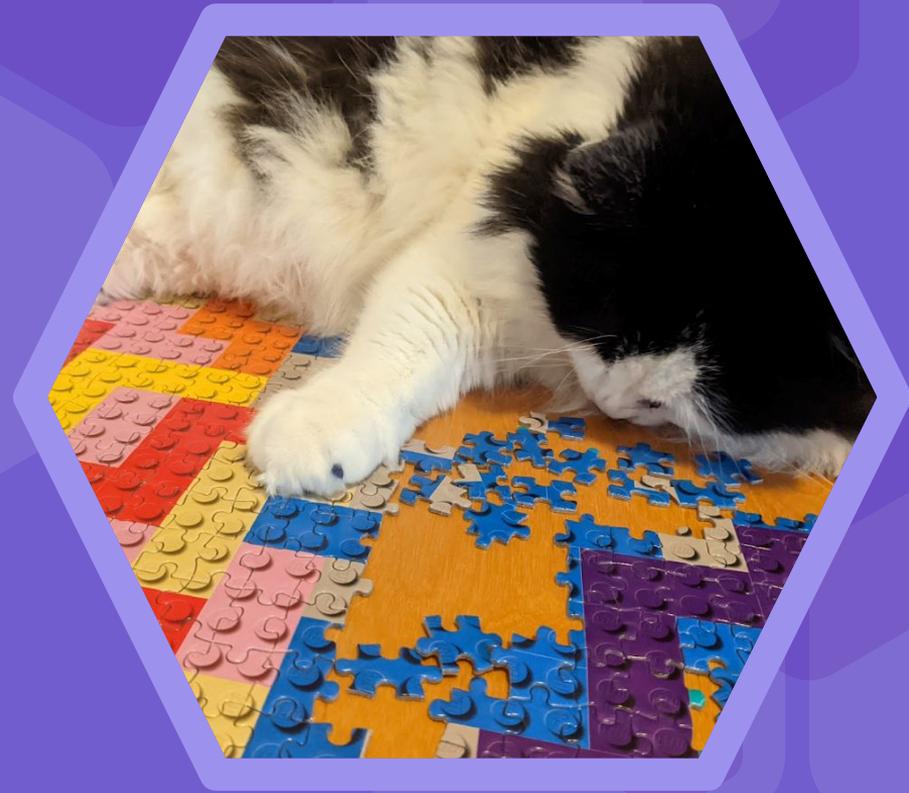


Project groups will be sent out this afternoon

Start working on your project proposal (due 10/13)

HW8 is due a week from now (10/11)

13: Scheduling and RTOS



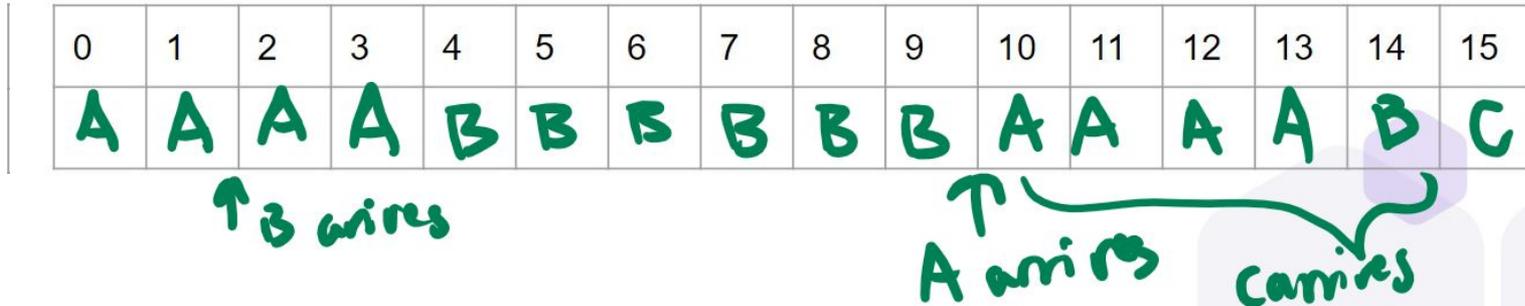
Latency and priority

High priority interrupt: A (4 ms every 10 ms)

Lower priority interrupts: B (7 ms every 100ms),

C (1ms every 15 ms)

Can C fail to execute within 15 ms?





