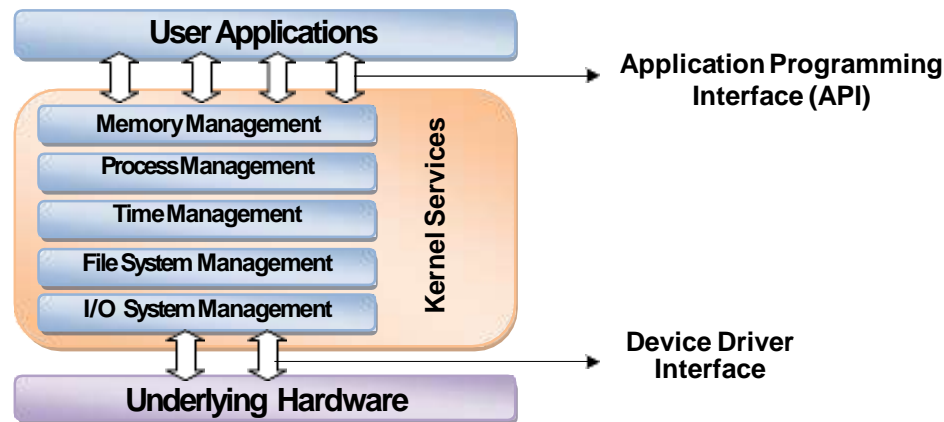


Module5
RTOS and IDE for Embedded System
Design

Designing with RTOS

Operating System Basics

- ✓ The Operating System acts as a bridge between the user applications/tasks and the underlying system resources through a set of system functionalities and services
- ✓ OS manages the system resources and makes them available to the user applications/tasks on a need basis
- ✓ The primary functions of an Operating system is
 - ✓ Make the system convenient to use
 - ✓ Organize and manage the system resources efficiently and correctly



The Operating System Architecture

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The Kernel

- ✓ The kernel is the core of the operating system
- ✓ It is responsible for managing the system resources and the communication among the hardware and other system services
- ✓ Kernel contains a set of system libraries and services. For a general purpose OS, the kernel contains different services like
 - ✓ Process Management
 - ✓ Primary Memory Management
 - ✓ File System management
 - ✓ I/O System (Device) Management
 - ✓ Secondary Storage Management
 - ✓ Protection
 - ✓ Time management
 - ✓ Interrupt Handling

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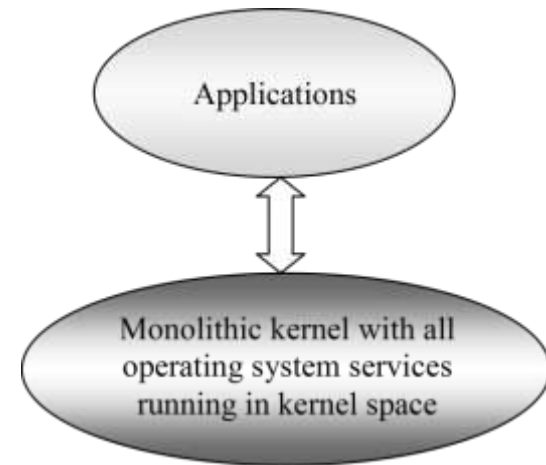
Kernel Space and User Space

- ✓ The program code corresponding to the kernel applications/services are kept in a contiguous area (OS dependent) of primary (working) memory and is protected from the un-authorized access by user programs/applications
- ✓ The memory space at which the kernel code is located is known as '*Kernel Space*'
- ✓ All user applications are loaded to a specific area of primary memory and this memory area is referred as '*User Space*'
- ✓ The partitioning of memory into kernel and user space is purely Operating System dependent
- ✓ An operating system with virtual memory support, loads the user applications into its corresponding virtual memory space with demand paging technique
- ✓ Most of the operating systems keep the kernel application code in main memory and it is not swapped out into the secondary memory

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Monolithic Kernel

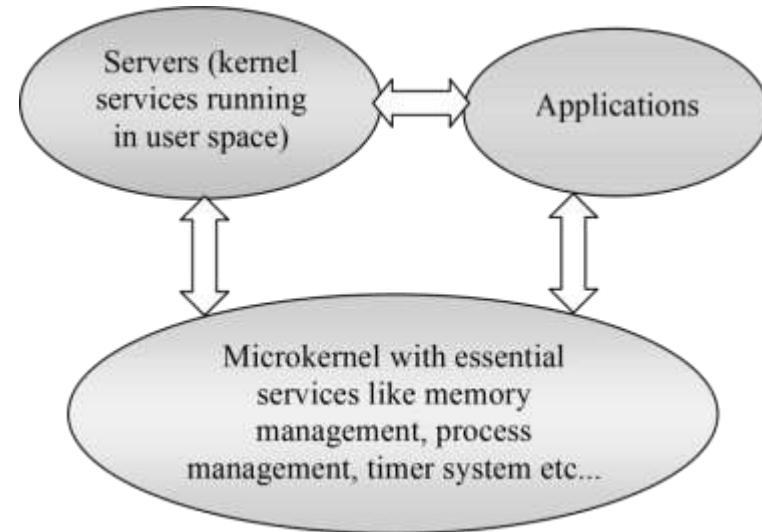
- ✓ All kernel services run in the kernel space
- ✓ All kernel modules run within the same memory space under a single kernel thread
- ✓ The tight internal integration of kernel modules in monolithic kernel architecture allows the effective utilization of the low-level features of the underlying system
- ✓ The major drawback of monolithic kernel is that any error or failure in any one of the kernel modules leads to the crashing of the entire kernel application
- ✓ LINUX, SOLARIS, MS-DOS kernels are examples of monolithic kernel



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Microkernel

- ✓ The microkernel design incorporates only the essential set of Operating System services into the kernel
- ✓ Rest of the Operating System services are implemented in programs known as ‘*Servers*’ which runs in user space
- ✓ Memory management, process management, timer systems and interrupt handlers are examples of essential services, which forms the part of the microkernel
- ✓ QNX, Minix 3 kernels are examples for microkernel



benefits

Robustness: If a problem is encountered in any of the services, which runs as ‘Server’ application, the same can be reconfigured and re-started without the need for re-starting the entire OS. Thus, this approach is highly useful for systems.

Configurability: Any services, which run as ‘Server’ application can be changed without the need to restart the whole system. This makes the system dynamically configurable.

Designing with RTOS

Types of Operating Systems

Depending on the type of kernel and kernel services, purpose and type of computing systems where the OS is deployed and the responsiveness to applications, Operating Systems are classified into

General Purpose Operating System (GPOS)

- ✓ Operating Systems, which are deployed in general computing systems
- ✓ The kernel is more generalized and contains all the required services to execute generic applications
- ✓ Need not be deterministic in execution behavior
- ✓ May inject random delays into application software and thus cause slow responsiveness of an application at unexpected times
- ✓ Usually deployed in computing systems where deterministic behavior is not an important criterion
- ✓ Personal Computer/Desktop system is a typical example for a system where GPOSs are deployed.
- ✓ Windows XP/MS-DOS etc are examples of General Purpose Operating System

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Real Time Purpose Operating System (RTOS)

- ✓ Operating Systems, which are deployed in embedded systems demanding real-time response
- ✓ Deterministic in execution behavior. Consumes only known amount of time for kernel applications
- ✓ Implements scheduling policies for executing the highest priority task/application always
- ✓ Implements policies and rules concerning time-critical allocation of a system's resources
- ✓ Windows CE, QNX, VxWorks MicroC/OS-II etc are examples of Real Time Operating Systems (RTOS)

Designing with RTOS

The Real Time Kernel

The kernel of a Real Time Operating System is referred as Real Time kernel. In complement to the conventional OS kernel, the Real Time kernel is highly specialized and it contains only the minimal set of services required for running the user applications/tasks. The basic functions of a Real Time kernel are

- Task/Process management
- Task/Process scheduling
- Task/Process synchronization
- Error/Exception handling
- Memory Management
- Interrupt handling
- Time management

Designing with RTOS

Real Time Kernel – Task/Process Management

Deals with setting up the memory space for the tasks, loading the task's code into the memory space, allocating system resources, setting up a Task Control Block (TCB) for the task and task/process termination/deletion. A Task Control Block (TCB) is used for holding the information corresponding to a task. TCB usually contains the following set of information

- *Task ID*: Task Identification Number
- *Task State*: The current state of the task. (E.g. State= 'Ready' for a task which is ready to execute)
- *Task Type*: Task type. Indicates what is the type for this task. The task can be a hard real time or soft real time or background task.
- *Task Priority*: Task priority (E.g. Task priority =1 for task with priority = 1)
- *Task Context Pointer*: Context pointer. Pointer for context saving
- *Task Memory Pointers*: Pointers to the code memory, data memory and stack memory for the task
- *Task System Resource Pointers*: Pointers to system resources (semaphores, mutex etc) used by the task
- *Task Pointers*: Pointers to other TCBs (TCBs for preceding, next and waiting tasks)
- *Other Parameters* Other relevant task parameters

The parameters and implementation of the TCB is kernel dependent. The TCB parameters vary across₁₀ different kernels, based on the task management implementation

Designing with RTOS

- **Task/Process Scheduling:** Deals with sharing the CPU among various tasks/processes. A kernel application called '*Scheduler*' handles the task scheduling. Scheduler is nothing but an algorithm implementation, which performs the efficient and optimal scheduling of tasks to provide a deterministic behavior.
- **Task/Process Synchronization:** Deals with synchronizing the concurrent access of a resource, which is shared across multiple tasks and the communication between various tasks.
- **Error/Exception handling:** Deals with registering and handling the errors occurred/exceptions raised during the execution of tasks. Insufficient memory, timeouts, deadlocks, deadline missing, bus error, divide by zero, unknown instruction execution etc, are examples of errors/exceptions. Errors/Exceptions can happen at the kernel level services or at task level. Deadlock is an example for kernel level exception, whereas timeout is an example for a task level exception. The OS kernel gives the information about the error in the form of a system call (API).

