**Introduction**

SquadRTOS is a real-time operating system designed to provide a reliable and efficient platform for embedded systems. It is specifically tailored for small to medium-sized embedded systems, and its highly customizable architecture can be adapted to meet the specific needs of each project.

One of the key features of SquadRTOS is its preemptive multithreading kernel, which allows multiple tasks to run concurrently while ensuring that critical tasks are given priority over non-critical tasks. This makes it an ideal choice for applications that require precise timing and responsiveness, such as robotics, control systems, and automotive electronics.

Another advantage of SquadRTOS is its comprehensive set of libraries, drivers, and tools that simplify the development process. This helps to reduce development time and costs, while improving the quality and reliability of the final product.

Overall, SquadRTOS is a powerful and flexible real-time operating system that provides an efficient and reliable platform for embedded systems. Its customizable architecture, real-time capabilities, and development tools make it an ideal choice for a wide range of applications in various industries, including aerospace, medical devices, and industrial automation. With its proven track record of success, SquadRTOS is a trusted and reliable choice for developers looking to build high-performance embedded systems.

**Defining RTOS**

RTOS stands for real-time operating system, which is a specialized operating system that is designed to provide a reliable and predictable platform for embedded systems that require precise timing and responsiveness.

Unlike general-purpose operating systems, which are designed to provide a wide range of features and functionality, RTOS is designed to prioritize real-time performance and ensure that critical tasks are given priority over non-critical tasks. This is achieved through features such as preemptive multitasking, task scheduling, and interrupt handling.

RTOS is commonly used in applications such as robotics, control systems, and automotive electronics, where precise timing and responsiveness are critical for the proper functioning of the system. It provides a highly customizable and efficient platform for developing embedded systems, with features such as low-level hardware access, optimized algorithms, and comprehensive libraries and tools.

Overall, RTOS is a powerful and specialized operating system that provides a reliable and predictable platform for embedded systems that require real-time performance.

**Hard real-time systems and Soft real-time systems**

Hard real-time systems and soft real-time systems are two categories of real-time systems that are differentiated by their degree of tolerance for missed deadlines.

Hard real-time systems are designed to be extremely time-sensitive and must meet strict timing constraints. Failure to meet these constraints can result in catastrophic consequences, such as system failure or loss of life. Examples of hard real-time systems include aerospace control systems, medical devices, and automotive safety systems. In hard real-time systems, missing a deadline can result in system failure, making it critical to ensure that all tasks are completed within the specified time limit.

Soft real-time systems, on the other hand, have less strict timing constraints, and missing a deadline may not have catastrophic consequences. Examples of soft real-time systems include multimedia applications, such as video and audio streaming, where occasional delays may be acceptable, but consistent delays can result in a degraded user experience.

Overall, the distinction between hard real-time systems and soft real-time systems is based on the degree of tolerance for missed deadlines, with hard real-time systems requiring strict adherence to timing constraints, while soft real-time systems can tolerate occasional delays.

**Tasks Definition:**

In an SquadRTOS (Real-Time Operating System), a task refers to a unit of execution that can run independently and concurrently with other tasks. A task is essentially a piece of code that can perform a specific function, such as reading data from a sensor, processing a set of instructions, or generating an output signal.

Tasks are created by the application and managed by the SquadRTOS kernel. Each task has its own stack and execution context, and can be scheduled to run at a specific time or in response to an event or interrupt. Tasks can communicate with each other through message passing, semaphores, or other synchronization mechanisms.

One of the key benefits of using tasks in an SquadRTOS is that they allow for efficient use of system resources by enabling concurrent execution of multiple tasks. This can help improve system responsiveness and reduce latency in real-time applications.

Tasks in an SquadRTOS can have different priorities, which determine their order of execution. Tasks with higher priorities are executed first, and lower priority tasks are executed only when higher priority tasks are blocked or suspended.

Overall, tasks are a fundamental concept in SquadRTOS programming, and understanding how to create, manage, and schedule tasks is essential for developing efficient and responsive real-time applications.

