will compare the current time with those timestamps and drop data when the specified Lifespan expires. The default setting is an infinite duration, meaning the data will never 'expire.'

If you have multiple publishers for the same instance, they should all use the same Lifespan value.

Valid settings range from 1 ms to 1 year, or "INF" for infinity (the default).

3.3.6 Using a Content Filtered Topic

The 'Use filter' checkbox is only available when creating a subscriber. If selected, a filter is created for data updates to a topic based on the content of the data. Only data that satisfies the filter will be made available to the subscriber.

3.3.7 Controlling the Read Method

When creating a subscriber, you can choose whether it will use **read()** or **take()**.

- With **read()** (the default), *RTI Data Distribution Service* will continue to store the data in the *DataReader*'s receive queue. The same data may be read again until it is taken in subsequent **take()** calls. Graphically, a "new" sample is shown with a thicker border.
- With **take()**, *RTI Data Distribution Service* will remove the data from the *DataReader*'s receive queue. The data returned by *RTI Data Distribution Service* is no longer stored by *RTI Data Distribution Service*.

3.4 Other Controls

The Controls sub-panel includes various commands that you can use to control the demo.

3.4.1 Delete All

This command deletes all the publishers and subscribers that have been created in the demo application. All objects moving in the application window will disappear and no data will be sent or received. (NOTE: **Delete All** removes all the entities but it does not destroy the participant. The quick reset is to select **DDS Config, Stop DDS, Start DDS**). If you have started multiple copies of *RTI Shapes Demo*, you will need to click **Delete All** in each copy to delete their respective publishers and subscribers.

3.4.2 Pause Publishing

The **Pause Publishing** command is only effective on publishers. It pauses the sending of coordinate data for the shape until you click Resume Publishing. When **Pause Publishing** is clicked, the label changes to **Resume Publishing**.

The **Pause/Resume Publishing** commands are also available when you right-click an entity (if it is a publisher) in the **Legend** tab.In this way you can individually pause each single publisher.

When publishing is paused, you will still see published topics (colored shapes) moving in the publisher demo window, but corresponding topics in a subscriber window will stop moving. That's because what you see in the publisher window is the data being generated (not necessarily sent); what you see in the subscriber window is data being received. When you pause publishing, the subscriber stops receiving updates to the topic (that is, the shape's coordinates).

3.4.3 Show/Hide History

The **Show History** and **Hide History** commands tells the demo to start/stop drawing the shapes from all the packets that are in the subscriber's history queue.

This command has no effect on subscribers that use the **take()** method of accessing data. It is only for subscribers that use **read()**. It also has no effect on publishers.

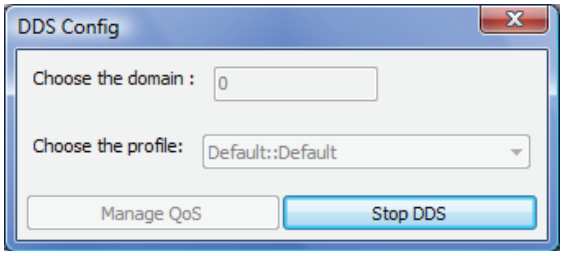
If you set History greater than 1, by default all the packets in the history queue are displayed, showing the historical path of the shapes on the subscriber's canvas. If History is 1 (the default), no historical samples appear because there is only room for one sample in the queue.

By default, historical samples are shown; that is, **Show History** is the default setting and you will see the **Hide History** command in the Controls panel.

When you select **Show History**, the samples stay in the reader's queue, so you can see the shadow trail of the historical samples (up to the number set in the History field).

3.4.4 DDS Config

The **DDS Config** command allows you to change the domain ID, manage QoS profiles, and start/stop *RTI Data Distribution Service*. This is the equivalent of a Reset button, short of quitting and restarting the application.

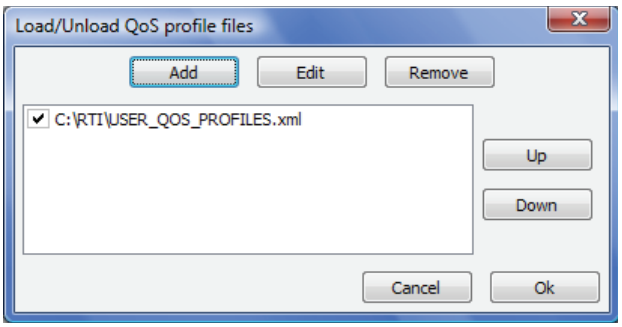


To make any changes with this command, first click **Stop DDS**, make the desired change, then click **Start DDS**.

If the "Choose the profile" listbox contains only "Default::Default", this means no XML files have been loaded.

To load an XML QoS Profiles file:

1. Click **Stop DDS**. (Any publishers/subscribers will be deleted when you do this.)
2. Click **Manage QoS**.
3. In the resulting dialog box, click **Add** and then browse to select an XML QoS profiles file.

   You can use your own file and the one provided with *RTI Shapes Demo*. **RTI_SHAPES_DEMO_QOS_PROFILES.xml** is in the same directory where you installed *RTI Shapes Demo*. This file is already included after installation. For more information on the contents of this file, see Section 3.3.4.

   If you specify multiple XML files, the **Up** and **Down** buttons change the order in which they are loaded. If you load files that contain profiles with is_default_qos="true", the last profile loaded is used. This information is saved in your workspace (see Section 3.5).

To unload an XML QoS Profiles file:

1. Select **DDS Config**, then **Stop DDS**.
2. Click **Manage QoS**.
3. In the resulting dialog box, clear the checkbox next to the file, or select the file and click **Remove**.

If the XML QoS Profile file has Errors:

If you add an XML QoS Profile file that has errors and you click Ok, *RTI Shapes Demo* will try detect the error and will show a popup that indicates with file has been detected to be wrong. Once you click **OK**, the **Load/Unload QoS profile files** window will automatically uncheck all the incorrectly formatted files.

At this point you can either press **Ok** and proceed without loading those files or edit them by pressing the **Edit button**: the default XML editor will open, allowing you to correct the file and correct the error.

3.4.5 Output and Legend Tabs

There are two tabs at the bottom of the demo application window.

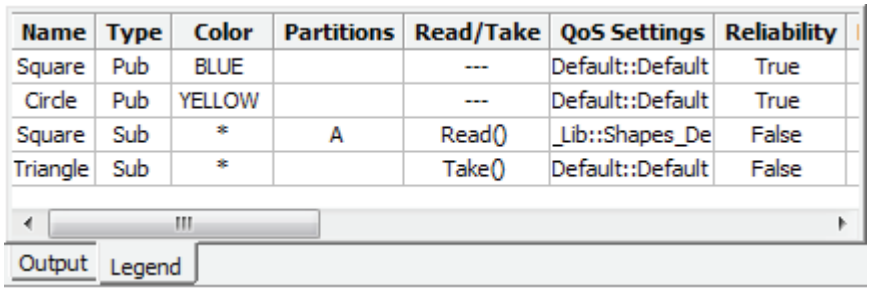
❑ The **Legend** tab shows you the publishers and subscribers created for the demo and their QoS settings.

If you right-click on a publisher entity in the **Legend** tab, you can access these commands:

- Pause/resume publishing (see Section 3.4.2)
- Dispose data and delete the *DataWriter.*
- Unregister data and delete the *DataWriter*.

If you right-click on a subscriber in the **Legend** tab, you can access a command to delete the *DataReader*.

Another way to delete a publisher or subscriber is to click on it in the **Legend** tab and press the **Delete** button on your keyboard.[1]

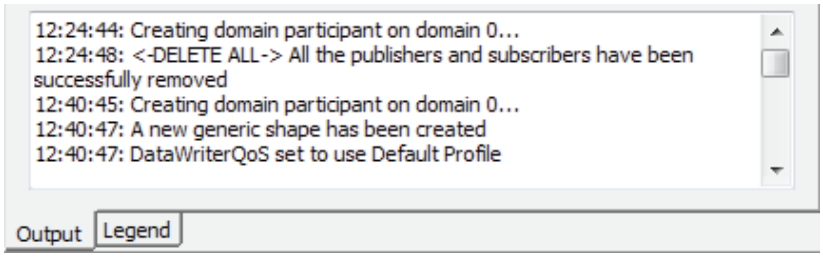


1. When you press Delete, the current setting for the WriterDataLifecycle QoS policy's autodispose_unregistered_instances field determines if the DataWriter's data is disposed before it is unregistered. If autodispose_unregistered_instances has not been changed via a QoS profile, the default setting will cause the data to be disposed and unregistered.

