



Real-Time Operating System (Day 1 Lab)

Jong-Chan Kim

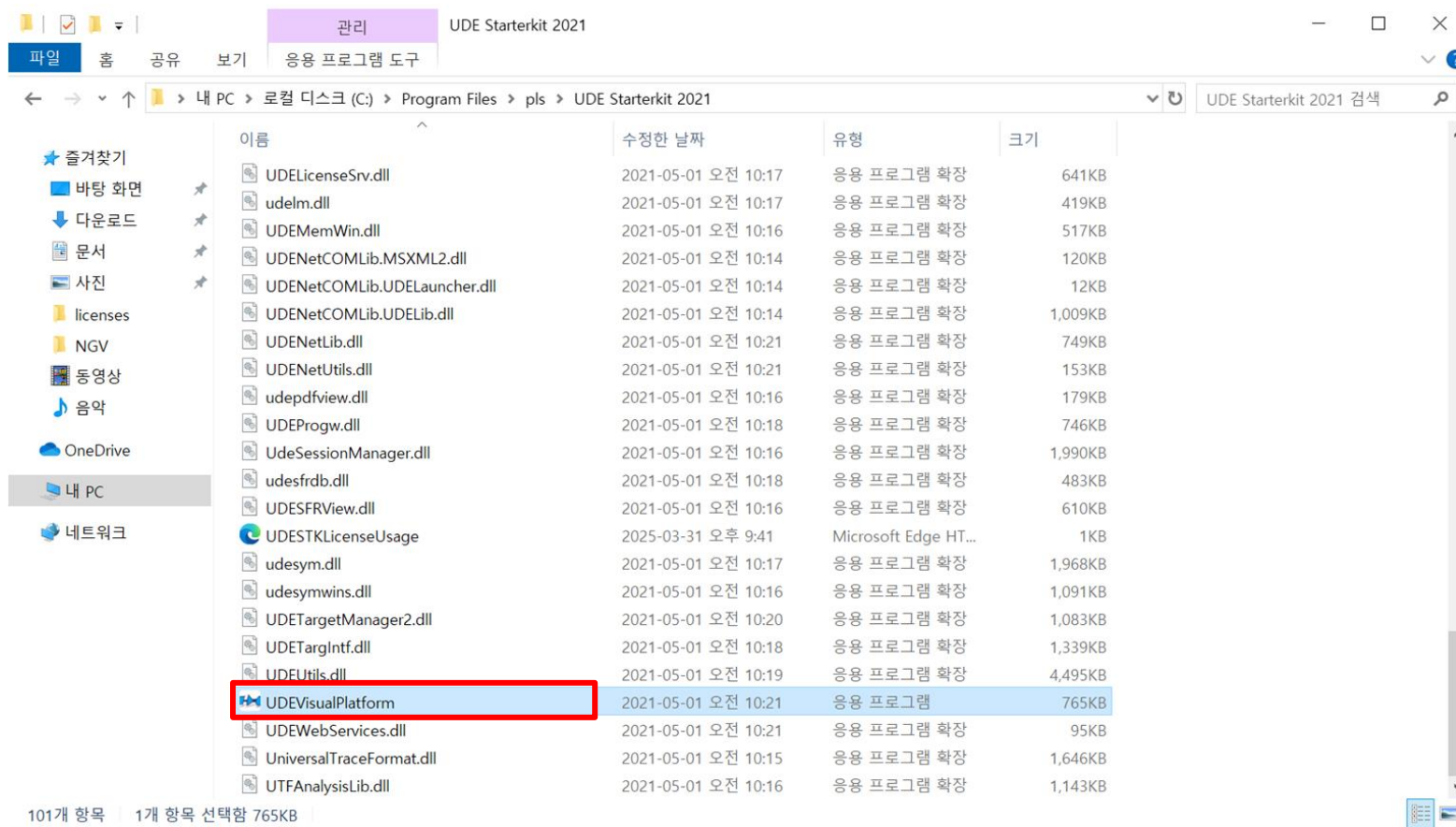
Graduate School of Automotive Engineering



국민대학교
KOOKMIN UNIVERSITY

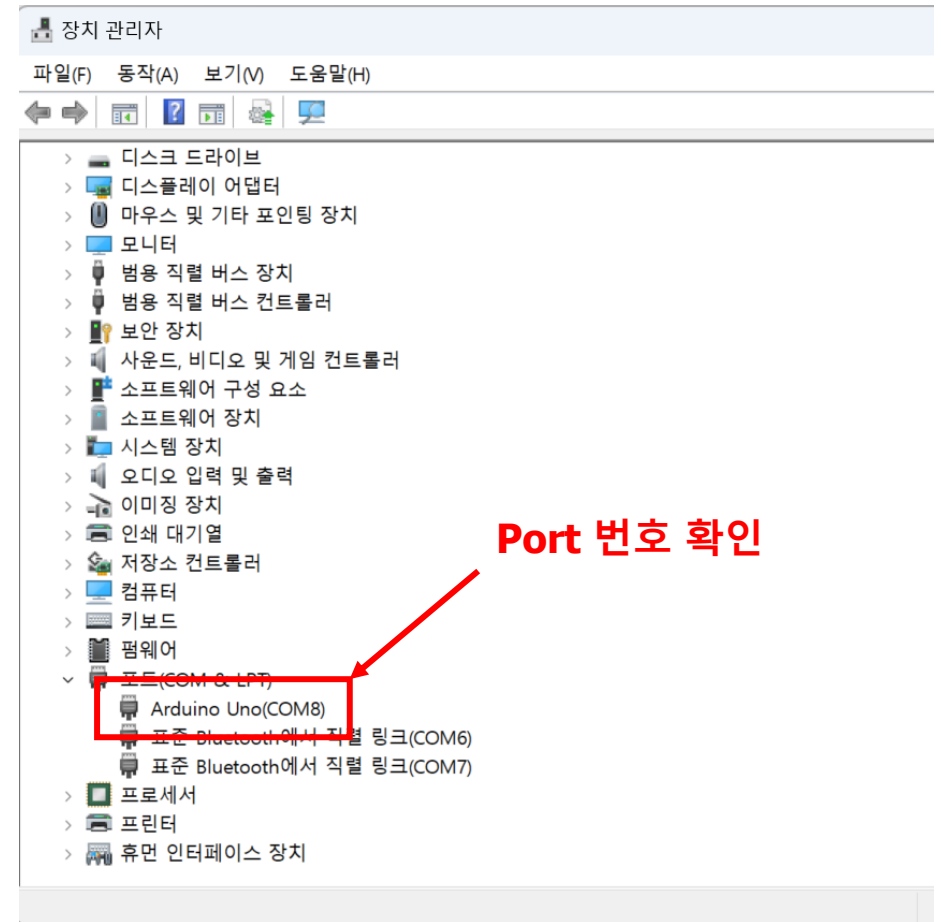
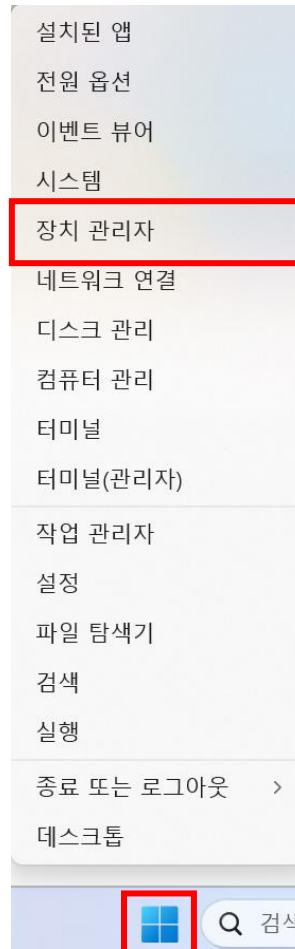
UDE 디버거 실행

- C:\Program Files\pls\UDE Starterkit 2021 경로에 있는 UDEVisualPlatform 바로가기 생성 후 실행



프로젝트 빌드

- TC275 연결 후 포트 번호 확인(장치 관리자 > 포트)



프로젝트 빌드

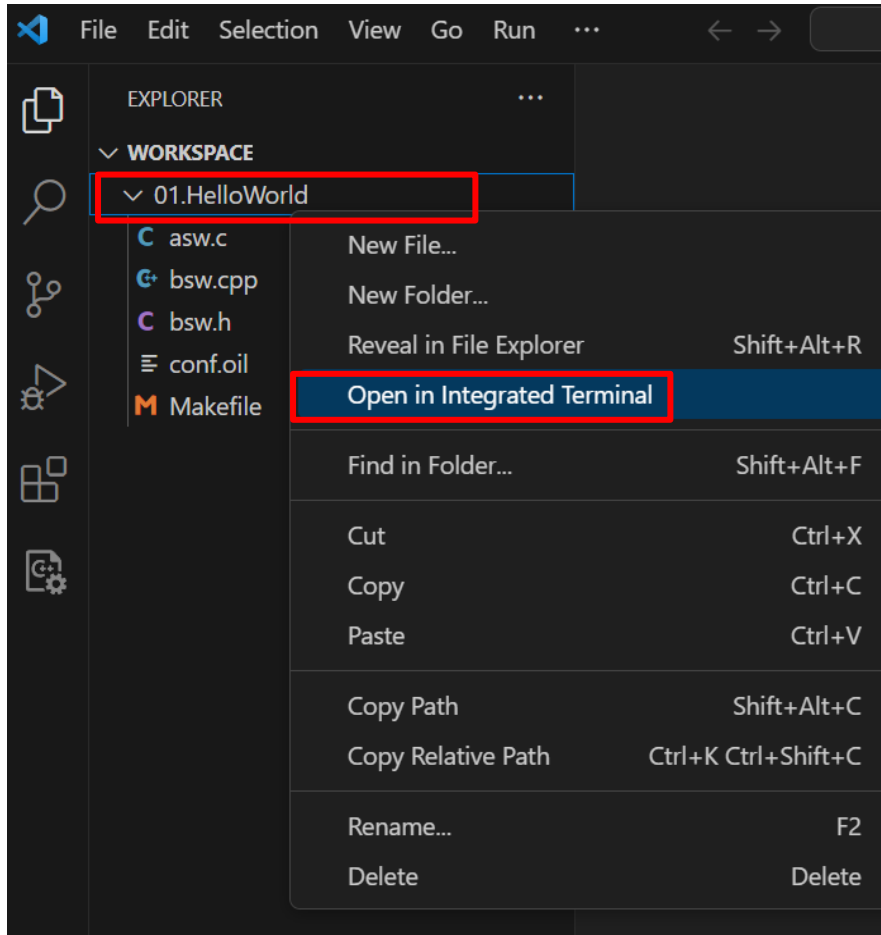
- NGV 폴더 안의 '01. Hello World' 폴더 복사
- 바탕화면에 workspace 생성 후 붙여넣기

이름	수정한 날짜	유형
01. Hello World	2025-03-31 오후 8:48	파일 폴더
eclipse	2025-03-31 오후 7:46	파일 폴더
free_tricore_entry_tool_chain	2025-03-31 오후 9:39	파일 폴더
make-4.3	2025-03-31 오후 7:47	파일 폴더
1. JAVA설치	2025-03-31 오후 7:45	응용 프로그램
2. Cygwin설치	2025-03-31 오후 7:45	응용 프로그램
3. Python 3.11.4 설치	2025-03-31 오후 7:45	응용 프로그램
4. VSCode 설치	2025-03-31 오후 7:45	응용 프로그램
free_tricore_entry_tool_chain	2025-03-31 오후 7:45	압축(ZIP) 폴더
TMACv6.0.7_Setup	2025-03-31 오후 10:08	응용 프로그램

workspace		
공유 보기		
내 PC > 바탕 화면 > workspace		
이름	수정한 날짜	유형
01. Hello World	2025-03-31 오후 10:41	파일 폴더