**Super loop :**

a super loop is a simple programming structure that can be used to create tasks and manage their execution. A super loop consists of an infinite loop that repeatedly executes a sequence of tasks, each of which performs a specific function.

To implement tasks with a super loop, you can define each task as a separate function, and then call these functions from within the super loop. Each task can be executed sequentially, one after the other, or concurrently, by using interrupts or other synchronization mechanisms.

Here's a simple example of how to create tasks with a super loop:

void task1(void) {

// Code for task 1

}

void task2(void) {

// Code for task 2

}

void main(void) {

while (1) {

task1(); // Execute task 1

task2(); // Execute task 2

}

}

In this example, we have defined two tasks, `task1()` and `task2()`, which are called sequentially from within the super loop in the `main()` function. Each task can perform a specific function, such as reading data from a sensor, processing a set of instructions, or generating an output signal.

Note that in this example, the tasks are executed sequentially, which means that `task2()` will not be executed until `task1()` has completed. If you want to execute tasks concurrently, you can use interrupts or other synchronization mechanisms to ensure that each task is executed at the appropriate time.

The super loop structure is a simple and flexible way to create tasks in an embedded system, and can be easily adapted to suit a variety of applications. However, it may not be suitable for more complex systems that require advanced scheduling or synchronization mechanisms. In such cases, an SquadRTOS may be a better option for managing tasks and ensuring system responsiveness.

Sure, I'd be happy to discuss the advantages and disadvantages of using a super loop in an embedded system.

Advantages of a Super Loop:

1. Simplicity: A super loop structure is easy to understand and implement, making it a popular choice for small and simple embedded systems.

2. Efficiency: A super loop can be very efficient, as it avoids the overhead of task switching and context switching that is required in more complex scheduling mechanisms.

3. Flexibility: The structure of a super loop is flexible, allowing the programmer to easily add, remove or modify tasks as needed.

Disadvantages of a Super Loop:

1. Limited concurrency: A super loop structure can only execute one task at a time, which can limit the concurrency and responsiveness of the system.

2. Lack of priority: A super loop does not provide a mechanism for task prioritization, which can be important in systems that require real-time performance.

3. Difficulty in managing timing: A super loop structure can make it difficult to manage the timing of tasks, especially if the tasks have different execution times or require precise timing.

4. Lack of synchronization: A super loop structure does not provide a mechanism for task synchronization, which can be important in systems that require coordination between tasks.

Overall, the choice of whether to use a super loop structure in an embedded system depends on the specific requirements and constraints of the system. While a super loop can be simple and efficient, it may not be suitable for more complex systems that require advanced scheduling or synchronization mechanisms. In such cases, an RTOS or other more advanced scheduling mechanism may be a better option.

Basic Super Loop

Task1

Task2

**Using interrupts :**

Programming using interrupts is a technique commonly used in embedded systems to handle events and tasks in a timely and efficient manner. Interrupts are signals that are generated by hardware or software events and cause the processor to temporarily suspend the current task and execute a specific interrupt service routine (ISR) that handles the event.

To program using interrupts, the programmer needs to define the ISR for each event and register it with the system. When the event occurs, the processor interrupts the current task, saves its context, and executes the ISR to handle the event. Once the ISR is completed, the processor restores the context of the interrupted task and resumes its execution.

Programming using interrupts has several advantages over other techniques, such as the super loop. Interrupts provide faster response times and more efficient use of system resources, as the processor can perform other tasks while waiting for an event to occur. Interrupts also allow the system to handle multiple events simultaneously, making it more scalable and adaptable to a wider range of applications.

However, programming using interrupts also requires a higher level of expertise and attention to detail, as the programmer must ensure that the ISR is properly designed, tested, and integrated into the system. Improperly designed or poorly implemented ISRs can lead to performance issues, system crashes, or other unexpected behaviors.

Advantages:  
  
**Faster response times**: Interrupts provide faster response times to events than other programming techniques, such as the super loop. This is because the processor can immediately suspend the current task and execute the interrupt service routine (ISR) to handle the event, without having to wait for the next iteration of the main loop.  
  