Dispose vs. Unregister:

When data is *disposed*, all *DataReaders* are informed that, as far as the *DataWriter* knows, the data instance no longer exists and can be considered "not alive." When data is *unregistered*, this indicates only that a particular *DataWriter* no longer wants to modify an instance—an important distinction if there are multiple *DataWriters* for the same instance.

❑ The **Output** tab shows statuses, events and other information.



3.5 RTI Shapes Demo's Workspace

RTI ShapesDemo uses the concept of a workspace, which is an XML file that contains the last settings used by *RTI Shapes Demo*. For example, it contains the list of QoS XML profile files loaded through the **Load/Unload QoS profile files** window and whether or not the files should be loaded. Another useful piece of information saved in the workspace is the last domain ID as specified by the Config window. This allows you to start *RTI Shapes Demo* with well-known settings each time. (If you start *RTI Shapes Demo* with the **-domainId** option, that domain ID setting is not saved in the workspace.)

If your current working directory contains a file named **RTI_SHAPES_DEMO.xml**, it will be used as the workspace. If the file cannot be found in the current working directory, *RTI Shapes Demo* will use the one located in **<executable dir>/../../**[1] if it can be found. If the file is still not found, on Windows systems *RTI Shapes Demo* will finally look for the file in **My Documents/RTI/RTI Shapes Demo <version>**.

You can specify a different workspace file by using the **-workspaceFile** command-line option. If the file specified after **-workspaceFile** is not found, it will be automatically created.

1. **<executable dir>/../../** means the directory two levels up from that of the *RTI Shapes Demo* executable.

If you do not use **-workspaceFile** and **RTI_SHAPES_DEMO.xml** is not found anywhere (in the current working directory, two levels up the executable directory, or **My Documents/RTI/RTI Shapes Demo <version>** on Windows systems), *RTI Shapes Demo* will automatically create a workspace file in **<executable directory>../../** on non-Windows systems or in **My Documents/RTI/RTI Shapes Demo <version>** on Windows systems; the file will be named **RTI_SHAPES_DEMO.xml**.

Chapter 4 Examples

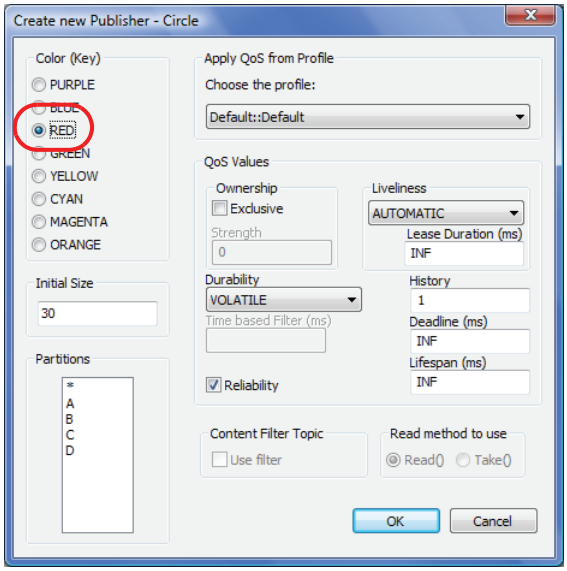
Important: Unless otherwise noted, these examples assume you are using the default *RTI Shapes Demo* settings—meaning the **RTI_SHAPES_DEMO_QOS_PROFILES.xml** file is loaded. By default, this file indicates to *RTI Data Distribution Service* to load the profile called **Shapes_Default_Profile** from the **RTI_Shapes_Lib** library and use it as default. For more information about profiles, see Section 3.3.4.

4.1 Publish-Subscribe Example

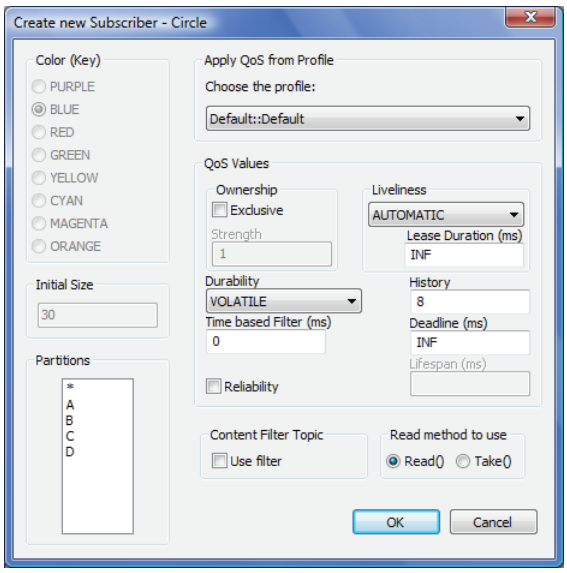
This example showcases the publish-subscribe concept. It uses best-effort communication and shows the decoupling between the publisher and the subscriber; i.e., the publisher can send data without knowing where/what the subscriber(s) are, and the subscriber can receive data without knowing where/what the publisher(s) are. In this example, you will be asked to start two copies of *RTI Shapes Demo*. There is no need to configure a discovery service or provide any *a priori* information about where the demo applications are being run.

1. Create a red circle publisher:
   a. Start *RTI Shapes Demo*. We will refer to this copy of the application as Publisher1.
   b. Under Publishers, click on **Circle**.
   c. In the Create New Publisher window:
      - Select **RED** for Color.
      - Click **OK**.

   You will see a red circle moving on the Publisher canvas. If there were any subscribers, the publisher would start sending data (the coordinates of the red circle).



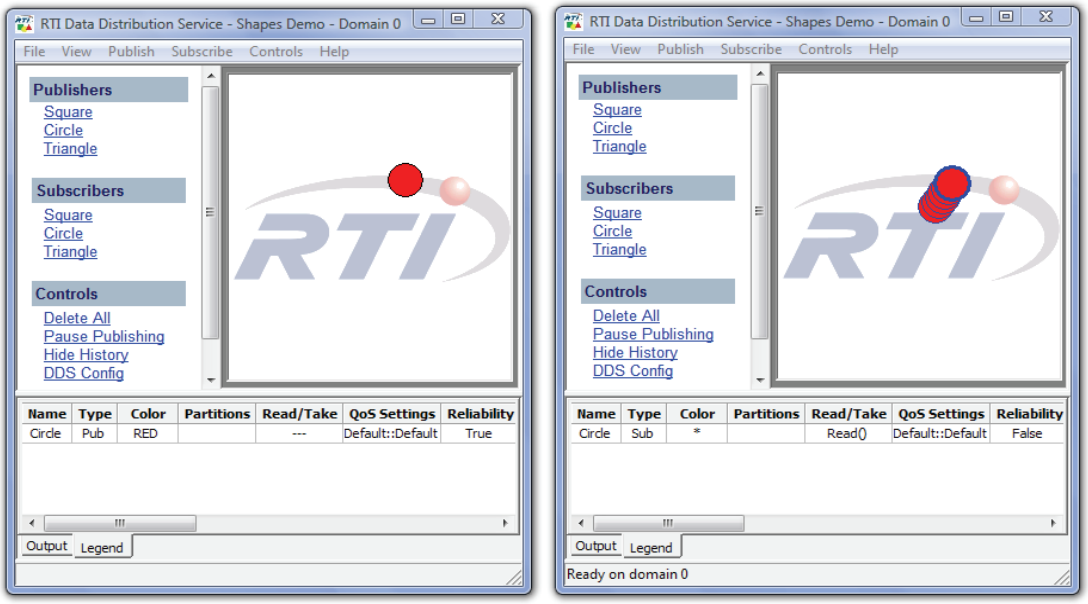
2. Create a subscriber for circles:
   a. Start a second *RTI Shapes Demo*. We will refer to this copy of the application as Subscriber1.
   b. Under Subscribers, click on **Circle**.
   c. In the Create New Subscriber window:
      - Click **OK**. (Use all the defaults.)



