School of Computer Science & Engineering

COMP9242 Advanced Operating Systems

2020 T2 Week 05a

Real Time Systems Basics

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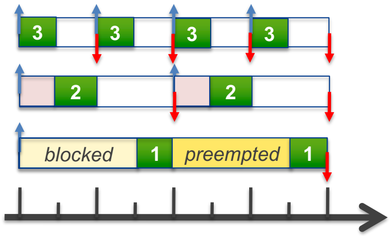
Incorporating material by Stefan Petters and Anna Lyons



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Real-Time Basics

Real-Time Systems

What's a Real-Time System?

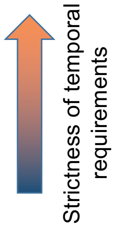
A real-time system is a system that is required to react to stimuli from the environment (including passage of physical time) within time intervals dictated by the environment.
[Randell et al., Predictably Dependable Computing Systems, 1995]

Real-time systems have timing constraints, where the correctness of the system is dependent not only on the results of computations, but on *the time at which those results arrive*. [Stankovic, IEEE Computer, 1988]

Issues:
- Correctness: What are the temporal requirements?
- Criticality: What are the consequences of failure?

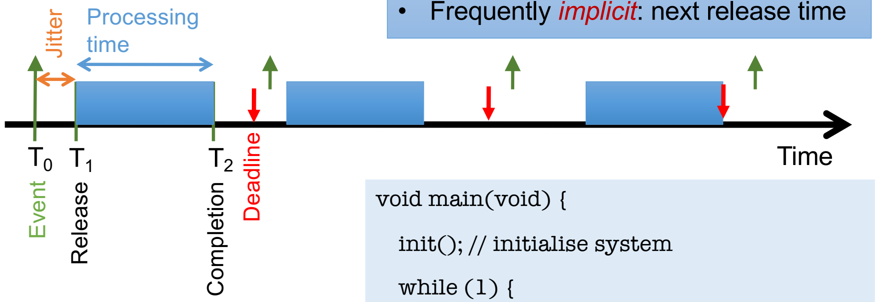
Strictness of Temporal Requirements

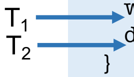
- Hard real-time systems
- Weakly-hard real-time systems
- Firm real-time systems
- Soft real-time systems
- Best-effort systems



Real-Time Tasks

Real-time tasks have deadlines
- Usually stated relative to release time
- Frequently *implicit*: next release time



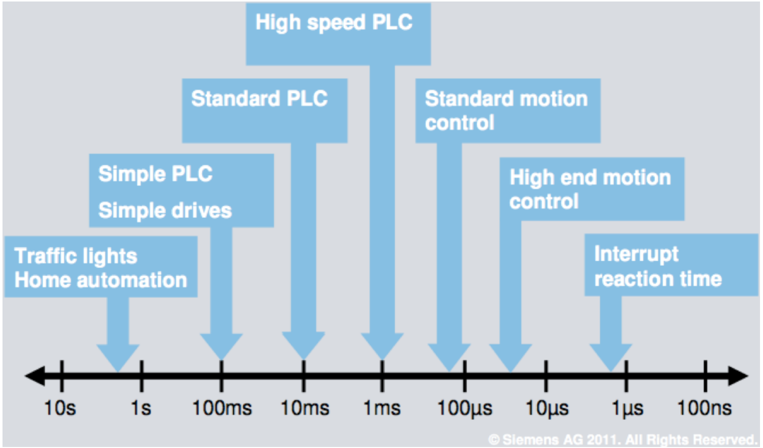


```
void main(void) {
  init(); // initialise system
  while (1) {
    wait();  // timer, device interrupt, signal
    doJob();
  }
}
```

Real Time ≠ Real Fast

System	Deadline	Single Miss Conseq	Ultimate Conseq.
Car engine ignition	2.5 ms	Catastrophic	Engine damage
Industrial robot	5 ms	Recoverable?	Machinery damage
Air bag	20 ms	Catastrophic	Injury or death
Aircraft control	50 ms	Recoverable	Crash
Industrial process	100 ms	Recoverable	Lost production, plant/environment damage
Pacemaker	100 ms	Recoverable	Death

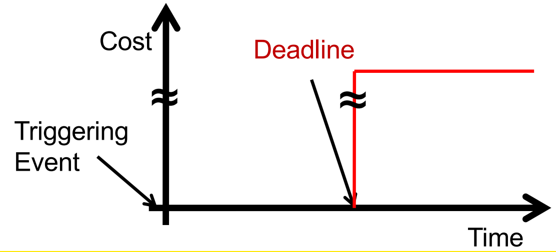
Example: Industrial Control

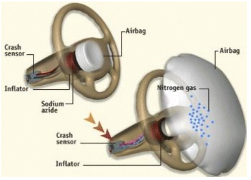


Hard Real-Time Systems

- Safety-critical: Failure ⇒ death, serious injury
- Mission-critical: Failure ⇒ massive financial damage