**Efficient use of resources**: Interrupts allow the processor to perform other tasks while waiting for an event to occur, which makes better use of system resources and reduces the overall processing time.  
  
**Scalability**: Interrupts can handle multiple events simultaneously, making them more scalable and adaptable to a wider range of applications.  
  
**Deterministic behavior**: Interrupts provide deterministic behavior, which means that the response time of the system can be accurately predicted and controlled.  
  
Disadvantages:  
  
**Complexity**: Programming using interrupts is more complex than other programming techniques, such as the super loop. This is because the programmer must design, test, and integrate the ISR into the system, which requires a higher level of expertise and attention to detail.  
  
**Debugging**: Interrupt-driven programming can be difficult to debug since the execution order of the tasks is not determined by the programmer. This can make it harder to isolate and fix bugs in the code.  
  
**Overhead latency**: Interrupts have an overhead latency, which is the additional time taken to perform tasks that are not directly related to their main code execution, such as context switching and interrupt handling. This overhead latency can impact the overall performance and responsiveness of the system.  
  
**Unpredictability**: The execution order of the tasks is determined by the events that trigger the interrupts, which can make the behavior of the system harder to predict and control. This can lead to unexpected or undesirable behaviors in the system.

Diagram

Description automatically generated

**Making system using super loop and interrupts :**

to achieve concurrent execution of tasks, you can also use interrupts to trigger the execution of specific tasks in response to external events or input signals.

To implement tasks with a super loop and interrupts, you can define each task as a separate function, and then register these functions as interrupt service routines (ISRs) for the corresponding interrupt sources. When an interrupt occurs, the ISR is automatically executed, allowing the associated task to be performed in a timely and efficient manner.

Here's a simple example of how to create tasks with a super loop and interrupts:

void task1(void) {

// Code for task 1

}

void task2(void) {

// Code for task 2

}

void isr1(void) {

// Call task 1

task1();

}

void isr2(void) {

// Call task 2

task2();

}

void main(void) {

// Register ISR 1 for interrupt source 1

register\_isr(isr1, INTERRUPT\_SOURCE\_1);

// Register ISR 2 for interrupt source 2

register\_isr(isr2, INTERRUPT\_SOURCE\_2);

// Enable interrupts

enable\_interrupts();

while (1) {

// Super loop

}

}

In this example, we have defined two tasks, task1() and task2(), and two ISRs, isr1() and isr2(), which are registered for the corresponding interrupt sources. When an interrupt occurs, the associated ISR is automatically executed, allowing the corresponding task to be performed.

Note that in this example, the super loop is empty, because the tasks are executed in response to interrupts. The super loop may still be used to perform other tasks that do not require interrupt-driven execution.

The combination of a super loop and interrupts provides a simple and efficient way to create tasks in an embedded system that require concurrent execution. However, it may not be suitable for more complex systems that require advanced scheduling or synchronization mechanisms. In such cases, an SquadRTOS may be a better option for managing tasks and ensuring system responsiveness.

Advantage:

Interrupts allow for a more complex programming model, which can handle a greater number of events and tasks, without overloading the processor. This can lead to more efficient and responsive systems, especially in larger and more complex embedded systems.

Disadvantage:

However, the increased complexity of interrupt-driven programming can also make it more difficult to debug and maintain the code. This is because the execution order of the tasks is determined by the events that trigger the interrupts, which can be unpredictable and harder to understand than the deterministic execution order of the super loop.

On the other hand, the super loop provides a simpler programming model that is easier to understand and maintain, especially for small and less complex systems. However, this simplicity comes at the cost of reduced efficiency and scalability, which can limit the performance and responsiveness of the system as it grows in complexity.

Diagram

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**why are we made Real-Time Operating system (SquadRTOS vs Super loop and Interrupts )?**

In the context of embedded systems development with SquadRTOS, real-time operating systems (RTOS) offer several advantages over super loops and interrupts. RTOS provides a preemptive multitasking kernel, allowing multiple tasks to run concurrently while ensuring that critical tasks are given priority over non-critical tasks. This makes it ideal for applications that require precise timing and responsiveness.

