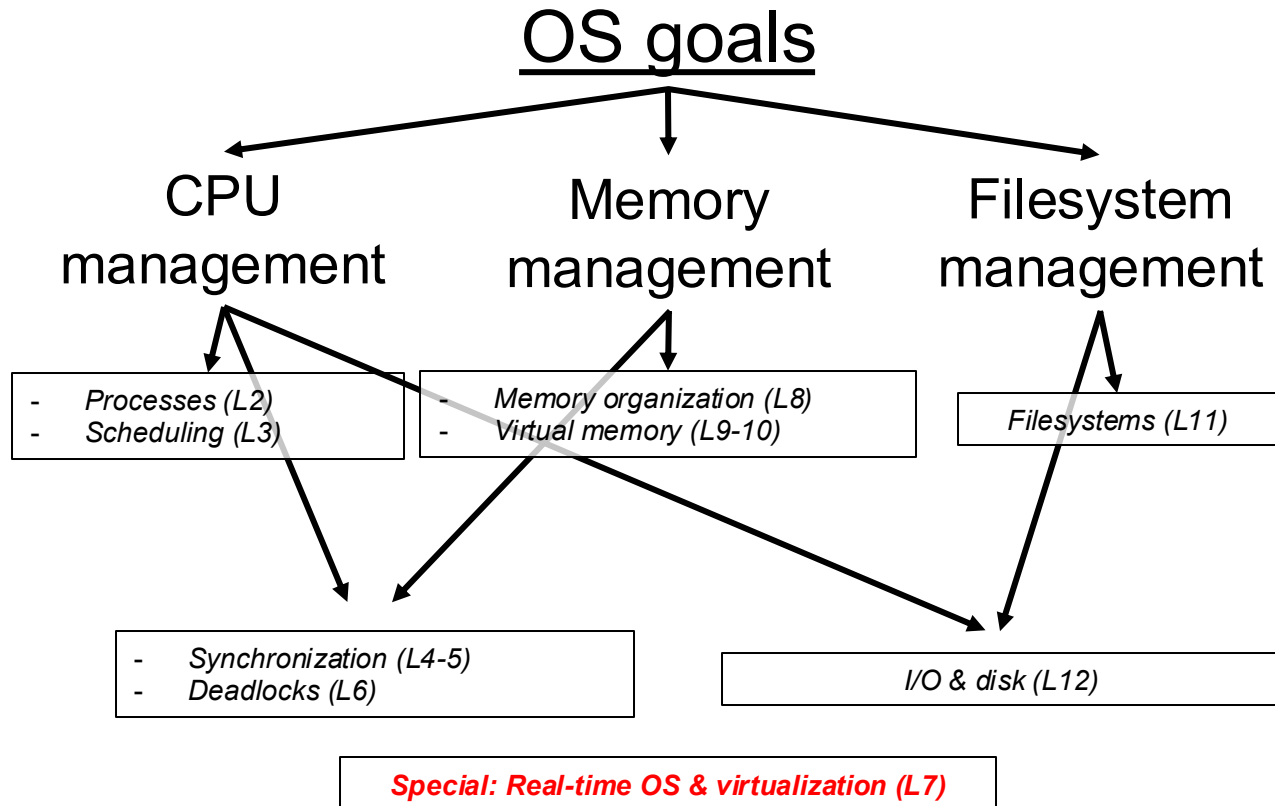


Course Overview



Part 6: Real-Time OS & Virtualization

- **What is a Real-Time OS (RTOS)?**
- Real-Time Process Specification
- Real-Time CPU Scheduling
- Virtualization

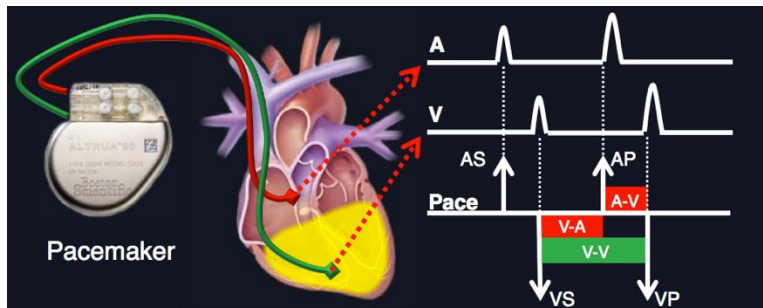
Cyber-Physical Systems

- Physical/Engineered systems whose operations are monitored, coordinated and controlled by a reliable computing and communication core
 - Automotive Systems (Autonomous driving, Parking assist, Airbag controls)
 - Avionics (Flight navigation & control)
 - Manufacturing Systems (Robotics, Process controls)
 - Medical Systems (Robotic surgery, devices)
 - ...

