Real Time Operating Systems

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Real-time operating systems

Three key requirements

1. **Predictable OS timing behavior**
   - upper bound on the execution time of OS services
   - short times during which interrupts are disabled,
   - contiguous files to avoid unpredictable head movements

2. **OS must be fast**

3. **OS must manage the timing and scheduling**
   - OS possibly has to be aware of task deadlines;
     (unless scheduling is done off-line).
   - OS must provide precise time services with high resolution.
RTOS-Kernels

• Distinction between real-time kernels and modified kernels of standard OSes.

<table>
<thead>
<tr>
<th>Application software</th>
<th>Middleware</th>
<th>Middleware</th>
<th>Device driver</th>
<th>Device driver</th>
<th>Real-time kernel</th>
</tr>
</thead>
</table>

- Distinction between general and RTOSes for specific domains,
- Standard APIs (e.g. POSIX RT-Extension of Unix) or proprietary APIs.
How to organize multiple tasks?

- **Cyclic executive (Static table driven scheduling)**
  - static schedulability analysis
  - resulting schedule or table used at run time

- **Event-driven non-preemptive**
  - tasks are represented by functions that are handlers for events
  - next event processed after function for previous event finishes

- **Static and dynamic priority preemptive scheduling**
  - Static schedulability analysis
  - At run time tasks are executed “highest priority first”
  - Rate monotonic, deadline monotonic, earliest deadline first, least slack
RTOS Organization: Cyclic Executive

- Application
- Device Drivers
- I/O Services
- TCP/IP Stack
- Network Drivers

Kernel Mode

Hardware
RTOS Organization:
Monolithic Kernel

User Mode (protected)

Kernel Mode

Application

Filesystems
Device Drivers

I/O Managers
Network Drivers

Graphics Subsystem
Graphics Drivers

Other….

Hardware Interface Layer

Hardware
RTOS Organization: Microkernel

User Mode (protected)

Kernel Mode

Kernel (tiny)
Faster kernels

• Designed to be fast
  – Many are inadequate for complex systems

• Proprietary examples:
  – QNX, PDOS, VCOS
  – VxWORKS

• Open source example:
  – FreeRTOS
VxWorks Development Platform

Host Development Platform

Wind River Platform:

- Tools:
  - Tornado IDE
  - GNU & DIAB Compilers
  - Wind View Analyzer

- Runtime:
  - Device Management
  - Connectivity Protocols
  - Connectivity Enablers
  - Multimedia API
  - Multimedia Enablers
  - File Systems
  - VxWorks RTOS
  - BSP Developer Kit
  - Reference Hardware and Bring-up Tools

- Services:
  - Wind Sprints, Service Credits
VxWorks Configuration

Automatic dependency analysis and size calculations allow users to quickly custom-tailor the VxWORKS operating system.
VxWorks 7

- 1.5 billion embedded devices use it
  - world’s most widely deployed proprietary RTOS
- Recently introduced virtualization, multicore scheduling, MMU support, security & safety infrastructure
- Supports lots of CPU architectures: ARM, Intel, etc.
Portability with Virtualization
User vs. Kernel Mode & Security

- Protected user mode: applications
- Unprotected kernel mode: OS kernel & drivers
- VxWorks has a lightweight kernel-based threading model

ELOC = effective lines of code; all lines that are not comments, blanks or standalone braces or parenthesis
VxWorks Task States

- **Suspended** – used primarily for debugging
- **Ready** – waiting for CPU, a single primitive = create + activate
- **Pended** – blocked, wait $\Delta t$ time for recourses.
- **Delay** – asleep for $\Delta t$ time, after $\Delta t$ goes to ready state.

On a context switch, a task’s context is saved in task control block (TCB).
Real-Time Process (RTP) Model

• Processes run in their own memory space
  – The kernel and other processes are protected
• Takes advantage of CPUs with a memory management unit (MMU)
• RTPs are isolated both from the kernel and from each other – error protection
• Application libraries and data memory can be shared between RTPs
• Supports both user and kernel modes
Kernel and RTP Interaction

- A system call trap interface is used to access kernel services
- Tasks in different RTPs may interact using shared data regions and inter-process communication (IPC) mechanisms
Memory Model

• Virtual memory manager
• Kernel heap is reduced to create an area of unmapped physical pages
• Kernel heap size is configurable
• An RTP task running in user mode only has access to the RTPs memory space
• The task can trap into kernel mode via a system call
Scheduling