You will see 6 red circles with blue borders on the Subscriber canvas, mirroring the movements of the circle in the Publisher canvas. The leading circle indicates the current position of the published circle. The other circles are the historical samples kept by *RTI Data Distribution Service*. You can see the difference between historical data and new data looking at the thickness of the border. You can also hide historical data by selecting **Hide History** from the Controls menu.

Your windows should look similar to Figure 4.1.

Figure 4.1 **Publisher and Subscriber Displays**



Publisher1 Subscriber1

3. Test real-time data delivery:

   To show that the subscriber is receiving real-time data, move the cursor over the Publisher's red circle and click the mouse button. This will stop the red circle in the publisher canvas. Drag the cursor and move it around while holding down the mouse button. The red circles on the subscriber canvas should exactly mirror your mouse movements.

Congratulations, you have just finished the first exercise, which illustrates basic publish-subscribe functionality!

If you plan to continue with the next exercise, leave the two demo windows running. The next exercise will use the red circles.

4.2 Multiple Instances Example

Instances are useful when you are dealing with data that is unpredictable in terms of its creation and deletion—e.g., aircraft/airplane flight tracks and shipment tracking. Flights and shipments can come and go. The application has no way of knowing when or how many flights/shipments show up. DDS provides rich semantics that can be used to track, monitor, and check the state (new, deleted, no writers, etc.) of individual instances. Some of the possible notifications are displayed in the Output tab.

Publishers and subscribers are associated with a topic. If you create a new topic every time a new flight is detected, you would need to create a matching subscriber and publisher pair. This is obviously not scalable, since you can have many different aircraft flight plans.

Instances give you the ability to scale a topic. Unique instances of a topic are defined by unique key values. A subscriber of a topic will get all the data sent on all the instances of this topic. Take the example of flight track data: the key could be the flight ID, pilot name or mission code. Regardless of how many new flights there are, you would only need one subscriber to get the data, because the topic is the same.

In this example, the topic is the shape of the object (Square, Circle or Triangle) and the key is its color. So different colors of an object give you different instances of the topic. For example, a red circle is a different instance from a green circle, yet they are all instances of the Circle topic.

At this point, you should have two copies of *RTI Shapes Demo* running, which will be referred to as Publisher1 and Subscriber1. In this example, you will be asked to start additional copies of *RTI Shapes Demo*.

Tip: If you make a mistake during the following steps and need to delete a single publisher or subscriber, select the item in the Legend tab and press the **Delete** key on your keyboard.

1. This exercise picks up where the previous one left off. So you should have two demo windows running: one is publishing red circles and the other is subscribing to circles.
2. In Subscriber1, choose Delete All from the Controls Menu.
3. Create a circle subscriber with History = 1:
   a. In Subscriber1, under Subscribers, click on **Circle**.

b. In the Create New Subscriber window:

- Change the History field from 6 to 1.
- Click **OK.**

You should now see one red circle moving in each instance of *RTI Shapes Demo*.

4. Create a green circle publisher:

a. In Publisher1 under Publishers, click on **Circle**.

b. In the Create New Publisher window:

- Select **GREEN** for Color.
- Click **OK**.

You should now see two circles moving on each canvas—one red and one green.

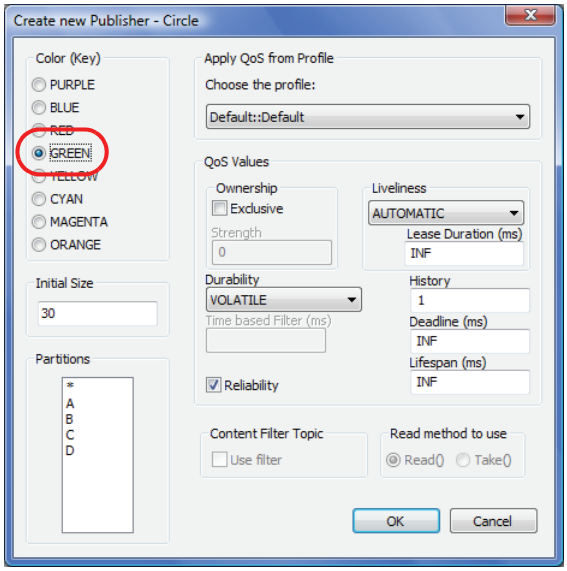
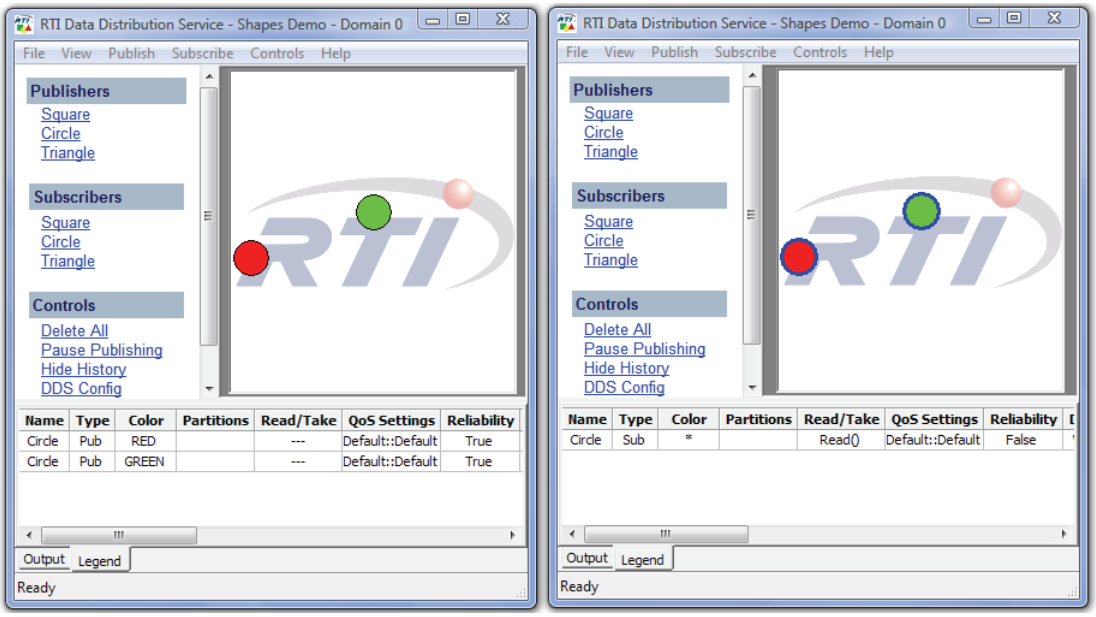


Figure 4.2 **Publisher and Subscriber Displays for Multiple Instances**



Publisher1 Subscriber1

Notice that we did not have to do anything in Subscriber1 to start receiving the green circle's data. That's because the subscriber of a topic (Circle, in this case) gets all data sent for all instances of the topic. The green circle was just another instance of the topic Circle, so the subscriber received this new data automatically.