Super loops, on the other hand, can be simple to implement but may not be able to handle complex systems with multiple tasks. Interrupts can be used to handle events but may result in high system overhead and increased complexity.

SquadRTOS provides a highly efficient and reliable real-time operating system that offers minimal system overhead and simplified development. This includes features such as optimized algorithms, low-level hardware access, and full control over system resources.

The main differences between tasks in SquadRTOS and super loops and interrupts are as follows:

1. Private Stack (Tasks isolated ): Each task is assigned its own private stack, which is not shared with any other task in the system. This allows each task to have its own call stack without interfering with the execution of other tasks, unlike a super loop which shares the system stack.

2. Priority Assigned: Each task is assigned a priority, which enables the scheduler to make decisions on which task should be running at any given time. The goal is to ensure that the highest priority task in the system is always doing useful work.

Advantages :

Memory protection: Each task's private stack is protected from other tasks in the system, preventing memory corruption and other errors that can occur when multiple tasks share the same stack.

Improved robustness: By having its own stack, each task is less likely to be affected by stack overflows or other stack-related errors that can occur when multiple tasks share the same stack.

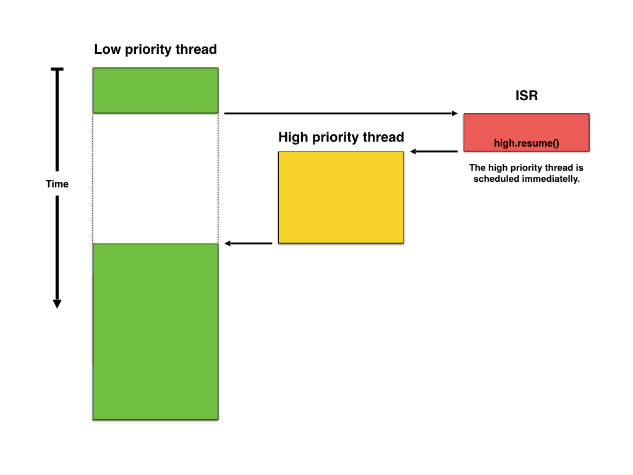
Better context switching: Context switching between tasks is faster and more efficient when each task has its own stack. This is because the processor does not have to save and restore the entire stack for each task switch, but only the necessary parts of the stack for the current task.

Improved debugging: Debugging is easier when each task has its own stack, as it is easier to isolate and identify errors that occur within a specific task.

Overall, while super loops and interrupts can be useful for simple systems, SquadRTOS provides a more reliable and efficient platform for larger and more complex systems that require precise timing and responsiveness.

Super loop Tasks with priorities if task have Priority higher than current thread it will work

Chart, waterfall chart

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Chapter one (Kernal)

**Schedular definition:**

the scheduler is a component that manages the allocation of system resources, such as CPU time, memory, and I/O devices, to different tasks or threads with real-time requirements.

**Schedular responsibility:**

The scheduler is responsible for ensuring that tasks or threads are executed in a timely and predictable manner, according to their criticality and deadline requirements.

**SquadRTOS Schedular overview:**

SquadRtos schedulers typically use scheduling policies and algorithms that prioritize tasks based on their criticality and deadline requirements. For example, tasks with hard real-time requirements, such as control tasks in a robotic system, may be given higher priority than tasks with soft real-time requirements, such as user interface tasks.

Real-time schedulers may also include features such as preemption, where a higher-priority task can interrupt a lower-priority task, and interrupt handling, where the scheduler can respond to hardware or software interrupts in a timely manner.

Real-time schedulers are critical components of real-time systems, where tasks or threads must be executed in a predictable and reliable manner, often with strict timing requirements. By managing the allocation of system resources and prioritizing tasks based on their criticality and deadline requirements, real-time schedulers can ensure that real-time systems meet their performance and reliability goals.