Scheduling

Decide when CPU runs what task so that deadlines are met

Soft: correctness “degrades” if deadlines aren’t met

vs

Hard: correctness fails if deadlines aren’t met

Example: interrupts

Dynamic: done at run-time

vs

Static: done at compile-time

Preemptive: task can interrupt lower-priority task

vs

Non-preemptive: tasks can’t interrupt each other

Example: cyclic execution



Feasibility of scheduling periodic tasks

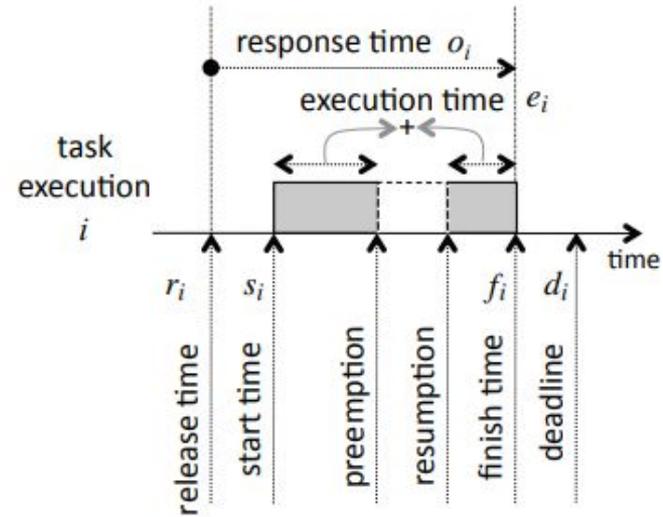
Feasibility: feasible if $f_i \leq d_i$ for all i

Utilization: % of time CPU spends executing tasks (vs idle)

Necessary but not **Sufficient** condition for feasibility:

Sum of e_i/p_i (aka e_i/d_i) for all i is at most 1

Aka utilization $\leq 100\%$



latency: $s_i - r_i$

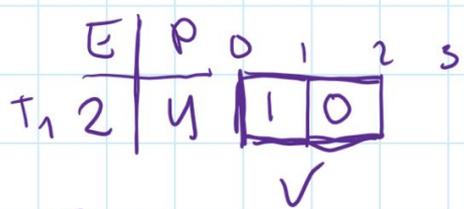


Scheduling examples on the board

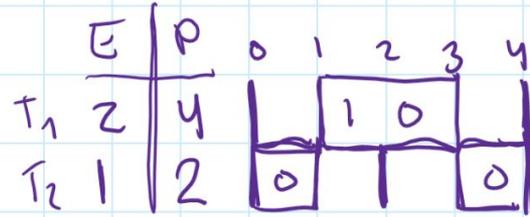
Dynamic scheduling:

- ◆ EDF (earliest deadline first) – schedule next task based on deadline
- ◆ LSF/LLF (least slack/laxity first) – schedule next task based on how much execution it has left to do