5. Create another red circle publisher in a new window:

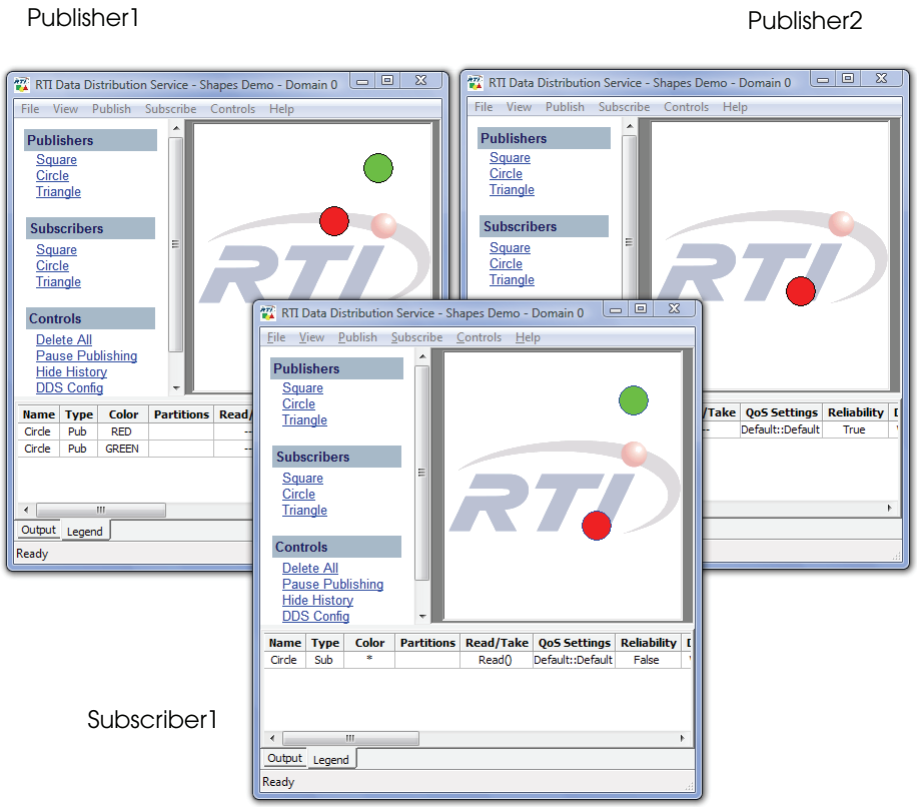
   a. Start a third *RTI Shapes Demo*. We will refer to this copy of the application as Publisher2.

   b. Under Publishers, click on **Circle**.

   c. In the Create New Publisher window:

   - Select **RED** for Color
   - Click **OK**.

Figure 4.3 **Two Publishers and One Subscriber**



We now have multiple publishers updating the same instance (Red) of the topic Circle. You'll see that the red circle in Subscriber1's canvas flickers between different locations. This happens because the subscriber is receiving position data from both of the publishers and is trying to display them at the same time. Details on how to handle such a situation will be discussed in the next section.

6. Click **Delete All** in the **Controls** sub-panel of each of the three demo windows.

4.3 Ownership Example

As you saw in the previous example, it's possible for multiple publishers to simultaneously send data to the same instance of a topic. You may or may not want this behavior.

For certain types of data such as commands, you may want to receive updates from just one publisher at a time in order to be ensure consistency. Exclusive ownership is a way to ensure that only one publisher's data for a specific instance can get through to a subscriber. With multiple publishers, the one with the highest ownership strength wins.

At this point, you should have three copies of *RTI Shapes Demo* running, which will be referred to as Publisher1, Publisher2 and Subscriber1.

Tip: If you make a mistake during the following steps and need to delete a single publisher or subscriber, select the item in the Legend tab and press the **Delete** key on your keyboard.

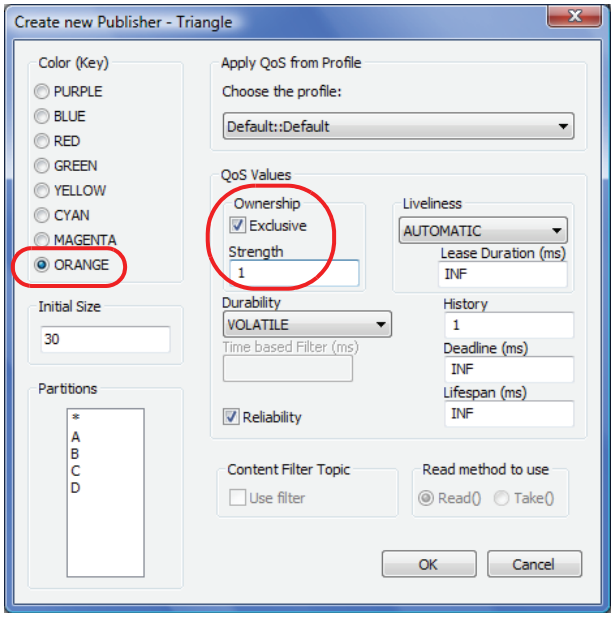
1. In Publisher1, create an orange triangle publisher, with **Exclusive** ownership and **Strength** = 1:

   a. Under Publishers, click on **Triangle**.

   b. In the Create New Publisher window:

   - Select **ORANGE** for Color.
   - Check **Exclusive**.
   - Ensure **Strength** is 1.
   - Click **OK.**

   You should see a floating orange triangle on the canvas. We created a publisher with exclusive ownership and a strength of 1.



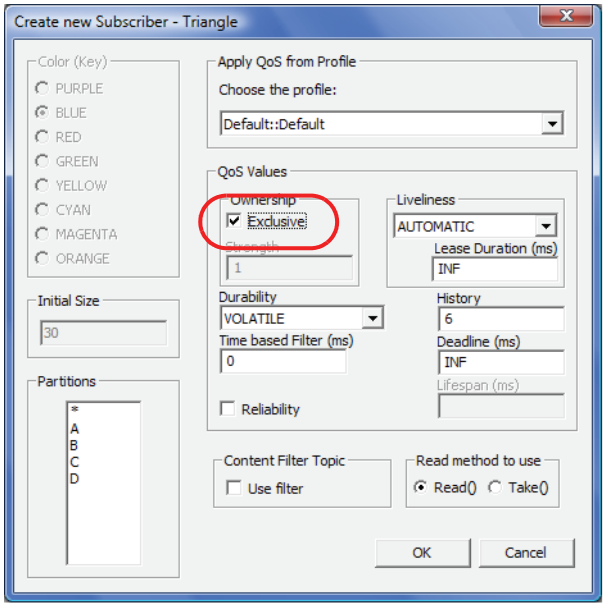
2. In one of the other *RTI Shapes Demo* windows, create a triangle subscriber with **Exclusive** ownership. We will call this window Subscriber1.

   a. Under Subscribers, click on **Triangle**.

   b. In the Create New Subscriber window:

   - Check **Exclusive**.
   - Click **OK**.

   You should see 6 orange triangles with blue borders moving around in the Subscriber1 canvas. So far, this is similar to the publisher-subscriber exercise.

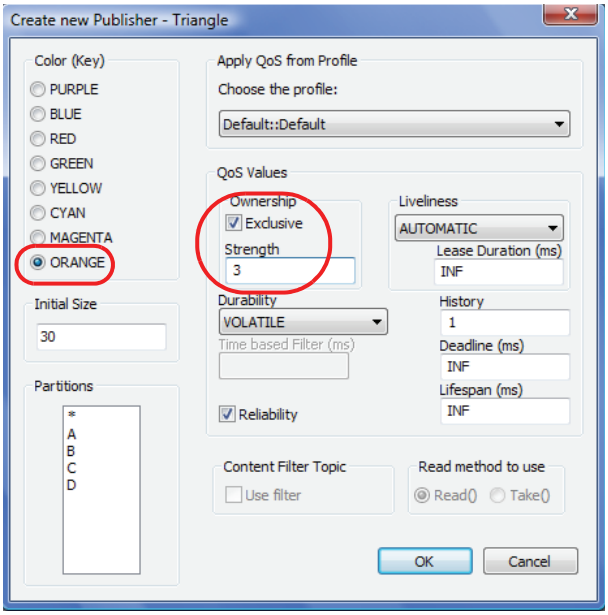


3. In the third window, create an orange triangle publisher with Exclusive ownership and **Strength** = 3. We will call this window Publisher2.

   a. Under Publishers, click on **Triangle**.

   b. In the Create New Publisher window:

   - Select **ORANGE** for Color.
   - Check **Exclusive** and set **Strength** to 3.
   - Click **OK**.