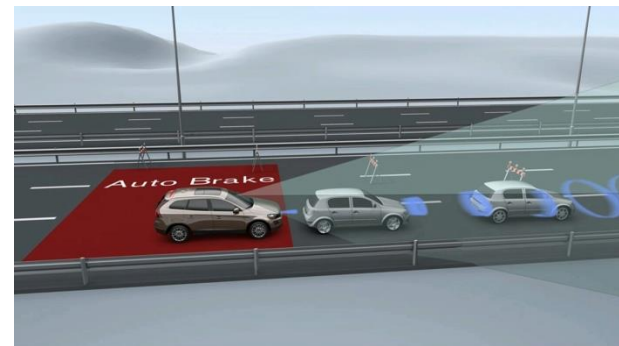
Relevance of Real-Time

- Common to many application examples we saw in the previous slide:
 - **Collect data** from various sensing devices
 - **Execute control law(s)** to determine response
 - **Send actuator commands** in a **reasonable amount of time**

Pacemaker timing diagram



Collision avoidance and braking



Collision Warning with Auto Brake

What is a Reasonable Time?

- What is the functionality?
 - Collision avoidance in automotive (milliseconds)
 - Pacemaker (up to a second)
 - Robotic surgery (varies greatly depending on the target)
- What are the environment constraints?
 - Available computing and communication resources
 - Timing characteristics of sensors/actuators/operations
- Failure-mitigation strategies?
 - Time to detect and recover from failures
 - Example: execution replication for redundancy

Common Misconception

- Real-Time \neq Fast
- Real-Time = Predictable even in the worst-case



“Man drowned in a river with average depth 20 cms”

Check Your Understanding



Real-Time CPS / Real-Time OS

- **Definition:** System whose correctness depends not only on the **logical/functional aspects**, but also on the **temporal aspects**
 - Application has deadlines that must be met
 - **A real-time OS (RTOS) provides OS services to such systems (e.g., FreeRTOS, MicriumOS, ...)**
- **Key performance measure for RTOS**
 - Timeliness/Predictability on timing constraints (**deadlines**)
 - Significance of **worst-case** over average-case
 - Deadlines are a function of application requirements

Check Your Understanding

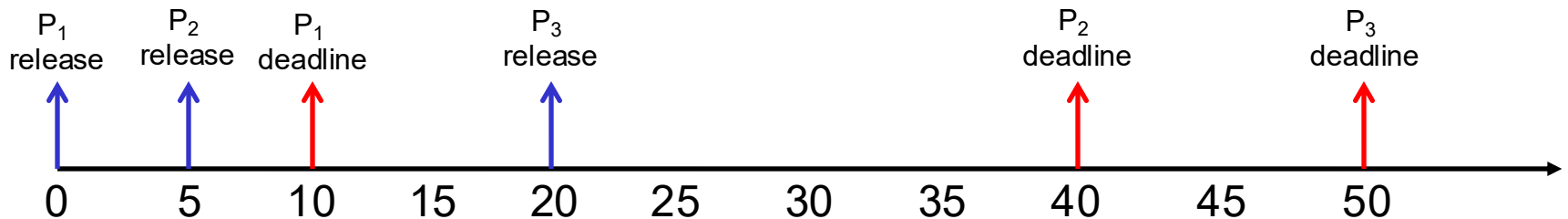


Part 5: Real-Time OS & Virtualization

- What is a Real-Time OS (RTOS)?
- **Real-Time Process Specification**
- Real-Time CPU Scheduling
- Virtualization

RTOS (Real-Time) Process

- **Definition:** A real-time process is specified as $\langle R, C, D \rangle$, where R is process release time, C is execution requirement and D is relative deadline
 - Requires C time units of CPU in the interval $[R, R+D)$
 - How does one determine these parameters?
- Example: $P_1 \langle 0, 5, 10 \rangle$, $P_2 \langle 5, 10, 35 \rangle$, $P_3 \langle 20, 10, 30 \rangle$