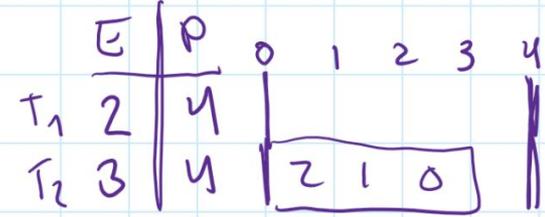
non-preemptive, static



$$\sum e/p = 2/4 = 50\%$$

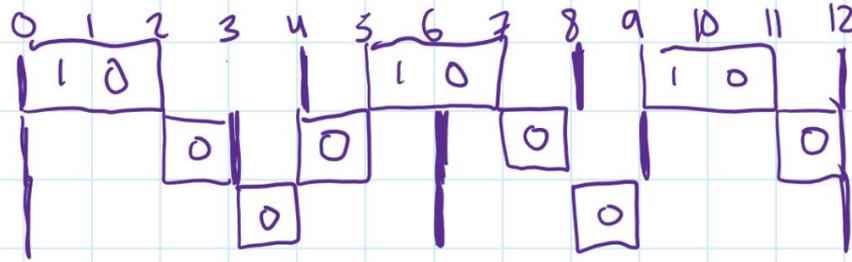
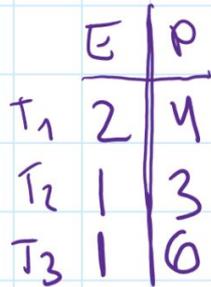


$$\sum e/p = \frac{2}{4} + \frac{1}{2} = 100\%$$



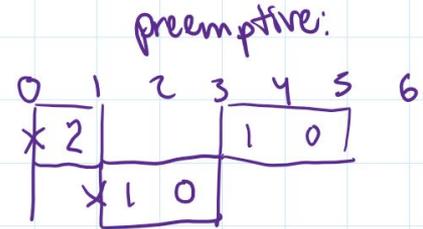
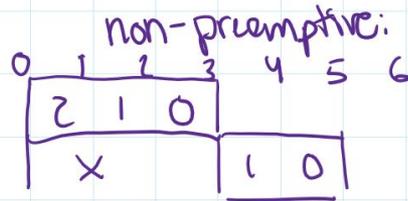
$$\sum e/p = \frac{2}{4} + \frac{3}{4} = 125\%$$

Still non-preemptive, static



non-periodic EDF (dynamic)

	Release	Exec.	Deadline
T ₁	0	3	6
T ₂	1	2	5



	Release	Exec.	Deadline
T ₁	0	4	5
T ₂	2	6	15
T ₃	5	4	13



preemptive:



(still according to EDF)

T₁
T₂
T₃



Rate Monotonic Scheduling (RMS)

Fixed-priority, determined ahead of time

Each task has its own priority

Task with smallest period = highest priority

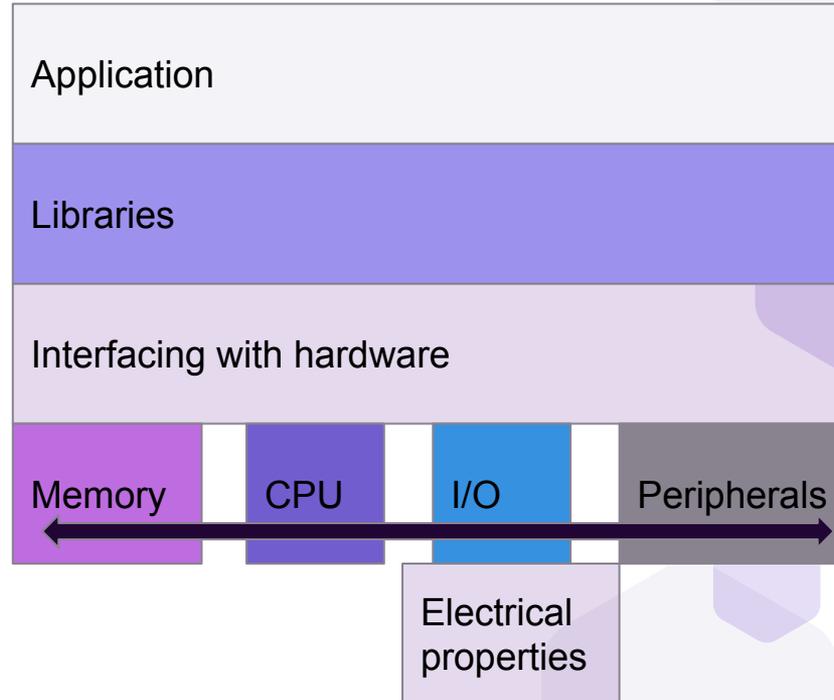
Pre-emptive (higher priority tasks interrupt lower-priority tasks)

