

Real Time Embedded System Assignment – 1

Real-time Tasks Models in Linux

Team - 12

Chinmay Bolumbu (ASU ID: 1213329869)

Rama Kumar Kana Sundara (ASU ID: 1213347614)

The Input file used is as follows:

4 1000

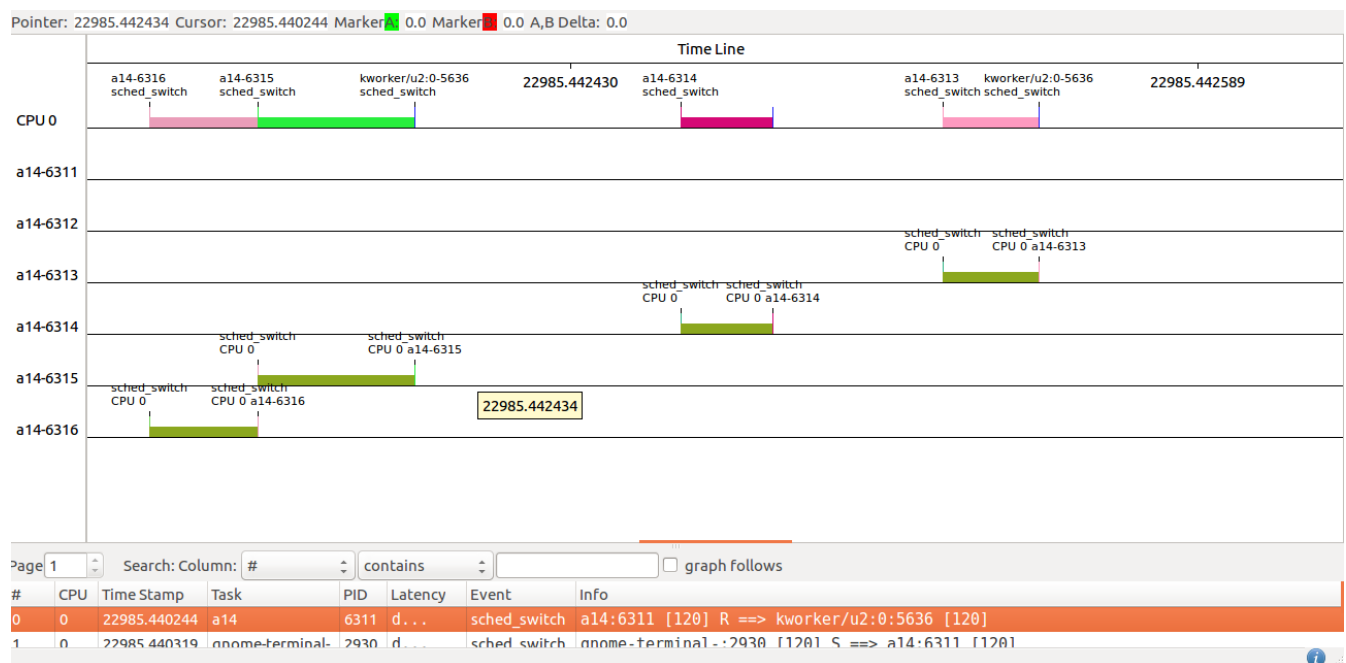
P 20 20 10 L1 1995000 U1 300

P 80 25 40 L1 200000 U1 100

P 40 30 20 L2 400000 U2 100

A 10 0 500

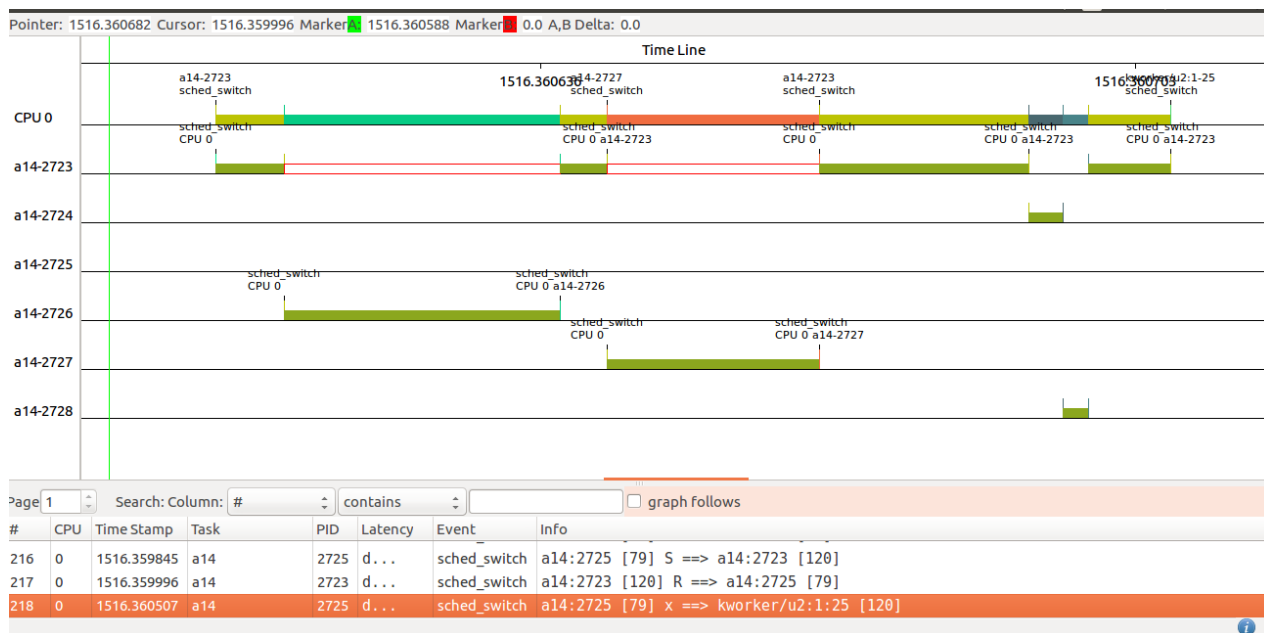
Scheduling of tasks are shown in kernelshark:



From the above image, pid-6316 with a priority of 80 has the highest priority out of the 4 processes. Hence it is scheduled immediately and is then followed by pid-6315 with priority as 40. Then comes pid-6314 with priority 20. With the least priority of 10 among the 4 processes pid-6313 is scheduled after all other higher priority processes.

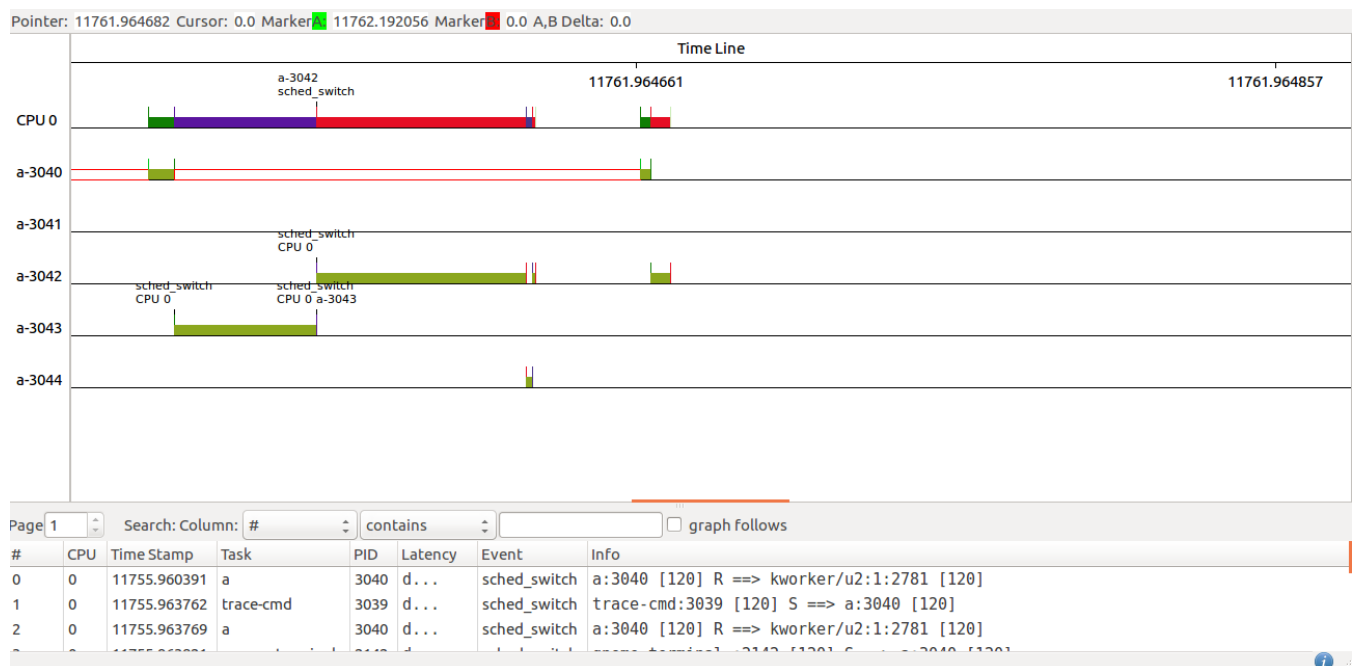
Task Over-run condition:

Following image shows Over-run condition where pid-2723 is requested to start but has not finished its previous execution yet. It is over-running due to pre-emption by pid-2726 and pid-2727.



Priority inversion:

Priority inversion scenario in scheduling can be seen in this image where a high priority task (pid-3040) is indirectly pre-empted by a lower priority task (pid-3043) effectively "inverting" the relative priorities of the two tasks.



Priority Inheritance:

Priority Inheritance is shown in this image where pid-7002 is holding L1. Pid-7003 tries to acquire the resource but cannot because of the lock. Thus, it gets blocked.

Pid-7004 with priority 40 tries to run but is pre-empted by pid-7002 which is at a temporary priority of 80. Here we see the priority getting inherited.