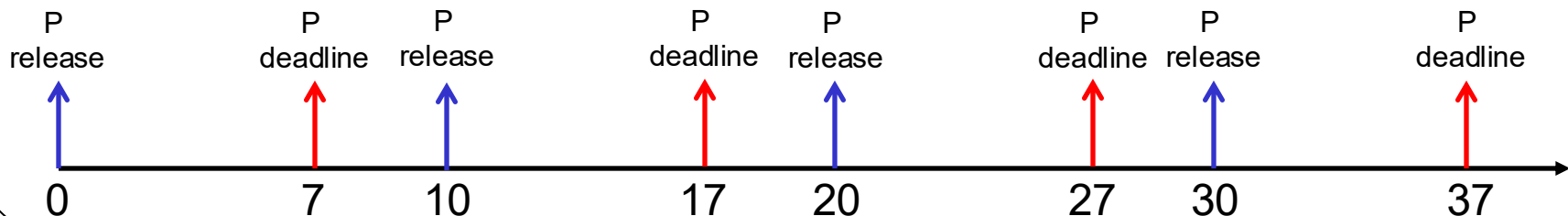
In this lecture, we assume processes only have a single CPU burst; C is the duration of this burst

Recurrent Real-Time Process

- **Nature of real-time processes**
 - Collect data from sensing devices, execute control laws to determine responses, and send actuator commands in reasonable time
 - **Repeat the above steps regularly**
 - Examples: airbag control, flight control, collision avoidance, pacemaker, etc.
- **A recurrent real-time process**
 - **Executes some function repeatedly over time**
 - Each instance of execution is a real-time process $\langle R, C, D \rangle$

Periodic Real-Time Process

- **Definition:** A process that **repeats periodically**
 - Processes generated by a **time-triggered phenomena** (sensor sending data periodically)
 - Example: Perception function for collision detection
- A periodic process is specified as $\langle T, C, D \rangle$, where T is process period, C & D are as defined earlier
 - Real-time processes are released at $R=0, T, 2T, \dots$
 - Example: Periodic process $P\langle 10, 5, 7 \rangle$



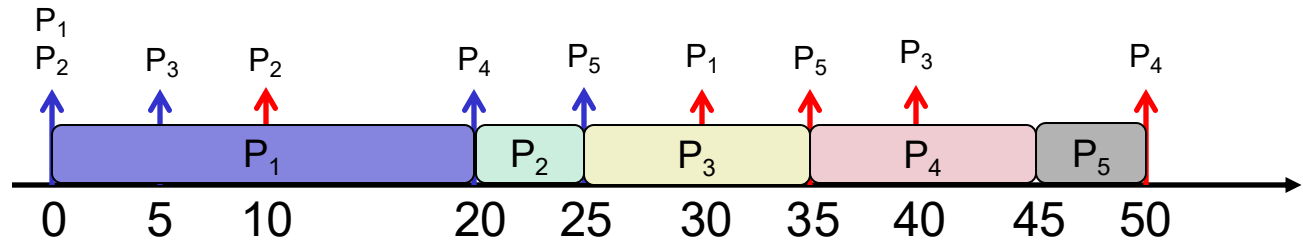
Part 5: Real-Time OS & Virtualization

- What is a Real-Time OS (RTOS)?
- Real-Time Process Specification
- **Real-Time CPU Scheduling (short-term scheduler)**
 - **Fixed-priority scheduling**
 - **Dynamic-priority scheduling**
- Virtualization

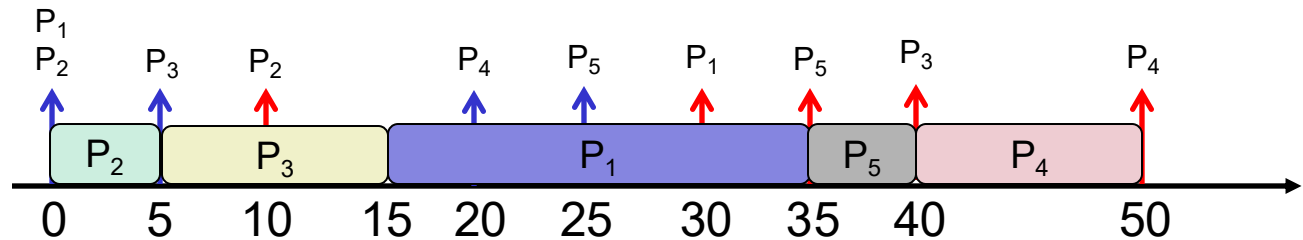
Why Classic Algorithms Fail?

