Robotics Real-Time Programming
Ludovic Saint-Bauzel

To cite this version:

HAL Id: cel-01170371
https://hal.sorbonne-universite.fr/cel-01170371
Submitted on 1 Jul 2015

HAL is a multi-disciplinary open access archive for the deposit and dissemination of scientific research documents, whether they are published or not. The documents may come from teaching and research institutions in France or abroad, or from public or private research centers.

L’archive ouverte pluridisciplinaire HAL, est destinée au dépôt et à la diffusion de documents scientifiques de niveau recherche, publiés ou non, émanant des établissements d’enseignement et de recherche français ou étrangers, des laboratoires publics ou privés.
Robotics Real-Time Programming

Ludovic Saint-Bauzel

2013-14

Contents

1 Introduction 4
  1.1 What is a robot? ................................................. 4
    1.1.1 Definition ........................................... 4
    1.1.2 Hardware ............................................ 4
    1.1.3 Software ............................................ 10
  1.2 What is a controller? ........................................ 10
    1.2.1 System Design ....................................... 10
    1.2.2 Methodology ....................................... 11

2 Robotics Software Frameworks 13
  2.1 RUPI ......................................................... 13
    2.1.1 RUPI Point Of View .................................. 13
  2.2 OROCOS ...................................................... 14
    2.2.1 Open RObotics COntrol Software ..................... 14
  2.3 ROS ........................................................... 23
    2.3.1 Robotics Operating System ............................ 23
  2.4 Frameworks .................................................. 26
    2.4.1 Conclusion ........................................... 26

3 OS : Tasks And Threads 27
  3.1 Operating System Approach ................................. 27
    3.1.1 Introduction ......................................... 27
    3.1.2 Properties ........................................... 28
    3.1.3 Multitasks ........................................... 29
    3.1.4 Real-Time ............................................ 35
  3.2 Scheduling .................................................. 36
    3.2.1 Model ............................................... 36
    3.2.2 Algorithms .......................................... 38
    3.2.3 Thread Scheduling .................................. 42
3.3 Management ................................................. 43
  3.3.1 Process ............................................. 43
  3.3.2 Posix Thread ....................................... 44
3.4 Time Services ............................................ 48
  3.4.1 Posix Time ......................................... 48
  3.4.2 Xenomai Time services ......................... 50
3.5 Synchronization .......................................... 50
  3.5.1 Mutex ............................................... 50
  3.5.2 Variable Conditionnal ......................... 51
  3.5.3 Counting Semaphore ............................. 52
  3.5.4 Xenomai Native API Synchronisation tools .... 54
3.6 Messages and Communication ............................ 54
  3.6.1 Signals ............................................. 54
  3.6.2 Mail Queue ....................................... 56
  3.6.3 Xenomai Native API ............................. 57
3.7 IO Control ................................................ 59
  3.7.1 Memory ............................................. 59
  3.7.2 IO .................................................. 60
4 OS Driver Programming ................................... 62
  4.1 First Idea : From Scratch ............................ 62
     4.1.1 Example ......................................... 62
     4.1.2 x86 example .................................... 63
     4.1.3 From scratch approach ......................... 68
  4.2 Second Idea : Operating System Approach ........... 68
     4.2.1 Introduction .................................... 68
     4.2.2 Linux Kernel Introduction .................... 69
  4.3 Linux Kernel .......................................... 71
     4.3.1 Main Concepts ................................. 71
     4.3.2 Components and mechanisms .................. 73
     4.3.3 Developing environment ....................... 77
  4.4 Tools .................................................. 78
     4.4.1 Dev. tools ...................................... 78
     4.4.2 Debugging ...................................... 79
     4.4.3 Practical ....................................... 80
  4.5 User Space Mechanisms ................................. 81
     4.5.1 Review ........................................... 81
     4.5.2 System Calls .................................... 81
     4.5.3 Hardware access ............................... 82
  4.6 Kernel/Hardware Interface ............................. 84
     4.6.1 Devices .......................................... 84
     4.6.2 Interruptions and events ..................... 86
     4.6.3 Waiting queues ................................ 88
  4.7 Driver (Module) ........................................ 89
     4.7.1 Manipulation .................................... 89
     4.7.2 Basic Routines ................................ 90
<table>
<thead>
<tr>
<th>Section</th>
<th>Title</th>
<th>Page</th>
</tr>
</thead>
<tbody>
<tr>
<td>4.7.3</td>
<td>Char Devices</td>
<td>92</td>
</tr>
<tr>
<td>4.7.4</td>
<td>Memory Management</td>
<td>94</td>
</tr>
<tr>
<td>4.7.5</td>
<td>Xenomai a RTOS example</td>
<td>94</td>
</tr>
<tr>
<td>4.7.6</td>
<td>Description</td>
<td>94</td>
</tr>
<tr>
<td>4.7.7</td>
<td>Main Mechanisms</td>
<td>98</td>
</tr>
<tr>
<td>4.7.8</td>
<td>RTDM</td>
<td>99</td>
</tr>
</tbody>
</table>

5 Application 100

5.1 Examples 100

5.1.1 Examples 100

6 Documentations 106

6.1 Doc 106

6.1.1 Interface with community 106

6.1.2 References 107

6.1.3 Licences 109

6.1.4 Glossary 109
1 Introduction

1.1 What is a robot?

1.1.1 Definition

Robot

- Definition: An Autonomous Robot is a complex system that has the ability to decide its actions on its environment from its sensing, state in order to fill his aims. Survive, Assist ...
  - Sensors
  - Decision
  - Action

- Physical ability: read information from sensor, send orders to actuators, have a regulation (Time based computation) and a decision computation unit (policy).