프로젝트 빌드

- '01.Hello World' 폴더 우클릭 후
'Open in Integrated Terminal' 실행



- Terminal에서 make config 실행

A screenshot of the VS Code Terminal window. The terminal shows the command 'make config' being executed in a PowerShell session. The output includes the removal of 'erika' and 'out' directories, the execution of a batch file to generate code, and the configuration of RT-Druid. The 'make config' command is highlighted with a red box. The output text is as follows:

```
PS C:\Users\AVEES\Desktop\cp4ad_2023\workspace\01.HelloWorld> make config
rm -rf 'erika'
rm -rf 'out'
'/cygdrive/c/eclipse/evidence/generate_code.bat' 'C:\eclipse' conf.oil .; echo "[Config DONE]"
RT-Druid generator
-- time : 0ms
Using:
- ERIKA_FILES = C:\eclipse\plugins\com.eu.evidence.ee3_3.0.1.20190524_gh65\ee_files
- RT-Druid ext. =

#####
#
# RT-Druid 3 generator: Version 3.0.1 (Build GH 65)
#
# Date      : 2024/01/16 12:18:31
# Oil file  : conf.oil
#
# Erika     : C:\eclipse\plugins\com.eu.evidence.ee3_3.0.1.20190524_gh65\ee_files
```

A screenshot of the VS Code Terminal window showing the completion of the build process. The terminal output includes the time taken for the build (406ms), the generation of OS and Appl configuration files, and the storage of the signature file. The final output shows the build completed and the configuration done. The text is as follows:

```
-- time : 406ms (delta 0ms)
Run build
Missing OS signature
Enable the generation of OS configuration files.
Missing Appl signature
Enable the generation of Appl configuration files.
Start the computation of event's masks.
Computation of event's masks completed.
Start the generation of OS configuration files.
Start the generation of Appl configuration files.
Generation completed.

Storing Appl signature file: C:\Users\AVEES\Desktop\cp4ad_2023\workspace\01.HelloWorld\out\applSignature.oil
Storing OS signature file: C:\Users\AVEES\Desktop\cp4ad_2023\workspace\01.HelloWorld\erika\osSignature.oil
-- time : 2443ms (delta 2036ms)
Build completed
[Config DONE]
PS C:\Users\AVEES\Desktop\cp4ad_2023\workspace\01.HelloWorld>
```

"Build Completed"
출력 확인 (빌드 완료)

프로젝트 빌드

- Terminal에서 make 실행

```
PROBLEMS OUTPUT DEBUG CONSOLE TERMINAL PORTS SERIAL MONITOR
PS C:\Users\AVEES\Desktop\cp4ad_2023\workspace\01.HelloWorld> make
cd 'out'; sed -i 's/cygpath -ms ""/cygpath -ms "C:\\Arduino\\<del>/</del>' makefile; make BINDIR="/cygdrive/C/Arduino/hardware/tools/avr/bin"
make[1]: Entering directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/out'
make[2]: Entering directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/erika'
ERIKA_FILES=/cygdrive/c/eclipse/plugins/COMEUE~4.201/ee_files
make[3]: Entering directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/erika'
*****
* Pulling erika files from:
*****
* ERIKA_FILES=/cygdrive/c/eclipse/plugins/COMEUE~4.201/ee_files
*****
* Erika Enterprise Pulled successfully! *
*****
make[3]: Leaving directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/erika'
make[2]: Leaving directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/erika'
make[2]: Entering directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/erika'
ERIKA_FILES=/cygdrive/c/eclipse/plugins/COMEUE~4.201/ee_files
make[3]: Entering directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/erika'
*****
* Erika Enterprise Libraries build... *
*****
CC hooks.c
CC wiring.c
CC wiring_digital.c
CC wiring_analog.c
```

```
*****
* Erika Enterprise Application built successfully! *
*****
make[2]: Leaving directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/out'
make[1]: Leaving directory '/cygdrive/c/Users/AVEES/Desktop/cp4ad_2023/workspace/01.HelloWorld/out'
PS C:\Users\AVEES\Desktop\cp4ad_2023\workspace\01.HelloWorld>
```

**“Built successfully”
출력 확인 (make 완료)**

Erika Enterprise



- 이탈리아 EVIDENCE에서 개발된 오픈소스 OSEK/VDX RTOS
- 듀얼 라이선스 정책 (오픈소스 라이선스 + 상용 라이선스)
- RTOS 연구 및 교육에 널리 사용
- GitHub 리포



evidence / erika3 Public

Watch 25 Fork 72 Star 155

Code Issues 2 Pull requests 1 Actions Projects Wiki Security Insights

master 1 branch 15 tags Go to file Add file Code

eguidieri [tricore] Fixed interrupt regression in... 85c445d on 13 Sep 2019 245 commits

contrib	[kernel] PostTaskHook called twice fixed and Initial ...	3 years ago
doc	[kernel] Fixed WaitEvent, in case of multicore enviro...	4 years ago
mk	[kernel] Fixed WaitEvent, in case of multicore enviro...	4 years ago
pkg	[tricore] Fixed interrupt regression introduced by co...	3 years ago
LICENSE.TXT	Update LICENSE to all files	4 years ago
README.md	[kernel] Fixed WaitEvent, in case of multicore enviro...	4 years ago
THIRDPARTY.TXT	[THIRDPARTY] Rephrased and fixed the statement r...	3 years ago

About

ERIKA Enterprise v3 RTOS

www.erika-enterprise.com

arduino avr arm real-time

cortex-m x86-64 xen rtos

cortex-a autosar osek dspic

aurix tricore-development cortex-r5f

erika-enterprise jailhouse

Readme

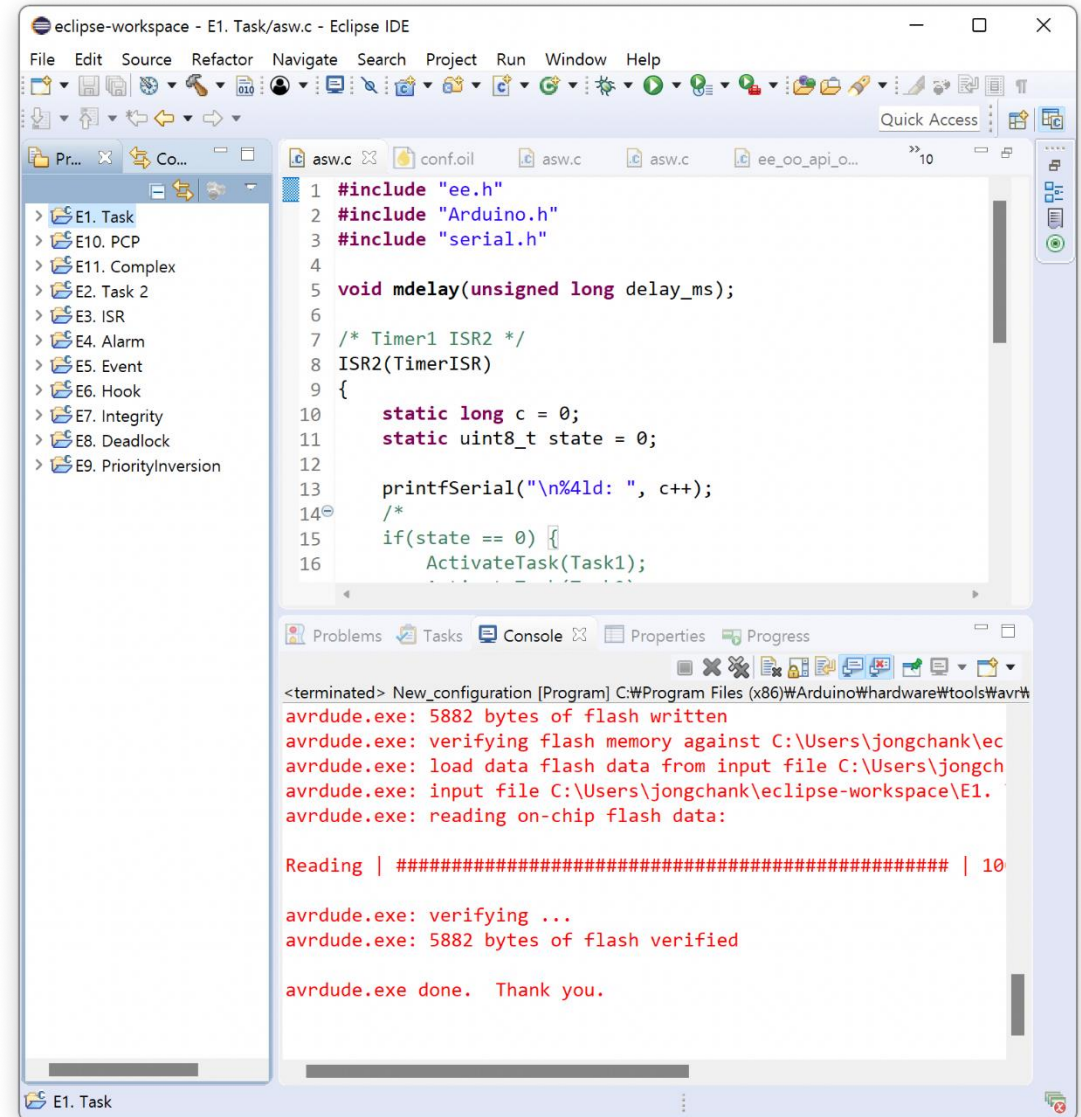
View license

155 stars

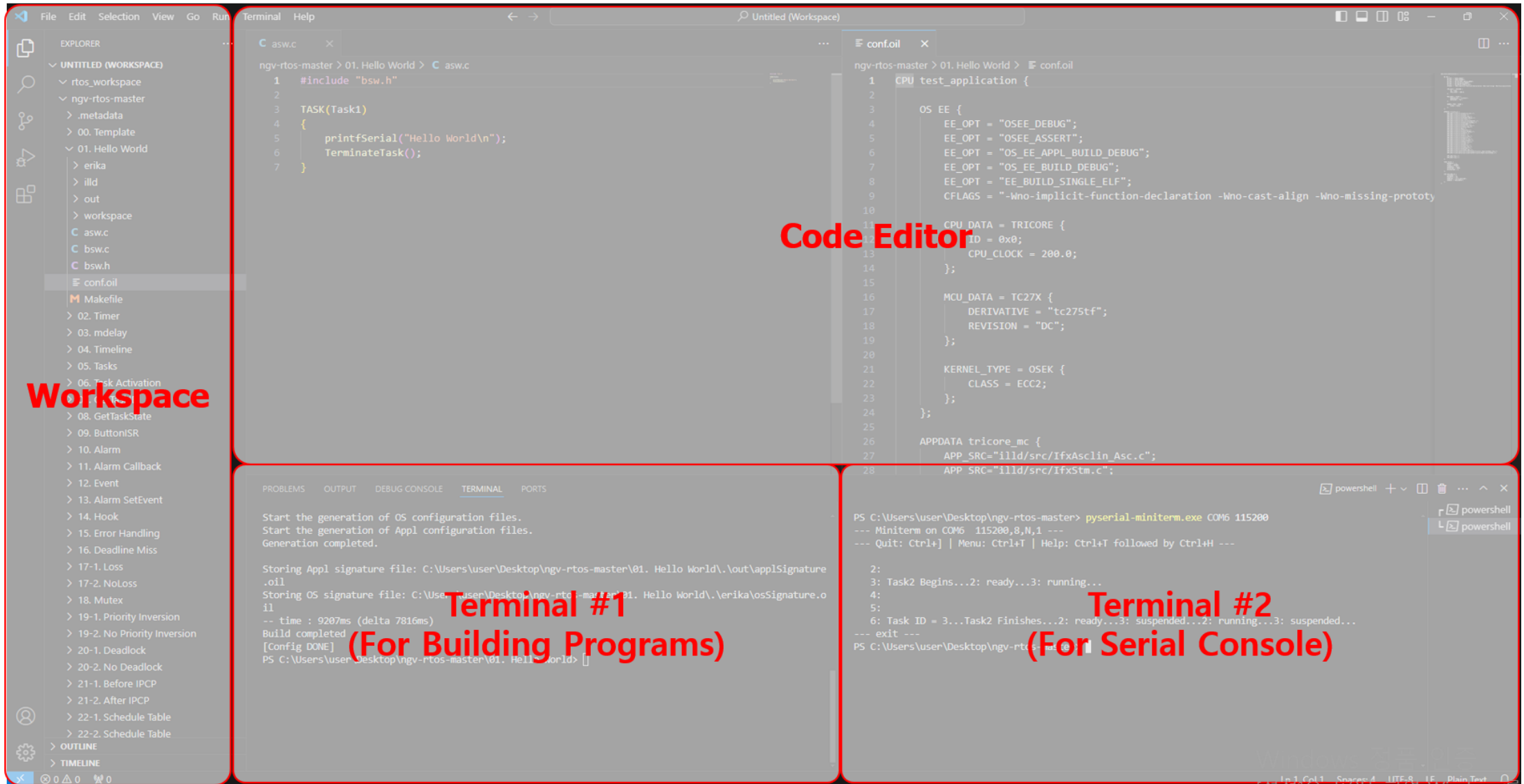
25 watching

Eclipse 기반 IDE (old)

- 프로젝트 생성
- OIL 파일, C/C++ 파일 편집
- 프로젝트 빌드
- 실행파일 다운로드
- ...