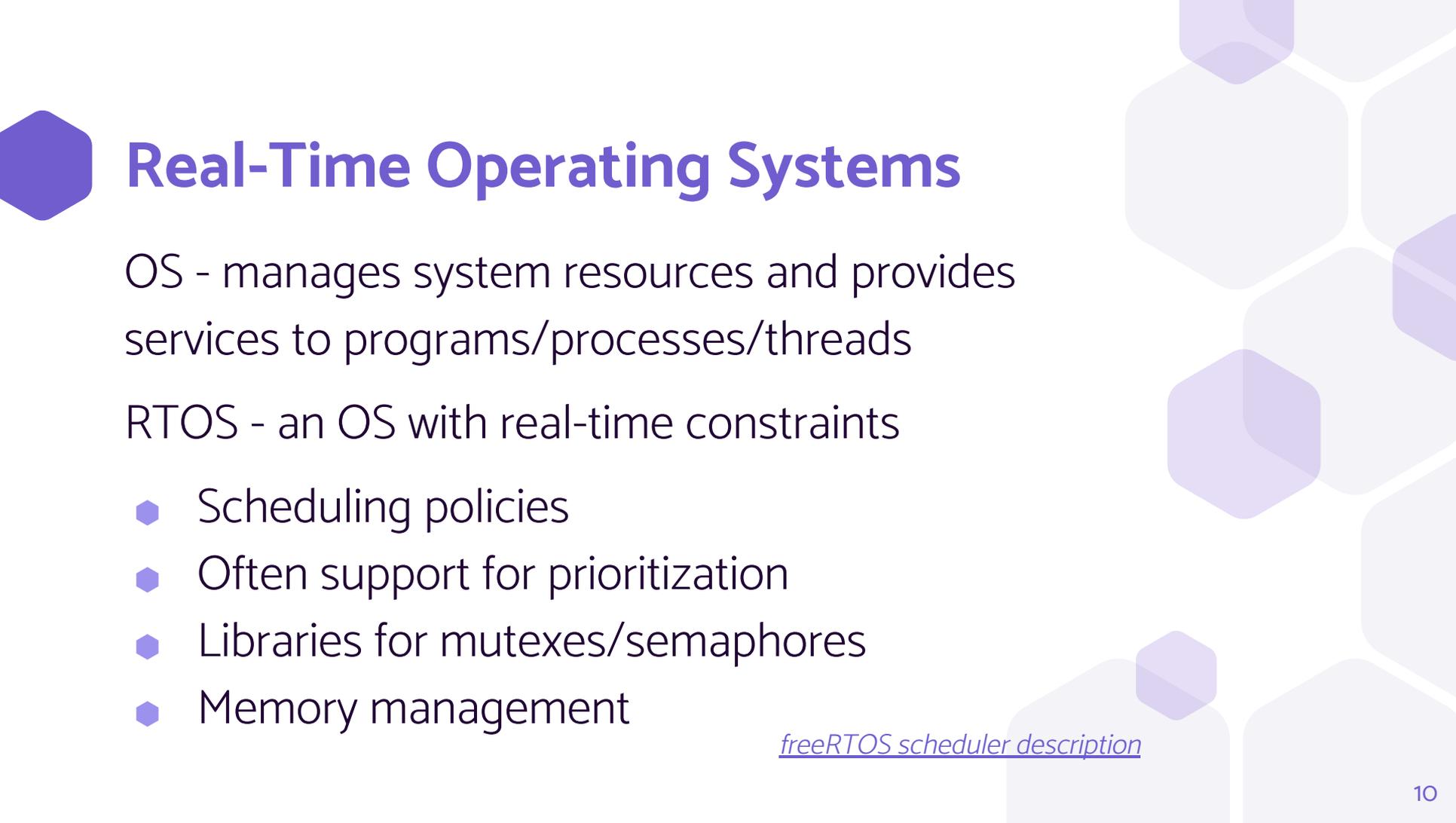
Guarantee of scheduling when utilization $< 69.3\%$