- Consider real-time processes (non-recurring): $P_1<0,20,30>$, $P_2<0,5,10>$, $P_3<5,10,35>$, $P_4<20,10,30>$, $P_5<25,5,10>$

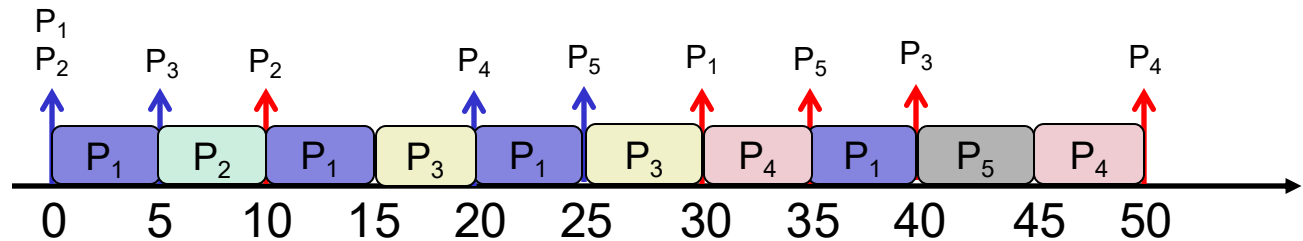
FCFS schedule



SJF schedule



RR(q=5) schedule

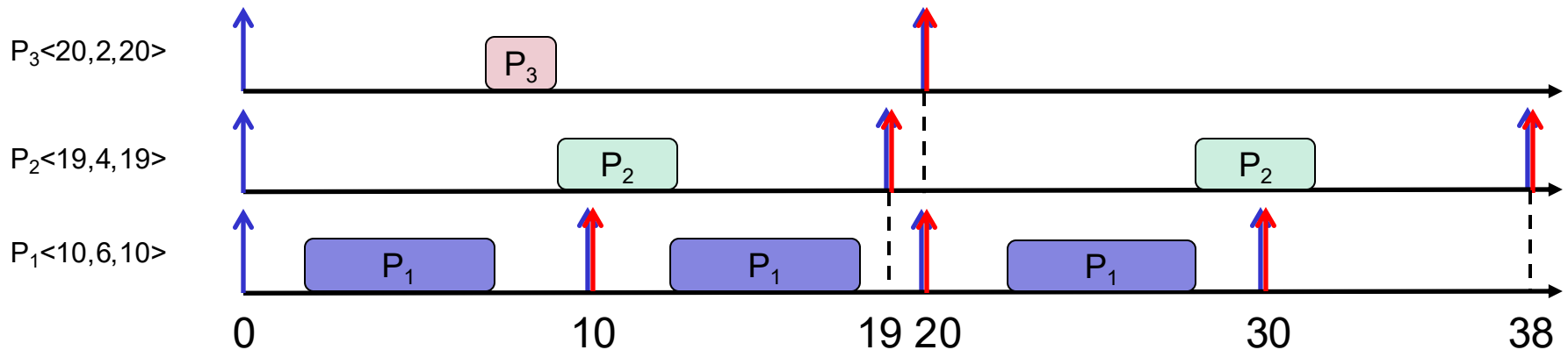


They don't prioritize deadlines and hence perform poorly

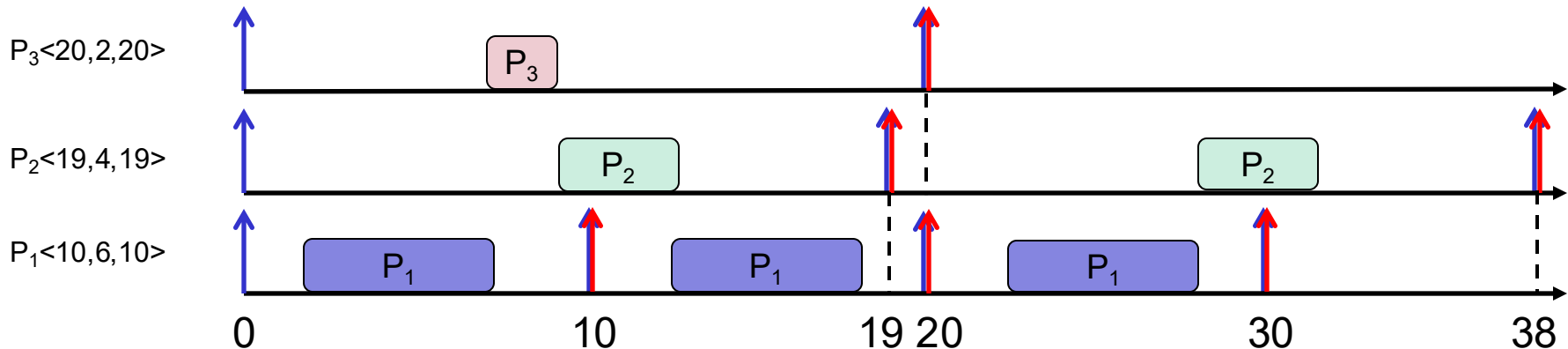
Real-Time CPU Scheduling Problem

Given a set of periodic/sporadic real-time processes, find a uni-processor CPU scheduling algorithm that can meet process deadlines

- We will use a running example (periodic real-time process set): $P_1<10,6,10>$, $P_2<19,4,19>$, $P_3<20,2,20>$



Fixed-Priority CPU Scheduling