Robot: Computer science point of view

A computer science way to see a robot is to say it is a computer with peripherals that bring sensing, actuation ability and because of real life interaction need to put the stress on the time. So like a computer we will have to deal with:

- bus
- memory
- cpu

1.1.2 Hardware

Structure Choice criteria

- Critical path?
  - the main loop
  - delayed sensors

- Method
  - Tasks
  - Pipes (read only, read write, write)
Figure 1: Classic (up) and Autonomous (down) Robot Models
Figure 2: mc2e

- Parameters
  - Computation
  - Time constraints
  - Memory needs
  - Precision of measure

**Monocomputer**

- Properties
  - Limited Computation Ability
  - Delays are limited too
  - Simple but efficient

- Recent Improvements
  - GPU
  - Multicore CPU

- Example
Figure 3: mc2e Architecture

Monocomputer

- Properties
  - Limited Computation Ability
  - Delays are limited too
  - Simple but efficient

- Recent Improvements
  - GPU
  - Multicore CPU

- Example

Multi computer

- Properties
  - High scalability of computation
  - High time lost: Bus communication

- Recent Improvement
  - Distributed algorithms development

- Example
Multi computer

- Properties
  - High scalability of computation
  - High time lost: Bus communication
- Recent Improvement
  - Distributed algorithms development
- Example

Master Computer - Slave Computing Units

- Master is connected to slave unit
- Often a bus
- Image
Figure 5: Staubli Architecture

**Bus**

- **Definition**
  - Physical connection
  - Multiple devices

- **Common elements:**
  - Base Address called ports
  - Local Address

- **Examples:**
  - Serial
    * RS485
    * USB
    * CAN
  - Parallel
    * ISA
    * PCI
    * ...
1.1.3 Software

How the robot can make environment interaction?

- Categories
  - Perception
  - Decision
  - Actions
- Computer Science Name: tasks

Real-Time Programming

- Low Level Access
- High Time constraints
  - Don’t mean quick!
  - Mean ability to respect those constraints

Low Level Programming

LINUX

```c
#include <asm/io.h>
...
unsigned char inb (unsigned short port);
void outb (unsigned char byte, unsigned short port);
unsigned char insb (unsigned short port, void *addr,
                    unsigned long count);
void outsb (unsigned short port, void *addr,
            unsigned long count);
```

DOS

```c
#include <dos.h>
...
unsigned char inputb (unsigned short port);
void outputb (unsigned short port, unsigned char byte);
```

1.2 What is a controller?

1.2.1 System Design

SADT: Description

SADT: Structure

Petri Net
1.2.2 Methodology

Find the tasks!

- No Fuzzy properties
  - Real-Time
  - Good Refresh rate

- Nothing is perfect
  - Properties
    - Time (Loop (Freq?), Oneshot)
    - Load (CPU)
  - Boundaries
    - Delays
    - Memory
  - Task repeated every milliseconds with acceptable delay of 0.01 ms

Classical Robotics Tasks

- Control Task
  - Loop, Delay
  - Variable Parameters
  - Static parameters

- User Interface
  - Supervision
  - Send Orders (Asynchronous, Parameters)
Figure 7: SADT: Hierarchical Structure

Figure 8: Petri Net
MVC+

- View
  - Supervision
  - GUI

- Controller
  - Send Orders
  - Control Task Information
  - GUI

- Model
  - Synchronization
  - Communication System
  - Database

- RT Task

2 Robotics Software Frameworks

2.1 RUPI

2.1.1 RUPI Point Of View

Challenging Scenario
2.2 OROCOS

2.2.1 Open RObotics COntrol Software

Introduction

The aim of this part is to present a framework that is a state of art of what can be done by a system that manages the control of a robot. Of course this framework is not perfect and some choices can be questioned but I decided to choose this to give you the main rationales that one can imagine to use to make a good controller. As a summary of the properties I appreciate:

- **component programming** that provides a good reusability of the code and lets deploy different things according to the needs
- **Dataflow**: The main system is based on a software dataflow approach. That is very close to the control of systems.
- **State-Machine** of components lets work with hooks for every state. Gives a supervision of the components.
- **State-Machine** of deployment, lets implement complex behaviour, change the control kind
- **Activity mechanism** to update each component: gives a wide variety of updating mechanism different to the data-flow
- **logging**: Thanks to the component approach and the hook approach, it is possible to subscribe to ports of component and see what happens

OROCOS Project
History

- December 2000, as an idea of Herman Bruyninckx
- European Funding
- European Labs
  - K.U.Leuven in Belgium (Orocos@KUL)
  - LAAS Toulouse in France (Orocos@LAAS)
  - KTH Stockholm in Sweden (Orocos@KTH)

Orocos Toolchain = RTT + OCL

- Real-Time Toolkit
- Orocos Component Library

![Figure 11: Orocos Component/Plugins Architecture](image)