- A global task scheduler schedules tasks across all RTPs
  - Only tasks are schedulable
- Priority-based preemptive scheduling
  - Each task has priority (0 - highest to 255) with its own queue.
  - If two tasks are ready, a lower priority task is pre-empted
  - Priorities can be changed at runtime.
  - A user can lock a task so that it can’t be preempted even by higher priority tasks or interrupts. This allows the use of the fixed priority response time analysis to check schedulability offline.
- Round-robin scheduling
  - After time slice for a task expires, another task with the same priority will execute during the given time slice.
- Preemption locks
  - They prevent task context switching, but do not prevent interrupts.
  - Handles priority inversion with priority ceiling and priority inheritance
VxWorks task scheduling examples

- Priority-bases preemptive

- Round-Robin

Source: T.B.Skaali
Scheduling: task criticality and CPU affinity
Criticality in VxWorks

- Foreground vs. background RTPs
Interrupts

• Inform the system of external events
• Interrupt Service Routines (ISRs) run outside any task context -> no task context switch
• Limitations of ISR:
  – All ISRs share the same stack
  – ISR has no context that can be suspended
  – Cannot take the semaphore, but can give the semaphores, releasing any task waiting on them.
  – Cannot perform I/O through drivers except pipe.
Shared Code and Reentrancy

- **Shared Code** - a single copy of code executed by multiple tasks.
  - Must be *reentrant*
    - A single copy of the routine can be called simultaneously from several task contexts without conflict.

- **Reentrancy Techniques**:
  - Dynamic Stack Variables
  - Global and Static Variables Guarded by Semaphores
    - Mutual exclusion – only one task can change data at a time
    - Uses counting semaphore with timeout (real time)
  - Task Variables
    - 4B variables added to TCB
Dynamic Stack Variables

Tasks

Task1() { ..... 
comFun(myData1)
}

Task2() { ..... 
comFun(myData2)
}

Task Stacks

myData1

Common Function

comFun(yourData){
}

myData2
Intertask Communication

- VxWorks supports:
  - Shared memory
  - Semaphores (binary & counting)
    - Timeout option: If time > timeout, ERROR occurs
  - Mutexes (POSIX interfaces)
  - Message queues and Pipes
  - Sockets and RPCs
  - Signals

- The mutex semaphore supports the priority-inheritance algorithm

Source: Brandon Miller
Microkernel with VxWorks

• A complete high-performance RTOS in a tiny footprint
  – 20 KB or smaller in size
• Very fast response times
  – Time to boot: 25 µs (on Intel Quark)
  – Time to switch from fiber to ISR execution: 1955 ns (on Intel Quark)
• Multi-threaded
• Multi-core support
• Power management ready
Application Examples

- Flight simulators
- Radio and optical telescopes
- Navigation systems
- Deep sea instrumentation
- Traffic control systems
- Modems

- Printers
- Digital cameras
- Hand-held computing devices
- Routers, switches, etc

… any systems where rigid time requirement have been placed on the operation of a processor or the flow of the data.
Medical application example

• BD Biosciences is a leading global provider of systems for sorting and analyzing CD4 cells to monitor the stages of HIV/AIDS infection and the effectiveness of new vaccines and therapies.

• VxWorks allowed BD to cut its development time by 25%!
VxWorks & Mars Rover Curiosity

• NASA chose VxWorks to run the craft's controls
  – rocket left Earth Nov 2011
  – successfully landed on Mars Aug 2012

• VxWorks supported more than 20 JPL missions
Open Source Fast RTOS: FreeRTOS

• Leading open source RTOS
  – E.g. basis for DuinOS used in Arduino

• Key features:
  • Preemptive and co-operative scheduling, Multitasking, Services, Interrupt management, MMU; Supports stacks for TCP/IP, USB, & basic file systems

• Highly portable C, 24 architectures supported, Ports are freely available in source code.

• Scalable:
  • Only use the services you only need by specifying in FreeRTOSConfig.h
  • Minimum footprint = 4KB
Scheduling & Multitasking

• Preemptive task scheduling:
  o Fully preemptive
  o Always runs the highest priority task that is ready to run
  o Task priorities are dynamic
  o Comparable with other preemptive kernels
  o Cooperative
    o Context switch occurs if a task blocks or yields the CPU

• Multitasking:
  • No software restriction on # of tasks that can be created, # of priorities that can be used
  • Priority assignment
    ▪ More than one task can be assigned the same priority.
    ▪ RR with time slice = 1 RTOS tick
Services & Interrupts

• Services
  – Queues
  – Semaphores
    • Binary and counting
  – Mutexes
    • With priority inheritance
    • Support recursion

• Interrupts
  • An interrupt can suspend a task execution, mechanism is port dependent.
Task status in FreeRTOS

- **Running**
  - Task is actually executing

- **Ready**
  - Task is ready to execute but a task of equal or higher priority is Running.