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Memory Management

- ✓ The memory management function of an RTOS kernel is slightly different compared to the General Purpose Operating Systems
- ✓ In general, the memory allocation time increases depending on the size of the block of memory needs to be allocated and the state of the allocated memory block (initialized memory block consumes more allocation time than un-initialized memory block)
- ✓ RTOS generally uses '*block*' based memory allocation technique, instead of the usual dynamic memory allocation techniques used by the GPOS.
- ✓ RTOS kernel uses blocks of fixed size of dynamic memory and the block is allocated for a task on a need basis. The blocks are stored in a '*Free buffer Queue*'.
- ✓ Most of the RTOS kernels allow tasks to access any of the memory blocks without any memory protection to achieve predictable timing and avoid the timing overheads
- ✓ RTOS kernels assume that the whole design is proven correct and protection is unnecessary. Some commercial RTOS kernels allow memory protection as optional and the kernel enters a *fail-safe* mode when an illegal memory access occurs

Designing with RTOS

Interrupt Handling

- ✓ Interrupts inform the processor that an external device or an associated task requires immediate attention of the CPU.
- ✓ Interrupts can be either *Synchronous* or *Asynchronous*.
- ✓ Interrupts which occurs in sync with the currently executing task is known as *Synchronous* interrupts. Usually the software interrupts fall under the Synchronous Interrupt category. Divide by zero, memory segmentation error etc are examples of Synchronous interrupts.
- ✓ Asynchronous interrupts are interrupts, which occurs at any point of execution of any task, and are not in sync with the currently executing task.
- ✓ For asynchronous interrupts, the interrupt handler is usually written as separate task (Depends on OS Kernel implementation) and it runs in a different context. Hence, a context switch happens while handling the asynchronous interrupts.
- ✓ Priority levels can be assigned to the interrupts and each interrupts can be enabled or disabled individually.

Designing with RTOS

Time Management

- ✓ Interrupts inform the processor that an external device or an associated task requires immediate attention of the CPU.
- ✓ Accurate time management is essential for providing precise time reference for all applications
- ✓ The time reference to kernel is provided by a high-resolution Real Time Clock (RTC) hardware chip (hardware timer)
- ✓ The hardware timer is programmed to interrupt the processor/controller at a fixed rate. This timer interrupt is referred as '*Timer tick*'
- ✓ The '*Timer tick*' is taken as the timing reference by the kernel. The '*Timer tick*' interval may vary depending on the hardware timer. Usually the '*Timer tick*' varies in the microseconds range
- ✓ The time parameters for tasks are expressed as the multiples of the '*Timer tick*'
- ✓ The System time is updated based on the '*Timer tick*'

Designing with RTOS

Time Management

The '*Timer tick*' interrupt is handled by the 'Timer Interrupt' handler of kernel. The '*Timer tick*' interrupt can be utilized for implementing the following actions.

- ✓ Save the current context (Context of the currently executing task)
- ✓ Increment the System time register by one. Generate timing error and reset the System time register if the timer tick count is greater than the maximum range available for System time register
- ✓ Update the timers implemented in kernel (Increment or decrement the timer registers for each timer depending on the count direction setting for each register. Increment registers with count direction setting = '*count up*' and decrement registers with count direction setting = '*count down*')
- ✓ Activate the periodic tasks, which are in the idle state
- ✓ Invoke the scheduler and schedule the tasks again based on the scheduling algorithm
- ✓ Delete all the terminated tasks and their associated data structures (TCBs)
- ✓ Load the context for the first task in the ready queue. Due to the re-scheduling, the ready task might be changed to a new one from the task, which was pre-empted by the 'Timer Interrupt' task

Designing with RTOS

Hard Real-time System

- ✓ A Real Time Operating Systems which strictly adheres to the timing constraints for a task
- ✓ A Hard Real Time system must meet the deadlines for a task without any slippage
- ✓ Missing any deadline may produce catastrophic results for Hard Real Time Systems, including permanent data lose and irrecoverable damages to the system/users
- ✓ Emphasize on the principle '*A late answer is a wrong answer*'
- ✓ Air bag control systems and Anti-lock Brake Systems (ABS) of vehicles are typical examples of Hard Real Time Systems
- ✓ As a rule of thumb, Hard Real Time Systems does not implement the virtual memory model for handling the memory. This eliminates the delay in swapping in and out the code corresponding to the task to and from the primary memory
- ✓ The presence of *Human in the loop (HITL)* for tasks introduces un-expected delays in the task execution. Most of the Hard Real Time Systems are automatic and does not contain a 'human in the loop'

Designing with RTOS

Soft Real-time System

- ✓ Real Time Operating Systems that does not guarantee meeting deadlines, but, offer the best effort to meet the deadline
- ✓ Missing deadlines for tasks are acceptable if the frequency of deadline missing is within the compliance limit of the Quality of Service (QoS)
- ✓ A Soft Real Time system emphasizes on the principle ‘*A late answer is an acceptable answer, but it could have done bit faster*’
- ✓ Soft Real Time systems most often have a ‘*human in the loop (HITL)*’
- ✓ Automatic Teller Machine (ATM) is a typical example of Soft Real Time System. If the ATM takes a few seconds more than the ideal operation time, nothing fatal happens.
- ✓ An audio video play back system is another example of Soft Real Time system. No potential damage arises if a sample comes late by fraction of a second, for play back

Designing with RTOS

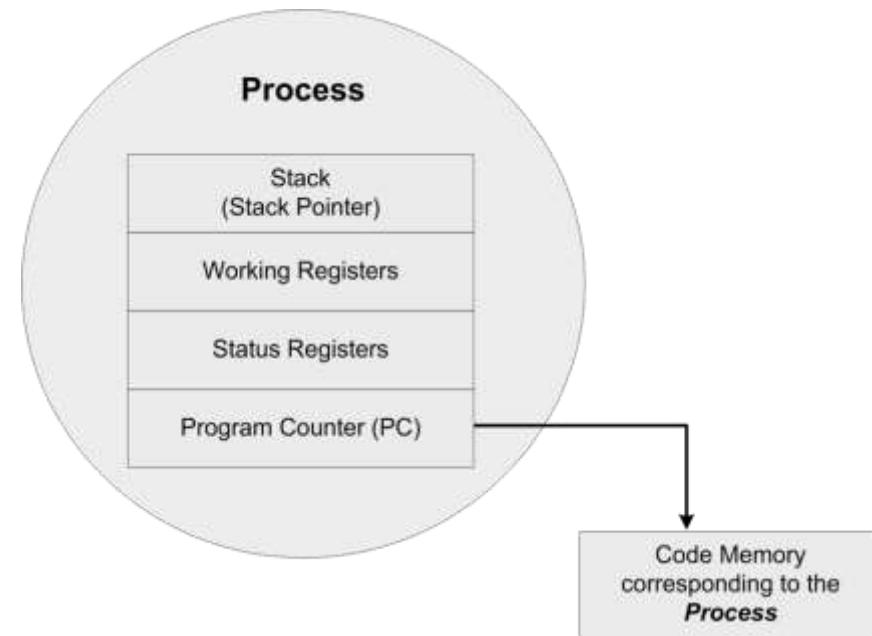
Tasks, Processes & Threads

- ✓ In the Operating System context, a task is defined as the program in execution and the related information maintained by the Operating system for the program
- ✓ Task is also known as '*Job*' in the operating system context
- ✓ A program or part of it in execution is also called a '*Process*'
- ✓ The terms '*Task*', '*job*' and '*Process*' refer to the same entity in the Operating System context and most often they are used interchangeably
- ✓ A process requires various system resources like CPU for executing the process, memory for storing the code corresponding to the process and associated variables, I/O devices for information exchange etc

Designing with RTOS

The structure of a Processes

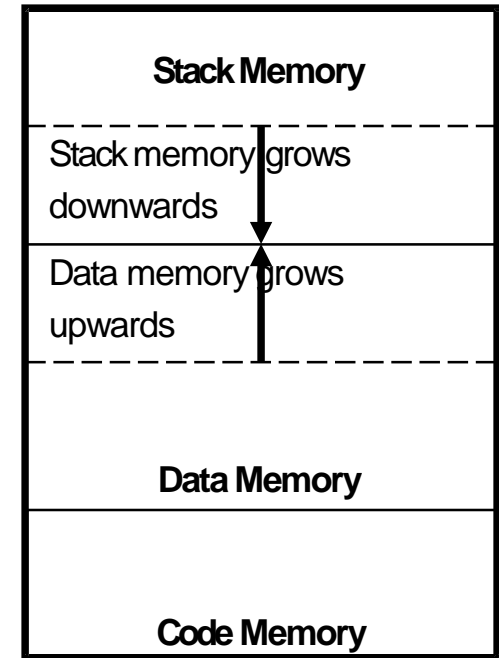
- ✓ The concept of '*Process*' leads to concurrent execution (pseudo parallelism) of tasks and thereby the efficient utilization of the CPU and other system resources
- ✓ Concurrent execution is achieved through the sharing of CPU among the processes
- ✓ A process holds a set of registers, process status, a Program Counter (PC) to point to the next executable instruction of the process, a stack for holding the local variables associated with the process and the code corresponding to the process
- ✓ When the process gets its turn, its registers and Program counter register becomes mapped to the physical registers of the CPU