Task Context

**OCL -> Logging Tools**

- 2 Solutions
  - Custom Component
    - + Complete control of the generated file
    - - Some additional code that is not the heart of the controller
  - Listen a component through logging tools
    - In C++ code:
    - In deployment:
Figure 12: RTT Workflow

Figure 13: Component Description
Figure 14: Component State Diagram

Figure 15: Component Activity Diagram

An Activity object executes the ExecutionEngine, which in turn processes incoming messages, plugin functions and finally updateHook() is called.
Task State Diagram

Activity vs Threads

Data Flow

![Diagram of Components Connections](image)

Figure 16: Components Connections

Example: Definition

- **Supervisor**
  - Initialisation
  - Waiting
  - Standing-Up
  - Walking
  - Alert

- **Sensors**
  - Force Handles
  - Orientation of the arm
  - Orientations of the wheels (Beta_L, Theta_L, Beta_R, Theta_R)

- **Controls**
  - Impedance Control
  - Position Control
  - Speed Control
- Models
  * XZ MGD
  * XYPhi MGD
  * Trajectory Generator

Example: Modelling State Machine

Example: Modelling Data Flows

Example: State Machine (Excerpt)

```c
StateMachine OurStateMachineType
{
  var bool detected;
  initial state INIT {
    entry {
      ConsoleOut.display("[INIT]");
      /*...*/ Plant.configure();
    }
    transition select Waiting;
  }
  state Waiting {
    entry {
      STSDetector.start();
    }
    transition STSDetected(detected) STS
      if (detected) then select SitToStand;
  } /*...*/
RootMachine OurStateMachineType statemachine
```
Figure 18: State Machine of Walky Experiment
Figure 19: Dataflow of Walky Controller
Example: Component Skeleton (Excerpt)

```cpp
class Supervisor : public TaskContext {
    protected:
        InputPort< std::vector<char> > inButtons;
        InputPort<bool> STSDetected; /*...*/
        string stateMachineName;
    public:
        Supervisor(string const & name) 
            : TaskContext(name),
            stateMachineName("statemachine")
        {
            this->addEventPort("STSDetected", STSDetected);
            this->addProperty("stateMachineName", stateMachineName);
        }

        bool configureHook() {
            return true;
        }

        bool startHook() {
            scripting::ScriptingService::shared_ptr sa
                = boost::dynamic_pointer_cast< scripting::ScriptingService >( 
                    provides()->getService("scripting"));
            scripting::StateMachinePtr sm = sa->getStateMachine(stateMachineName);
            if (!sm) {
                log(Error) << "State Machine not loaded in Supervisor." << endlog();
                return false;
            }
            return sm->activate() && sm->start();
        }

        void updateHook() {
        }

        void errorHook() {
        }

        void stopHook() {
            scripting::ScriptingService::shared_ptr sa
                = boost::dynamic_pointer_cast< scripting::ScriptingService >( 
                    provides()->getService("scripting"));
            scripting::StateMachinePtr sm = sa->getStateMachine(stateMachineName);
            if (!sm) {
                log(Error) << "State Machine not loaded in Supervisor." << endlog();
                return;
            }
            sm->stop();
            sm->deactivate();
        }

        void cleanupHook() {
        }
};
```
Example: Deployment File (Excerpt)

```xml
<properties>
  <struct name="Supervisor" type="Supervisor">
    <struct name="Activity" type="Activity">
      <simple name="Period" type="double"><value>0.1</value></simple>
      <simple name="Priority" type="short"><value>50</value></simple>
      <simple name="Scheduler" type="string"><value>ORO_SCHED_RT</value></simple>
    </struct>
    <struct name="Peers" type="PropertyBag">
      <simple type="string"><value>STSDetector</value></simple>
    </struct>
    <struct name="Ports" type="PropertyBag">
      <simple name="STSDetected" type="string"><value>STSDetected</value></simple>
    </struct>
  </struct>
  <simple name="RunScript" type="string"><value>deployment/smSTSandWALK.osd</value></simple>
</properties>
```

2.3 ROS

2.3.1 Robotics Operating System

Definition

- ROS (Robot Operating System) provides libraries and tools to help software developers create robot applications. It provides hardware abstraction, device drivers, libraries, visualizers, message-passing, package management, and more.

- Willow Garage
  - Created in 2006
  - 2008 first stable release of ROS
  - 2010 ROS 1.0

Connecting Middleware

- Nodes
  - Server (roscore)
  - Output (rosout)

- Topics
  - Publishers
  - Subscribers

- Parameterized Connections
  - TCP
– SharedMemory
– Serial (Arduino RosSerial)

Figure 20: rxgraph of /Example node with its topics

Meta-Operating System

• Meta-Operating-System
  – rosdep
  – rosmake
  – roscd
  – rosed
  – rosrun
• Useful tools
  – rxgraph
  – rxplot
Figure 21: rxplot of /Example node with its topics
2.4 Frameworks

2.4.1 Conclusion

Connectivity Question

- Exercice:

- Description
  - Kinect
  - OpenCV
  - SLAM
  - Directions

- Aim
  - When someone do hello then go to its direction

Example

- Exercice
  - Description
    * Kinect
    * OpenCV
    * SLAM
    * Directions
  - Aim
    * When someone do hello then go to its direction