- **Blocked**
  - Task is waiting for some event.
    - **Time**: if a task calls `vTaskDelay()` it will block until the delay period has expired.
    - **Resource**: Tasks can also block waiting for queue and semaphore events.

- **Suspended**
  - Much like blocked, but not waiting for anything.
  - Tasks will only enter or exit the suspended state when explicitly commanded to do so via API.

Mostly from http://www.freertos.org/RTOS-task-states.html
Standard OS with real-time extensions

- RT-kernel running all RT-tasks.
- Standard-OS executed as one task.

<table>
<thead>
<tr>
<th>RT-task 1</th>
<th>RT-task 2</th>
<th>non-RT task 1</th>
<th>non-RT task 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>device driver</td>
<td>device driver</td>
<td>Standard-OS</td>
<td></td>
</tr>
</tbody>
</table>

+ Crash of standard-OS does not affect RT-tasks;
- RT-tasks cannot use Standard-OS services;
  less comfortable than expected
Example: RT-Linux

Init ➔ Bash ➔ Mozilla ➔ scheduler ➔ Linux-Kernel ➔ driver ➔ RT-Linux ➔ RT-Scheduler ➔ RT-Task ➔ RT-Task ➔ Hardware

interrupts ➔ I/O ➔ interrupts ➔ interrupts ➔ interrupts

Bash
Mozilla
Linux-Kernel
RT-Task
RT-Task
RT-Linux
RT-Scheduler
Hardware
RT-Linux philosophy

• Real time programs need to be split into two parts:
  – a small light component with hard real time constraints, scheduled via real time scheduler
  – larger component that does most of the processing, scheduled via normal Linux scheduler
• The two parts communicate through a real-time-FIFO, a non-blocking queue which allows the real time parts to read and write data from normal processes.
RT-Linux schedulers

- Real time tasks are implemented as kernel modules
  - At initialization they send the real time scheduler all the information about their release times, periods, and deadlines.
- Rt-Linux allows for swappable real-time schedulers:
  - EDF algorithm, RM algorithm & priority-based round-robin
  - Does not schedule dependent real-time tasks
  - Memory is allocated in non-pageable blocks saving the uncertainty of swap file usage
  - All real time tasks run in the same kernel memory space
    - No protected memory benefits
    - Context switches are much faster because we save the cost of flushing the TLB cache and using trap instructions to enter and exit kernel mode
- Linux is the lowest priority process
  - It can be preempted anytime when RT scheduler requires
  - Executes only if the real time scheduler has nothing else to do.
  - Linux uses its own scheduler to schedule tasks running under it.
RT-Linux & interrupts

- A very serious problem is the disabling of interrupts by the Linux kernel
  - Function call to disable interrupts in the kernel source is replaced with a macro that masks these interrupts from the Linux process but not from the other real time processes

- Real-time kernel handles masking all the interrupts
  - It passes the ones intended to the Linux process on to it as software interrupts if Linux enabled interrupts

- RTLinux is very fast in handling interrupts
  - running on a x86 runs in less than 15μs from the moment a hardware interrupt is detected to when its interrupt handler starts to execute
RT-Linux - summary

• Demonstrates the “hack in to the architecture” approach to adding real time.
• Example application: Henson Company Creature Shop's Performance Control System
  – The ``animatronic'' version of the system is capable of precise control of real-world puppets that are actuated by electromechanical or hydraulic servos.
  – The system runs RTLinux on the front end for I/O and timing & communicates serially with a back-end embedded PC residing in the puppet, which communicates serially with microcontroller-based motor driver peripherals.
RTOS for Raspberry Pi

• Limitation of Raspberry Pi for real-time OS support
  – No real-time clock
    • Cannot maintain the actual time and date (should be connected to the internet)
    • Cannot generate deterministic timing pulses
    • Need to connect additional hardware modules
  – There is no support of real-time in standard Linux / BSD kernels
    • OS may be slow due to processors

• RTOS kernel ports for Raspberry Pi
  – FreeRTOS: basic port to Raspberry Pi
  – ChibiOS/RT: efficient and preemptive kernel
  – Xenomai: real-time extension of Linux
  – Machinoid: hard real-time support targeting to Robotics, CNC and 3D Printing
  – RTEMS: similar to VxWorks and ported to Raspberry Pi
**RTOS Research systems**