Designing with RTOS

Memory organization of a Processes

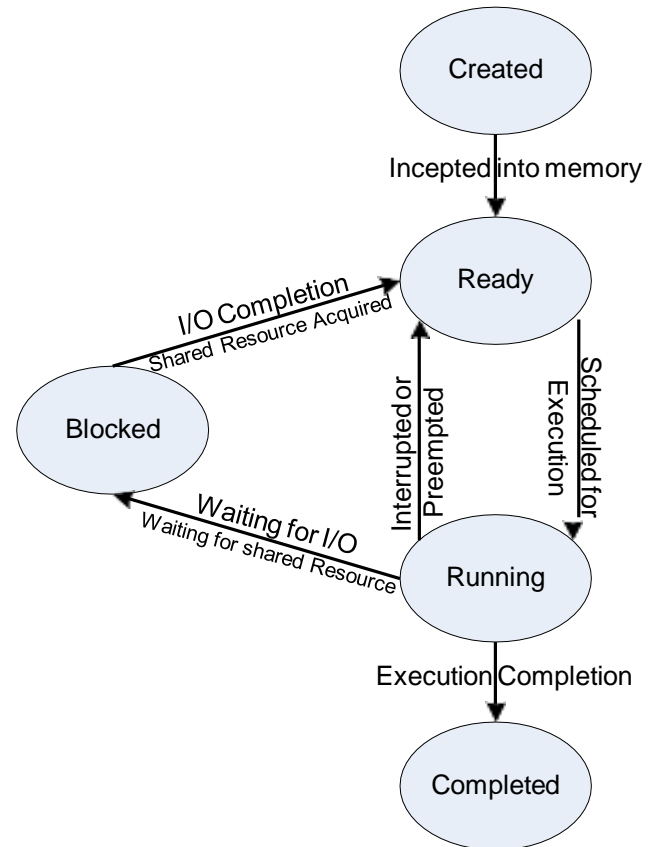
- ✓ The memory occupied by the *process* is segregated into three regions namely; Stack memory, Data memory and Code memory
- ✓ The ‘Stack’ memory holds all temporary data such as variables local to the process
- ✓ Data memory holds all global data for the process
- ✓ The code memory contains the program code (instructions) corresponding to the process
- ✓ On loading a process into the main memory, a specific area of memory is allocated for the process
- ✓ The stack memory usually starts at the highest memory address from the memory area allocated for the process (Depending on the OS kernel implementation)



Designing with RTOS

Process States & State Transition

- ✓ The creation of a process to its termination is not a single step operation
- ✓ The process traverses through a series of states during its transition from the newly created state to the terminated state
- ✓ The cycle through which a process changes its state from ‘*newly created*’ to ‘*execution completed*’ is known as ‘*Process Life Cycle*’. The various states through which a process traverses through during a Process Life Cycle indicates the current status of the process with respect to time and also provides information on what it is allowed to do next



Designing with RTOS

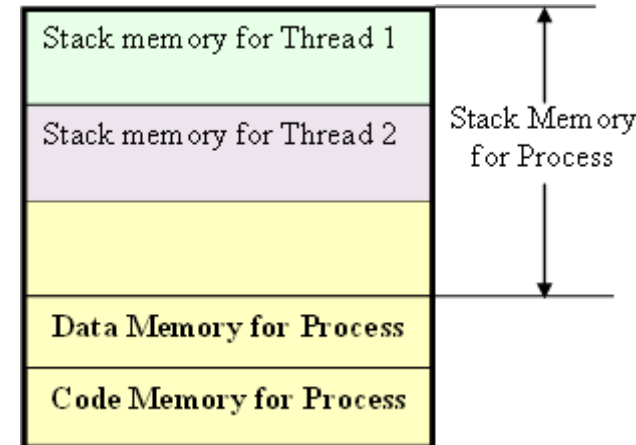
Process States & State Transition

- **Created State:** The state at which a process is being created is referred as 'Created State'. The Operating System recognizes a process in the '*Created State*' but no resources are allocated to the process
 - **Ready State:** The state, where a process is incepted into the memory and awaiting the processor time for execution, is known as '*Ready State*'. At this stage, the process is placed in the '*Ready list*' queue maintained by the OS
 - **Running State:** The state where in the source code instructions corresponding to the process is being executed is called '*Running State*'. Running state is the state at which the process execution happens.
 - **Blocked State/Wait State:** Refers to a state where a running process is temporarily suspended from execution and does not have immediate access to resources. The blocked state might have invoked by various conditions like- the process enters a wait state for an event to occur (E.g. Waiting for user inputs such as keyboard input) or waiting for getting access to a shared resource like semaphore, mutex etc
 - **Completed State:** A state where the process completes its execution
- ✓ The transition of a process from one state to another is known as '*State transition*'
- ✓ When a process changes its state from Ready to running or from running to blocked or terminated or from blocked to running, the CPU allocation for the process may also₂₃ change

Designing with RTOS

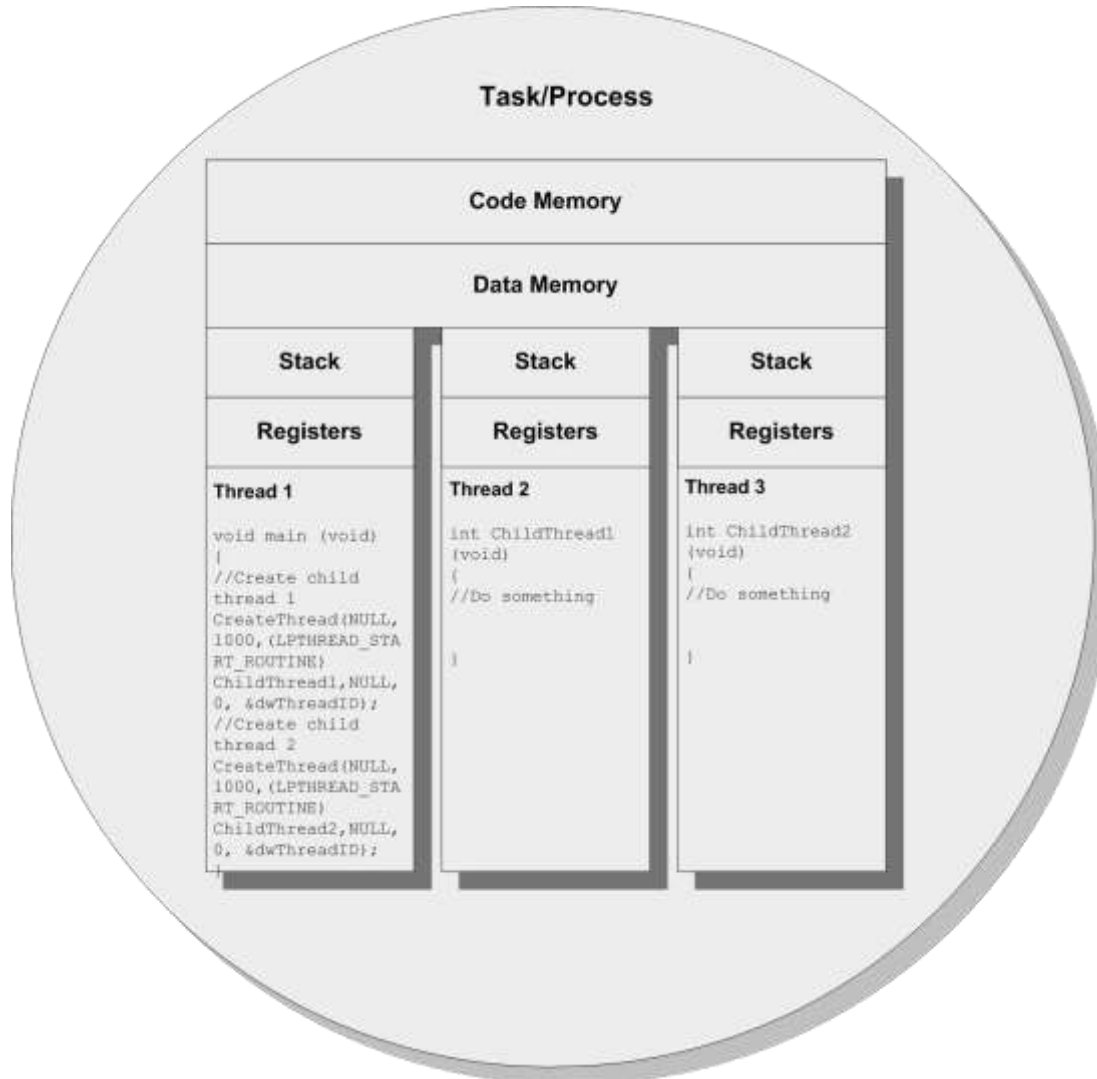
Threads

- ✓ A *thread* is the primitive that can execute code
- ✓ A *thread* is a single sequential flow of control within a process
- ✓ '*Thread*' is also known as lightweight process
- ✓ A process can have many threads of execution
- ✓ Different threads, which are part of a process, share the same address space.
- ✓ Threads maintain their own thread status (CPU register values), Program Counter (PC) and stack



Designing with RTOS

The Concept of multithreading



Designing with RTOS

The Concept of multithreading

Use of multiple threads to execute a process brings the following advantage.