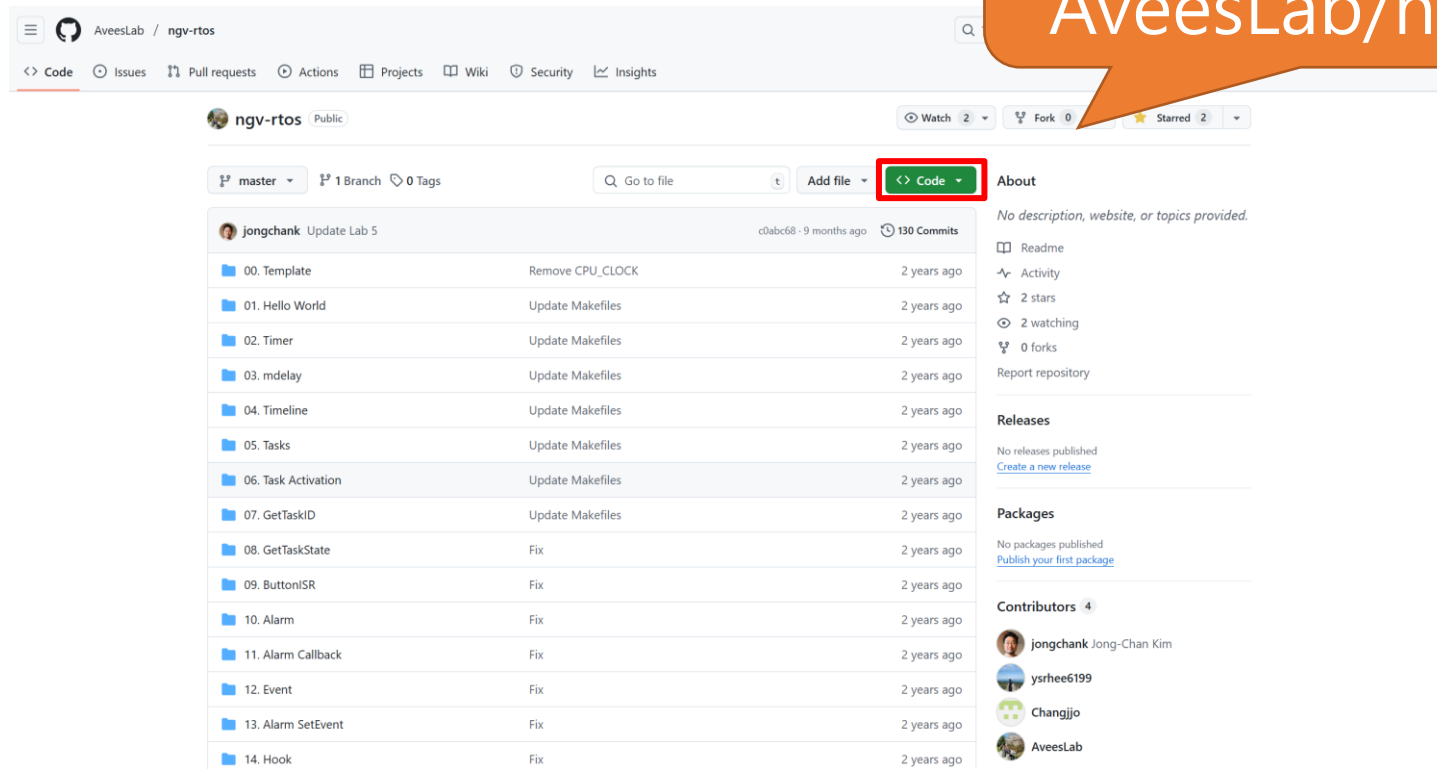
Visual Studio Code 기반 개발환경 (new)



workspace

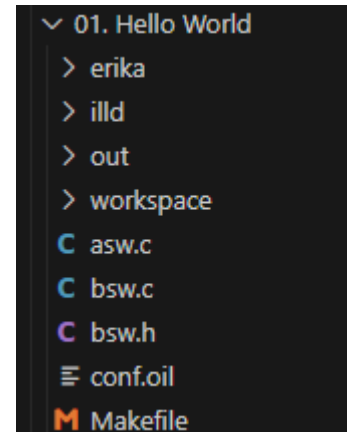
- Directory Structure
 - workspace
 - rtos_workspace: working directory
 - ngv-rtos-master: example source files

<https://github.com/AveesLab/ngv-rtos>



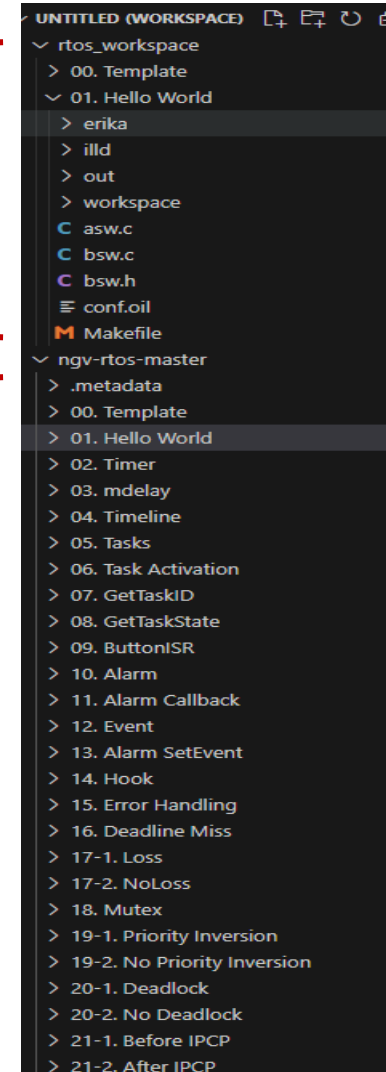
Visual Studio Code 기반 개발환경 (new)

- Directory Structure
 - rtos_workspace: working directory
 - ngv-rtos-master: example source files
- Example Projects Directory Structure
 - illd/: Infineon Low Level Driver
 - **asw.c**: Application SW code
 - bsw.c: Basic SW code
 - bsw.h: Basic SW header
 - **conf.oil**: OIL configuration file
 - Makefile: Top-level Makefile



Working

Examples



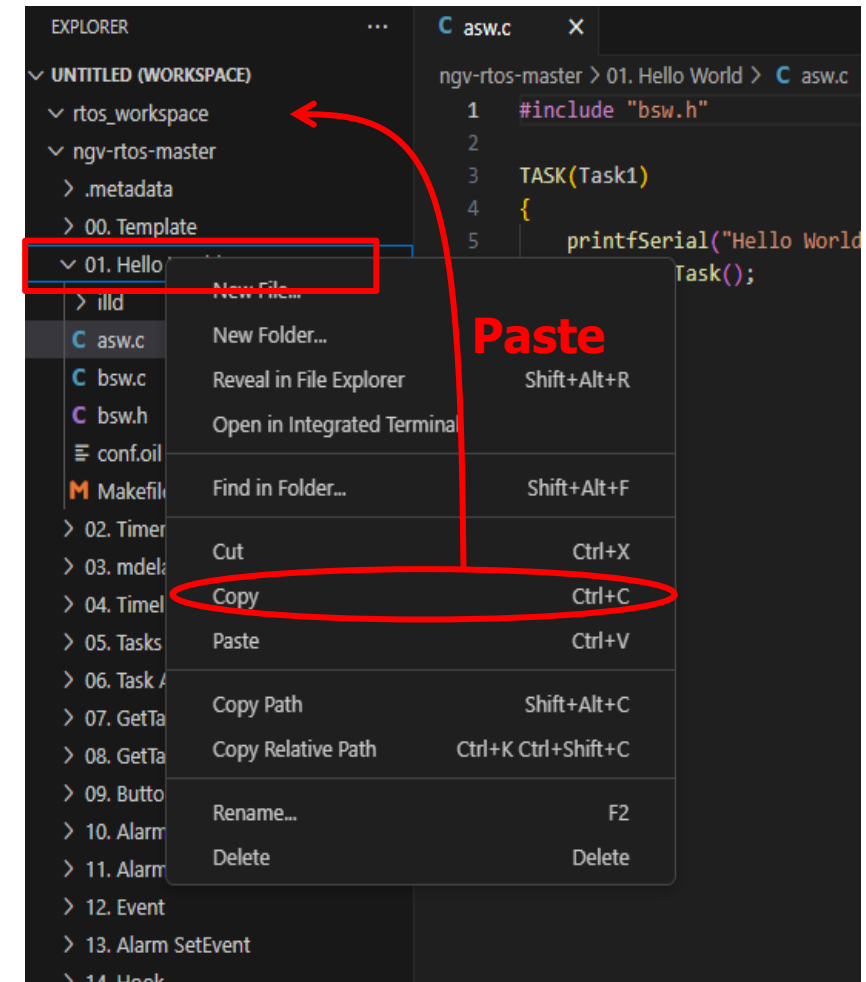
Workflow

- Basic Workflow

- 1) Copy a project (e.g., 01. Hello World) from to working directory
- 2) Edit source files (.C or .H) and OIL files
- 3) Build

- Build Process (in Terminal #1)

- 1) `cd 01. Hello World\`
- 2) `make config`
 - Generate OS kernel files from `conf.oil`
- 3) `make`
 - Generate an executable file

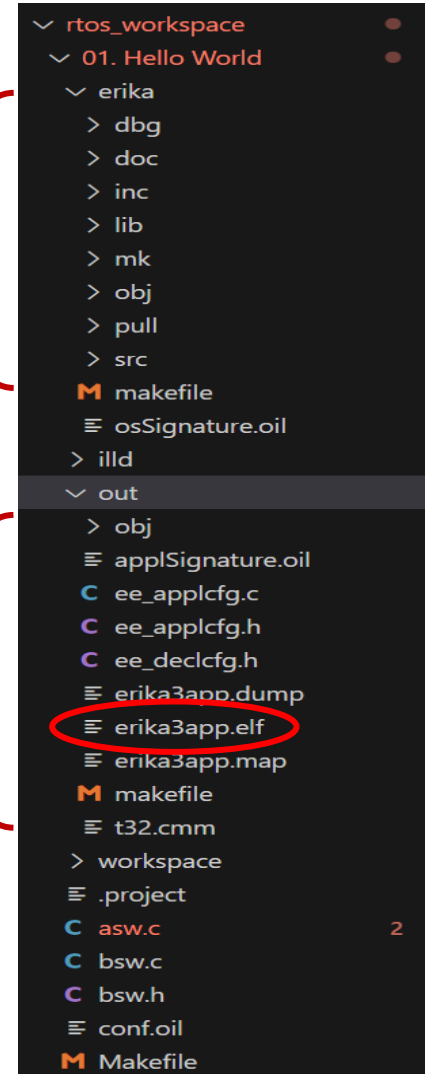


Generated Files

- erika/
 - OS source files
- out/
 - Generated files from the OIL file
 - Object files
 - Executable (ELF) file (erika3app.elf)