- **Research issues**
  - low overhead memory protection,
  - temporal protection of computing resources
  - RTOSes for on-chip multiprocessors
  - support for continuous media
  - quality of service (QoS) control.
Research Kernel Examples

- Small kernels
  - PALOS, TinyOS
- Medium size
  - uCos II, eCos
- Larger
  - Linux-based systems
Small kernel: PALOS

- Structure – PALOS Core, Drivers, Managers, and user defined Tasks
  - PALOS Core
    - Task control: slowing, stopping, resuming
    - Periodic and aperiodic handling and scheduling
    - Inter-task Communication via event queues
    - Event-driven tasks: task routine processes events stored in event queues
  - Drivers
    - Processor-specific: UART, SPI, Timers..
    - Platform-specific: Radio, LEDs, Sensors
  - Small Footprint
    - Core (compiled for ATMega128L) Code Size: 956 Bytes, Mem Size: 548 Bytes
    - Typical( 3 drivers, 3 user tasks) Code Size: 8 Kbytes, Mem Size: 1.3 Kbytes
Execution control in PALOS

- Each task has a task counter
- Counters initialized to:
  - 0: normal
  - >>: slowdown
  - -: stop
  - >=: restart
- Decremented
  1) every iteration (relative timing)
  2) by timer interrupts (exact timing)
- If counter = 0, call tasks; reset counter to initialization value
Event Handlers in PALOS

- Periodic or aperiodic events can be scheduled using Delta Q and Timer Interrupt
- When event expires appropriate event handler is called
Small Kernel: TinyOS

- System composed of
  - scheduler, graph of components, execution context

- Component model
  - Basically FSMs
  - Four interrelated parts of implementation
    - Encapsulated fixed-size frame (storage)
    - A set of command & event handlers
    - A bundle of simple tasks (computation)
  - Modular interface
    - Commands it uses and accepts
    - Events it signals and handles

- Tasks, commands, and event handlers
  - Execute in context of the frame & operate on its state
  - Commands are non-blocking requests to lower level components
  - Event handlers deal with hardware events
  - Tasks perform primary work, but can be preempted by events

- Scheduling and storage model
  - Shared stack, static frames
  - Events preempt tasks, tasks do not
  - Events can signal events or call commands
  - Commands don’t signal events
  - Either can post tasks
TinyOS Overview

- Stylized programming model with extensive static information
  - Compile time memory allocation
- Easy migration across HW/SW boundary
- Small Software Footprint - 3.4 KB
- Two level scheduling structure
  - Preemptive scheduling of event handlers
  - Non-preemptive FIFO scheduling of tasks
  - Bounded size scheduling data structure
- Rich and Efficient Concurrency Support
  - Events propagate across many components
  - Tasks provide internal concurrency
- Power Consumption on Rene Platform
  - Transmission Cost: 1 µJ/bit
  - Inactive State: 5 µA
  - Peak Load: 20 mA
- Efficient Modularity - events propagate through stack <40 µS
Complete TinyOS Application

<table>
<thead>
<tr>
<th>Component Name</th>
<th>Code Size (bytes)</th>
<th>Data Size (bytes)</th>
</tr>
</thead>
<tbody>
<tr>
<td>Multihop router</td>
<td>88</td>
<td>0</td>
</tr>
<tr>
<td>AM_dispatch</td>
<td>40</td>
<td>0</td>
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<tr>
<td>AM_temperature</td>
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<tr>
<td>AM_light</td>
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<td>8</td>
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<tr>
<td>AM</td>
<td>356</td>
<td>40</td>
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<tr>
<td>Packet</td>
<td>334</td>
<td>40</td>
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<tr>
<td>RADIO_byte</td>
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<td>8</td>
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<td>RFM</td>
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<td>1</td>
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<tr>
<td>Photo</td>
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<td>Temperature</td>
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<tr>
<td>UART</td>
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<tr>
<td>UART_packet</td>
<td>314</td>
<td>40</td>
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<tr>
<td>I2C_bus</td>
<td>198</td>
<td>8</td>
</tr>
<tr>
<td>Processor_init</td>
<td>172</td>
<td>30</td>
</tr>
<tr>
<td>TinyOS scheduler</td>
<td>178</td>
<td>16</td>
</tr>
<tr>
<td>C runtime</td>
<td>82</td>
<td>0</td>
</tr>
<tr>
<td>Total</td>
<td>3450</td>
<td>226</td>
</tr>
</tbody>
</table>