- Deadline miss is *catastrophic*
- Steep and real *cost* function

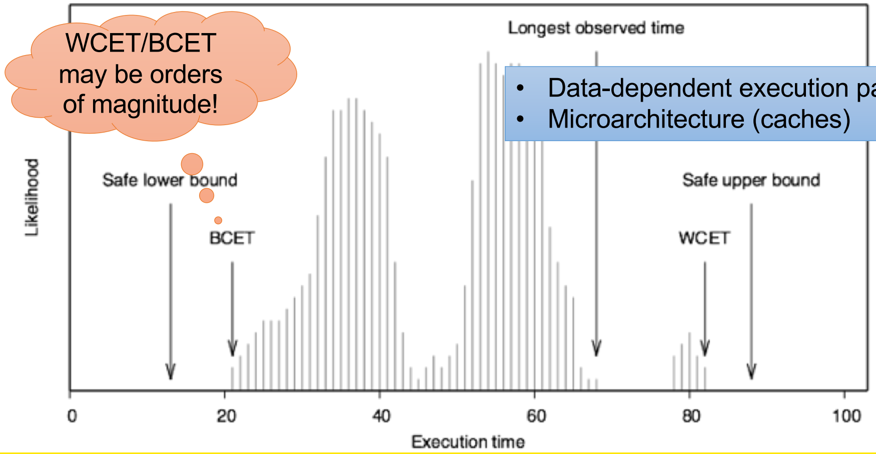




Challenge: Execution-Time Variance

WCET/BCET may be orders of magnitude!

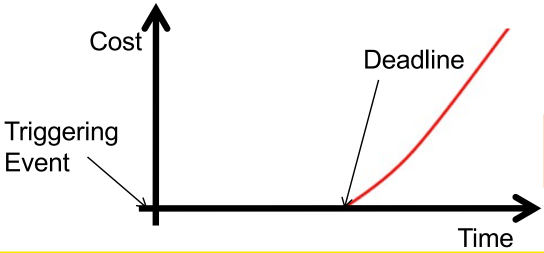
- Data-dependent execution paths
- Microarchitecture (caches)



Weakly-Hard Real-Time Systems

- Most feedback control systems (incl life-support!)
  - Control compensates for occasional miss
  - Becomes unstable if too many misses
- Typically integrated with fault tolerance for HW issues

Tolerate small fraction of deadline misses

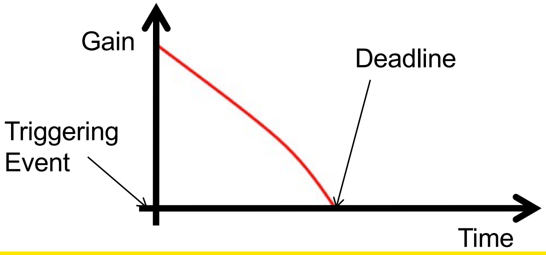


In practice, certifiers treat critical avionics as hard RT

Firm Real-Time Systems

Result obsolete if deadline missed (loss of revenue)

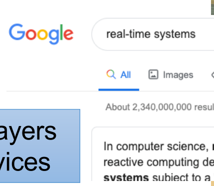
- Forecast systems
- Trading systems



Soft Real-Time Systems

Deadline miss undesirable but tolerable, affects QoS

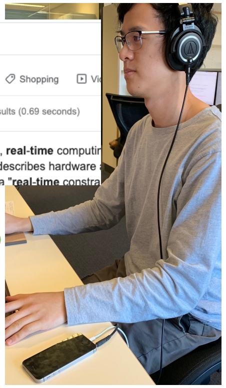
- Media players
- Web services



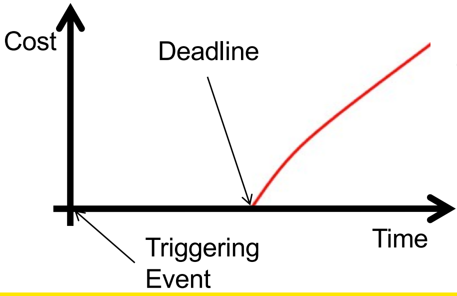
real-time systems

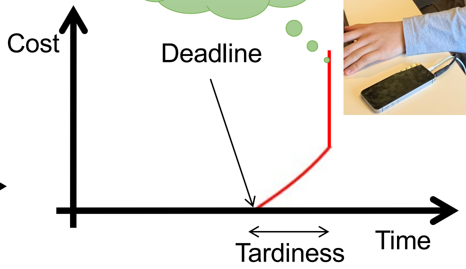
About 2,340,000,000 results (0.69 seconds)

In computer science, **real-time** computi
reactive computing describes hardware
systems subject to a "**real-time** constra



Bounded Tardiness

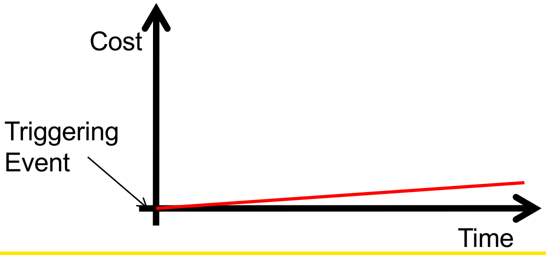




Best-Effort Systems

No deadline

In practice, duration is rarely totally irrelevant



Real-Time Operating System (RTOS)

