# Definitions

Resource Ceiling: Highest preemption level among all tasks that can use the shared resource (statically defined)  
System Ceiling: Largest resource ceiling among all currently locked shared resources (changes at runtime)

# Phase 2

1. System Ceiling– OS\_SYSTEM\_CEILING
   1. Stack used to store Resource Ceilings
   2. head->data->Resource\_Ceiling->Deadline;
      1. Find minimum deadline function
         1. Min deadline = highest preemption leve
   3. Pushing and popping mutex pointer
      1. Push --> pend
      2. Pop --> post
2. Resource Ceiling 🡪 highest preemption level among all task that can use shared resource
   1. T1 is the resource ceiling for all mutexes
   2. Periods: T1 = 3, T2 = 4, T3 = 5.
   3. Period implicitly the deadline also
   4. Store as TCB pointer
   5. Store inside mutex object
3. Mutex pend
   1. Update system ceiling
4. Mutex post
   1. Update system ceiling
   2. Unblock tasks from RB Tree that have higher preemption (lower deadline) than the newly changed system ceiling.
      1. If not we risk the blocked tasks never being able to run
5. OSSched
   1. If a task that is NOT the current task wants to pre-empt, need check   
      deadline from EDF < deadline (from system ceiling) 🡪 higher priority than system ceiling
      1. If fail check, remove task from ready list, add to RB tree. Run EDF scheduler again for new task to run; run the above check again.
   2. If task picked by EDF is current task, resume current task

To improve:

* Use event flags for synchronous release
* Use memget for memory management

# Flow of Events

1. OSRecTaskCreate() 🡪 push all recursive tasks into heap
2. Revive rec task 🡪 synchronous release of tasks into readylist
   1. Done by when tick counter = 5, iterate through heap then put in readylist
   2. We also insert them into avl tree
      1. Problem here as same deadline not inserted at all
   3. When OSSched called, readylist stuff will be used, then when task is called it will run rectaskdelete to delete the task and remove it from readylist
3. When time’s up according to tick counter when compared to heap[0] (always the lowest deadline)
   1. Initialize every p\_tcb thing
   2. Update its new deadline for future use
      1. Then we need to pop and push new details into heap
      2. Same for avl tree
         1. Problem here too!
      3. Insert into ready list
   3. When OSSched runs, will call accordingly
4. In OSSched, we have rbtree to handle blocked tasks which is blocked when it does not satisfy SRP requirements
   1. Depends on mutex holding
   2. Problem in OSSched because we will check avl tree accordingly
      1. But when the task to run is in readylist, but not here cos same deadline
         1. Problem!!!

Tried a method to increment deadline by 1, but problematic after task3 rectaskdel.