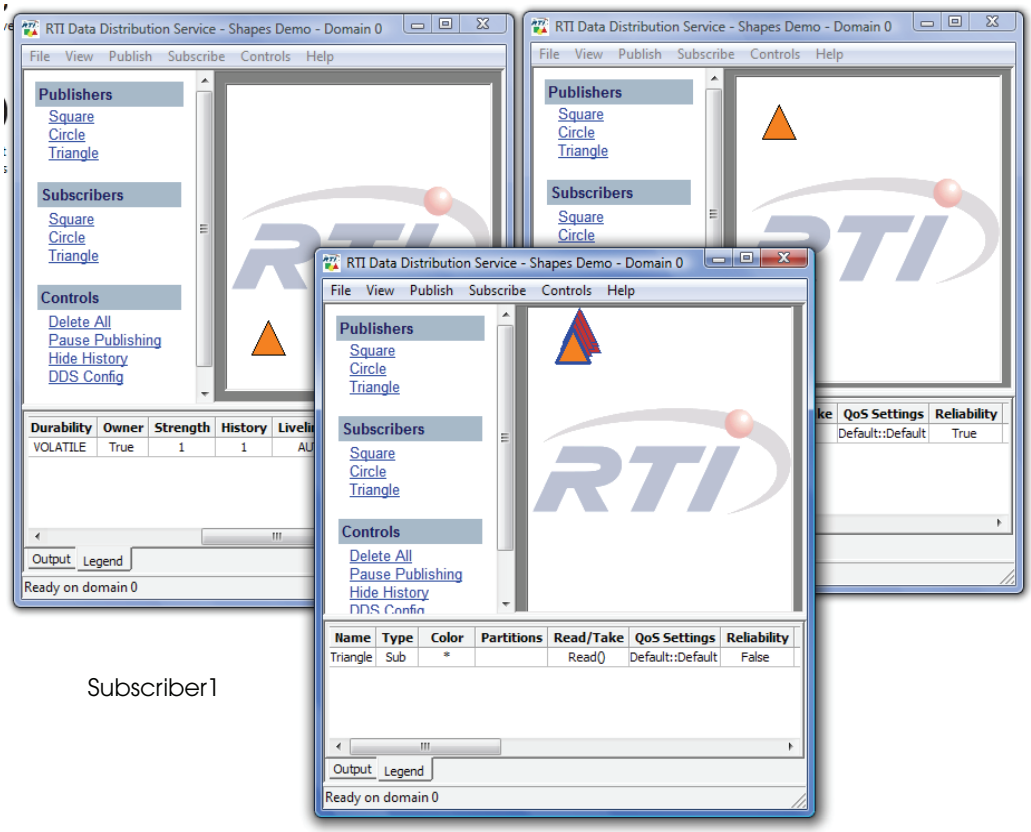


You should see an orange triangle in Publisher2's canvas.

Figure 4.4 **Different Ownership Strengths**

Publisher1, strength = 1

Publisher2, strength = 3



Subscriber1

4. Use your mouse in Publisher2 to drag the triangle around the canvas. The triangle in Subscriber1 should exactly mirror your mouse movements, because Publisher2 has a higher strength than Publisher1.
5. Click **Delete All** in the **Controls** sub-panel of each of the three demo windows.

4.4 Failure Detection Example

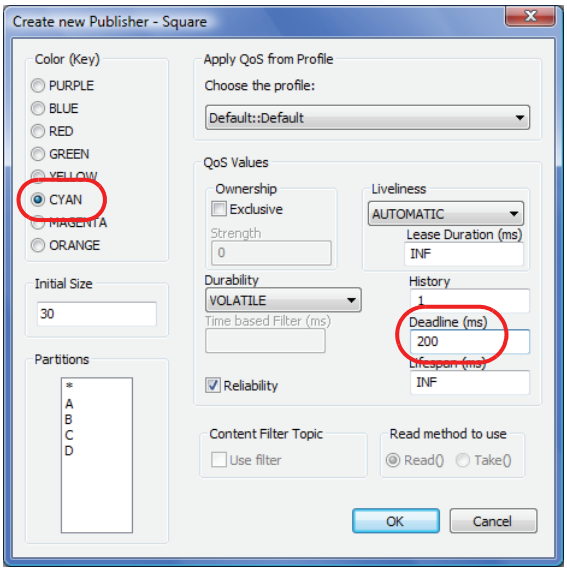
You may want to detect when the publisher or the network is behaving abnormally and the subscriber hasn't seen updates for an instance within a specified period of time. The Deadline QoS offers a way to do this.

Deadline is a contract between the publisher and the subscriber based on the data rate. The publisher offers to send data at least once in its specified deadline period and the subscriber requests to receive data within its deadline period. If either the subscriber or the publisher misses their deadline, an event callback for "deadline missed" occurs.

At this point, you should have three copies of *RTI Shapes Demo* running, though you will only use two of them for this example. The two copies will be referred to as Publisher1 and Subscriber1.

Tip: If you make a mistake during the following steps and need to delete a single publisher or subscriber, select the item in the Legend tab and press the **Delete** key on your keyboard.

1. In Publisher1, create a cyan square publisher, **Deadline** = 200 ms.:
   a. Under Publishers, click on **Square**.
   b. In the Create New Publisher window:
      - Select **CYAN** for Color.
      - Set **Deadline** to 200 ms.
      - Click **OK**.

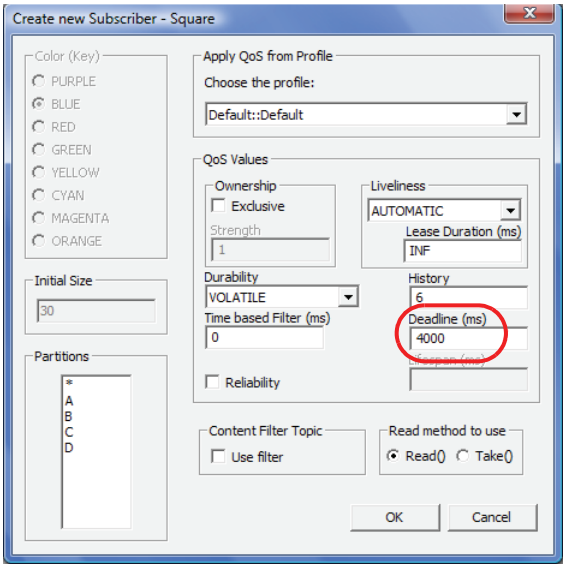


2. Create a squares subscriber in Subsriber1:

   a. Under Subscribers, click on **Square**.

   b. In the Create New Subscriber window:

   - Set **Deadline** to 4000 ms.
   - Click **OK**.



   You'll see a cyan set of 6 squares moving around Subscriber1's canvas. This set of squares mirrors the movement of the cyan square in Publisher1's canvas along with 5 historical samples.

   Note: The subscriber's deadline must be greater than or equal to the publisher's deadline. If not, an "Incompatible QoS (Deadline) on Square" error message will be displayed in the Output tab of the Subscriber demo application.

3. In Publisher1's **Controls** sub-panel, click **Pause Publishing**.

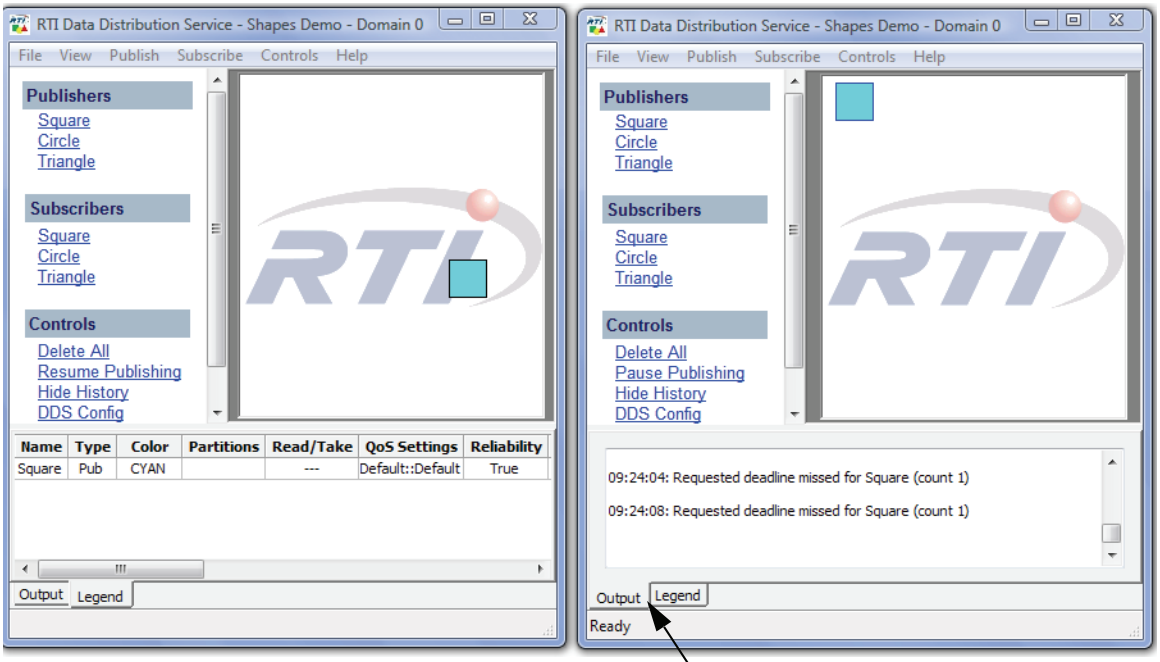
   The cyan square in Subscriber1's canvas should freeze. Note that now all the samples' borders have the same thickness: this indicates that all of them are historical data. In Subscriber1, select the Output tab to see messages notifying the application that the promised deadline of 4000 ms has been missed, as seen in Figure 4.5.