- Designed to support real-time operation
  - Fast context switches, fast interrupt handling
  - More importantly, *predictable* response time
- **Main duty is scheduling tasks to meet their deadline**

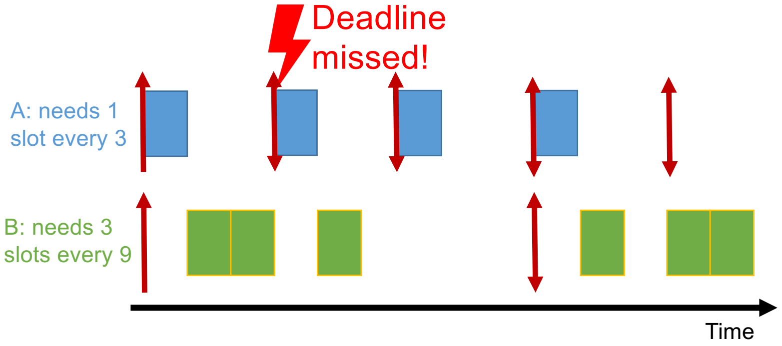
Requires analysis of worst-case execution time (WCET)

Traditional RTOS is very primitive
- single-mode execution
- no memory protection
- inherently cooperative
- *all code is trusted*

RT vs OS terminology:
- "task" = thread
- "job" = execution of thread resulting from event

Real-Time Scheduling

- Ensuring all deadlines are met is harder than bin-packing
- Reason: time is not fungible



Real-Time Scheduling

- Ensuring all deadlines are met is harder than bin-packing
- Time is not fungible

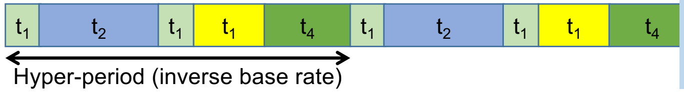
Terminology:
- A set of tasks is **feasible** if there is a known algorithm that will schedule them (i.e. all deadlines will be met).
- A scheduling algorithm is **optimal** if it can schedule all **feasible** task sets.

Cyclic Executives

- Very simple, completely static, scheduler is just table
- Deadline analysis done off-line
- Fully deterministic

Drawback: Latency of event handling is hyper-period

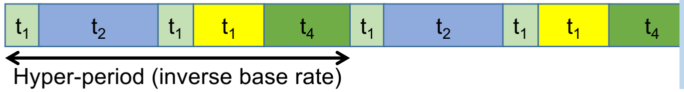
```
while (true) {
    wait_tick();
    job_1();
    wait_tick();
    job_2();
    wait_tick();
    job_1();
    wait_tick();
    job_3();
    wait_tick();
    job_4();
}
```



Are Cyclic Executives Optimal?

- Theoretically yes if can slice (interleave) tasks
- Practically there are limitations:
  - Might require very fine-grained slicing
  - May introduce significant overhead

```
while (true) {
    wait_tick();
    job_1();
    wait_tick();
    job_2();
    wait_tick();
    job_1();
    wait_tick();
    job_3();
    wait_tick();
    job_4();
}
```



On-Line RT Scheduling

- Scheduler is part of the OS, performs scheduling decision on-demand
- Execution order not pre-determined
- Can be preemptive or non-preemptive
- Priorities can be
  - fixed: assigned at admission time
    - scheduler doesn't change prios
    - system may support dynamic adjustment of prios
  - dynamic: prios potentially different at each scheduler run

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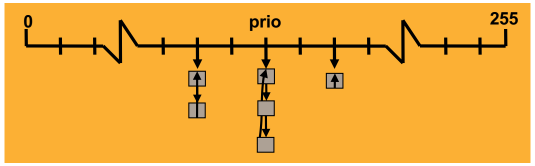
Fixed-Priority Scheduling (FPS)

- Classic L4 scheduling is a typical example:
  - always picks highest-prio runnable thread
  - round-robin within prio level
  - will preempt if higher-prio thread is unblocked or time slice depleted

FPS is not optimal, i.e. cannot schedule some feasible sets



In general may or may not:
- preempt running threads
- require unique prios

Rate Monotonic Priority Assignment (RMPA)

- Higher rate ⇒ higher priority:
  - $T_i < T_j \Rightarrow P_i > P_j$

T: period
1/T: rate
P: priority
U: utilisation

- Schedulability test: Can schedule task set with periods $\{T_1 \ldots T_n\}$ if

Assumes "*implicit*" deadlines: release time of next job

$$U \equiv \sum C_i/T_i \le n(2^{1/n}-1)$$

RMPA is optimal for FPS

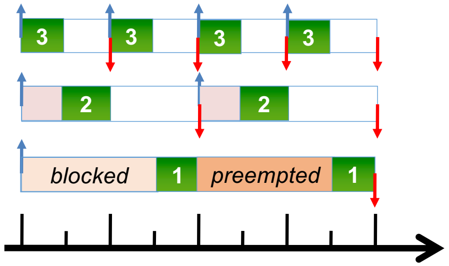
n	1	2	3	4	5	10	∞
U [%]	100	82.8	78.0	75.7	74.3	71.8	log(2) = 69.3