- Result
  - Kinect -> OpenCV -> Position -> SLAM -> Directions
Connectivity Solutions

- In OROCOS:
  - Omni ORB
  - From Scratch Components Connection
    - RPC
    - CORBA
    - Sockets -> Server/Client Approach

- ROS

Conclusion

- Overview Implementation
  - Controller on one Computer: OROCOS
  - Communication between computing units: ROS

- Method
  - Identify the states of your system (Tasks, loops)
  - Think of the time, delays and how to overlay some of them
  - Write the data flow for each state
  - Look at the Computing Units At least one node per Unit (ROS)
  - Therefor the components are described (inside one node)

3 OS: Tasks And Threads

3.1 Operating System Approach

3.1.1 Introduction

Operating System few words
A software:
or precisely the first software executed by your computer Consequences:
Manager

- Schedule task order
- Manage resources in order to fulfil every needs
- Use of all the resources.
Resources

Computer Science:
- Processor: CPU, IRQ
- Communication: BUS
- Memory
- ...

Robotics:
- Motor
- Sensors

What is RealTime

Two examples:
- A navigation system computing the best path for a boat.
- A navigation system computing a boat position during its sailing.

- First case: Computing time is not a constraint, the result is this only thing that is interesting
- Second case, if computing time is too long, position is false.

An informal definition

Real-Time system: A system where the behaviour relies on precision of computation and also the time when it is produced.

In other words, a delay is considered as an error that can lead to severe consequences

3.1.2 Properties

Time scheduling
- time-driven system: measure of time leads to actions
- event-driven system: arising of an event leads to actions
- reactive system: constrained time to process
**Predictability determinism reliability**

Real time system : in worst case.

**Predictability** : Ability to identify in advance if a system is able to respect its time constraints Knowledge of parameters related to computation.

**Determinism** : remove any uncertainty in individual task behaviour and when they are together

- Variation of task execution time
- IO duration, reaction time
- Interruption reaction

**Reliability** : Behaviour and Fault tolerance

**Classical system limits**

Classical systems are based on multiple task not well adapted to real time constraints :

- scheduling policy that aims to share time in a balance way for each task
- access mechanisms that shares resources and synchronizes time uncertainty
- interruption management is not optimal
- Virtual memory and cache memory management generate some delays
- timer management is not very accurate

### 3.1.3 Multitasks

**Services of a multitasks system**

Conclusion : A single program rarely use all CPU load

Used those idle times to compute some concurrent other tasks from other software : a part of what an operating system must do

- running concurrent tasks
- exchanging with outside world
- managing memory resources
- sharing hardware, synchronization, communication
- time management

What are the limits for real-time system?
CPU Management - Task, process
Standard operating systems manage process that can be described as follow:

- separated memory room
- special channels for communication
- high time cost spent for creation of a new one
- protection mechanisms are also time costing
- switch between two processes need a lot of memory switches

CPU Management - Task, process
One process works on many memory areas

- computing area (instructions of the software)
- a heap data area
- a stack area for temporary data (variable)

Context of a process is composed of registers, a name, a state, etc.
A thread only owns individual context data, everything else is shared with the father process

Management multiple task and scheduling
A activated process can have many states, here are the main one:

- created
- terminated
- **running**: task is currently using the CPU. We say it is **elected**.
- **waiting**: task is asking for CPU. It is **electable**.
- **blocked**: task is blocked waiting for an event to arise.

Management multiple task and scheduling
State transitions are:

- **waking**: blocked → waiting
- **allocating**: waiting → running
- **unallocating** or **pre-empted**: running → waiting
- **blocking**: running → blocked
**Scheduling**

Scheduler must manage how the task are allocated to the CPU. Schedule in the best way is very hard.

A scheduler called with request or pre-emptive if running process can be unallocated by scheduler.

Non pre-emptive systems can do context switch only when a task is terminated or when it is asking for context switch

Scheduler works most of the time on-line. That means that a policy must exists and be applied

**Scheduling policy**

Classical scheduling rules :

- First In First Out (FIFO)
- Each one its turn (tourniquet, Round Robin : RR)
- Priority based

**Example**

<table>
<thead>
<tr>
<th>Task</th>
<th>Length</th>
<th>Priority</th>
<th>Start time</th>
</tr>
</thead>
<tbody>
<tr>
<td>T1</td>
<td>6</td>
<td>1</td>
<td>0</td>
</tr>
<tr>
<td>T2</td>
<td>3</td>
<td>2</td>
<td>0</td>
</tr>
<tr>
<td>T3</td>
<td>4</td>
<td>1</td>
<td>0</td>
</tr>
</tbody>
</table>
Scheduling example 1