4. Click **Resume Publishing**.

   The cyan squares in Subscriber1's canvas will start moving again, mirroring the movement in Publisher1's canvas.

5. Click **Delete All** in the **Controls** sub-panel of each demo window.

Figure 4.5 **Missed Deadline**



4.5 Failover Example

In most mission-critical systems, there are failover mechanisms to handle unexpected behaviors. In this exercise, we combine the previous two exercises to illustrate hot-failover behavior where the "primary" publisher goes down and the subscriber immediately detects the loss and starts taking data from the "secondary" publisher.

At this point, you should have three copies of *RTI Shapes Demo* running, referred to as Publisher1, Publisher2 and Subscriber1.

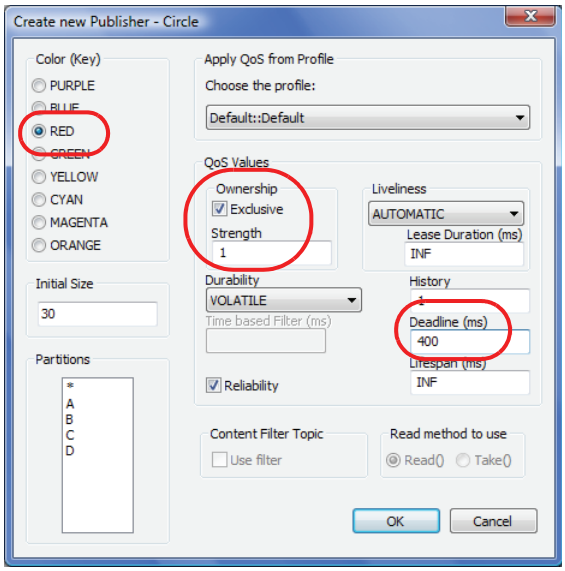
Tip: If you make a mistake during the following steps and need to delete a single publisher or subscriber, select the item in the Legend tab and press the **Delete** key on your keyboard.

1. In Publisher1, create a red circle publisher with **Exclusive** ownership and **Strength** = 1:

   a. In Publisher1, under Publishers, click on **Circle**.

   b. In the Create New Publisher window:

   - Select **RED** for Color.
   - Check **Exclusive**.
   - Set **Strength** to 1.
   - Set **Deadline** to 400 ms.
   - Click **OK**.

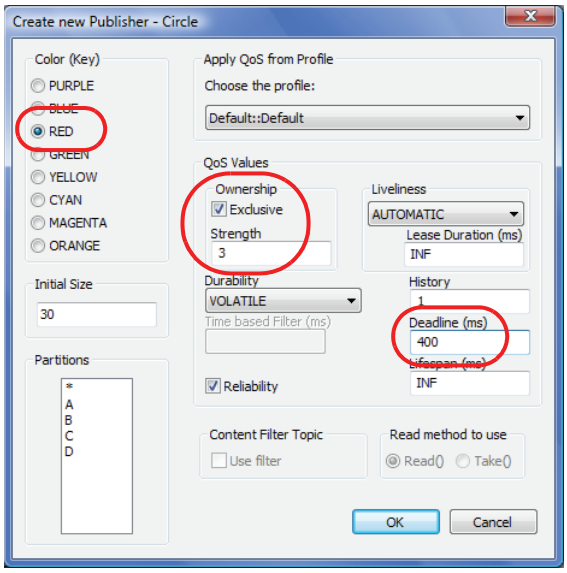


2. In Publisher2, create a red circle publisher with **Exclusive** ownership and **Strength** = 3:

   a. Under Publishers, click on **Circle**.

   b. In the Create New Publisher window:

   - Select **RED** for Color.
   - Check **Exclusive**.
   - Set **Strength** to 3.
   - Set **Deadline** to 400 ms.
   - Click **OK**.

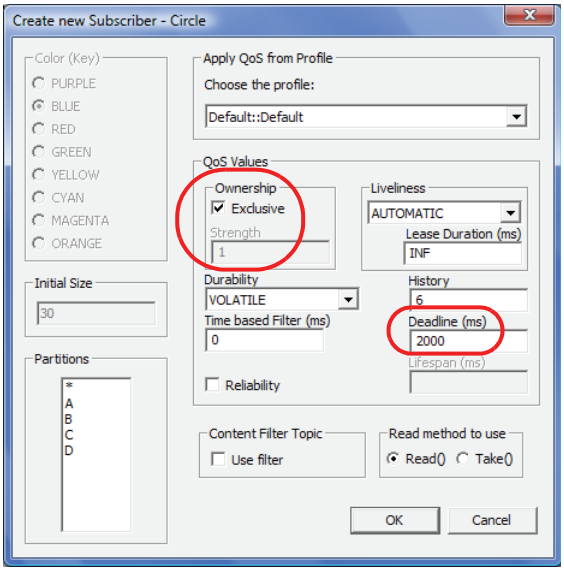


3. In Subscriber1, create a circle subscriber, **Exclusive** selected, **Deadline** = 2000 ms.

   a. Under Subscribers, click on **Circle.**

   b. In the Create New Subscriber window:

   - Check **Exclusive**.
   - Set **Deadline** to 2000 ms.
   - Click **OK**.



   In the subscriber canvas, you should see red circles that mirrors the movement of the one in Publisher2. This happens because the Publisher2's circle has a higher strength that Publisher1's. The deadline setting for the subscriber is the time at which the subscriber application will "failover" to the lower strength publisher application.

4. In Publisher2, click on **Pause Publishing**.

After 2000ms, Subscriber1 will show the "deadline missed" callback in its Output tab and at the same time, fail over to displaying the movements of the red circle in Publisher1.

Publisher2 initially had exclusive ownership of the red circle instance because it had a higher strength. However, this ownership was lost to the lower-strength publisher when the subscriber missed a deadline. This is especially useful if a publisher is unable to gracefully shutdown and relinquish its ownership.

5. In Publisher2, click on **Resume Publishing**.

   Subscriber1's red circle should immediately switch to tracking the movements of Publisher2.

4.6 More Experiments

Please feel free to experiment and run tests using the other QoS options in the Create New Subscriber and Create New Publisher windows. Described below are a few other interesting behaviors to test.

4.6.1 Content Filtered Topics Example

This is a very useful feature if you want to filter data received by the Subscriber. It also helps to control network and CPU usage on the subscriber side because only data that is of interest to the subscriber is sent.

For example, assume your application is a radar monitor that draws flights detected within a 20-mile radius. The application can subscribe to the track data with a content filtered topic for a 20-mile radius on the coordinates of all flights. With the filter, only coordinates that are within the 20-mile radius will be sent to the application.

1. In Publisher1, create a circle publisher (any color):
   a. Under Publishers, click on **Circle**.
   b. In the Create New Publisher window, click **OK**.

2. In Subscriber1, create a circle subscriber with a content filtered topic:

   a. Under Subscribers, click on **Circle**.

   b. In the Create New Subscriber window:

   - Check **Use filter**.
   - Click **OK**.

   You will see a shaded rectangle appear in the subscriber canvas. This is the filter for the coordinates of the Circle topic. The subscriber will receive position data for the Circle only when it is with the area defined by the content filter.