**Preemptive-based:**

Preemptive-based scheduling with round robin is a type of CPU scheduling algorithm that combines the features of both preemptive and round-robin scheduling.

Preemptive scheduling means that the operating system can interrupt a running process and switch to another process at any time, based on priority or other scheduling criteria. This allows higher-priority processes to execute before lower-priority processes, which can improve system responsiveness and reduce wait times.

Round-robin scheduling is a time-sharing algorithm that assigns a fixed time slice to each process in a circular queue. When the time slice expires, the current process is interrupted and moved to the back of the queue, and the next process is executed. This ensures that each process gets a fair share of the CPU time and prevents any single process from monopolizing the CPU.

In preemptive-based scheduling with round robin, the time slice assigned to each process is smaller than in pure round-robin scheduling, typically in the range of a few milliseconds. This allows the operating system to switch between processes more frequently, based on their priority or other scheduling criteria. If a higher-priority process becomes available, the operating system can preempt the current process and switch to the higher-priority process immediately, ensuring that critical tasks are completed as soon as possible.

Preemptive-based scheduling with round-robin is a versatile and effective algorithm that strikes a balance between the requirements of multiple processes and the timely execution of critical tasks.

advantages and disadvantages of both preemption round-robin scheduling:

Advantages:

Both preemption and round-robin scheduling can provide fair access to system resources among all tasks, preventing starvation.

They can both be efficient and effective in meeting the performance and timing requirements of different types of tasks.

They can both be combined with other scheduling techniques to create hybrid scheduling algorithms that take advantage of the strengths of multiple techniques.

Disadvantages:

Both preemption and round-robin scheduling can increase system overhead and complexity by adding scheduling and context-switching overhead.

They can both result in priority inversion and race conditions, which can lead to missed deadlines or system failure.

They may not be suitable for all types of systems or applications and may require careful consideration of the specific requirements of the system.

In summary, the selection of a scheduling technique, whether preemption or round-robin, should be based on the particular needs of the system or application. By thoughtfully weighing the pros and cons of each technique, and exploring the possibility of hybrid scheduling algorithms, the system can be optimized to achieve its performance and reliability objectives while minimizing unnecessary overhead and complexity.

**Dispatcher:**

A dispatcher in a real-time operating system (SquadRTOS) is responsible for selecting which task or thread should execute next, based on scheduling policies and algorithms. The dispatcher is a key component of the SquadRTOS kernel and plays a critical role in ensuring that real-time tasks are executed in a timely and predictable manner.

The dispatcher works in conjunction with the scheduler, which is responsible for managing the allocation of system resources, such as CPU time, memory, to different tasks or threads. The scheduler uses scheduling policies and algorithms to determine which task or thread should execute next, based on factors such as task priority, deadline, and available resources. The dispatcher then selects the next task or thread to execute, based on the scheduling decision made by the scheduler.

The dispatcher typically operates at a lower level than the scheduler ,and is responsible for performing context switches between tasks or threads. When the dispatcher selects a new task or thread to execute, it saves the context of the current task or thread and restores the context of the selected task or thread. Context switching involves saving and restoring the contents of CPU registers, program counter, stack pointer, and other state information, and can have a significant impact on system performance.

In a typical SquadRTOS, the dispatcher uses a priority-based scheduling algorithm, where tasks or threads with higher priority are executed first. The dispatcher may also use other scheduling policies, such as round-robin scheduling or earliest deadline first (EDF) scheduling, depending on the specific requirements of the system or application.

The dispatcher must be designed to respond to scheduling decisions in a timely and predictable manner, to ensure that real-time tasks are executed in a timely and reliable manner. The dispatcher must also be designed to handle interrupts and other asynchronous events, which can affect scheduling decisions and require immediate attention.

The dispatcher is a crucial part of real-time operating systems, and it is imperative to carefully design and implement it to guarantee the timely and predictable execution of real-time tasks. The dispatcher works in tandem with the scheduler and other components of the RTOS kernel to ensure that real-time systems fulfill their performance and reliability objectives.

Text

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