Rate-Monotonic Scheduling Example

RMPA schedulability bound is sufficient but not necessary

WCET

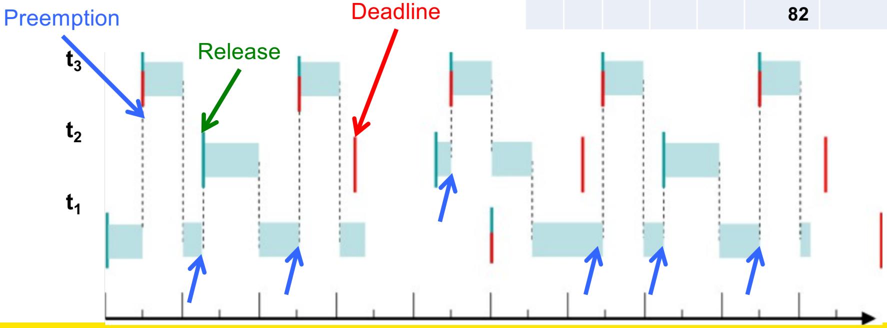
Task	T	P	C	U [%]
t_3	20	3	10	50
t_2	40	2	10	25
t_1	80	1	20	25
				100



Another RMPA Example

Deadline

	P	C	T	D	U [%]	release
t_3	3	5	20	20	25	5
t_2	2	8	30	20	27	12
t_1	1	15	50	50	30	0
					82	



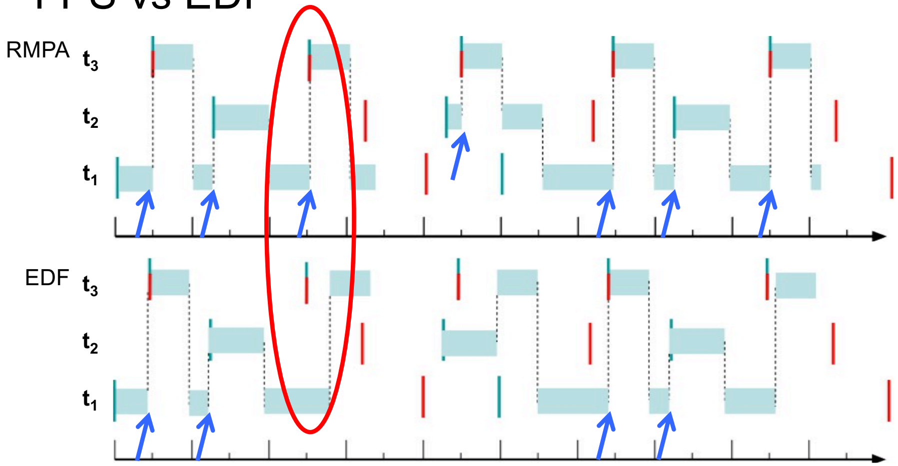
Dynamic Prio: Earliest Deadline First (EDF)

- Job with closest deadline executes
  - priority assigned at job level, not task (i.e. thread) level
  - deadline-sorted release queue
- Schedulability test: Can schedule task set with periods $\{T_1 \ldots T_n\}$ if

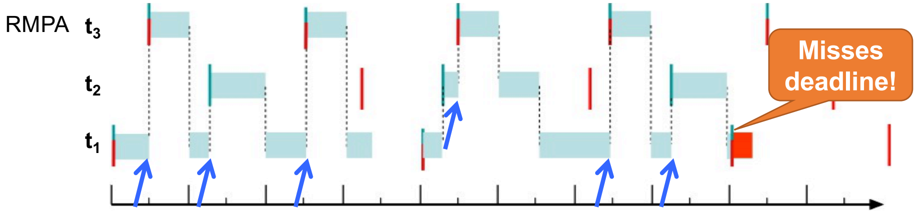
$$U \equiv \sum C_i/T_i \leq 1$$

Preemptive EDF is optimal

FPS vs EDF

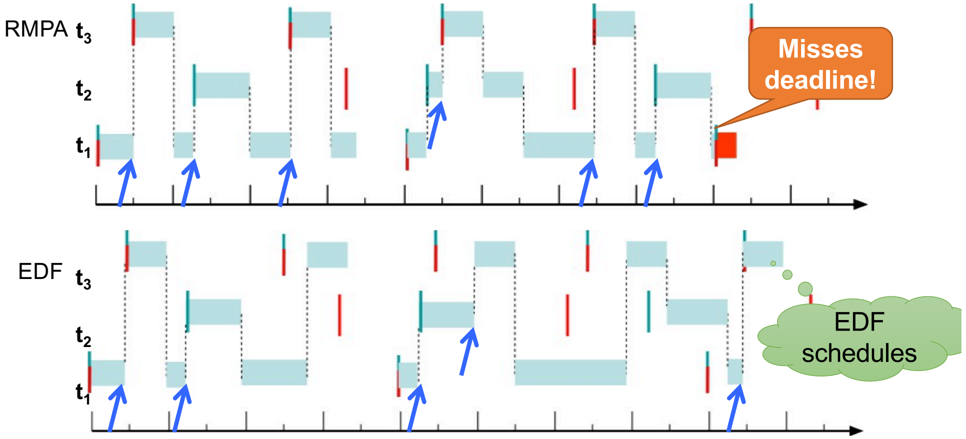


FPS vs EDF



Task	P	C	T	D	U [%]	release
t_3	3	5	20	20	25	5
t_2	2	8	30	20	27	12
t_1	1	15	40	40	37.5	0
					89.5	