- FIFO

| T1 | T1 | T1 | T1 | T1 | T1 | T2 | T2 | T2 | T2 | T3 | T3 | T3 | T3 |

- RR

| T1 | T2 | T3 | T1 | T2 | T3 | T1 | T2 | T3 | T1 | T1 | T1 | T1 | T1 |

- Priority

| T2 | T2 | T2 | T1 | T1 | T1 | T1 | T1 | T1 | T1 | T1 | T1 | T1 | T1 |

Scheduling example 2

Scheduler with task interactions

<table>
<thead>
<tr>
<th>Task 1 (prio = 2)</th>
<th>Task 2 (prio = 2)</th>
<th>Task 3 (prio = 3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>T[1.1] wait (event)</td>
<td>T[2.1] Signal (Task 1, event)</td>
<td>(not started) T[3.1] wait (1 sec.)</td>
</tr>
<tr>
<td>T[1.2]</td>
<td>T[2.2] Starting Task 3</td>
<td>T[3.2]</td>
</tr>
</tbody>
</table>

Scheduling example 2

Pre-emption after OS signal
### Scheduling example 2

**Without pre-emption**

<table>
<thead>
<tr>
<th>Task 1 (prio = 2)</th>
<th>Task 2 (prio = 2)</th>
<th>Task 3 (prio = 3)</th>
</tr>
</thead>
<tbody>
<tr>
<td>T[1.1] Wait (evt)</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>T[2.1] Signal T1</td>
<td></td>
</tr>
<tr>
<td>T[1.2]</td>
<td></td>
<td></td>
</tr>
<tr>
<td></td>
<td>T[2.2] Start T3</td>
<td></td>
</tr>
<tr>
<td></td>
<td></td>
<td>T[3.2]</td>
</tr>
</tbody>
</table>

### Interruptions

- 2 kind
  - **asynchronous**: emitted by external context (hardware) can arise at any time
  - **synchronous**: emitted by a specific instruction can only arrive in known date for the developer

- processed by the same mechanism

### Interruption management

The way interruptions are processed have a large influence on efficiency of the OS

- Control of interruptions: mostly hardware
  - Context switch
  - Source identification
- Processing interruption
  - Short: same context
  - Long: task are called: signal/wait
- Back to original process
Resources management
Those mechanisms are used to give one access to one resource in one time.

- Define some sections as **atomic**: critical sections
- Mask interruptions (hardware)
- Scheduler is disabled during this critical section (software)
  - Mutex
    * Block other tasks whatever priority they are
    * Problem to choose the task when Mutex is released
  - Counting Semaphores to manage a set of devices

Synchronization
Force an order of processing instructions of a process

- Mutex
- Rendezvous
- Product/Consume

Uses the following mechanisms:

- Signal an event
- Semaphores use
- Mailboxes
- Rendezvous

Synchronization Limits
Maintain coherency of data: creation of waiting queues

- "Balanced" Systems inefficient
- Priority: Synchronization brings some priority issues where a low priority can block a high priority task

Some solutions:

- Priority based waiting management: unlock view the priority level of the task
- Flag like "availability test"
- Time out on blocking flags
Input/Output
Different policies for CPU scheduling and for Input/Output (IO)

• Access through a specialized layer
• Synchronous processing
• Asynchronous processing
• Difficult to manage priorities
• Bad time management

3.1.4 Real-Time Services

• Definition: a software that schedules computing of tasks in one shot way, manage devices of the system and bring development libraries (Application Programming Interface or API)

• It is organized with:
  – a kernel that schedules tasks and manage devices
  – often it proposes services packaged as modules for example. These service can bring the ability of the system to manage File Systems, network devices or any services that are needed by software

Components
The main components of a RTOS are:

• scheduler, inside every kernel, it is the component that apply different algorithms to manage access to the CPU
• kernel interfaces that give developers the ability to create software
  – tasks
  – semaphores
  – message queue...
• services: actions that a kernel can do on a device or on the system like time measurement, interruption, bus controller,...
3.2 Scheduling

3.2.1 Model

Scheduler

Aim: address any needs of a real-time software like emergency stop, high level action or reactivity need

Taxonomy:
- Off-line/On-line algorithm: static/dynamic algorithm
- Static/Dynamic priorities
- Pre-emptive/non pre-emptive algorithms:
  - Ability to have mutual exclusion of a device
  - Scheduler cost low
  - Small efficient

Scheduler

Properties that we look for:
- Feasibility: ability to decide "a priori" that all the constraints will be fulfilled
- Predictability: response time of tasks is predictable.
- Optimality: Optimal if able to find a schedule of every set of feasibility tasks
- Complexity: feasibility test is long and difficult?
- Easiness to implement

Scheduler

Scheduler works only on active tasks:
- Schedule Table: off-line scheduling
- Off-line priorities definition, root of the scheduling
- On-line analysis and scheduling

Analysis recipe

Scheduling problem:
- To Model tasks of the system and their constraints
- To Choose a scheduling algorithm
- To Validate feasibility on a set of tasks
  - Theoretical feasibility: scheduling ability and complexity
  - Empirical feasibility: implement scheduler
Task model

Task families:

• Linked task or not (Precedence constraint).
• Important task or not
• Repetitive or periodic task: activated regularly
• Non periodic task
  – Sporadic: irregular activation but a minimum time between each activation
  – Aperiodic: deadline is less strict and no minimum time between each activation

Task model

Parameters for task $i$

• $S_i$: start time when task arrives in the scheduler
• $C_i$: Computation time needed by the task (Capacity).
• $P_i$: Period
• $D_i$: Deadline of the task
• $R_i$: Earliest activation time

• Aperiodic task is defined by: $[2mm]$
  $(S_i, C_i, D_i, R_i)$
• Periodic task is defined by:
  $(S_i, C_i, D_i, P_i)$

Task model

Let’s consider a simplified model:

• Periodic task
• Independent (No precedence constraint)
• Starting time (worst case): $S_i = 0$
• Deadline equal to Period: $P_i = D_i$
Scheduler Structure

Computation of scheduling information

- On-line or Off-line
- Period, Deadline...