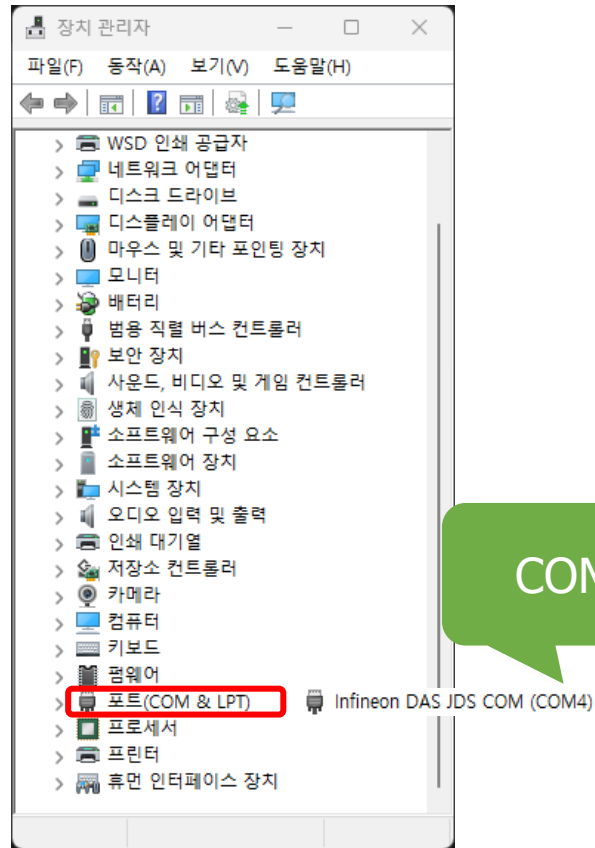
OS source files

Generated files



Serial Console

- 장치관리자에서 COM 포트 확인 (e.g., COM4)
- pyserial-miniterm 이용하여 시리얼 콘솔 시작 (Terminal #2)



pip3 install pyserial

COM 포트

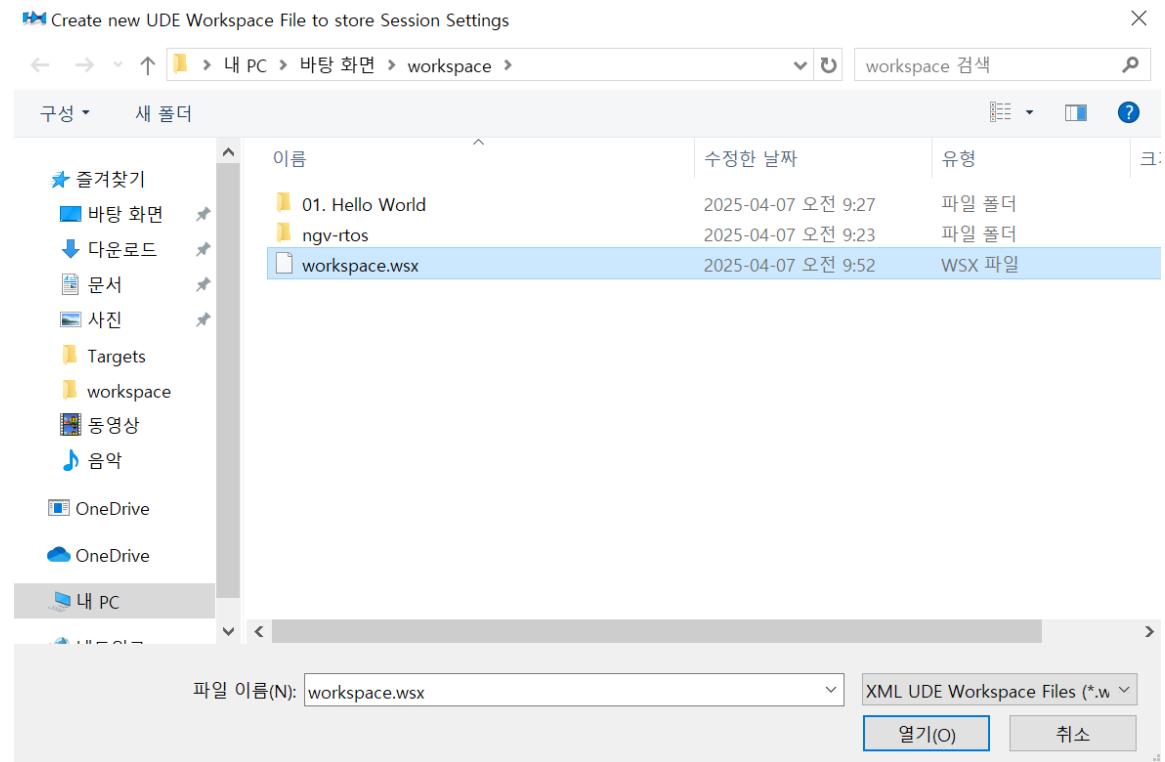
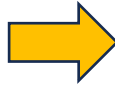
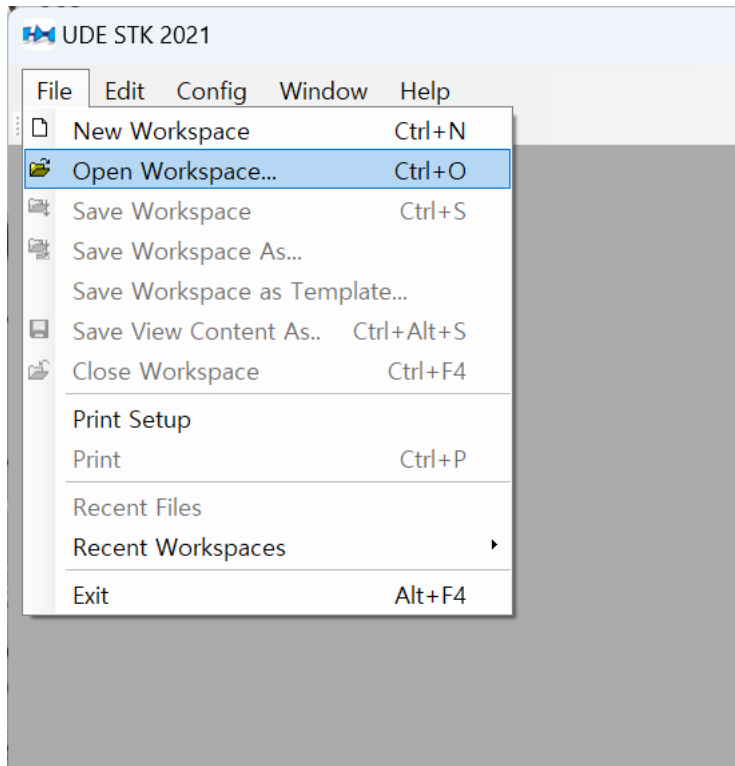
Baudrate

```
PS C:\Users\jongchank\work> pyserial-miniterm.exe COM4 115200
--- Miniterm on COM4 115200,8,N,1 ---
--- Quit: Ctrl+] | Menu: Ctrl+T | Help: Ctrl+T followed by Ctrl+H ---

