CEOSmp

a whitebox RTOS for multicore embedded systems

GR740 User Day

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Embedded System Characteristics (1)

- Fixed Code Base Software not added during system life => can use physical addresses, RTOS doesn't need page tables etc.
- Code must be robust So an RTOS design should... => ensure certain failure modes are impossible
 - e.g. unbounded priority inversion, ...
 - => allow behaviour policing by the application (white box)
 - performance data recorded and checkable at any time
 - => automatically check for problems
 - e.g. stack overrun, missed deadlines...
 - => automatically trigger application problem handlers
 => provide calls to deal with problems
 - e.g. kill task, disable task, disable a CPU, ...







Embedded System Characteristics (2)

- But things can go wrong So an RTOS design must provide => Fault Anticipation, Detection, Isolation, Reporting, Recovery - make it easy for the application to police the system: min time between task start requests max execution times, deadline misses max pre-emptions, max stack usage - make it easy to exploit redundancy: run same task on many CPUs, check results agree - automatic checks of key components memory area sentinels, stack space - automatic logging of anomalies - triggers for user defined problem handler functions - kill tasks, disable tasks, disable CPU cores,
 - restart CPU core, ...







OCEOSmp: For Multi-Core Embedded Systems

Based on 'Stack Resource Policy' (Baker 1991)
 => single system stack per CPU (not stack per task)

Deterministic

- => behaviour predictable
- => memory statically allocated
- => timing overheads minimized and quantifiable
- Schedulability analysis
 => simpler to perform

• Application task timing recorded for analysis

- => maximum execution times, maximum times to completion,...
 => missed deadlines trigger application defined action
- Timed actions independent of scheduling
 => output at specific time, task start request at specific time







OCEOSmp: Multi-Core

• Exclude

=> exclude some cores from OCEOSmp use, e.g. for use by Linux

• Reserve

=> reserve cores for higher priority OCEOSmp tasks

• Symmetric

=> after start-up, all cores are equal

Work Distribution

=> task execution instances distributed evenly across cores
=> unless task restricted to a particular core

Control

=> take core out of use, put core back in use







OCEOSmp: RTOS (1)



• Fixed priority

=> task priorities fixed based on task importance

Pre-emption threshold

=> pre-emption only by tasks with higher priority than threshold

Multiple execution instances

=> multiple same task 'jobs' can be in execution at same time typically using different data

- Timed actions independent of scheduling
 - => data output at specific time
 - => task start request at specific time



OCEOSmp for RISC-V



OCEOSmp: RTOS (2)

USER DAY 2022

Mutexes

=> unbounded priority inversion cannot occur => deadlock warning, cannot occur if single core

Read-Write mutexes

- => allow multiple simultaneous reads of protected area when not being written, prevent writing if being read
- Counting semaphores
 - => allow wait with timeout
- Data queues

=> allow read with timeout





OCEOSmp: RTOS (3)

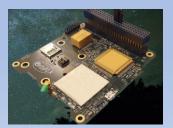
- System time => in microseconds, 64 bit
- Context switch timing
 - => context switching shared across all cores
 - => context switch time minimized

• Interrupts

=> interrupt disabled timing is minimized => high priority timer interrupt reserved for timed actions

Some numbers

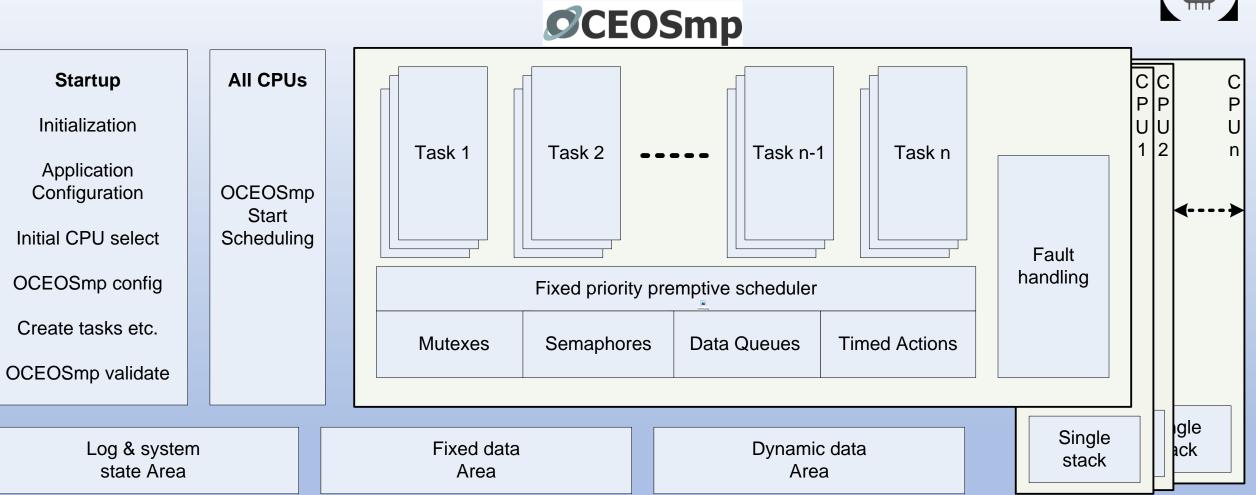
Up to 255 cores, 255 tasks, 15*255 execution instances (jobs), 63 mutexes, 63 read-write mutexes, 63 semaphores, 63 data queues, memory < 20KiB













OCEOSmp: RTOS (4) – USING IT

- Library components not used not linked into the executable
- Servant not Master started by application main()
- Step 1 : Create application configuration, pass to oceos_init() what cores to use, what stack space, log entries how many tasks, jobs per task, timed actions, how many mutexes, semaphores, data queues
- Step 2: Create corresponding tasks, mutexes, etc. using oceos_task_create() etc.
- Step 3: Use oceos_init_finish() to complete fixed data and checksum
- Step 4: Pass fixed data and initial task (if any) to oceos_start() dynamic data area is set up multi-core scheduling begins





OCEOS for automobiles





Debug support - DMON

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2	02.425 772 US						0x0000000	0x0000caf1		0x6FFFFF40										
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Current Status

OCEOS (single core)

 SPARC and ARM versions complete (with additional support for GR716 microcontroller) ESA Flight Level B qualification ready

• OCEOSmp (multicore)

- Multicore SPARC & RISC-V scheduling in initial test, ARM later
- Example test results using SPARC quad core Gaisler GR740:
 - 1001 task starts even distribution: Per CPU 251,250,250,250
 - 4096 sample FFT (one task, four jobs in parallel): Speedup factor 3.7

• Availability

- OCEOS single-core development kit on-sale
- OCEOSmp multicore beta evaluations available soon





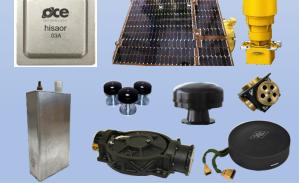
OCEOS task usage & debug screen







- Thanks to ESA for their support
- Thank you for listening
- Any Questions?



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