FPS vs EDF

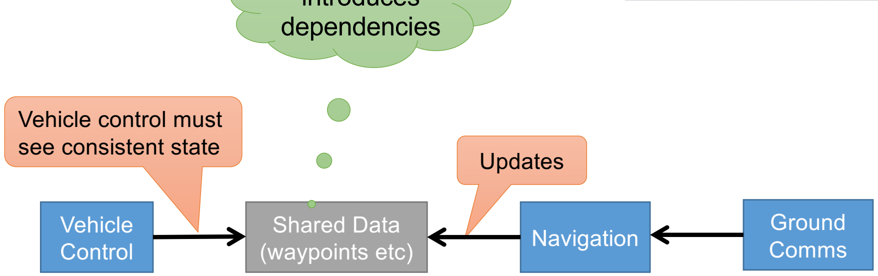


Misses deadline!

EDF schedules

Resource Sharing

Challenge: Sharing



Sharing introduces dependencies

Vehicle control must see consistent state

Updates

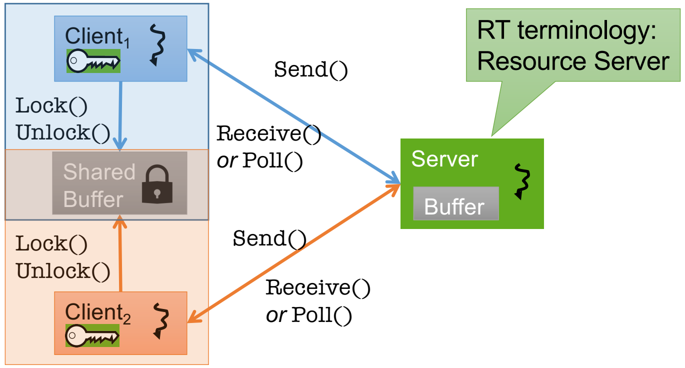
Vehicle Control

Shared Data (waypoints etc)

Navigation

Ground Comms

Critical Sections: Locking vs Delegation



Client_1

Lock()
Unlock()

Shared Buffer

Lock()
Unlock()

Client_2

Send()

Receive()
or Poll()

Send()

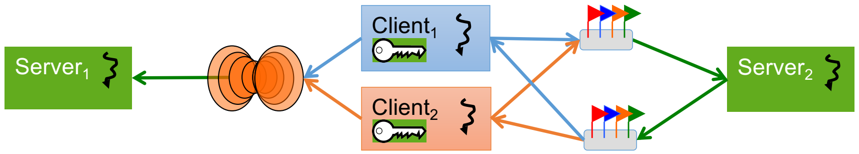
Receive()
or Poll()

Server

Buffer

RT terminology: Resource Server

Implementing Delegation



```
serv_local() {
  ...
  wait(ep);
  while (1) {
    /* critical section */
    Reply&wait(ep);
  }
}
```

```
client() {
  while (1) {
    ...
    call(ep);
    ...
    signal(not_ry);
    ...
    wait(not_rq);
  }
}
```

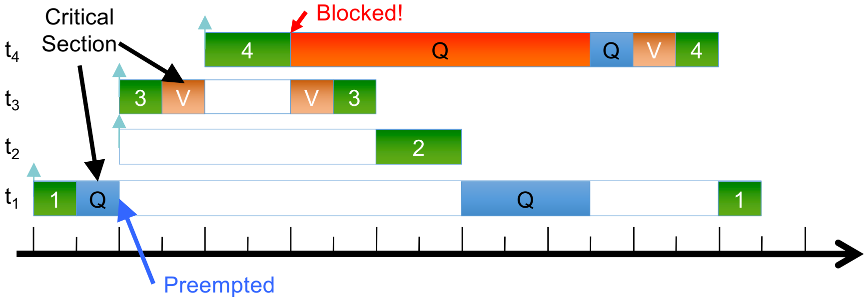
```
serv_remote() {
  ...
  while (1) {
    wait(not_rq);
    /* critical section */
    signal(not_ry);
  }
```

Hoare-style monitor
Suitable intra-core

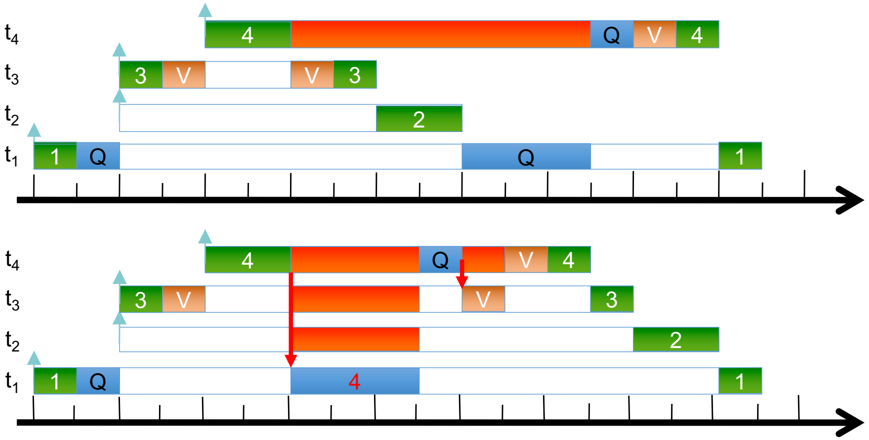
Semaphore synchronisation
Suitable inter-core