```

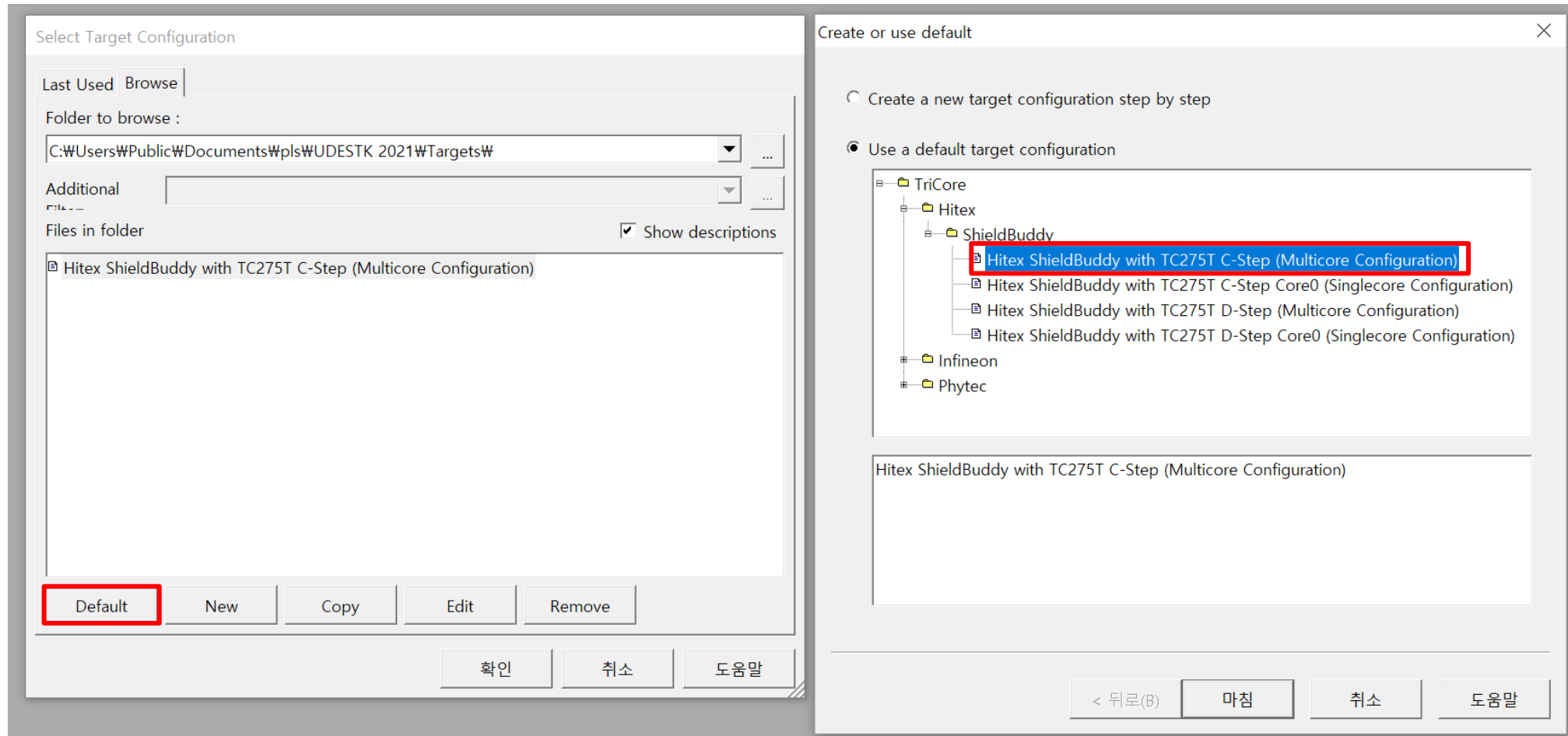
New Workspace

- File → New Workspace
- 바탕화면 > workspace > workspace.wsx 생성



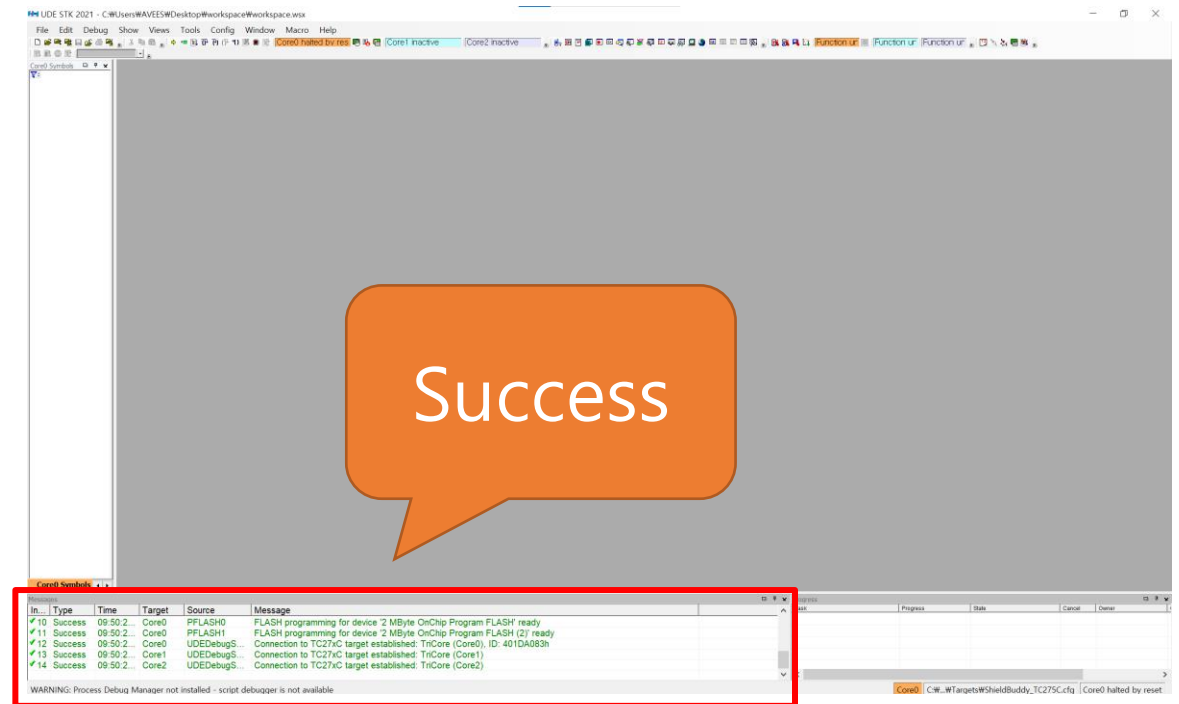
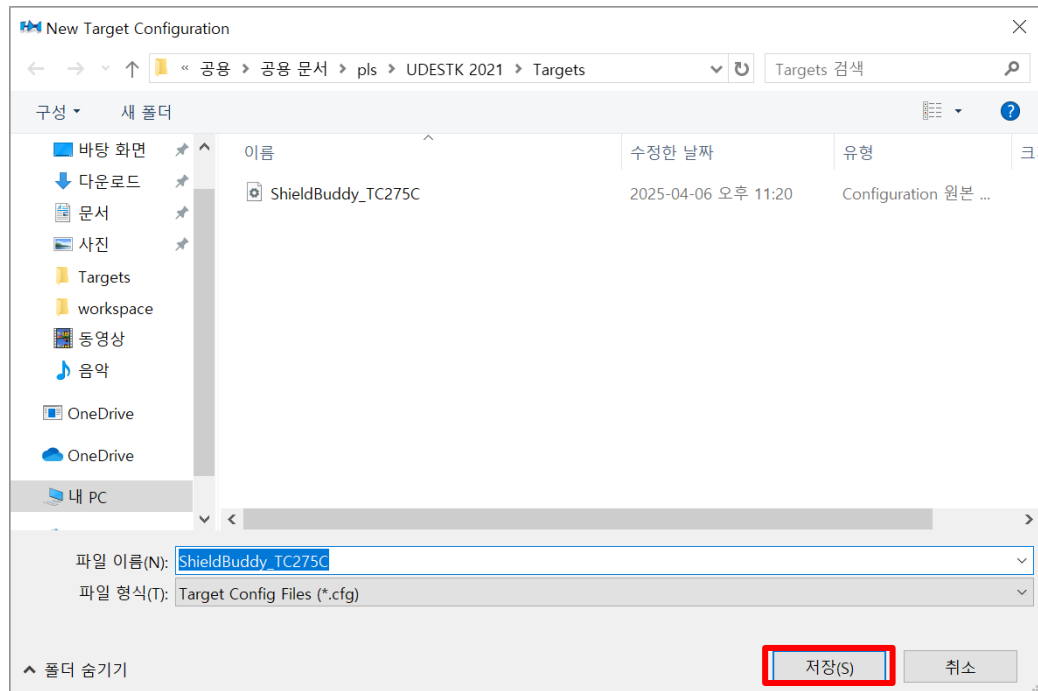
New Workspace

- Select Target Configuration > Default
- TriCore > HiTex > ShieldBuddy > ... with TC275T C-step (Multicore...)



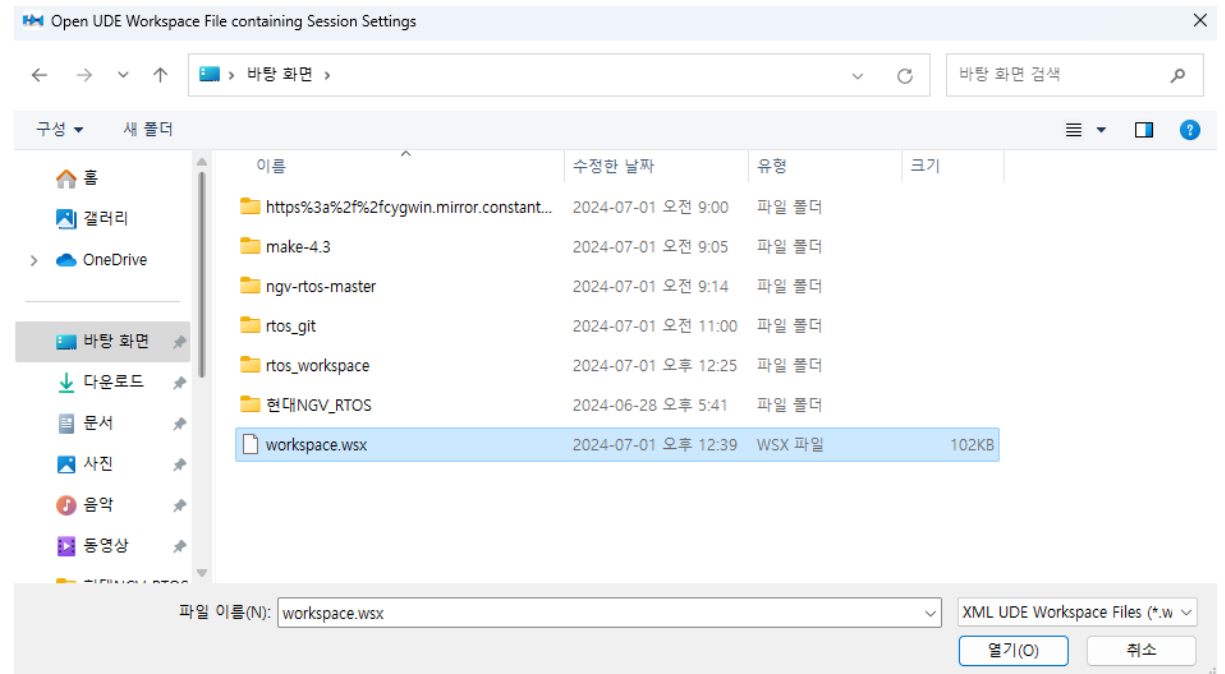
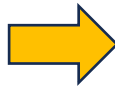
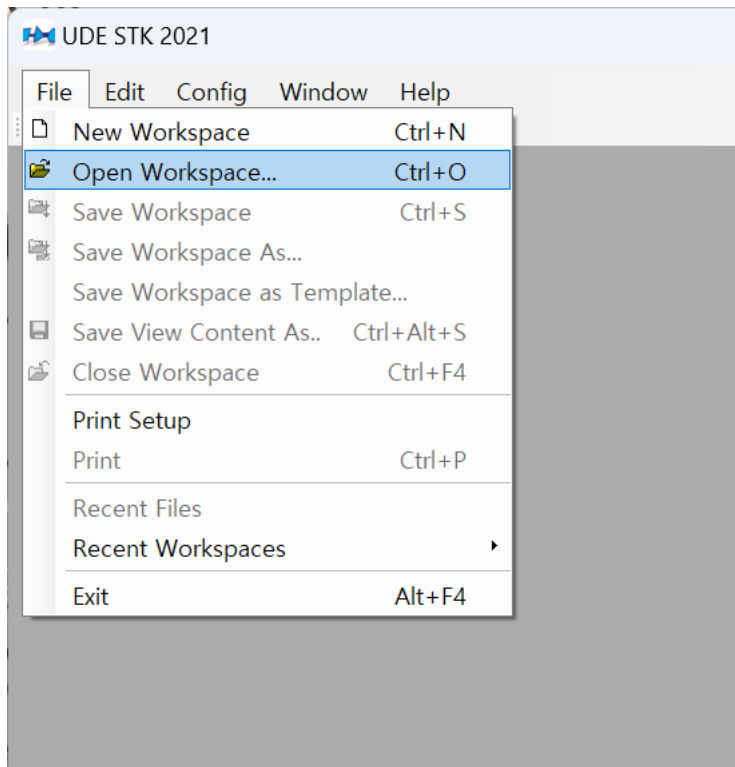
New Workspace

- ShiedlBuddy_TC275C.cfg 저장
- 연결 실패시, ... with TC275T D-step (Multicore...)으로 다시 진행



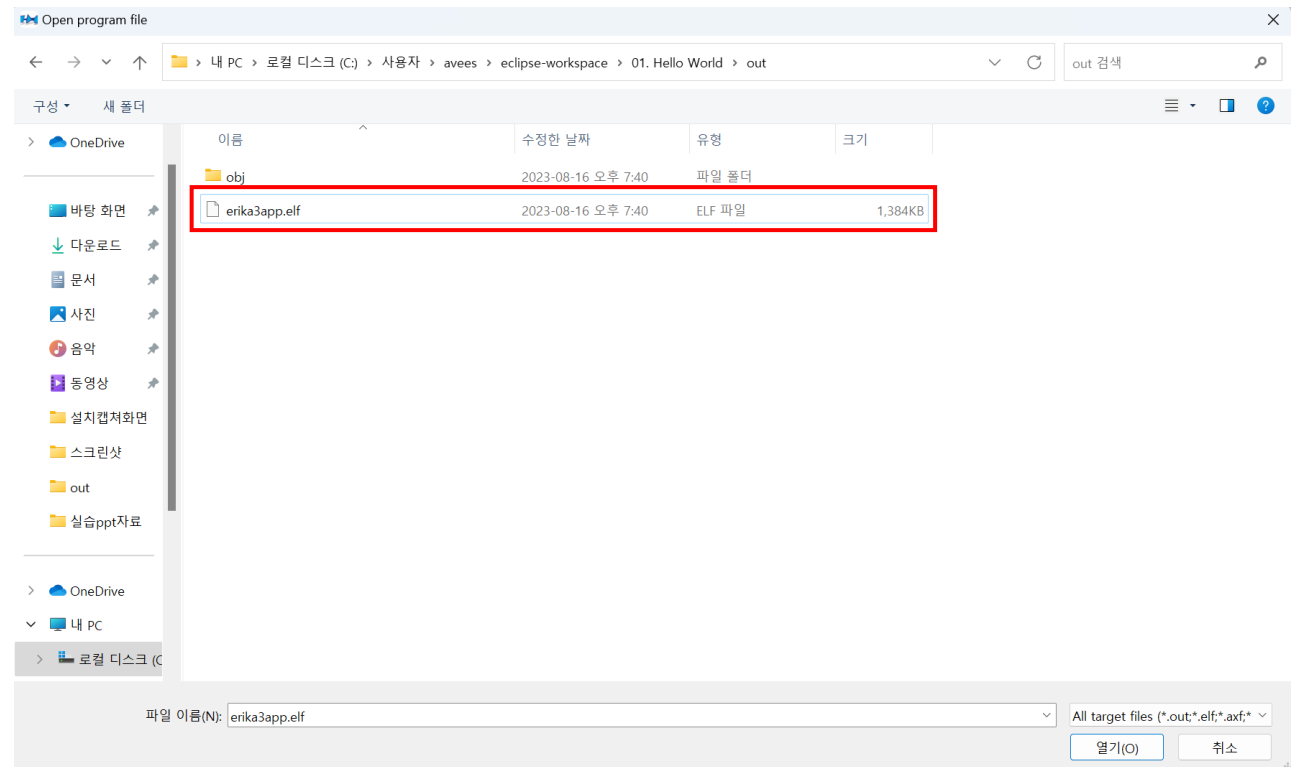
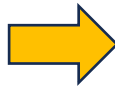
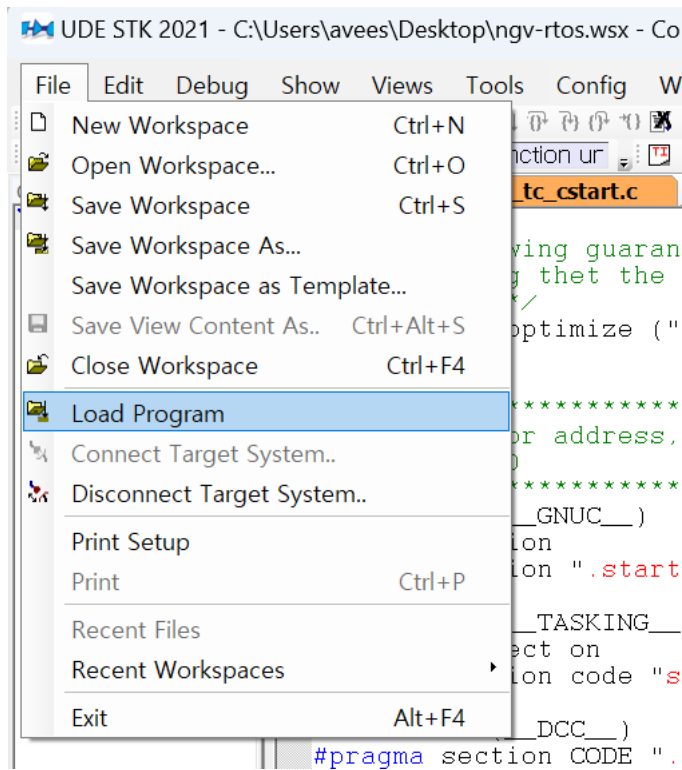
Program Flashing by UDE #1