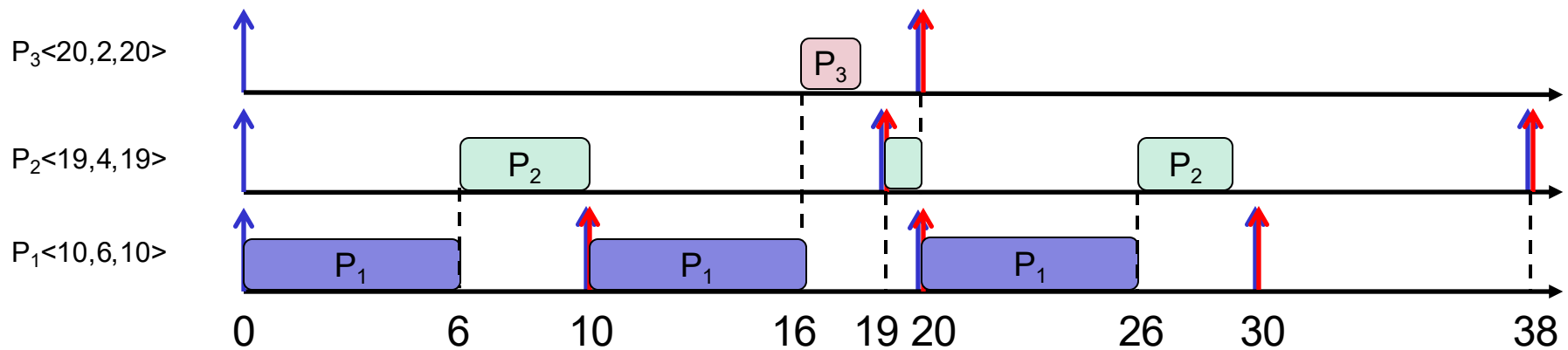


Priorities are fixed for each recurrent process

- **Priorities are fixed across instances of recurrent processes**
- Suppose instance of $P_1(R=0)$ has higher priority than instance of $P_2(R=0)$. Then,
 - $P_1(R=10)$ has higher priority than $P_2(R=0)$
 - $P_1(R=10)$ has higher priority than $P_2(R=19)$
 - $P_1(R=20)$ has higher priority than $P_2(R=19)$...

Rate Monotonic (RM) Scheduler

- Assign priorities based on process periods / minimum release-separation time (T)
 - Shorter T implies higher priority
 - Ties are broken arbitrarily



RM is a very popular short-term CPU scheduler in the real-time CPS industry. Why?