- ✓ Better memory utilization. Multiple threads of the same process share the address space for data memory. This also reduces the complexity of inter thread communication since variables can be shared across the threads.
- ✓ Since the process is split into different threads, when one thread enters a wait state, the CPU can be utilized by other threads of the process that do not require the event, which the other thread is waiting, for processing. This speeds up the execution of the process.
- ✓ Efficient CPU utilization. The CPU is engaged all time.

Designing with RTOS

User & Kernel level threads

- **User Level Thread:** : User level threads do not have kernel/Operating System support and they exist solely in the running process. Even if a process contains multiple user level threads, the OS treats it as single thread and will not switch the execution among the different threads of it. It is the responsibility of the process to schedule each thread as and when required. In summary, user level threads of a process are non-preemptive at thread level from OS perspective.
- **Kernel Level/System Level Thread:** Kernel level threads are individual units of execution, which the OS treats as separate threads. The OS interrupts the execution of the currently running kernel thread and switches the execution to another kernel thread based on the scheduling policies implemented by the OS.

Designing with RTOS

Thread V/s Process

Thread	Process
Thread is a single unit of execution and is part of process.	Process is a program in execution and contains one or more threads.
A thread does not have its own data memory and heap memory. It shares the data memory and heap memory with other threads of the same process.	Process has its own code memory, data memory and stack memory.
A thread cannot live independently; it lives within the process.	A process contains at least one thread.
There can be multiple threads in a process. The first thread (main thread) calls the main function and occupies the start of the stack memory of the process.	Threads within a process share the code, data and heap memory. Each thread holds separate memory area for stack (shares the total stack memory of the process).
Threads are very inexpensive to create	Processes are very expensive to create. Involves many OS overhead.
Context switching is inexpensive and fast	Context switching is complex and involves lot of OS overhead and is comparatively slower.
If a thread expires, its stack is reclaimed by the process.	If a process dies, the resources allocated to it are reclaimed by the OS and all the associated threads of the process also dies.

Designing with RTOS

Multiprocessing & Multitasking

- ✓ The ability to execute multiple processes simultaneously is referred as *multiprocessing*
- ✓ Systems which are capable of performing multiprocessing are known as *multiprocessor* systems
- ✓ The ability of the Operating System to have multiple programs in memory, which are ready for execution, is referred as *multiprogramming*
- ✓ *Multitasking* refers to the ability of an operating system to hold multiple processes in memory and switch the processor (CPU) from executing one process to another process
- ✓ *Multitasking* involves ‘*Context switching*’, ‘*Context saving*’ and ‘*Context retrieval*’
- ✓ *Context switching* refers to the switching of execution context from task to other
- ✓ When a task/process switching happens, the current context of execution should be saved to (*Context saving*) retrieve it at a later point of time when the CPU executes the process, which is interrupted currently due to execution switching
- ✓ During context switching, the context of the task to be executed is retrieved from the saved context list. This is known as *Context retrieval*

Designing with RTOS

Types of Multitasking

Depending on how the task/process execution switching act is implemented, multitasking can be classified into

- **Co-operative Multitasking:** Co-operative multitasking is the most primitive form of multitasking in which a task/process gets a chance to execute only when the currently executing task/process voluntarily relinquishes the CPU. In this method, any task/process can avail the CPU as much time as it wants. Since this type of implementation involves the mercy of the tasks each other for getting the CPU time for execution, it is known as co-operative multitasking.
Preemptive Multitasking: Preemptive multitasking ensures that every task/process gets a chance to execute. When and how much time a process gets is dependent on the implementation of the preemptive scheduling. As the name indicates, in preemptive multitasking, the currently running task/process is preempted to give a chance to other tasks/process to execute. The preemption of task may be based on time slots or task/process priority
- **Non-preemptive Multitasking:** The process/task, which is currently given the CPU time, is allowed to execute until it terminates (enters the 'Completed' state) or enters the 'Blocked/Wait' state, waiting for an I/O. The co-operative and non-preemptive multitasking differs in their behavior when they are in the 'Blocked/Wait' state. In co-operative multitasking, the currently executing process/task need not relinquish the CPU when it enters the 'Blocked/Wait' state, waiting for an I/O, or a shared resource access or an event to occur whereas in non-preemptive

multitasking the currently executing task relinquishes the CPU when it waits for an I/O.

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Task Scheduling

- ✓ In a multitasking system, there should be some mechanism in place to share the CPU among the different tasks and to decide which process/task is to be executed at a given point of time
- ✓ Determining which task/process is to be executed at a given point of time is known as task/process scheduling
- ✓ Task scheduling forms the basis of multitasking
- ✓ Scheduling policies forms the guidelines for determining which task is to be executed when
- ✓ The scheduling policies are implemented in an algorithm and it is run by the kernel as a service
- ✓ The kernel service/application, which implements the scheduling algorithm, is known as '*Scheduler*'
- ✓ The task scheduling policy can be *pre-emptive*, *non-preemptive* or *co-operative*

Designing with RTOS

Task Scheduling - Scheduler Selection

The selection of a scheduling criteria/algorithm should consider

- **CPU Utilization:** The scheduling algorithm should always make the CPU utilization high. CPU utilization is a direct measure of how much percentage of the CPU is being utilized.
- **Throughput:** This gives an indication of the number of processes executed per unit of time. The throughput for a good scheduler should always be higher.
- **Turnaround Time:** It is the amount of time taken by a process for completing its execution. It includes the time spent by the process for waiting for the main memory, time spent in the ready queue, time spent on completing the I/O operations, and the time spent in execution. The turnaround time should be a minimum for a good scheduling algorithm.
- **Waiting Time:** It is the amount of time spent by a process in the '*Ready*' queue waiting to get the CPU time for execution. The waiting time should be minimal for a good scheduling algorithm.
- **Response Time:** It is the time elapsed between the submission of a process and the first response. For a good scheduling algorithm, the response time should be as least as possible.

To summarize, a good scheduling algorithm has high CPU utilization, minimum Turn Around Time (TAT), maximum throughput and least response time.

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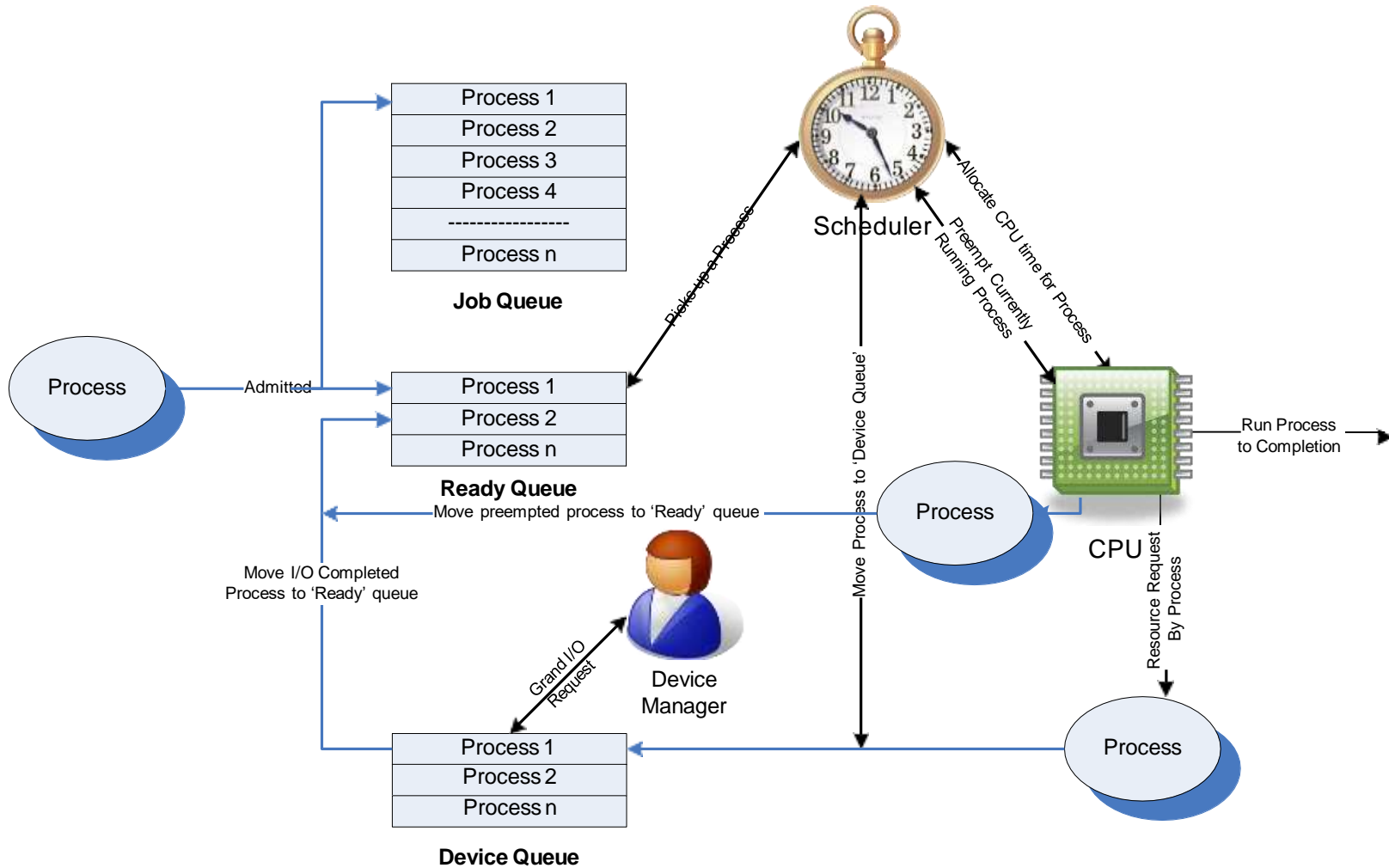
Task Scheduling - Queues