Problem: Priority Inversion

- High-priority job is blocked by low-prio for a long time
- Long wait chain: $t_1 \rightarrow t_4 \rightarrow t_3 \rightarrow t_2$
- Worst-case blocking time of t_1 bounded by total WCET: $C_2+C_3+C_4$

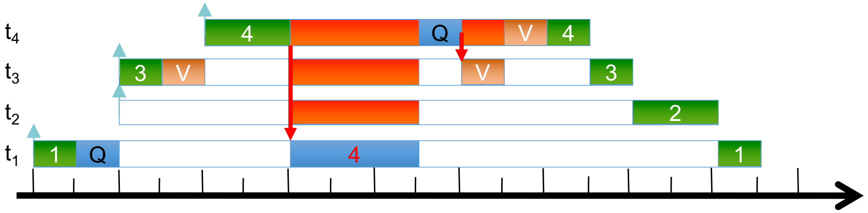


Solution 1: Priority Inheritance (“Helping”)



Solution 1: Priority Inheritance (“Helping”)

If t_1 blocks on a resource held by t_2, *and* $P_1 > P_2$, then
- t_2 is temporarily given priority P_1
- when t_t releases the resource, its priority reverts to P_2



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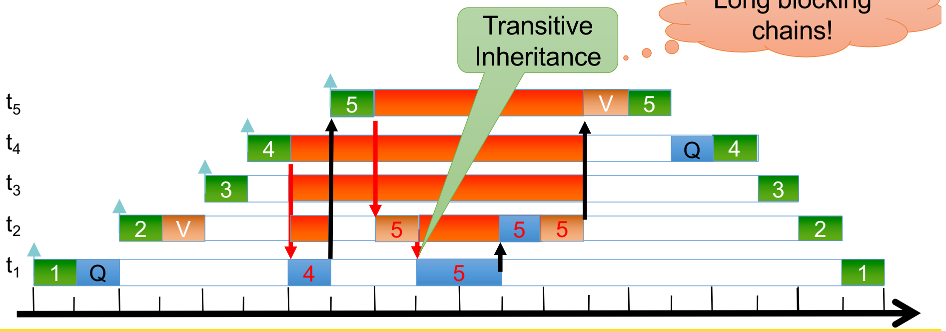


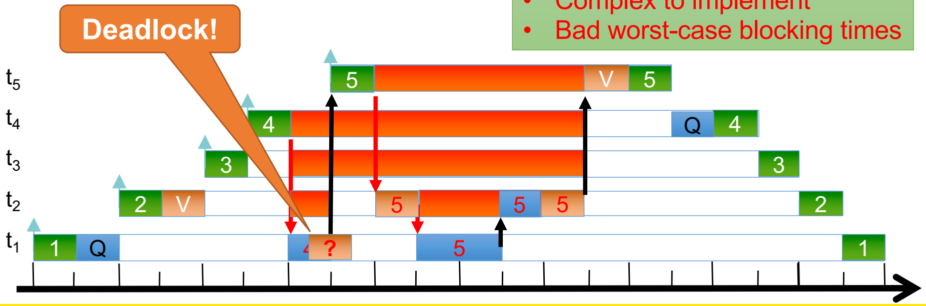
Transitive Inheritance

Long blocking chains!

Solution 1: Priority Inheritance ("Helping")

If t_1 blocks on a resource held by t_2, *and* $P_1 > P_2$, then
- t_2 is temporarily given priority P_1
- when t_t releases the resource, its priority

Priority Inheritance:
- Easy to use
- Potential deadlocks
- Complex to implement
- Bad worst-case blocking times

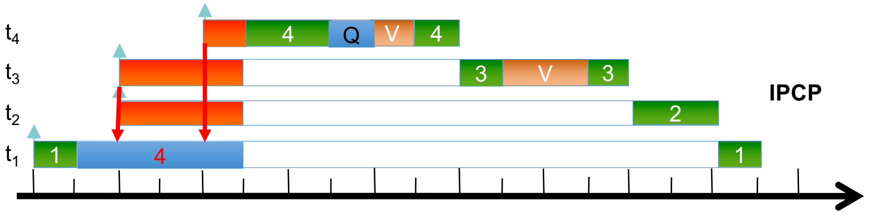


Deadlock!