- File → Open Workspace
- 바탕화면의 workspace.wsx 열기



Program Flashing by UDE #2

- File → Load Program
- 프로젝트 폴더의 out/erika3app.elf 열기

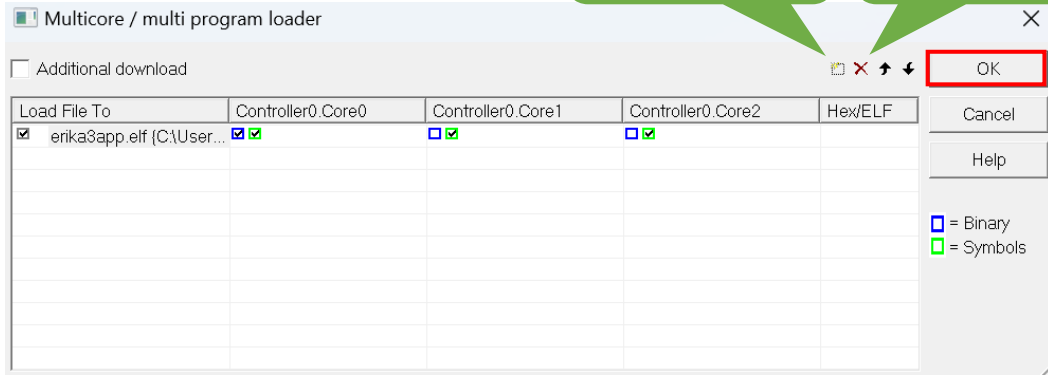


Program Flashing by UDE #3

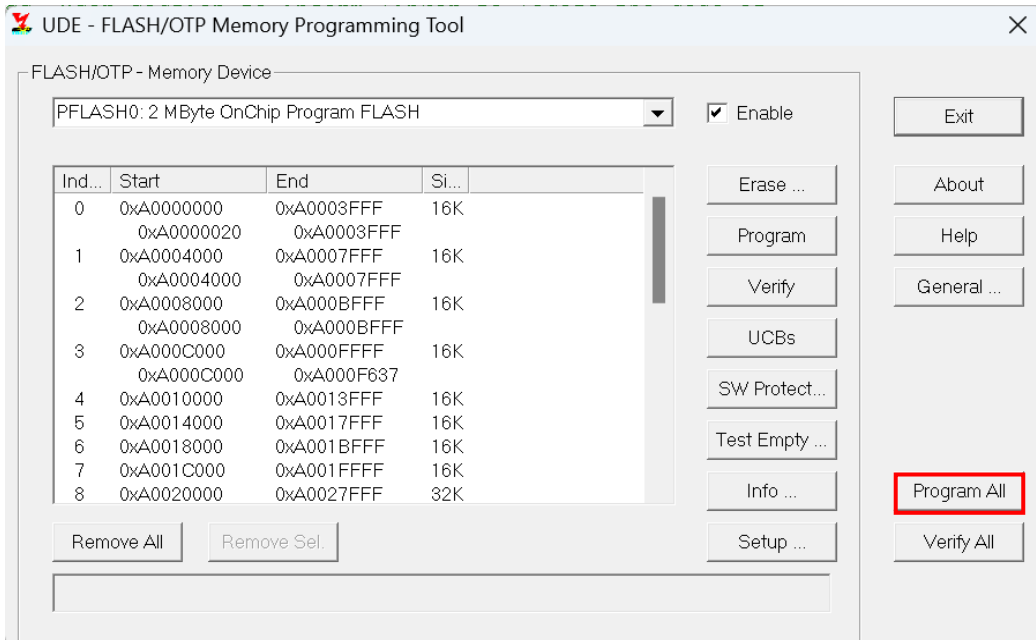
새 파일
열기

기존 파일
해제

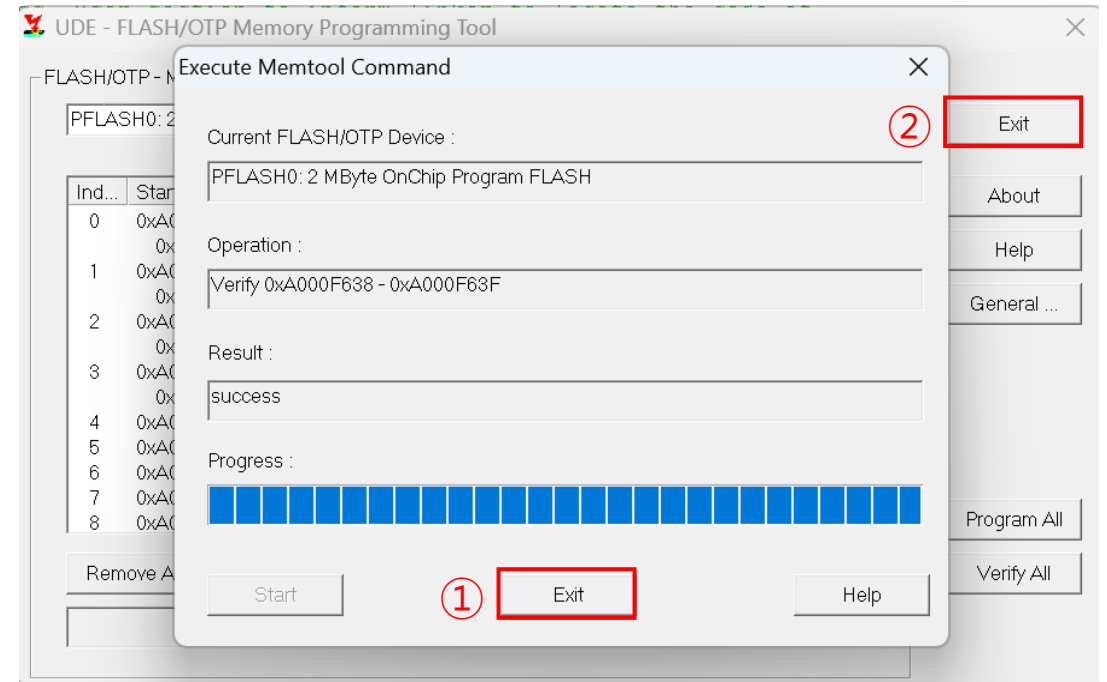
• Step1



• Step2

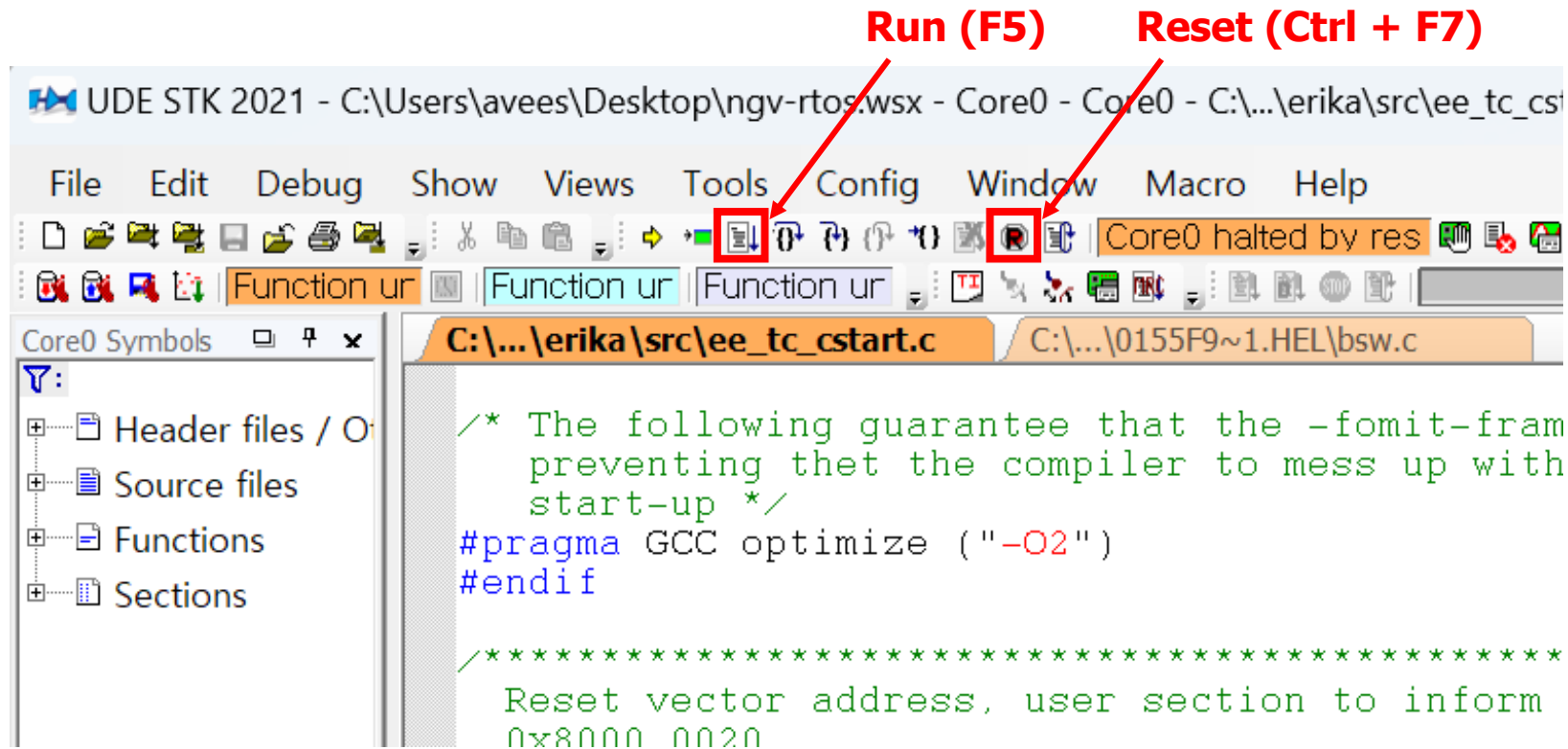


• Step3



Program Flashing by UDE #4

- 프로그램 실행 (run)
- 기존 프로그램 실행중일 경우 reset 후 실행



01. Hello World

- 00. Template 복사
- asw.c에 TASK 추가
- OIL 파일에 TASK 추가
- printfSerial() 함수 사용 (시리얼 콘솔 출력)