The various queues maintained by OS in association with CPU scheduling are

- **Job Queue:** Job queue contains all the processes in the system
- **Ready Queue:** Contains all the processes, which are ready for execution and waiting for CPU to get their turn for execution. The Ready queue is empty when there is no process ready for running.
- **Device Queue:** Contains the set of processes, which are waiting for an I/O device

Designing with RTOS

Task Scheduling – Task transition through various Queues

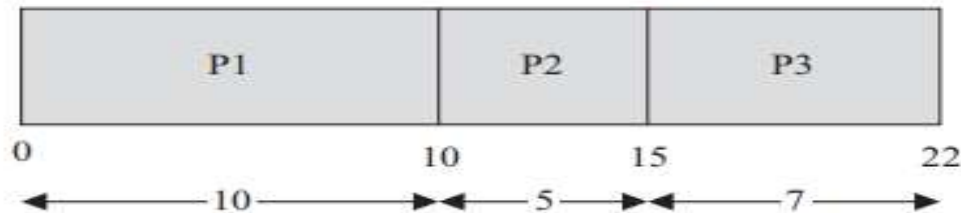


Non- Preemptive scheduling

First-Come-First-Served (FCFS)/ FIFO Scheduling

Three processes with process IDs P1, P2, P3 with estimated completion time 10, 5, 7 milliseconds respectively enters the ready queue together in the order P1, P2, P3. Calculate the waiting time and Turn Around Time (TAT) for each process and the average waiting time and Turn Around Time (Assuming there is no I/O waiting for the processes).

The sequence of execution of the processes by the CPU is represented as



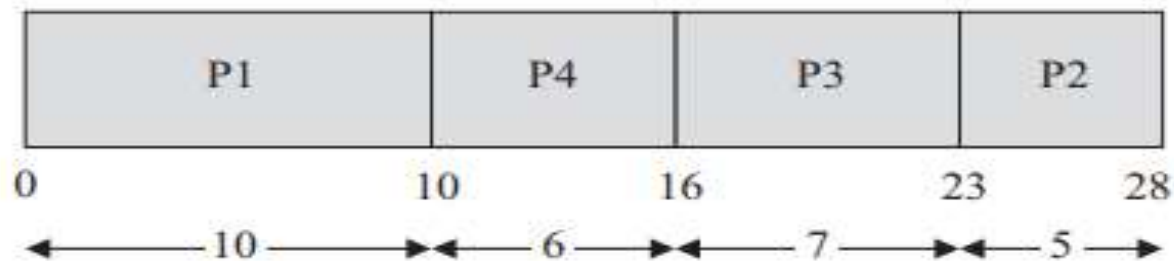
Average waiting time = (Waiting time for all processes) / No. of Processes
= 8.33 milliseconds

Average Turn Around Time = (Turn Around Time for all processes) / No. of Processes
= 15.66 milliseconds

Average Execution Time = (Execution time for all processes) / No. of processes
= 7.33

Last-Come-First Served (LCFS)/LIFO Scheduling

Three processes with process IDs P1, P2, P3 with estimated completion time 10, 5, 7 milliseconds respectively enters the ready queue together in the order P1, P2, P3 (Assume only P1 is present in the 'Ready' queue when the scheduler picks it up and P2, P3 entered 'Ready' queue after that). Now a new process P4 with estimated completion time 6 ms enters the 'Ready' queue after 5 ms of scheduling P1. Calculate the waiting time and Turn Around Time (TAT) for each process and the Average waiting time and Turn Around Time (Assuming there is no I/O waiting for the processes). Assume all the processes contain only CPU operation and no I/O operations are involved

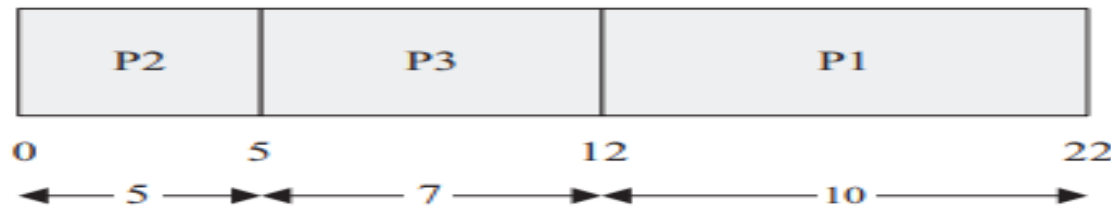


$$\begin{aligned}\text{Average waiting time} &= (\text{Waiting time for all processes}) / \text{No. of Processes} \\ &= (\text{Waiting time for (P1+P4+P3+P2)}) / 4 \\ &= (0 + 5 + 16 + 23)/4 = 44/4 \\ &= 11 \text{ milliseconds}\end{aligned}$$

$$\begin{aligned}\text{Average Turn Around Time} &= (\text{Turn Around Time for all processes}) / \text{No. of Processes} \\ &= (\text{Turn Around Time for (P1+P4+P3+P2)}) / 4 \\ &= (10+11+23+28)/4 \\ &= 72/4 = 18 \text{ milliseconds}\end{aligned}$$

Shortest Job First (SJF) Scheduling

Three processes with process IDs P1, P2, P3 with estimated completion time 10, 5, 7 milliseconds respectively enters the ready queue together. Calculate the waiting time and Turn Around Time (TAT) for each process and the Average waiting time and Turn Around Time (Assuming there is no I/O waiting for the processes) in SJF algorithm.



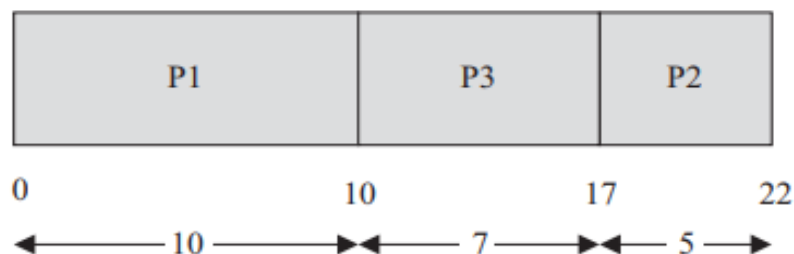
$$\text{Average waiting time} = (0+5+12)/3 = 17/3 \\ = 5.66 \text{ milliseconds.}$$

$$\text{Average Turn Around Time} = (5+12+22)/3 = 39/3 \\ = 13 \text{ milliseconds}$$

$$\text{The average Execution time} = (10+5+7)/3 = 22/3 = 7.33$$

Priority Based Scheduling

Three processes with process IDs P1, P2, P3 with estimated completion time 10, 5, 7 milliseconds and priorities 0, 3, 2 (0—highest priority, 3—lowest priority) respectively enters the ready queue together. Calculate the waiting time and Turn Around Time (TAT) for each process and the Average waiting time and Turn Around Time (Assuming there is no I/O waiting for the processes) in priority based scheduling algorithm.



Average waiting time = $(0+10+17)/3 = 27/3 = 9$ milliseconds

Average Turn Around Time = $(10+17+22)/3 = 49/3 = 16.33$ milliseconds

Designing with RTOS

Preemptive scheduling

- ✓ Employed in systems, which implements preemptive multitasking model
- ✓ Every task in the '*Ready*' queue gets a chance to execute. When and how often each process gets a chance to execute (gets the CPU time) is dependent on the type of preemptive scheduling algorithm used for scheduling the processes
- ✓ The scheduler can preempt the currently executing task/process and select another task from the '*Ready*' queue for execution
- ✓ When to pre-empt a task and which task is to be picked up from the '*Ready*' queue for execution after preempting the current task is purely dependent on the scheduling algorithm
- ✓ A task which is preempted by the scheduler is moved to the '*Ready*' queue. The act of moving a '*Running*' process/task into the '*Ready*' queue by the scheduler, without the processes requesting for it is known as '*Preemption*'
- ✓ Time-based preemption and priority-based preemption are the two important approaches adopted in preemptive scheduling

Designing with RTOS

Preemptive scheduling – Preemptive SJF Scheduling/ Shortest Remaining Time (SRT)

- ✓ The *non preemptive SJF* scheduling algorithm sorts the ‘Ready’ queue only after the current process completes execution or enters wait state, whereas the *preemptive SJF* scheduling algorithm sorts the ‘Ready’ queue when a new process enters the ‘Ready’ queue and checks whether the execution time of the new process is shorter than the remaining of the total estimated execution time of the currently executing process
- ✓ If the execution time of the new process is less, the currently executing process is preempted and the new process is scheduled for execution
- ✓ Always compares the execution completion time (ie the remaining execution time for the new process) of a new process entered the ‘Ready’ queue with the remaining time for completion of the currently executing process and schedules the process with shortest remaining time for execution

Designing with RTOS

Preemptive scheduling – Preemptive SJF Scheduling

- Three processes with process IDs P1, P2, P3 with estimated completion time 10, 5, 7 milliseconds respectively enters the ready queue together. A new process P4 with estimated completion time 2ms enters the 'Ready' queue after 2ms. Assume all the processes contain only CPU operation and no I/O operations are involved.
- At the beginning, there are only three processes (P1, P2 and P3) available in the 'Ready' queue and the SRT scheduler picks up the process with the Shortest remaining time for execution completion (In this example P2 with remaining time 5ms) for scheduling. Now process P4 with estimated execution completion time 2ms enters the 'Ready' queue after 2ms of start of execution of P2. The processes are re-scheduled for execution in the following order