$$\mu \leq n(2^{1/n} - 1), \quad (12.2)$$



Stepping back – Embedded systems as systems





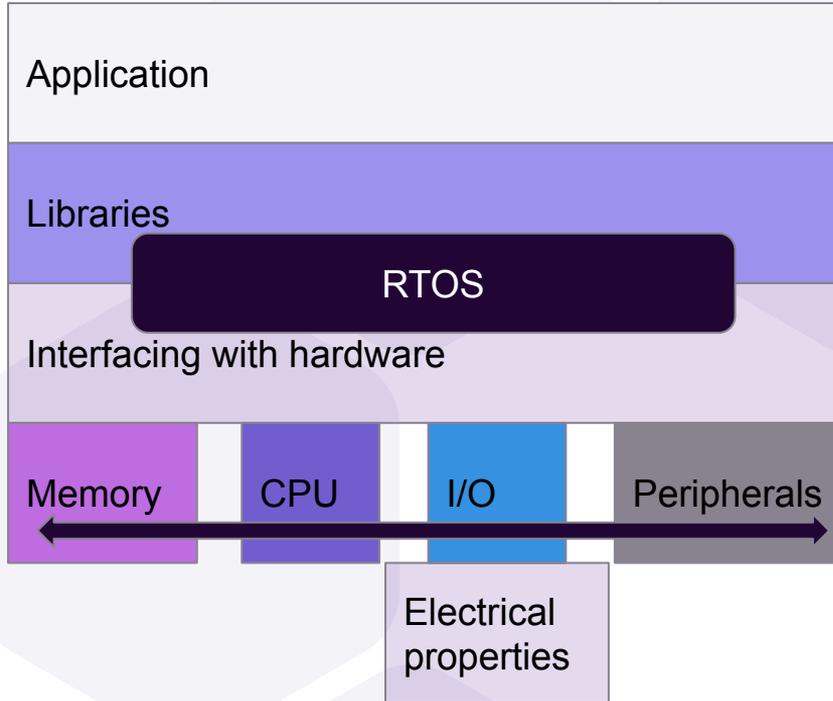
Real-Time Operating Systems

OS - manages system resources and provides services to programs/processes/threads

RTOS - an OS with real-time constraints

- ◆ Scheduling policies
- ◆ Often support for prioritization
- ◆ Libraries for mutexes/semaphores
- ◆ Memory management

[freeRTOS scheduler description](#)





Pros/cons to using an RTOS?



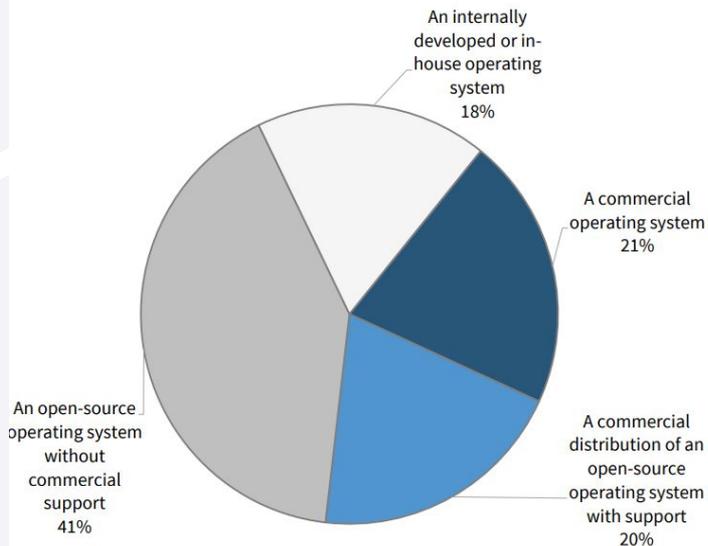
*Would you want to write your
own RTOS?*

Most embedded projects utilize an operating system

Although open source is popular, four in ten use either commercial OS or open-source OS distributed commercially