Make config는 OIL
변경시에만

```
$ make config  
$ make
```

```
#include "bsw.h"  
  
TASK(Task1)  
{  
    printfSerial("Hello World\n");  
  
    TerminateTask();  
}
```

```
TASK Task1 {  
    PRIORITY = 1;  
    STACK = SHARED;  
    SCHEDULE = FULL;  
    AUTOSTART = TRUE;  
    ACTIVATION = 1;  
};
```

자동
시작

01. Hello World

- OS 시작 후
- Hello World 출력

```
PS C:\Users\jongchank\work> pyserial-miniterm.exe COM4 115200
--- Miniterm on COM4 115200,8,N,1 ---
--- Quit: Ctrl+] | Menu: Ctrl+T | Help: Ctrl+T followed by Ctrl+H ---

.....
...OS Starts...
.....
Hello World
█
```


02. Timer

- C 파일에 ISR2로 TimerISR 추가
- OIL 파일에 TimerISR 추가
 - Category 2

1초 뒤
interrupt 등록

```
ISR2(TimerISR)
{
    osEE_tc_stm_set_sr0_next_match(1000000U);
    printfSerial("Timer\n");
}
```

```
ISR TimerISR {
    CATEGORY = 2;
    SOURCE = "STM0SR0";
    PRIORITY = 2;
};
```

02. Timer

- Hello World 출력후 Timer 반복

```
PS C:\Users\jongchank\work> pyserial-miniterm.exe COM4 115200
--- Miniterm on COM4 115200,8,N,1 ---
--- Quit: Ctrl+] | Menu: Ctrl+T | Help: Ctrl+T followed by Ctrl+H ---

.....
...OS Starts...
.....
Hello World
Timer
Timer
Timer
Timer
Timer
Timer
[]
```

03. mdelay

- mdelay 함수 이용 3초 실행시간

```
TASK(Task1)
{
    printfSerial("Hello World\n");

    mdelay(3000);

    printfSerial("Goodbye World\n");
    TerminateTask();
}
```

```
PS C:\Users\jongchank\work> pyserial-miniterm.exe COM4 115200
--- Miniterm on COM4 115200,8,N,1 ---
--- Quit: Ctrl+] | Menu: Ctrl+T | Help: Ctrl+T followed by Ctrl+H ---

.....
...OS Starts...
.....
Hello World
Goodbye World
[]
```

04. Timeline

- TimerISR 이용 초단위 Timeline 출력

```
ISR2(TimerISR)
{
    static long c = 0;
    osEE_tc_stm_set_sr0_next_match(1000000U);
    printfSerial("\n%4ld: ", c++);
}
```

```
.....
...OS Starts...
.....
Hello World

0:
1:
2: Goodbye World

3:
4:
5:
6:
7:
8:
9: []
```

05. Tasks

```
TASK(Task1)
{
    printfSerial("Task1 Begins...");
    mdelay(3000);
    printfSerial("Task1 Finishes...");

    TerminateTask();
}

TASK(Task2)
{
    printfSerial("Task2 Begins...");
    mdelay(3000);
    printfSerial("Task2 Finishes...");

    TerminateTask();
}
```

- 우선순위 2의 Task2 추가

클수록 높은
우선순위

```
TASK Task2 {
    PRIORITY = 2;
    STACK = SHARED;
    SCHEDULE = FULL;
    AUTOSTART = TRUE;
    ACTIVATION = 1;
};
```


05. Tasks

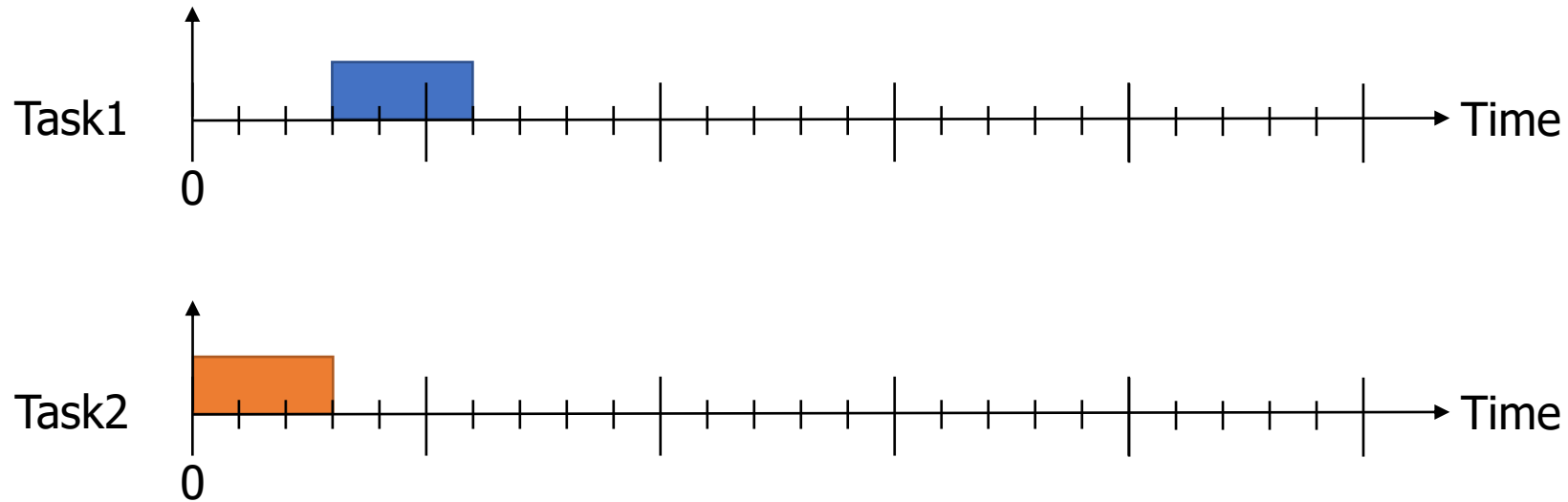
- Task2가 먼저 시작
- Task2 종료 후 Task1 시작

```
PS C:\Users\jongchank\work> pyserial-miniterm.exe COM4 115200
--- Miniterm on COM4 115200,8,N,1 ---
--- Quit: Ctrl+] | Menu: Ctrl+T | Help: Ctrl+T followed by Ctrl+H ---

.....
...OS Starts...
.....
Task2 Begins...
  0:
  1:
  2: Task2 Finishes...Task1 Begins...
  3:
  4:
  5: Task1 Finishes...
  6:
  7: []
```

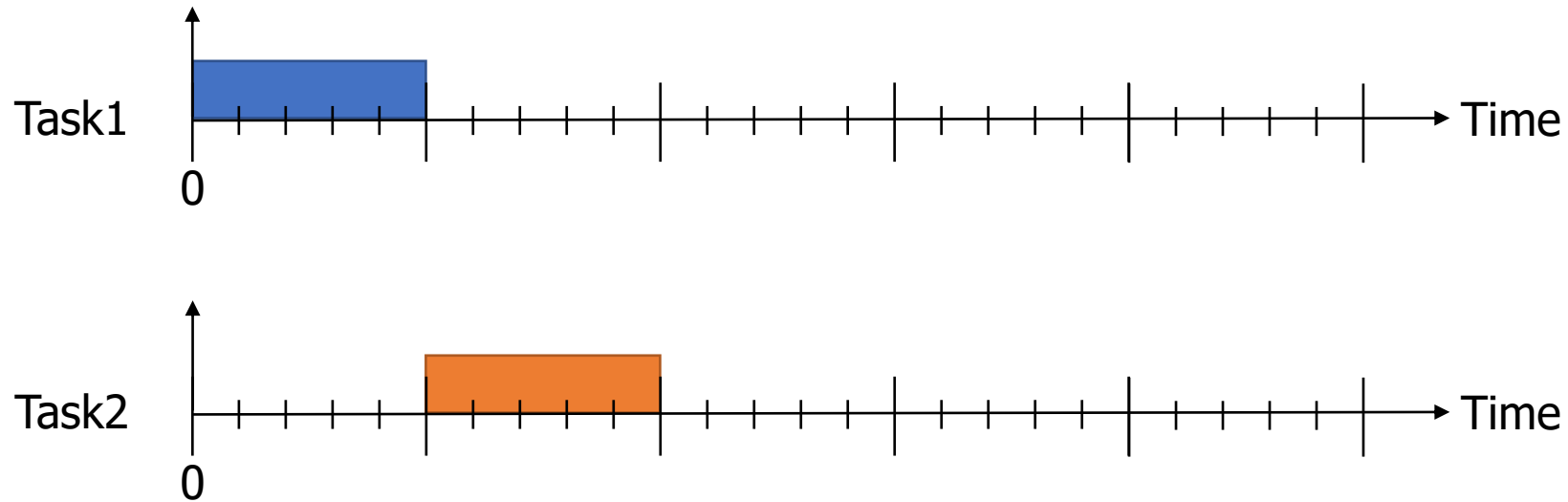
05. Tasks

- 실행 결과
 - Task1: 낮은 우선순위, 실행 시간 3초
 - Task2: 높은 우선순위, 실행 시간 3초



05. Tasks

- [예제] 아래 조건의 Task들을 구현해보기
 - Task1: 높은 우선순위, 실행 시간 5초
 - Task2: 낮은 우선순위, 실행 시간 5초



06. Task Activation

```
ISR2(TimerISR)
{
    static long c = -4;
    osEE_tc_stm_set_sr0_next_match(1000000U);
    if (c == 0)
        ActivateTask(Task1);
    printfSerial("\n%4ld: ", c++);
}
```

```
TASK(Task1)
{
    printfSerial("Task1 Begins...");
    mdelay(3000);
    ActivateTask(Task2);
    mdelay(3000);
    printfSerial("Task1 Finishes...");
    TerminateTask();
}
```

```
TASK(Task2)
{
    printfSerial("Task2 Begins...");
    mdelay(3000);
    printfSerial("Task2 Finishes...");
    TerminateTask();
}
```

```
TASK Task1 {
    ...
    AUTOSTART = FALSE;
    ...
};
```

```
TASK Task2 {
    ...
    AUTOSTART = FALSE;
    ...
};
```

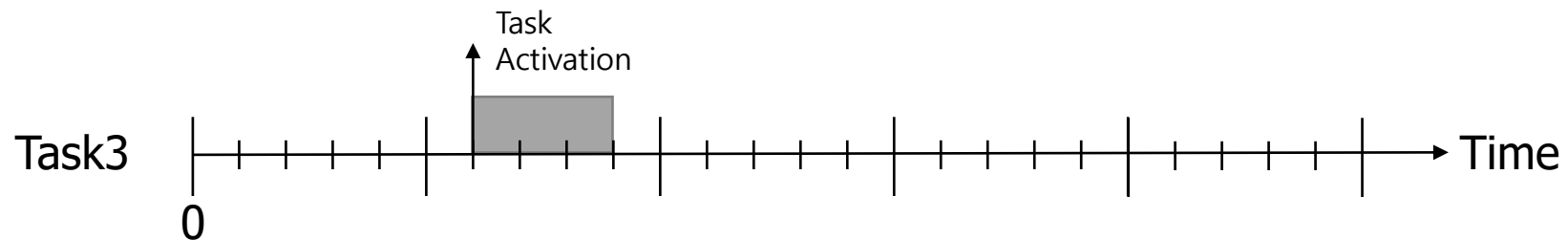
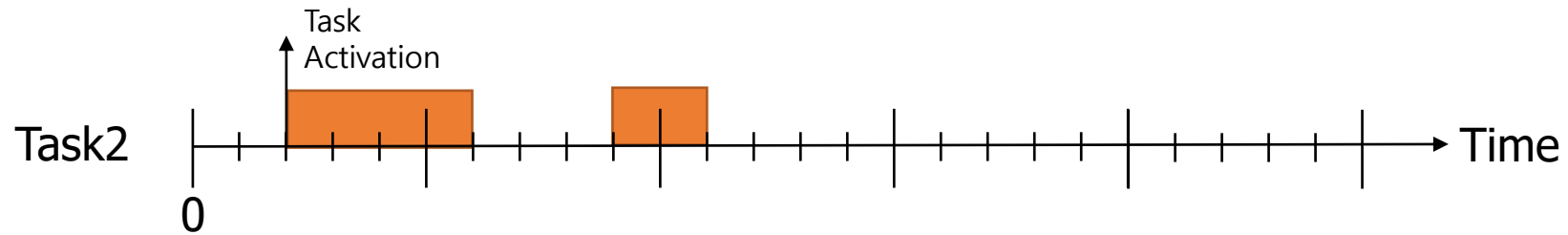
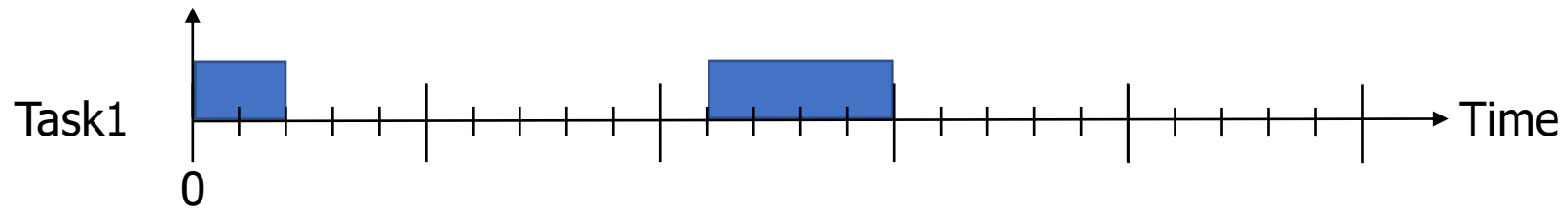
06. Task Activation