Waiting queue management

- One queue for each priority
- FIFO policy
- Round Robin policy

Election phase

- Priority, deadline, ...

3.2.2 Algorithms

Rate Monotonic Algorithm

Off-line analysis, fixed priority, periodic tasks: Static software

Rationale

- Computation phase: priority = $\frac{1}{\text{period}}$
- Election phase: highest priority is chosen

Properties

- Low Complexity
- Optimal Algorithm in fixed priority algorithm set

Rate Monotonic Algorithm

Example

- Task 1: $C_1 = 6, P_1 = 10$
- Task 2: $C_2 = 9, P_1 = 30$

- Pre-emptive case
- Non pre-emptive case

Can be scheduled if load rate of the CPU $U$ agrees with the following sufficient condition:

$$U = \sum_{i}^{n} \frac{C_i}{T_i} \leq n \times (2^{\frac{1}{2}} - 1)$$
Critical time theorem

If every tasks both arrive at the same time in a system if they respect their first deadline, then every other following deadlines will be respected whatever time they arrive in the system

- it’s a necessary and sufficient condition if every tasks arrive at the same time
- else, it is a sufficient condition

If \( D_i = T_i \), finishing test is:

\[
\forall i, 1 \leq i \leq n, \quad \min_{0 \leq t \leq D_i} \left[ \sum_{j=1}^{i} \frac{C_j}{T_j} \ceil{\frac{t}{T_j}} \right] \leq 1
\]

Response time computation

**Response time TR:** Duration between time when a task begin and time when it is finished. Result can be exact relying on task model. [3mm]

\[
TR_i = C_i + \sum_{j \in hp(i)} I_j
\]

\[
TR_i = C_i + \sum_{j \in hp(i)} \ceil{\frac{TR_j}{P_j}} C_j
\]

Where \( hp(i) \) represents a set of tasks with a higher priority than \( i \).

Response time computation

Computation method: iterative way of evaluation

\[
w_{i+1}^n = C_i + \sum_{j \in hp(i)} \ceil{\frac{w_j^n}{P_j}} C_j
\]

- Let start with \( w_0^0 = C_i \)
- Fail if \( w^n_i > P_i \)
- Achieved if \( w_{i+1}^n = w_i^n \)

**Example:** with \( P_1 = 7, C_1 = 3, P_2 = 12, C_2 = 2, P_3 = 20, C_3 = 5 \). We assume that every task have the same priority and are ran in this order

\[
TR_1 = 3 \quad TR_2 = 5 \quad TR_3 = 18
\]
Aperiodic tasks with high priorities
Periodic task dedicated to these tasks.

- bring feasibility in the worst case
- dedicated task is not activated if there is no aperiodic task to compute
- easy solution, but sometime we loose some CPU load

Earliest Deadline First EDF algorithm

- Periodic task and aperiodic
- On-line Algorithm, more useful than Rate Monotonic

Rationale:
- Computation phase: Deadline computation
  With priority\(_i(t)\) current priority at \(t\) and \(i\) the task:
  - Aperiodic task: priority\(_i(t) = S_i + D_i - t\)
  - Periodic task: priority\(_i(t) = S_i(t)\) [last start activation time when time is \(t\)] \(+ P_i - t\)

  Election phase: Earliest deadline is chosen.(Min)

EDF Example
Let consider 2 tasks:
\(T_1\) : \(C_1 = 6\), \(P_1 = 10\)
\(T_2\) : \(C_2 = 9\), \(P_2 = 30\)

- Pre-emptive case
- Non pre-emptive case

EDF Properties
Ability to schedule: Pre-emptive case, periodic and independent tasks

- Necessary and sufficient condition if \(\forall i, D_i = P_i\); Only necessary if \(\exists i, D_i \leq P_i\):
  \[ U = \sum_{j=1}^{n} \frac{C_j}{P_j} \leq 1 \]

- Sufficient condition if \(\exists i, D_i \leq P_i\):
  \[ U = \sum_{j=1}^{n} \frac{C_j}{D_j} \leq 1 \]
Server for aperiodic and sporadic jobs
- Periodic server:
  - Idle if waiting queue is empty
  - Running in its time

Server for aperiodic and sporadic jobs
- Deferred server:
  - Time Budget
  - Waiting for task
  - Used to be in highest priority

Server for aperiodic and sporadic jobs
- Sporadic server:
  - Like Deferred server
  - But extra computation is done in background (lowest priority)
3.2.3 Thread Scheduling

**Services**

**Properties:**
- Threads and process capability
- Fixed priorities, pre-emptive => RM easy. A minimum of 32 levels is mandatory
- One waiting queue for each priority and scheduling policy (SCHED_FIFO, SCHED_RR, SCHED_OTHERS).
- Available Services to specific users (like root)

Standard say that scheduling policies must be able to be applied each time the choice threadprocess exists (ex.: choice of a threadprocess to release a semaphore).