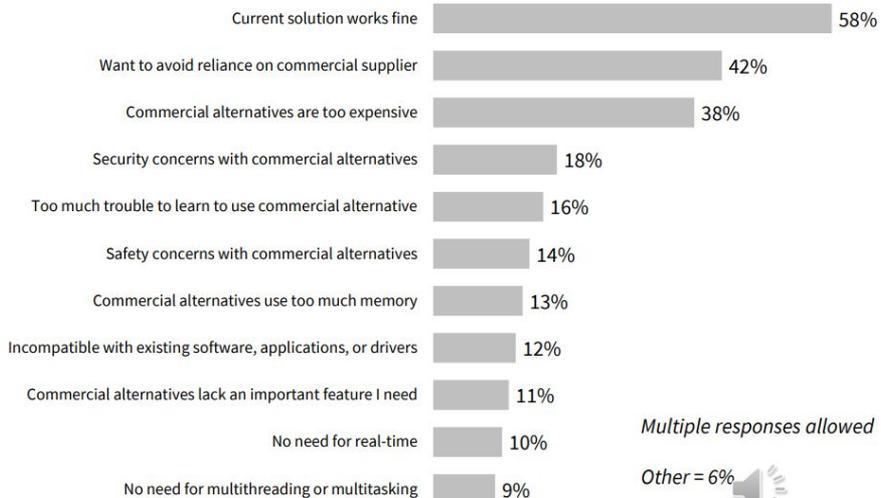
74% use an OS in current embedded project

OS Used in Current Embedded Project



Total Respondents

Reasons for not using commercial OS



Multiple responses allowed

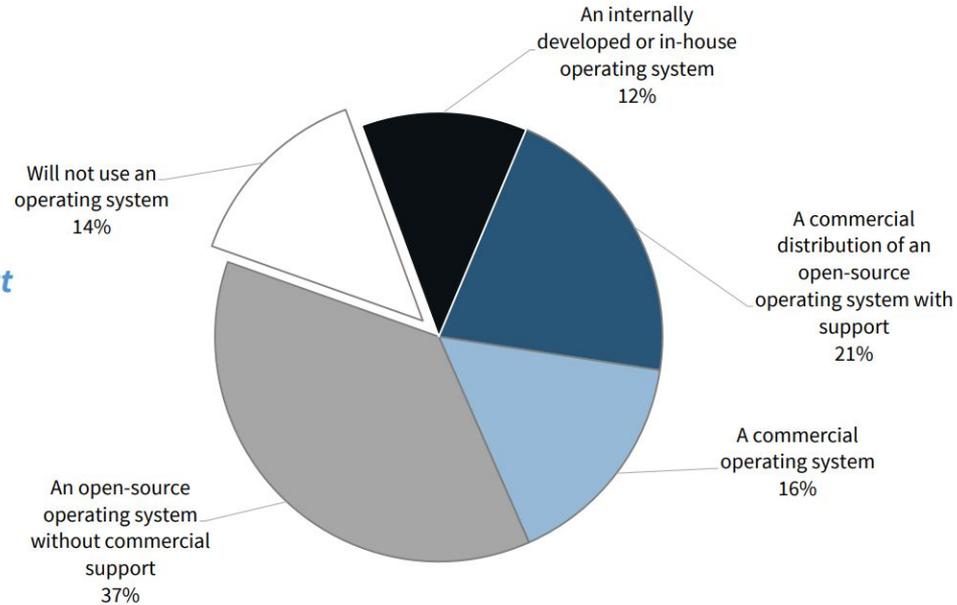
Other = 6%

Base = Those not using commercial OS (284)

OS use will increase, but open-source share will grow

Nearly 30% of those now using commercial OS are considering open-source alternatives