Designing with RTOS

Non-preemptive scheduling – Preemptive SJF Scheduling

The waiting time for all the processes are given as

Waiting Time for P2 = 0 ms + (4 - 2) ms = 2ms (P2 starts executing first and is interrupted by P4 and has to wait till the completion of P4 to get the next CPU slot)

Waiting Time for P4 = 0 ms (P4 starts executing by preempting P2 since the execution time for completion of P4 (2ms) is less than that of the Remaining time for execution completion of P2 (Here it is 3ms))

Waiting Time for P3 = 7 ms (P3 starts executing after completing P4 and P2)

Waiting Time for P1 = 14 ms (P1 starts executing after completing P4, P2 and P3)

Average waiting time = (Waiting time for all the processes) / No. of Processes
 = (Waiting time for (P4+P2+P3+P1)) / 4
 = (0 + 2 + 7 + 14)/4 = 23/4
 = 5.75 milliseconds

Turn Around Time (TAT) for P2 = 7 ms (Time spent in Ready Queue + Execution Time)

Turn Around Time (TAT) for P4 = 2 ms

(Time spent in Ready Queue + Execution Time = (Execution Start Time – Arrival Time) + Estimated Execution Time = (2-2) + 2)

Turn Around Time (TAT) for P3 = 14 ms (Time spent in Ready Queue + Execution Time)

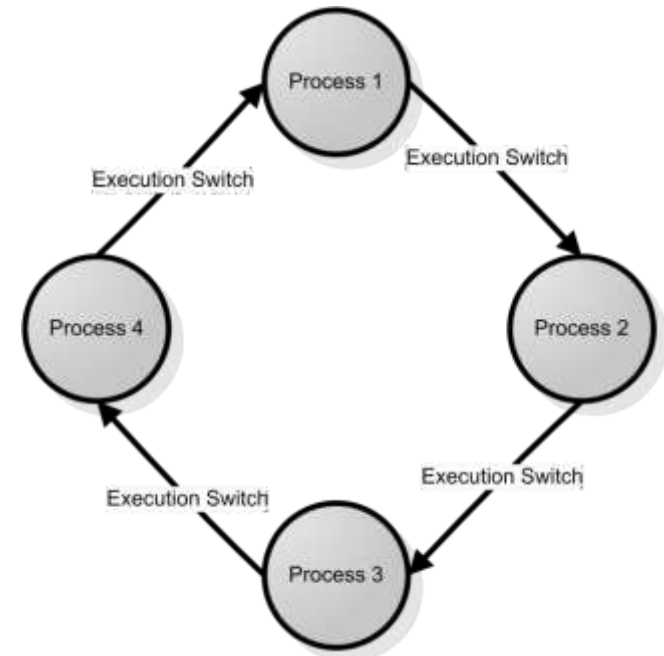
Turn Around Time (TAT) for P1 = 24 ms (Time spent in Ready Queue + Execution Time)

Average Turn Around Time = (Turn Around Time for all the processes) / No. of Processes
 = (Turn Around Time for (P2+P4+P3+P1)) / 4
 = (7+2+14+24)/4 = 47/4
 = 11.75 milliseconds

Designing with RTOS

Preemptive scheduling – Round Robin (RR) Scheduling

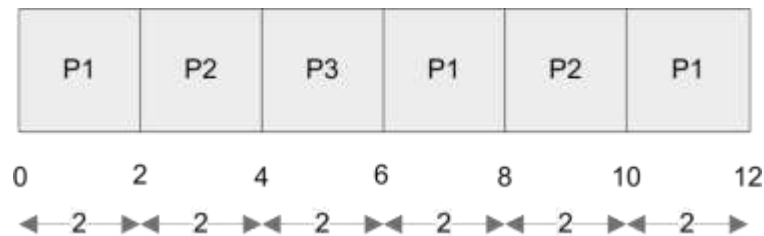
- ✓ Each process in the ‘Ready’ queue is executed for a pre-defined time slot.
- ✓ The execution starts with picking up the first process in the ‘Ready’ queue. It is executed for a pre-defined time
- ✓ When the pre-defined time elapses or the process completes (before the pre-defined time slice), the next process in the ‘Ready’ queue is selected for execution.
- ✓ This is repeated for all the processes in the ‘Ready’ queue
- ✓ Once each process in the ‘Ready’ queue is executed for the pre-defined time period, the scheduler comes back and picks the first process in the ‘Ready’ queue again for execution
- ✓ Round Robin scheduling is similar to the FCFS scheduling and the only difference is that a time slice based preemption is added to switch the execution between the processes in the ‘Ready’ queue



Designing with RTOS

Preemptive scheduling – Round Robin Scheduling

- Three processes with process IDs P1, P2, P3 with estimated completion time 6, 4, 2 milliseconds respectively, enters the ready queue together in the order P1, P2, P3. Calculate the waiting time and Turn Around Time (TAT) for each process and the Average waiting time and Turn Around Time (Assuming there is no I/O waiting for the processes) in RR algorithm with Time slice= 2ms.
- The scheduler sorts the ‘Ready’ queue based on the FCFS policy and picks up the first process P1 from the ‘Ready’ queue and executes it for the time slice 2ms. When the time slice is expired, P1 is preempted and P2 is scheduled for execution. The Time slice expires after 2ms of execution of P2. Now P2 is preempted and P3 is picked up for execution. P3 completes its execution within the time slice and the scheduler picks P1 again for execution for the next time slice. This procedure is repeated till all the processes are serviced. The order in which the processes are scheduled for execution is represented as



Designing with RTOS

Non-preemptive scheduling – Round Robin Scheduling

The waiting time for all the processes are given as

Waiting Time for P1 = $0 + (6-2) + (10-8) = 0+4+2 = 6\text{ms}$ (P1 starts executing first and waits for two time slices to get execution back and again 1 time slice for getting CPU time)

Waiting Time for P2 = $(2-0) + (8-4) = 2+4 = 6\text{ms}$ (P2 starts executing after P1 executes for 1 time slice and waits for two time slices to get the CPU time)

Waiting Time for P3 = $(4 - 0) = 4\text{ms}$ (P3 starts executing after completing the first time slices for P1 and P2 and completes its execution in a single time slice.)

Average waiting time = (Waiting time for all the processes) / No. of Processes
 = (Waiting time for (P1+P2+P3)) / 3
 = $(6+6+4)/3 = 16/3$
 = 5.33 milliseconds

Turn Around Time (TAT) for P1 = 12 ms (Time spent in Ready Queue + Execution Time)

Turn Around Time (TAT) for P2 = 10 ms (-Do-)

Turn Around Time (TAT) for P3 = 6 ms (-Do-)

Average Turn Around Time = (Turn Around Time for all the processes) / No. of Processes
 = (Turn Around Time for (P1+P2+P3)) / 3
 = $(12+10+6)/3 = 28/3$
 = 9.33 milliseconds

Designing with RTOS

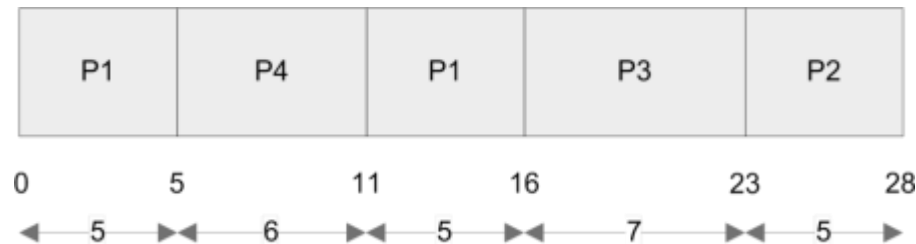
Preemptive scheduling – Priority based Scheduling

- ✓ Same as that of the *non-preemptive priority* based scheduling except for the switching of execution between tasks
- ✓ In *preemptive priority* based scheduling, any high priority process entering the ‘Ready’ queue is immediately scheduled for execution whereas in the *non-preemptive* scheduling any high priority process entering the ‘Ready’ queue is scheduled only after the currently executing process completes its execution or only when it voluntarily releases the CPU
- ✓ The priority of a task/process in preemptive priority based scheduling is indicated in the same way as that of the mechanisms adopted for non-preemptive multitasking

Designing with RTOS

Preemptive scheduling – Priority based Scheduling

- Three processes with process IDs P1, P2, P3 with estimated completion time 10, 5, 7 milliseconds and priorities 1, 3, 2 (0- highest priority, 3 lowest priority) respectively enters the ready queue together. A new process P4 with estimated completion time 6ms and priority 0 enters the ‘Ready’ queue after 5ms of start of execution of P1. Assume all the processes contain only CPU operation and no I/O operations are involved.
- At the beginning, there are only three processes (P1, P2 and P3) available in the ‘Ready’ queue and the scheduler picks up the process with the highest priority (In this example P1 with priority 1) for scheduling. Now process P4 with estimated execution completion time 6ms and priority 0 enters the ‘Ready’ queue after 5ms of start of execution of P1. The processes are re-scheduled for execution in the following order



Designing with RTOS

Preemptive scheduling – Priority based Scheduling

The waiting time for all the processes are given as

Waiting Time for P1 = $0 + (11-5) = 0+6 = 6$ ms (P1 starts executing first and gets preempted by P4 after 5ms and again gets the CPU time after completion of P4)