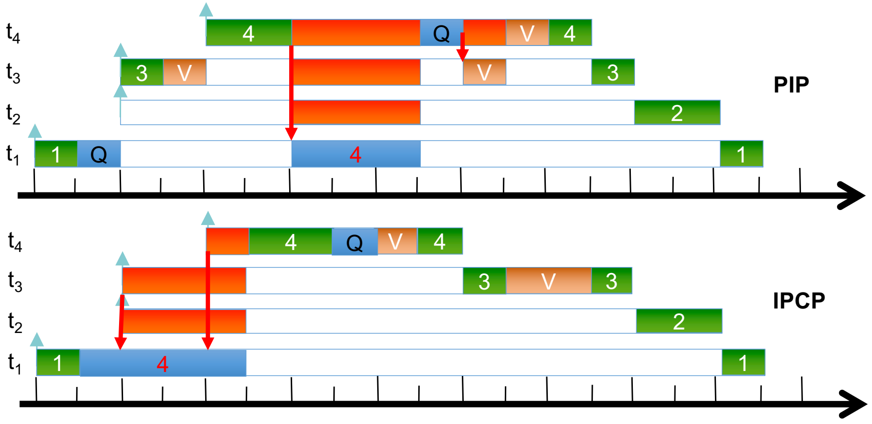
Solution 2: Priority Ceiling Protocol (PCP)

- Aim: Block at most once, avoid deadlocks
- Idea: Associate *ceiling priority* with each resource
  - Ceiling = Highest prio of jobs that may access the resource
  - On access, bump prio of job to ceiling

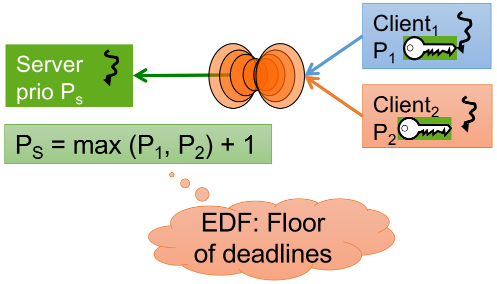
Immediate prio ceiling protocol (IPCP)



IPCP vs PIP



ICPC Implementation With Delegation

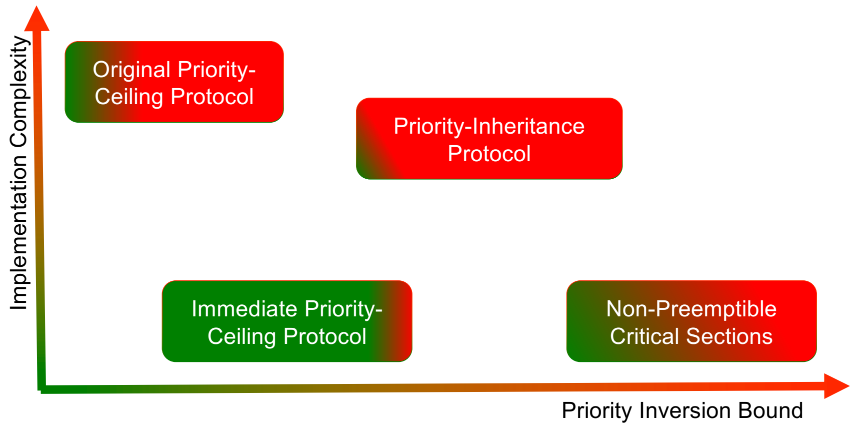


Immediate Priority Ceiling:
- Requires correct prio config
- Deadlock-free
- Easy to implement
- Good worst-case blocking times

Each task must declare all resources at admission time
- System must maintain list of tasks using resource
- Defines ceiling priority

Easy to enforce with caps

Comparison of Locking Protocols



Scheduling Overloaded RT Systems

Naïve Assumption: Everything is Schedulable

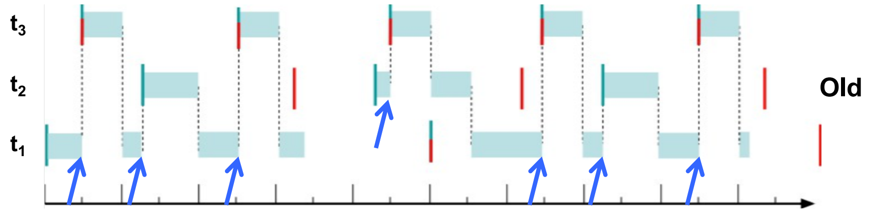
Standard assumptions of classical RT systems:
- All WCETs known
- All jobs complete within WCET
- Everything is trusted

More realistic: Overloaded system:

Which job will miss its deadline?

- Total utilisation exceeds schedulability bound
- Cannot trust everything to obey declared WCET