Source: Hill, Szewczyk et al., ASPLOS 2000
Medium size: µCOS-II

• Size 5-24KB
• Portable, ROMable, scalable, preemptive, multitasking RTOS
• Services
  – Semaphores, event flags, mailboxes, message queues, task management, fixed-size memory block management, time management
• Used in avionics, medical applications, industrial controls, appliances etc.
Medium size: eCos

- Embedded, Configurable OS, Open-source
- Several scheduling options
  - bit-map scheduler, lottery scheduler, multi-level scheduler
- Three-level processing
  - Hardware interrupt (ISR), software interrupt (DSR), threads
- Inter-thread communication
  - Mutex, semaphores, condition variables, flags, message box
- Portable - Hardware Abstraction Layer (HAL)
- Based on configurable components
  - Package based configuration tool
  - Kernel size from 32 KB to 32 MB
  - Implements ITRON standard for embedded systems
  - OS-neutral POSIX compliant EL/IX API
Larger Size: Linux-based

- Microcontroller (no MMU) OS:
  - uClinux - small-footprint Linux (< 512KB kernel)

- QoS extensions:
  - Linux-SRT and QLinux
    - soft real-time kernel extension
    - target: media applications
  - Posix 1.b RT

- Embedded hard deadlines:
  - RTLinux, RTAI
    - hard real time OS
      - E.g. RTLinux has Linux kernel as the lowest priority task in a RTOS
    - fully compatible with GNU/Linux
Soft deadlines: Posix RT

- Standard scheduler can be replaced by POSIX scheduler implementing priorities for RT tasks

- Special RT & standard OS calls available.

- Easy programming, no guarantee of meeting deadlines
Embedded Market Study on Most Frequently Used Operating Systems

Only Operating Systems that had 2% or more are shown.
Middleware

• Between applications and OS
• Provides a set of higher-level capabilities and interfaces
• Customizable, composeable frameworks
• Types of services:
  – component – independent of other services
    • E.g. communication, information, computation
  – integrated sets
    • e.g. distributed computation environment
  – integration frameworks
    • Tailor to specific domain: e.g. transaction processing
Integrated sets

- A set of services that take advantage of each other
- Example: Distributed Computing Environment (DCE)
  - Provides key distributed technologies – RPC, DNS, distributed file system, time synch, network security and threads service
  - From Open SW Foundation, supported by multiple architectures and major SW vendors
DCE

- DCE Security Service
- DCE Distributed File Service
- DCE Distributed Time Service
- DCE Directory Service
- Other Basic Services
- DCE Remote Procedure Calls
- DCE Threads Services
- Operating System Transport Services
Integration frameworks middleware

• Integration environments tailored to specific domain
• Examples:
  – Workgroup framework
  – Transaction processing framework
  – Network management framework
  – Distributed object computing (e.g. CORBA, E-SPEAK, JINI, message passing)
Distributed Object Computing

- **Advantages:**
  - SW reusability, more abstract programming, easier coordination among services

- **Issues:**
  - latency, partial failure, synchronization, complexity

- **Techniques:**
  - Message passing (object knows about network)
  - Argument/Return Passing – like RPC
    - network data = args + return result + names
  - Serializing and sending
    - network data = obj code + obj state + synch info
  - Shared memory
    - network data = data touched + synch info
SW for access to remote objects

CORBA (Common Object Request Broker Architecture). Information sent to Object Request Broker (ORB) via local stub. ORB determines location to be accessed and sends information via the IIOP I/O protocol.

Access times not predictable.
Real-time CORBA

• End-to-end predictability of timeliness in a fixed priority system.

• respecting thread priorities between client and server for resolving resource contention,

• bounding the latencies of operation invocations.

• RT-CORBA includes provisions for bounding the time during which priority inversion may occur.
Message passing interface

- Message passing interface (MPI): alternative to CORBA
- MPI/RT: a real-time version of MPI [MPI/RT forum, 2001].
- MPI-RT does not cover issues such as thread creation and termination.
- MPI/RT is conceived as a layer between the operating system and non real-time MPI.
Summary

• SW
  – Various apps

• Middleware
  – E.g DCE, CORBA

• RTOS
  – E.g TinyOS, eCos, RT-Linux
Sources and References

• Nikil Dutt @ UCI
• Mani Srivastava @ UCLA
• Brandon Miller, T.B. Skaali
• Amr Ali Abdel-Naby for FreeRTOS
• WindRiver/VxWorks