**Policies**

POSIX.4 policies:
```
#define SCHED_OTHER 0
#define SCHED_FIFO 1
#define SCHED_RR 2
```

- Parameter(s): extendible to future policies

```c
struct sched_param{
    int sched_priority;
    ...
};
```
• Parameters modification:
  – Thread: creation of a thread from an attribute or modification of a running thread.
  – Inherit from a fork() or modify of a running process.

### API

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>sched_get_priority_max</td>
<td>Get max priority value.</td>
</tr>
<tr>
<td>sched_get_priority_min</td>
<td>Get min priority value.</td>
</tr>
<tr>
<td>sched_rr_get_interval</td>
<td>Get duration of one time unit.</td>
</tr>
<tr>
<td>sched_yield</td>
<td>Free the CPU of this thread.</td>
</tr>
<tr>
<td>sched_setscheduler</td>
<td>Choose the scheduler policy.</td>
</tr>
<tr>
<td>sched_getscheduler</td>
<td>Get the scheduler policy value.</td>
</tr>
<tr>
<td>sched_setparam</td>
<td>Set parameters of the scheduler.</td>
</tr>
<tr>
<td>sched_getparam</td>
<td>Get parameters of the scheduler.</td>
</tr>
<tr>
<td>pthread_setschedparam</td>
<td>Set parameters of the scheduler for thread.</td>
</tr>
<tr>
<td>pthread_getschedparam</td>
<td>Get parameters of the scheduler for thread.</td>
</tr>
</tbody>
</table>

The last 2 function are working only on threads, other functions can be applied on process/thread.

#### Example

```c
struct sched_param parm;
int res=-1;
...
/* Task T1 ; P1=10 */
parm.sched_priority=15;
res=sched_setscheduler(pid_T1,SCHED_FIFO,&parm)
if(res<0)
    perror("sched_setscheduler task T1");
/* Task T2 ; P2=30 */
parm.sched_priority=10;
res=sched_setscheduler(pid_T2,SCHED_FIFO,&parm)
if(res<0)
    perror("sched_setscheduler task T2");
```

### 3.3 Management

#### 3.3.1 Process

**Fork**

```c
#include <unistd.h>

pid_t fork(void);
```
3.3.2 Posix Thread

POSIX Threads
Defined in chapter POSIX.4a (Portable Operating System Interface). This chapter describe both threads and synchronization tools that are close to threads (ex: mutex).

Properties:
- A POSIX Thread is defined with a identifier that is local to the process. It owns its stack, its context and a set of attributes that describe its behaviour.
- A POSIX Thread can be implemented in user space or in kernel space ⇒ Standard describe only the interface not the way it is coded.

POSIX Threads
- Code must be re-entrant (or "thread safe") ⇒ code is able to be computed in multiple instances in a safe way
- re-entrant code means:
  - don’t manipulate shared variables.
  - or it manipulate shared variables in a critical section (that mean no other is able to access this variable when one is manipulating it).
- Everything must be re-entrant user code but also system libraries (ex. libc.so)

POSIX threads
<table>
<thead>
<tr>
<th>function</th>
<th>description</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_create</td>
<td>Creation of a thread. Parameter: code, attributes, arg.</td>
</tr>
<tr>
<td>pthread_exit</td>
<td>End of a thread. Parameter: return error value.</td>
</tr>
<tr>
<td>pthread_self</td>
<td>returns id of the running thread</td>
</tr>
<tr>
<td>pthread_cancel</td>
<td>Destroy a thread. Parameter: id of the thread.</td>
</tr>
<tr>
<td>pthread_join</td>
<td>Suspend a thread until another is not finished.</td>
</tr>
<tr>
<td>pthread_detach</td>
<td>Suppress parent link between threads.</td>
</tr>
</tbody>
</table>
POSIX Threads

<table>
<thead>
<tr>
<th>pthread_kill</th>
<th>Emit a signal to a thread.</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_sigmask</td>
<td>Modify signal mask of a thread.</td>
</tr>
</tbody>
</table>

In a POSIX.4a system, some services have a different semantic.

- fork() : create a new process containing a thread where the main() function is computed
- exit() : finish a process and all threads it contains.

POSIX Threads
Creation and join example of a thread

```c
#include <pthread.h>
void* th(void* arg)
{
    printf("I am thread %d ;
            process %d\n",
            pthread_self(), getpid());
    pthread_exit(NULL);
}
```

POSIX Threads
Creation and join example of a thread

```c
#include <pthread.h>
void* th(void* arg)
{
    printf("I am thread %d ;
            process %d\n",
            pthread_self(), getpid());
    pthread_exit(NULL);
}
```

POSIX Threads
Creation and join example of a thread

```c
int main(int argc, char* argv[])
{
    pthread_t id1, id2;
    pthread_create(&id1, NULL, th, NULL);
    pthread_create(&id2, NULL, th, NULL);
    pthread_join(id1, NULL);
    pthread_join(id2, NULL);
    printf("End of main thread %d ;
            process %d\n",
            pthread_self(), getpid());
    pthread_exit(NULL);
}
```
POSIX Threads

- With Solaris:

```bash
gcc -D_REENTRANT create.c -lpthread -lrt >a.out
I am thread 4 ; process 5539
I am thread 5 ; process 5539
End of main thread 1 ; process 5539
```

- With Linux:

```bash
gcc -D_REENTRANT create.c -lpthread >a.out
I am thread 1026 ; process 1253
I am thread 2051 ; process 1254
End of main thread 1024 ; process 1251
```

Thread Attributes

Thread Attributes: properties of a thread that are defined during its creation. No heritage between father and son threads.