- Timeline -4부터 카운트다운
- Task2의 Task1 선점 확인

```
-4:
-3:
-2:
-1:
 0: Task1 Begins...
 1:
 2:
 3: Task2 Begins...
 4:
 5:
 6: Task2 Finishes...
 7:
 8:
 9: Task1 Finishes...
10:
11: □
```

06. Task Activation

- [예제] ActivateTask 시점 변경 및 Task3까지 만들어서 연쇄 실행
- 아래 그림의 Task 구현해보기



07. GetTaskID

```
TASK(Task1)
{
    TaskType id;
    printfSerial("Task1 Begins...");
    mdelay(3000);
    ActivateTask(Task2);
    mdelay(3000);
    GetTaskID(&id);
    printfSerial("Task ID = %d...", id);
    printfSerial("Task1 Finishes...");
    TerminateTask();
}
```

```
TASK(Task2)
{
    TaskType id;
    printfSerial("Task2 Begins...");
    mdelay(3000);
    GetTaskID(&id);
    printfSerial("Task ID = %d...", id);
    printfSerial("Task2 Finishes...");
    TerminateTask();
}
```

07. GetTaskID

- 자연수 Task ID 확인
- Unique ID일 뿐 정의된 의미 없음

```
-4:
-3:
-2:
-1:
0: Task1 Begins...
1:
2:
3: Task2 Begins...
4:
5:
6: Task ID = 3...Task2 Finishes...
7:
8:
9: Task ID = 2...Task1 Finishes...
10:
11: []
```

Task2의
ID

Task1의
ID

08. GetTaskState

```
TASK(TaskM)
{
    printState(Task1);
    printState(Task2);

    TerminateTask();
}
```

```
TASK TaskM {
    PRIORITY = 3;
    STACK = SHARED;
    SCHEDULE = FULL;
    AUTOSTART = FALSE;
    ACTIVATION = 1;
};
```

```
void printState(TaskType id) {
    TaskStateType state;

    if (GetTaskState(id, &state) == E_OK) {
        switch (state) {
            case SUSPENDED:
                printfSerial("%d: suspended...", id);
                break;
            case READY:
                printfSerial("%d: ready...", id);
                break;
            case WAITING:
                printfSerial("%d: waiting...", id);
                break;
            case RUNNING:
                printfSerial("%d: running...", id);
                break;
        }
    }
}
```

08. GetTaskState

```
TASK(Task1)
{
    TaskType id;
    printfSerial("Task1 Begins...");
    printState(Task1);
    printState(Task2);
    mdelay(3000);
    ActivateTask(Task2);
    printState(Task1);
    printState(Task2);
    mdelay(3000);
    GetTaskID(&id);
    printfSerial("Task ID = %d...", id);
    printfSerial("Task1 Finishes...");
    ChainTask(TaskM);
}
```

```
TASK(Task2)
{
    TaskType id;
    printfSerial("Task2 Begins...");
    printState(Task1);
    printState(Task2);
    mdelay(3000);
    GetTaskID(&id);
    printfSerial("Task ID = %d...", id);
    printfSerial("Task2 Finishes...");
    ChainTask(TaskM);
}
```

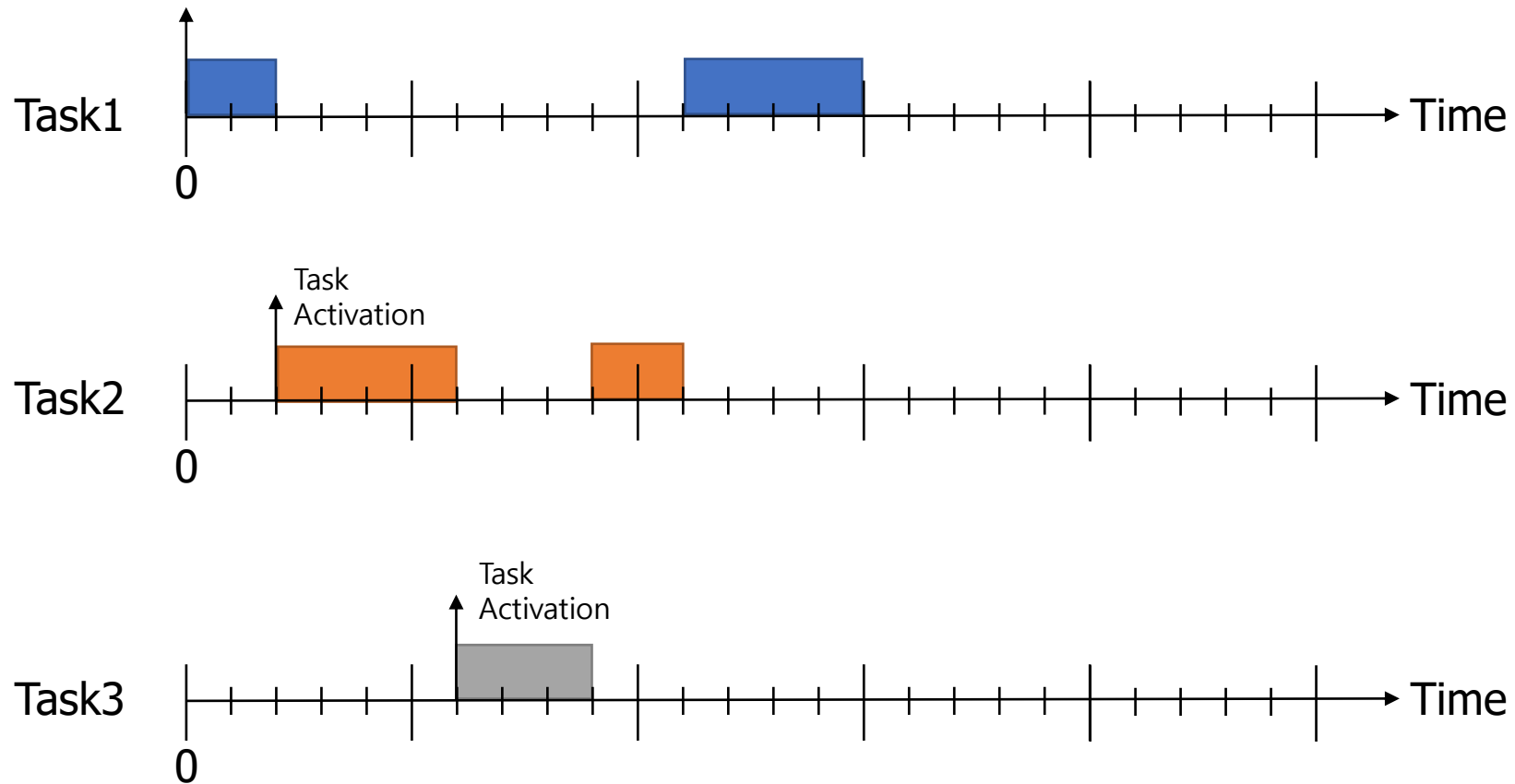
08. GetTaskState

- Task 상태 변화 관찰
- 우선순위, Activation 패턴 변화의 영향은?

```
-1:
0: Task1 Begins...2: running...4: suspended...
1:
2:
3: Task2 Begins...2: ready...4: running...
4:
5:
6: Task ID = 4...Task2 Finishes...2: ready...4: suspended...2: running...4: suspend
ed...
7:
8:
9: Task ID = 2...Task1 Finishes...2: suspended...4: suspended...
10:
11:
12:
13:
14: □
```

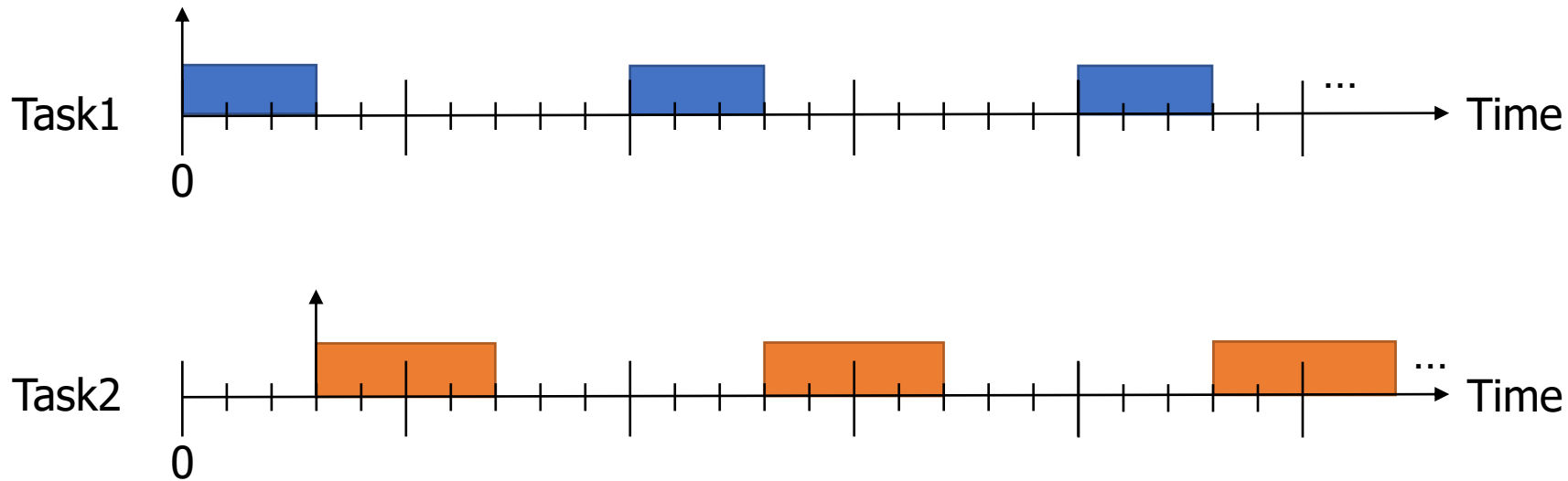
08. GetTaskState

- [예제] 06.Task Activation 2번째 실습에서 구현한 Task들 상태 변화 관찰



[예제] Tasks

- 아래 조건의 Task들을 구현해보기
 - Task1: 높은 우선순위, 실행 시간 3초
 - Task2: 낮은 우선순위, 실행 시간 4초
 - AUTOSTART = False로 수정하고 동일하게 구현
 - 10초마다 반복



Questions