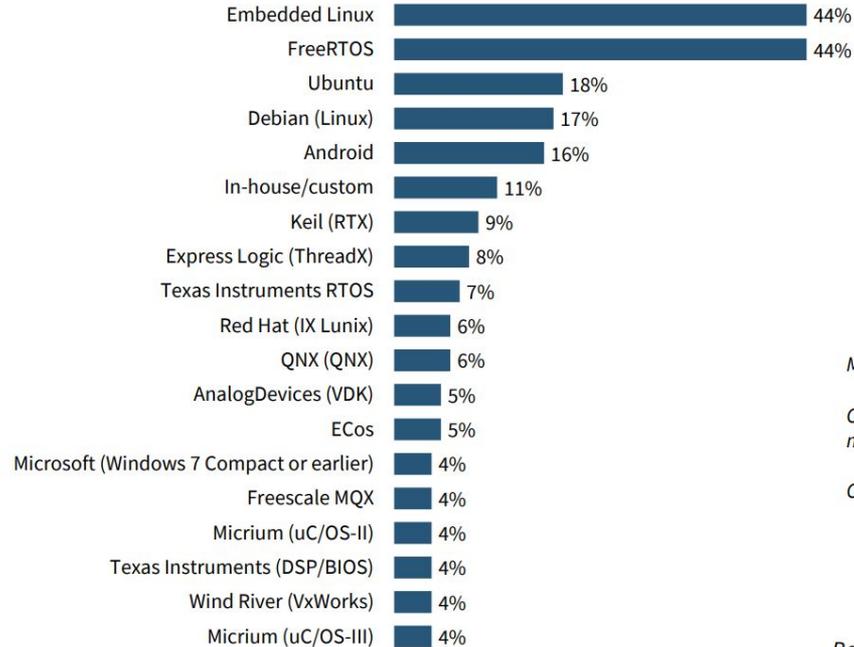
86% will use an OS for next embedded project



Total Respondents

Most popular embedded OSs – Embedded Linux, FreeRTOS and Ubuntu

Top 3 OSs are especially popular in APAC, while Embedded Linux is used more in the Americas



Multiple responses allowed

Only those with 4% or more total mentions shown

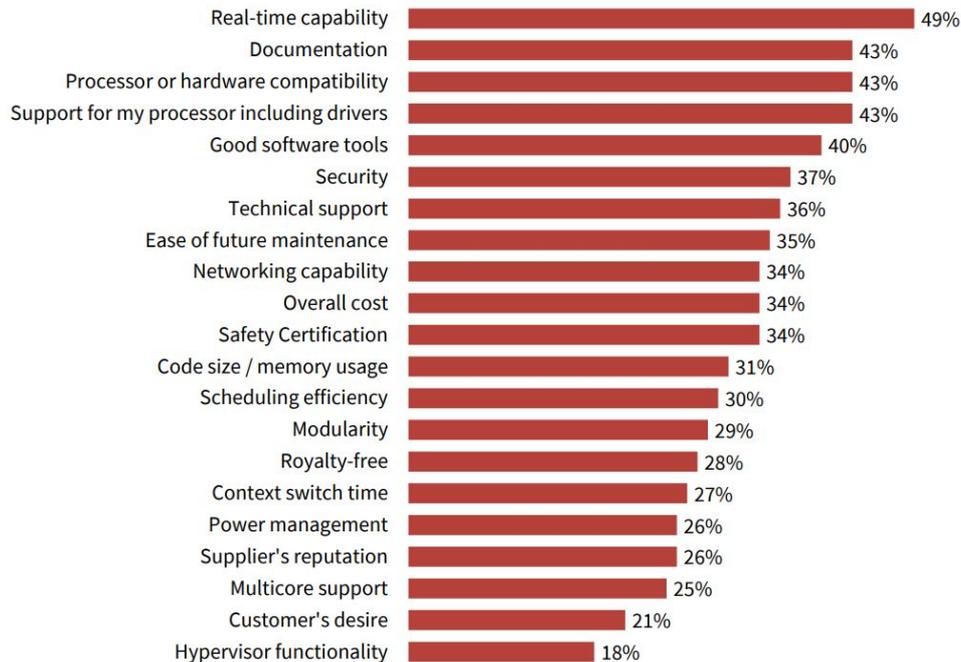
Other = 7%



Base = Those who will use an OS (566)

Those using a commercial OS look for documentation, hardware compatibility and support to complement real-time capabilities

Large OEMs and APAC developers put particular emphasis on most commercial OS capabilities



**'Very Important'
Summary**

Multiple responses allowed



Base = Those using commercial OS (200)