Waiting Time for P4 = 0 ms (P4 starts executing immediately on entering the ‘Ready’ queue, by preempting P1)

Waiting Time for P3 = 16 ms (P3 starts executing after completing P1 and P4)

Waiting Time for P2 = 23 ms (P2 starts executing after completing P1, P4 and P3)

$$\begin{aligned} \text{Average waiting time} &= (\text{Waiting time for all the processes}) / \text{No. of Processes} \\ &= (\text{Waiting time for (P1+P4+P3+P2)}) / 4 \\ &= (6 + 0 + 16 + 23)/4 = 45/4 \\ &= 11.25 \text{ milliseconds} \end{aligned}$$

Turn Around Time (TAT) for P1 = 16 ms (Time spent in Ready Queue + Execution Time)

Turn Around Time (TAT) for P4 = 6ms (Time spent in Ready Queue + Execution Time = (Execution Start Time – Arrival Time) + Estimated Execution Time = $(5-5) + 6 = 0 + 6$)

Turn Around Time (TAT) for P3 = 23 ms (Time spent in Ready Queue + Execution Time)

Turn Around Time (TAT) for P2 = 28 ms (Time spent in Ready Queue + Execution Time)

$$\begin{aligned} \text{Average Turn Around Time} &= (\text{Turn Around Time for all the processes}) / \text{No. of Processes} \\ &= (\text{Turn Around Time for (P2+P4+P3+P1)}) / 4 \\ &= (16+6+23+28)/4 = 73/4 \\ &= 18.25 \text{ milliseconds} \end{aligned}$$

Designing with RTOS

Preemptive scheduling – Priority based Scheduling

Summary:

- ✓ Priority based preemptive scheduling gives real time attention to high priority tasks
- ✓ Priority based preemptive scheduling is adopted in systems which demands ‘Real Time’ behavior
- ✓ Most of the RTOSs implements the preemptive priority based scheduling algorithm for process/task scheduling
- ✓ Preemptive priority based scheduling also possess the same drawback of non-preemptive priority based scheduling – ‘*Starvation*’
- ✓ This can be eliminated by the ‘*Aging*’ technique (Temporarily boosting the priority of a task which is ‘starving’ for a long time)

Designing with RTOS

Task Communication

In a multitasking system, multiple tasks/processes run concurrently (in pseudo parallelism) and each process may or may not interact between. Based on the degree of interaction, the processes /tasks running on an OS are classified as

- **Co-operating Processes:** In the co-operating interaction model one process requires the inputs from other processes to complete its execution.
- **Competing Processes:** The competing processes do not share anything among themselves but they share the system resources. The competing processes compete for the system resources such as file, display device etc

The co-operating processes exchanges information and communicate through

- **Co-operation through sharing:** Exchange data through some shared resources.
- **Co-operation through Communication:** No data is shared between the processes. But they communicate for execution synchronization.

Designing with RTOS

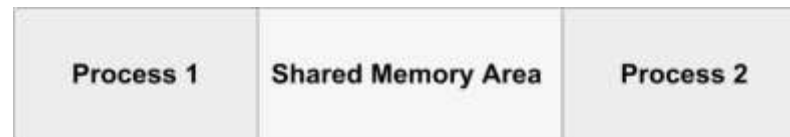
Inter Process (Task) Communication (IPC)

- ✓ IPC refers to the mechanism through which tasks/processes communicate each other
- ✓ IPC is essential for task /process execution co-ordination and synchronization
- ✓ Implementation of IPC mechanism is OS kernel dependent
- ✓ Some important IPC mechanisms adopted by OS kernels are:
 - ✓ Shared Memory
 - ✓ Global Variables
 - ✓ Pipes (Named & Un-named)
 - ✓ Memory mapped Objects
 - ✓ Message Passing
 - ✓ Message Queues
 - ✓ Mailbox
 - ✓ Mail slot
 - ✓ Signals
 - ✓ Remote Procedure Calls (RPC)

Designing with RTOS

IPC – Shared Memory

- ✓ Processes share some area of the memory to communicate among them
- ✓ Information to be communicated by the process is written to the shared memory area
- ✓ Processes which require this information can read the same from the shared memory area
- ✓ Same as the real world concept where a ‘Notice Board’ is used by the college to publish the information for students (The only exception is; only college has the right to modify the information published on the Notice board and students are given ‘Read’ only access. Meaning it is only a one way channel)



Concept of Shared Memory

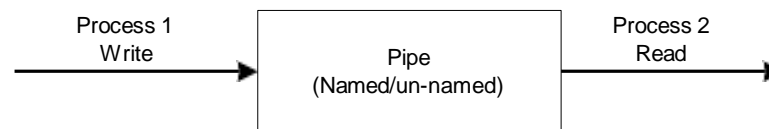
Designing with RTOS

IPC – Shared Memory: Pipes

‘Pipe’ is a section of the shared memory used by processes for communicating. Pipes follow the client-server architecture. A process which creates a pipe is known as pipe server and a process which connects to a pipe is known as pipe client. A pipe can be considered as a conduit for information flow and has two conceptual ends. It can be unidirectional, allowing information flow in one direction or bidirectional allowing bi-directional information flow. A unidirectional pipe allows the process connecting at one end of the pipe to write to the pipe and the process connected at the other end of the pipe to read the data, whereas a bi-directional pipe allows both reading and writing at one end

The implementation of ‘Pipes’ is OS dependent. Microsoft® Windows Desktop Operating Systems support two types of ‘Pipes’ for Inter Process Communication. Namely;

- **Anonymous Pipes:** The anonymous pipes are unnamed, unidirectional pipes used for data transfer between two processes.
- **Named Pipes:** Named pipe is a named, unidirectional or bi-directional pipe for data exchange between processes. Like anonymous pipes, the process which creates the named pipe is known as pipe server. A process which connects to the named pipe is known as pipe client. With named pipes, any process can act as both client and server allowing point-to-point communication. Named pipes can be used for communicating between processes running on the same machine or between processes running on different machines connected to a network



Concept of Shared Memory

Designing with RTOS

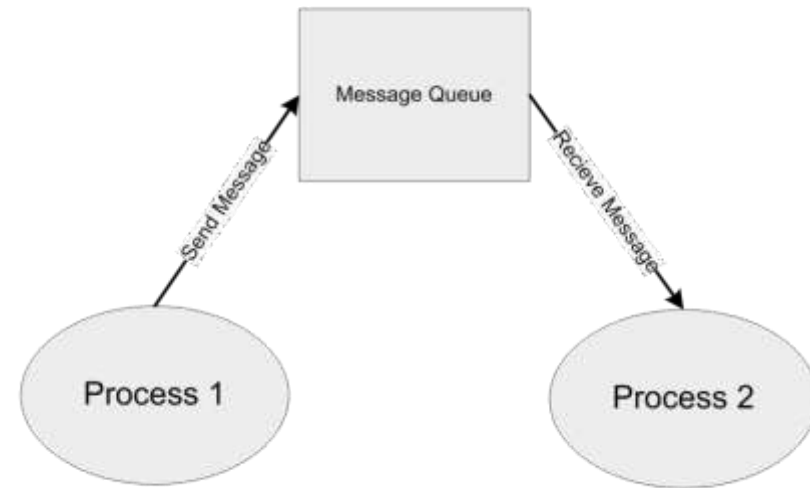
IPC – Message Passing

- ✓ A synchronous/asynchronous information exchange mechanism for Inter Process/ thread Communication
- ✓ Through shared memory lot of data can be shared whereas only limited amount of info/data is passed through message passing
- ✓ Message passing is relatively fast and free from the synchronization overheads compared to shared memory

Designing with RTOS

IPC – Message Passing: Message Queues

- ✓ Process which wants to talk to another process posts the message to a First-In-First-Out (FIFO) queue called 'Message queue', which stores the messages temporarily in a system defined memory object, to pass it to the desired process
- ✓ Messages are sent and received through *send* (Name of the process to which the message is to be sent, message) and *receive* (Name of the process from which the message is to be received, message) methods
- ✓ The messages are exchanged through a message queue
- ✓ The implementation of the message queue, *send* and *receive* methods are OS kernel dependent.