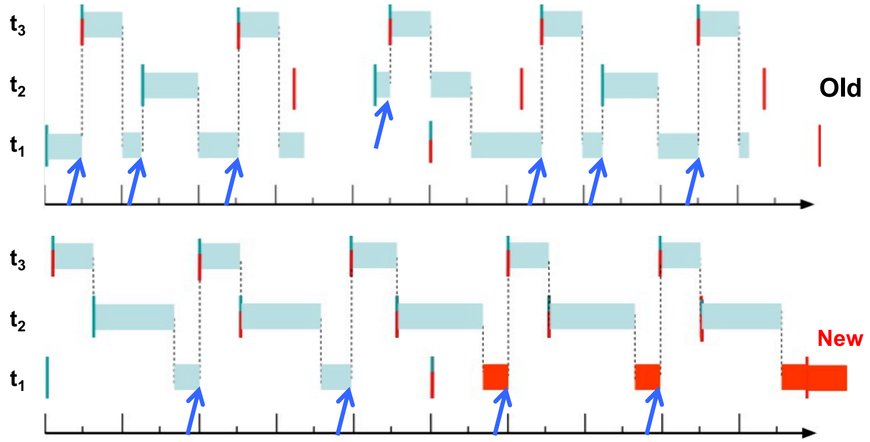
Overload: FPS



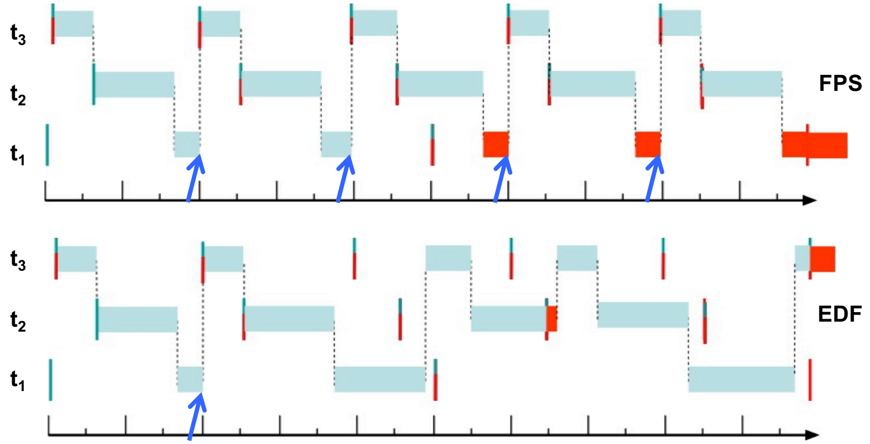
Task	P	C	T	D	U [%]
t_3	3	5	20	20	25
t_2	2	12	20	20	60
t_1	1	15	50	50	30
					115

New

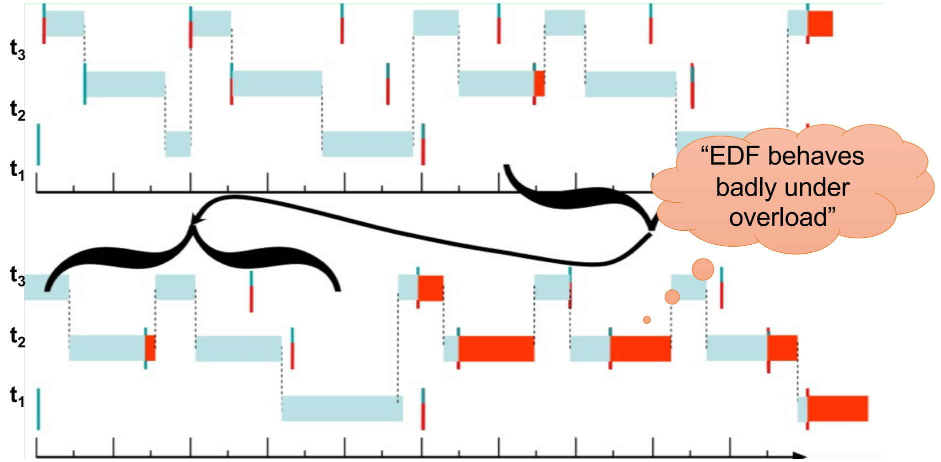
Overload: FPS



Overload: FPS vs EDF



Overload: EDF



Mixed-Criticality Systems

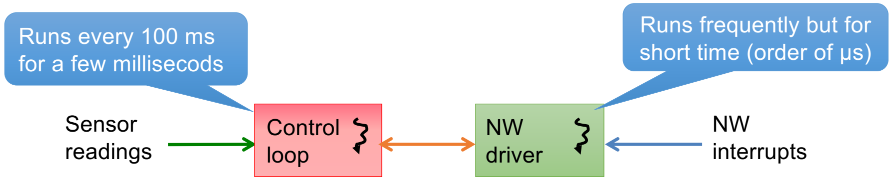
Mixed Criticality Systems

Mixed Criticality

Need temporal isolation!

NW driver must preempt control loop

- … to avoid packet loss
- Driver must run at high prio (i.e. RMPA)
- *Driver must not monopolise CPU*



Runs every 100 ms for a few millisecods

Runs frequently but for short time (order of μs)

Mixed Criticality

NW driver must preempt control loop

- … to avoid packet loss
- Driver must run at high prio (i.e. RMPA)
- *Driver must not monopolise CPU*

Certification requirement: More critical components must *not* depend on any less critical ones! [ARINC-653]

Critical system certification:

- expensive
- conservative assumptions
  - eg highly pessimistic WCET

- Must minimise critical software
- Need temporal isolation: Budget enforcement

Mixed-Criticality Support

For supporting *mixed-criticality systems* (MCS), OS must provide:

- *Temporal isolation*, to force jobs to adhere to declared WCET

- Mechanisms for *safely sharing resources* across criticalities

Will discuss seL4 approach next lecture!