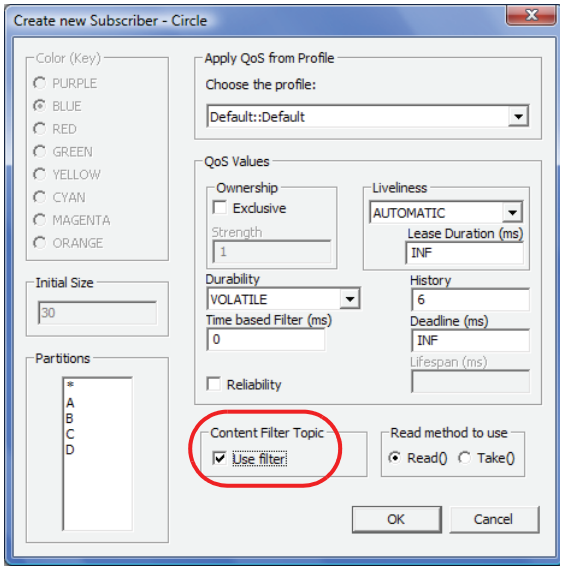
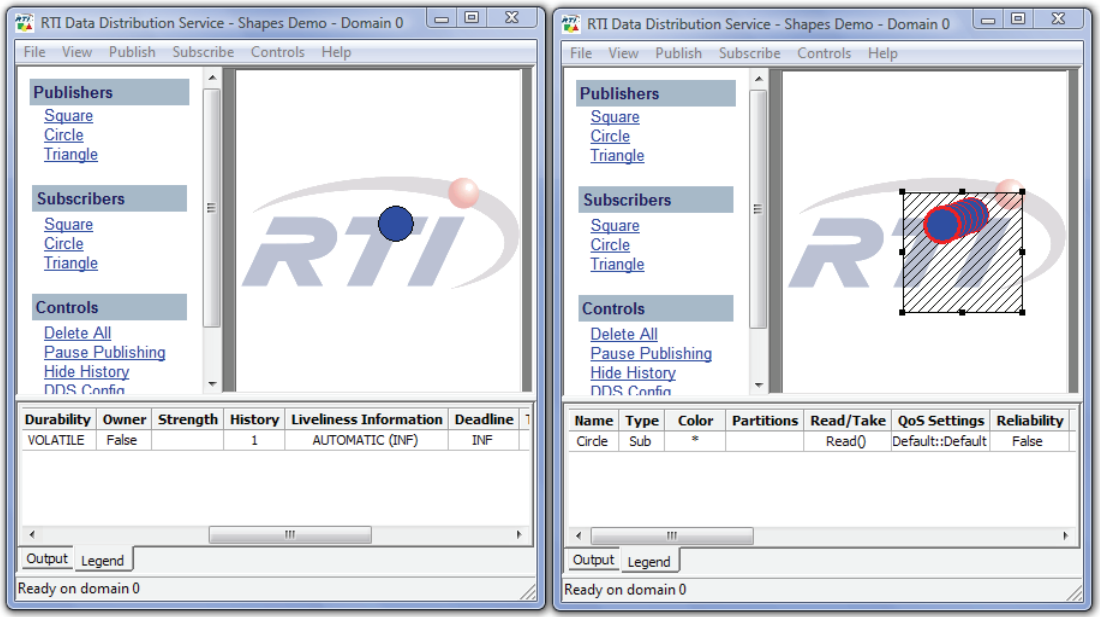


Figure 4.6 **Content Filtered Topic Example**



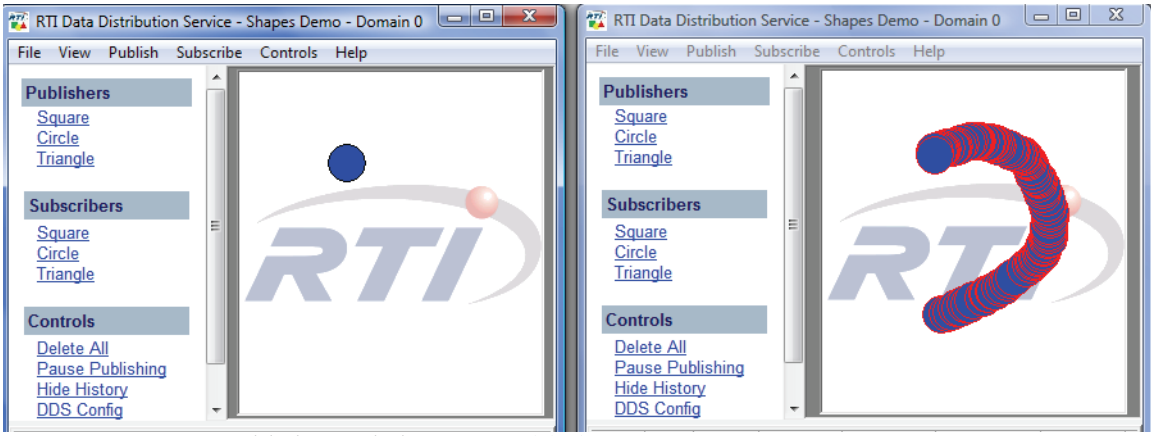
3. To see the effect of dynamic filters, use your mouse to move and resize the shaded area in Subscriber1.

4.6.2 Lifespan Example

The Lifespan QoS controls how long data samples are considered valid. You can use it to prevent sending data that is considered too old to be valid. The default setting is an infinite duration, meaning the data will never 'expire.'

1. In Publisher1, create a circle publisher (any color) with **History** = 100, **Lifespan** = 1000 ms.:
   a. Under Publishers, click on **Circle**.
   b. Set **History** to 100 and **Lifespan** to 4000.
   c. Click **OK**.
2. In Subscriber1, create a circle subscriber with History = 100:
   a. Under Subscribers, click on **Circle**.
   b. Set **History** to 100.
   c. Click **OK**.
3. Drag the shape around on Publisher1's canvas.

   On Subscriber1's canvas, you will see a "shadow" of objects printed out in a continuous pattern. The shadow is caused by the subscriber showing the last 100 data samples from the publisher's history queue.

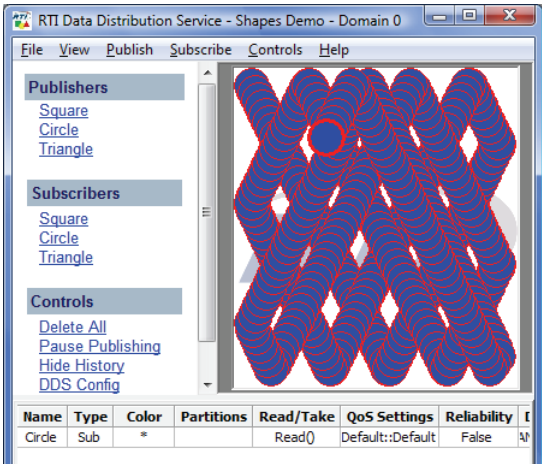


4. In Publisher1, click **Pause Publishing**.
5. On Subscriber1's canvas, notice that the samples disappear as they time out. Experiment with this by increasing the Lifespan setting for the publisher. The longer the Lifespan, the longer it takes for the samples to disappear when you pause publishing.

4.6.3 Reliability and Durability Example

In a dynamic system, you may want late-joining nodes to get the data that was sent before the nodes connected to the DDS network. For example, suppose you need to initialize the state of these late-joining nodes and don't want to be continually sending the state just in case some node joins late. The Durability QoS provides late-joining nodes with the ability to get previously sent data.

1. In Publisher 1, create a circle publisher (any color) with transient-local durability, reliability, and history = 200.
   a. Under Publishers, click on **Circle**.
   b. In the Create New Publisher window:
      - Use the drop-down list box to change Durability to **Transient Local**.
      - Set **History** to 200.
      - Click **OK**.
2. Wait for a bit.
3. In Subscriber1, create a circle subscriber with transient-local durability, reliability, and history = 200.
   a. Under Subscribers, click on **Circle**.
   b. In the Create New Subscriber window:
      - Use the drop-down list box to change Durability to **Transient Local**.
      - Set **History** to 200.
      - Click **OK**.
4. Watch the Subscriber canvas. You will see a "shadow" of objects printed out in a continuous pattern. The shadow results from the subscriber showing the last 200 samples from the publisher's history queue.
5. To stop showing the shadow trail of samples on Subscriber1, click on **Hide History**.