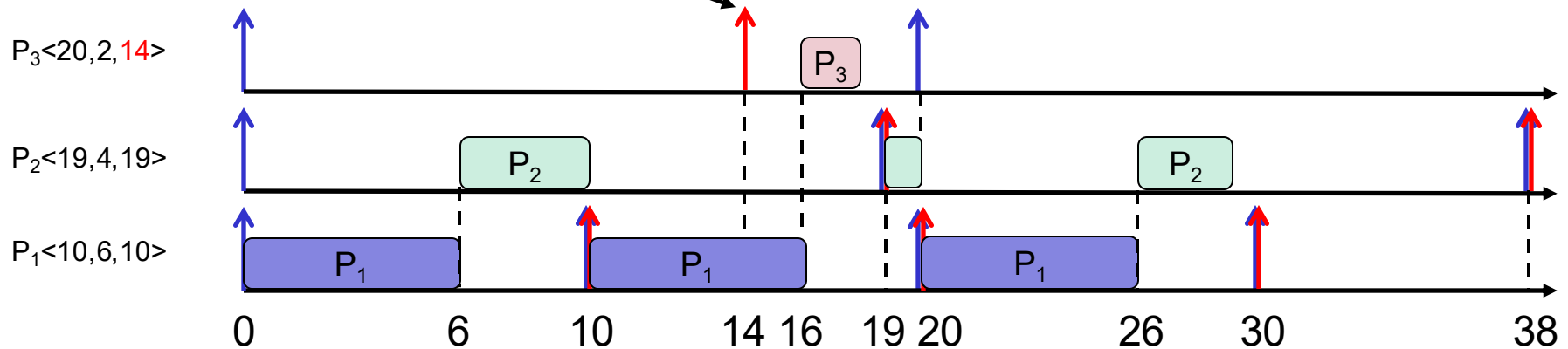
RM and Process Deadlines

- RM is good, but still does not always prioritize urgent processes

– Suppose we modify the process set as follows:

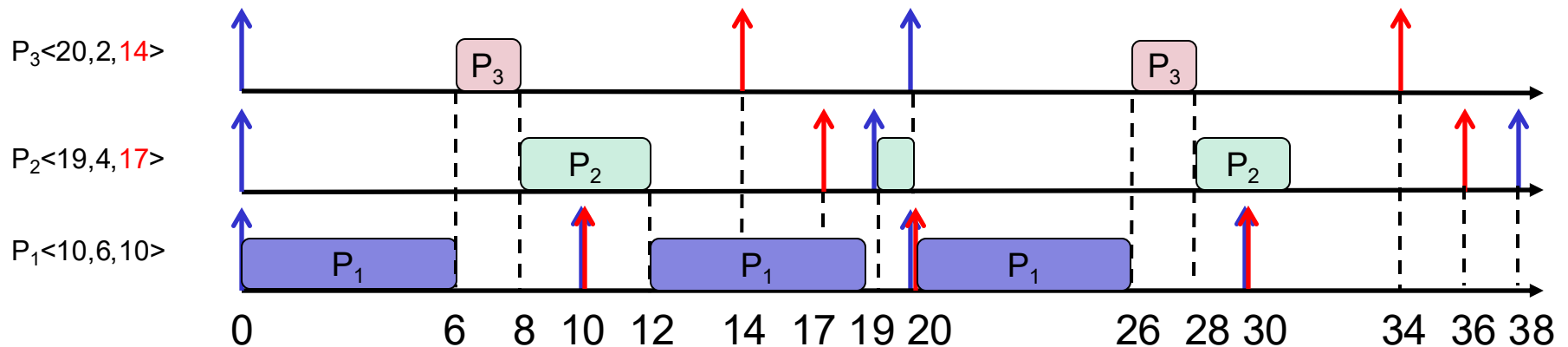
$P_1 < 10, 6, 10 >$, $P_2 < 19, 4, 19 >$, $P_3 < 20, 2, 14 >$

Deadline Miss



Earliest Deadline First (EDF) Scheduler

- Dynamic-priority scheduler that assigns priorities based on process **instance deadlines**
 - Instances with shorter deadline are given higher priority
 - **NOT the same as parameter D**
 - Ties are broken arbitrarily



EDF is a dynamic-priority scheduler, hence more powerful than RM

Check Your Understanding



RM/DM versus EDF

RM

- **Simpler implementation**
(separate queue for each recurrent process)
- **Predictability for high priority processes, even under high load**

EDF

- **Harder implementation**
(online sorting of queue based on instance deadlines)
- **Can be unpredictable under high load**

Part 5: Real-Time OS & Virtualization

- What is a Real-Time OS (RTOS)?
- Real-Time Process Specification
- Real-Time CPU Scheduling
- **Virtualization**