First name, Last name:

Lab2 Real-Time Operating Systems for sensors and actuators

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You will have to answer on the statement to questions R1, R2, ... You will have to write, test and provide the codes C1, C2, ...

Follow installation procedure (Appendix 1) to install Zpehyr.

The objective of this lab is to implement the behavior of the previous lab but using the RTOS Zephyr.

Documentation about Zephyr 3.5.0 is available at https://docs.zephyrproject.org/3.5.0/.

1) Create Tasks

R1. Recall the parameters of the Zephyr tasks creation macro k_thread_define(). What is the difference between k thread define() and k thread create()?

Name	Description	Туре	
	-		

2) Communication and synchronisation services

R2. Cite the different services under Zephyr.

Service	Communication or Synchronisation		

3) A first code with the RTOS

C1. Adapt the code of the template to create a communication between 2 tasks, the first one sends the value of a counter then waits for a certain delay D1, the second one shows the received value on the 7-segment displays then waits for another delay D2.

R3. Explain your choice of communication service.

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C2. Take the code from the 1st lab (reflex test) and convert it to Zephyr multitasking code.
To do so, you must first:

- Identify the necessary tasks (3 minimum).
- Set priorities
- Define the necessary IPC services
- Use the k uptime get() function to read time instead of HAL GetTick().

R4. Draw the Diagram of communications between tasks and ISR,	naming the tasks	according to
their priority (T1, T2, T12).		

Test the code

4) Monitoring the execution

C3. Add a thread analyzer to your application in order to collect runtime statistics.

R5. Note the information obtained with the measurement task.

Task	Total CPU cycles	CPU %	Free stack	Used stack

R6. Find the ROM and RAM usage with the help of the rom_report and ram_report build targets. What can be optimized in order to reduce the memory footprint?