4.6.4 Time-based Filtering Example

Sometimes subscribers are located on slower or more remote systems that cannot handle the amount of data that the publisher is capable of sending. For example, consider a system where a central command center is publishing high-resolution aerial photos of a geographic area once every 30 seconds and a soldier with a handheld computer is trying to subscribe to the data. In this case, the handheld computer does not have the bandwidth to handle the command center's send rate. With time-based filtering, the handheld computer can "throttle" the data so that it only receives data once every 5 minutes.

1. In Publisher1, create a circle publisher (any color).
   a. Under Publishers, click on **Circle**.
   b. In the Create New Publisher window, click **OK**.
2. In Subscriber1, create a circle subscriber, Time Based Filter = 1000 ms.
   a. Under Subscribers, click on **Circle**.
   b. In the Create New Subscriber window:
      - Set **History** to 1
      - Set **Time Based Filter** to 1000.
      - Click **OK**.

   You will see the circle jump once every second, instead of a fluid movement. In this case, the publisher is only sending data to the subscriber once a second, according to the subscriber's time-based filtering.

Chapter 5 About Real-Time Innovations (RTI)

Thank you for taking the time to explore *RTI Data Distribution Service*. For more information, please visit RTI's web site, www.rti.com or send email to **info@rti.com**.

This guide and hands-on example application demonstrate *RTI Data Distribution Service*, a high-performance publish-subscribe integration solution for real-time applications, data and devices. By delivering performance more than ten times faster than other middleware technologies, *RTI Data Distribution Service* empowers decision makers with more complete and timely information while minimizing hardware requirements and reducing total cost of ownership.

Available since 1996, *RTI Data Distribution Service* publish-subscribe architecture (formerly named NDDS) has been proven in hundreds of designs including radar systems, combat systems, railway control, industrial automation, highway traffic monitoring, financial systems and communications equipment.

RTI Data Distribution Service complies with the Object Management Group's (OMG) Data Distribution Service for Real-Time Systems (DDS) standard. It is the world's most widely used DDS solution and also provides the highest performance, as consistently demonstrated by independent benchmarks. It is a highly optimized, dynamic, true peer-to-peer implementation. Every application is self contained. There is no dependence on a configured or running central server or shared service, eliminating single points of failure and performance bottlenecks.

RTI Data Distribution Service is available for a broad array of platforms, including Linux, Windows, Solaris, VxWorks, LynxOS, INTEGRITY and other systems. A number of valuable OMG DDS extensions are also provided, including RDBMS integration, pluggable transports, custom filters (in addition to SQL-based DDS filters) and support for custom marshalling.

RTI backs its products with a comprehensive array of services including architecture studies, training, consulting, engineering services and technical support. Leveraging over 15 years of experience in the design and implementation of distributed real-time

systems and its deep knowledge of the DDS standard, RTI routinely provides design options, recommends implementation strategies, identifies risk areas and proposes mitigation options. RTI also offers hands-on workshops for organizations evaluating the DDS standard or who want general training because they have not yet selected a DDS solution. Please visit www.rti.com for the latest schedule.

The OMG DDS specification, available from www.omg.org, provides more information about the standard and the various Quality of Service (QoS) features described in this document.

Additional information and documentation is readily available from RTI's website in the form of white papers, data sheets, as well as the OMG DDS specification document. Additionally, the *RTI Data Distribution Service User's Manual*, which can be made available, provides a detailed overview of publish-subscribe and OMG DDS QoS options.

RTI also offers extensive training. RTI's DDS Quickstart course has over 1,000 graduates as of this writing. On-site training is available; public training schedules are available from www.rti.com.

Finally, RTI has many professionals ready to answer your questions. Email **sales@rti.com** with any business or technical questions you may have. We will happily support a no-obligation on-site evaluation.

Appendix A Running from the Command Line

In some cases you may want to run *RTI Shapes Demo* from the command line.

1. Open a command prompt and navigate to the folder where *RTI Shapes Demo* is installed.
2. Enter the following command (where <*arch*> is the architecture for your *RTI Shapes Demo* installation; for example, i86Linux2.6gcc4.1.1):

```
> bin/<arch>/rtishapesdemo <command-line options>
```

Table A.1 describes the command-line options. These options take precedence over conflicting settings in the configuration file (if any). (For example, if the configuration file specifies domain ID 1 and you enter **-domainId 2**, then domain ID 2 will be used.)

Table A.1 **Command-line Options**

Option	Description
`-compact`	Starts *RTI Shapes Demo* using a compact view
`-domainId <ID>`	For different copies of *RTI Shapes Demo* to communicate with each other, they must use the same domain ID. The default domain ID is 0; if you need to use a different domain ID, you must use the same value for all copies of *RTI Shapes Demo* that need to communicate with each other. The ID is an integer value, 0 or higher.
`-help`	Lists the command-line options.
`-posX`	Specifies the X position of the *RTI Shapes Demo* window on the screen.
`-posY`	Specifies the Y position of the *RTI Shapes Demo* window on the screen.
`-pubInterval <integer>`	Specifies how often the publisher should send data (in ms) Default: 50 ms
`-subInterval <integer>`	Specifies how often the subscriber should look for data (in ms) Default: 50 ms
`-workspaceFile <file>`	Specifies an XML configuration file. Default: See "RTI Shapes Demo's Workspace" on page 3-15.

Appendix B Using the Dynamic Version

The *RTI Shapes Demo* executable is provided in two formats, static and dynamic. Unless otherwise noted, this document refers to the static version.

The dynamic version of *RTI Shapes Demo* is built with dynamic *RTI Data Distribution Service* libraries and requires those libraries to be in the executable directory (on Windows systems) or in LD_LIBRARY_PATH (on Linux systems) at run time.

You may need to use the dynamic version if you want to use other *RTI Data Distribution Service* features that require the use of dynamic libraries.

❑ **On Linux systems**

Note: In the following commands, <*arch*> is the architecture for your *RTI Shapes Demo* installation; for example, i86Linux2.6gcc4.1.1.

1. Set your LD_LIBRARY_PATH environment variable to point to the dynamic *RTI Data Distribution Service* library for the target platform.

   For example, if you are using a **bash** shell:

   ```
   > export LD_LIBRARY_PATH=\
     <install directory>/bin/<arch>:${LD_LIBRARY_PATH}
   ```

   Or if you are using a **tcsh** shell:

   ```
   > setenv LD_LIBRARY_PATH \
     <install directory>/bin/<arch>:${LD_LIBRARY_PATH}
   ```

2. Open a command prompt and navigate to the folder where *RTI Shapes Demo* is installed.

3. Enter: `> bin/<arch>/rtishapesdemo_dynamic`

❑ **On Windows systems**

From the Start menu, select **Programs, RTI, RTI Shapes Demo <*version*>, RTI Shapes Demo Dynamic**.

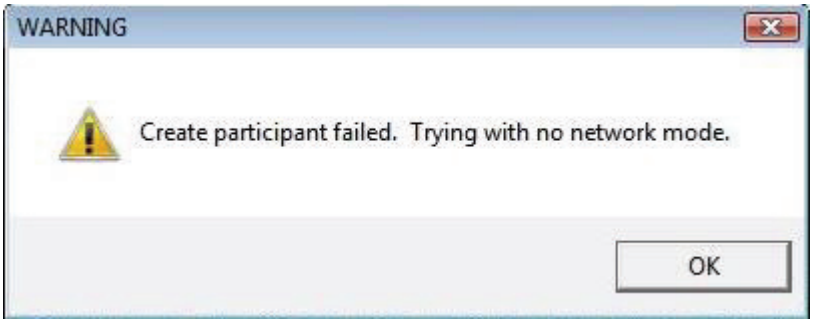
Appendix C Troubleshooting

C.1 Windows Security Alert

When you run the demo, you may encounter a "Windows Security Alert" dialog. Simply click **Unblock**.

C.2 Running without an Active Network Interface

If you run *RTI Shapes Demo* on a system that does not have an active network interface, you may see this warning:



Participant creation failed because, by default, *RTI Shapes Demo* uses UDPv4, which is not available if there is no active network interface.

After you select **OK**, *RTI Shapes Demo* will create a participant using shared memory instead of UDPv4.