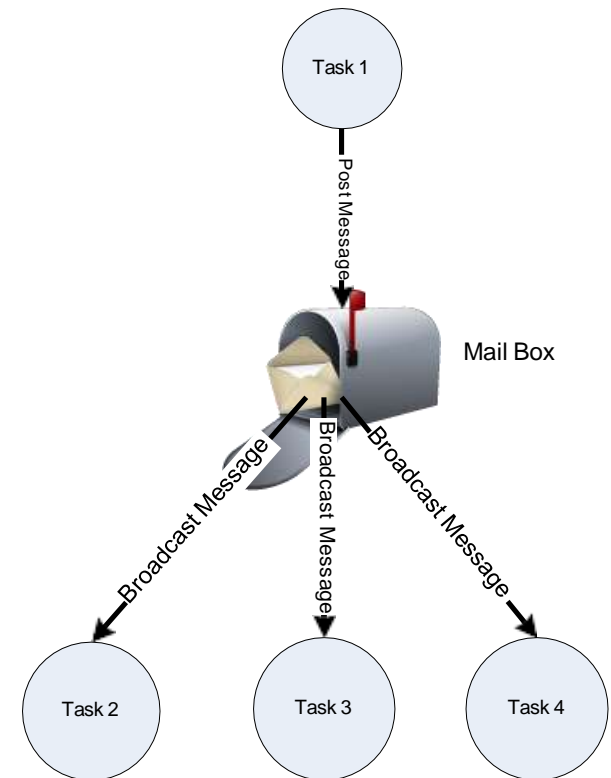


Concept of Message Queue

Designing with RTOS

IPC – Message Passing: Mailbox

- ✓ A special implementation of *message queue*
- ✓ Usually used for one way communication
- ✓ Only a single message is exchanged through *mailbox* whereas ‘message queue’ can be used for exchanging multiple messages
- ✓ One task/process creates the *mailbox* and other tasks/process can subscribe to this *mailbox* for getting message notification
- ✓ The implementation of the *mailbox* is OS kernel dependent
- ✓ The MicroC/OS-II RTOS implements *mailbox* as a mechanism for inter task communication



Concept of Message Queue

Designing with RTOS

IPC – Message Passing: Signal

- ✓ An asynchronous notification mechanism
- ✓ Mainly used for the execution synchronization of tasks process/tasks
- ✓ Signal do not carry any data and are not queued
- ✓ The implementation of *signals* is OS kernel dependent
- ✓ VxWorks RTOS kernel implements ‘signals’ for inter process communication
- ✓ A task/process can create a set of signals and register for it
- ✓ A task or Interrupt Service Routine (ISR) can signal a ‘*signal*’
- ✓ Whenever a specified signal occurs it is handled in a signal handler associated with the signal

Integration and Testing of Embedded Hardware and Firmware

Integration of

Hardware & Firmware

Deals with embedding firmware to target device

Out of Circuit Programming



In System Programming (ISP)

ISP with SPI Protocol

I/O lines involved in SPI

MOSI

MISO

SCK

RST

GND

In Application Programming (IAP)

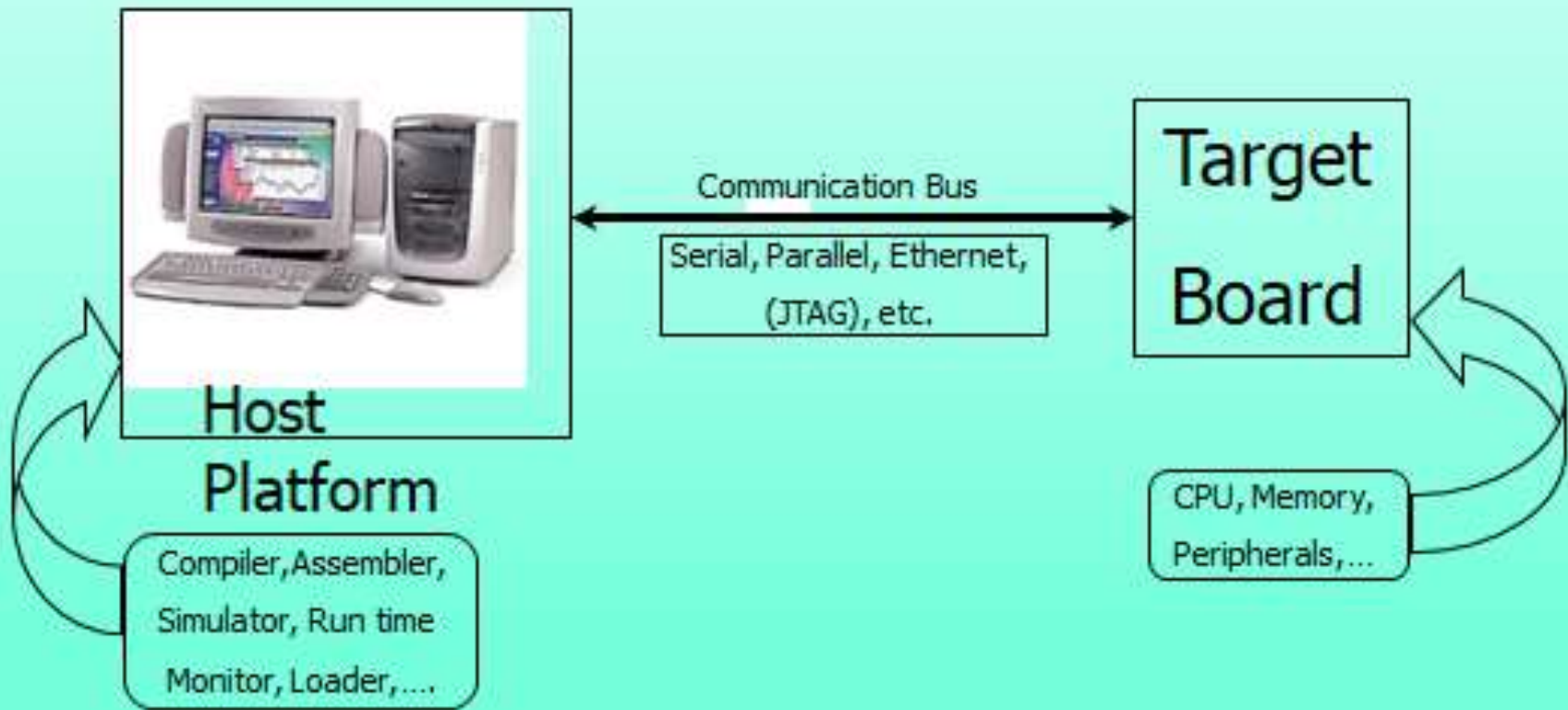
Technique used by firmware running on the target device for modifying a selected portion of the code memory

Use of Factory Programmed Chip

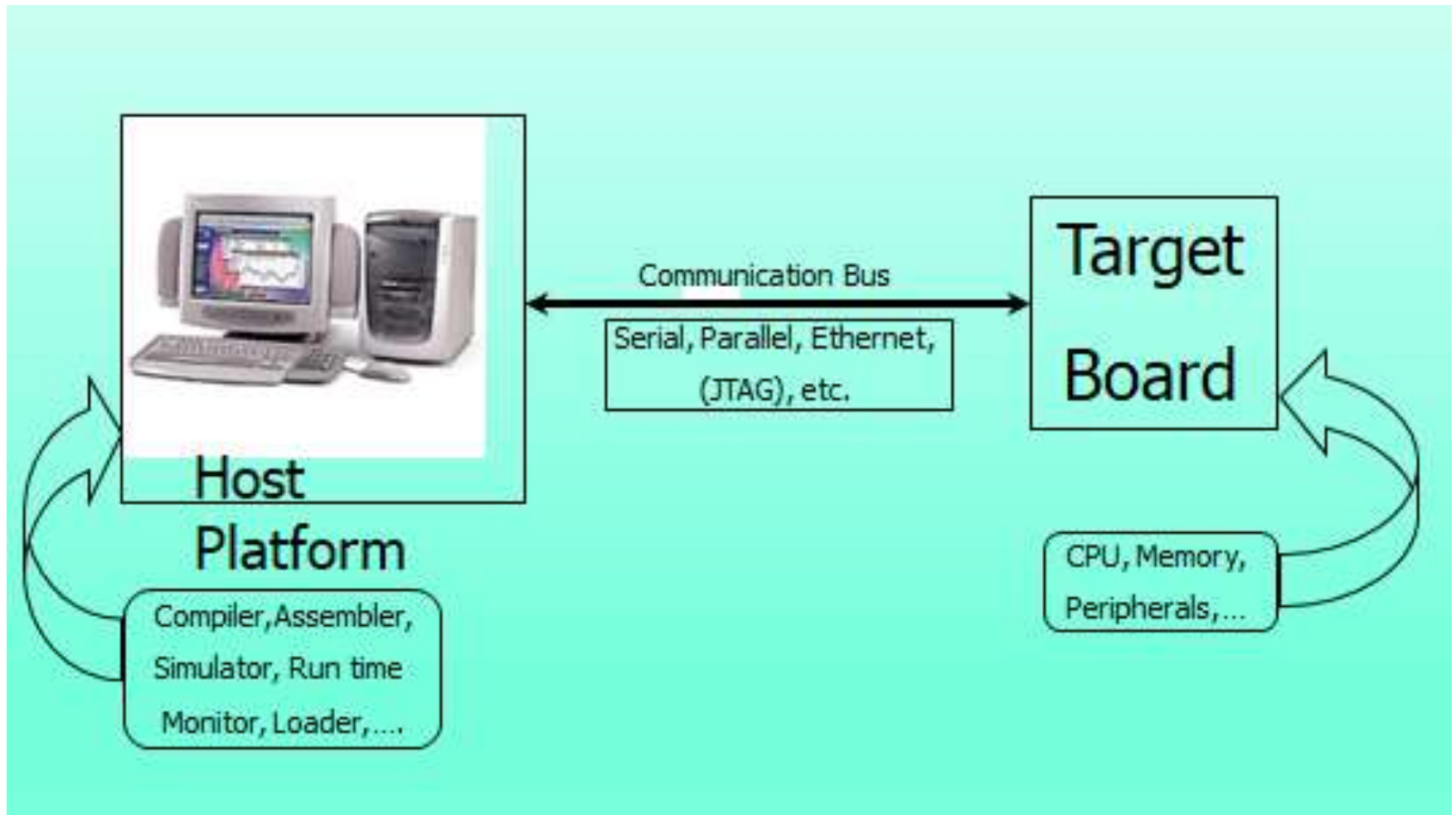
Firmware Loading for OS based Device

Board Power up

The Embedded System Development Environment



Integrated Development Environment (IDE)



Disassembler/

Decompiler

Disassembler : Machine code to Assembly code

Decompiler : Machine code to high level language instruction