Example of attributes:

<table>
<thead>
<tr>
<th>Attribute Name</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>detachstate</td>
<td>pthread_join possible or not</td>
</tr>
<tr>
<td>policy</td>
<td>scheduler policy</td>
</tr>
<tr>
<td>priority</td>
<td>level of priority of the thread ($\geq 0$)</td>
</tr>
<tr>
<td>stacksize</td>
<td>Size of the allocated stack</td>
</tr>
</tbody>
</table>

Thread Attributes

During creation of a thread, an structure of type pthread_attr_t can be filled and given if we want to specify none default attributes to the new thread:

```c
#include <pthread.h>
void* th(void* arg)
{
    printf("I am thread %d \n",
    pthread_self());
}
```

where ATT is replace by the name of the attribute.
Thread Attributes

```c
int main(int argc, char* argv[])
{
    int i;
    pthread_t id;
    pthread_attr_t attr;
    struct sched_param param;
    pthread_attr_init(&attr);
    pthread_attr_setdetachstate(&attr, PTHREAD_CREATE_DETACHED);
    pthread_attr_setschedpolicy(&attr, SCHED_FIFO);
    param.sched_priority=1;
    pthread_attr_setschedparam(&attr,&param);
    for(i=1;i<10;i++)
        pthread_create(&id, &attr, th, NULL);
}
```

The TSD (Thread Specific Data area) is an area of memory where are stored specific information of each thread. Allow extension of regular attributes.

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_key_create</td>
<td>Creation of a key.</td>
</tr>
<tr>
<td>pthread_key_delete</td>
<td>Destruction of the key.</td>
</tr>
<tr>
<td>pthread_getspecific</td>
<td>get pointer value linked to the key of the running thread.</td>
</tr>
<tr>
<td>pthread_setspecific</td>
<td>set pointer value linked to the key of the running thread.</td>
</tr>
</tbody>
</table>

Thread Attributes

Creation of a new attribute:

```c
pthread_key_t cd_key;

int pthread_cd_init(void)
{
    return pthread_key_create(&cd_key, NULL);
}

char* pthread_get_cd(void)
{
    return (char*)pthread_getspecific(cd_key);
}
```

Thread Attributes

```c
int pthread_set_cd(char* cd)
{
    char* mycd = (char*)malloc(sizeof(char)*100);
```
`strcpy(mycd, cd);`  
`return pthread_setspecific(cd_key, mycd);`  
`}`  

```c
int main(int argc, char* argv[])
{
    pthread_cd_init();
    pthread_set_cd("/here/dir");
    printf("My local directory is %s\n", pthread_get_cd());
}
```

### 3.4 Time Services

#### 3.4.1 Posix Time

**Time manipulation**  
Time linked services:

- What time is it?
- Block a thread/process during a defined time.
- Wake up a thread/process regularly (timer) \(\Rightarrow\) periodic tasks.

Precision of these services:

- Linked to what hardware we have (clock circuit), its features (interruption period) and also to the software that use it (interruption handler).
- Ex: Linux Intel: circuit activated periodically (10 ms) \(\Rightarrow\) waking between 10 to 12 ms.

**Time Manipulation : POSIX Extensions**

- Many timers are available \(\Rightarrow\) many physical clocks, profiling.
- Need at least one real-time clock: CLOCK_REALTIME (less than 20 ms precise).
- `timespec` structure \(\Rightarrow\) "theoretical" precision close to micro-seconds ....
- Available services:
  - Get and set clocks.
  - Put a task in sleep mode.
  - Link periodic timer to UNIX signals; and maybe with real-time signals. With or without automatic restart.
Time Manipulation

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>clock_gettime</td>
<td>Get clock value.</td>
</tr>
<tr>
<td>clock_settime</td>
<td>Set clock value.</td>
</tr>
<tr>
<td>clock_getres</td>
<td>Get clock resolution.</td>
</tr>
<tr>
<td>timer_create</td>
<td>Create a timer.</td>
</tr>
<tr>
<td>timer_delete</td>
<td>Remove a timer.</td>
</tr>
<tr>
<td>timer_getoverrun</td>
<td>Give the number of unprocessed signals</td>
</tr>
<tr>
<td>timer_settime</td>
<td>Activate a timer.</td>
</tr>
<tr>
<td>timer_gettime</td>
<td>Get time to the end of the timer</td>
</tr>
<tr>
<td>nanosleep</td>
<td>Block a process/thread during a defined duration</td>
</tr>
</tbody>
</table>

Time Manipulation: Example

```c
int main(int argc, char * argv[]){
    timer_t monTimer; struct sigaction sig;
    struct itimerspec ti;
    timer_create(CLOCK_REALTIME,NULL,&monTimer);
    sig.sa_flags=SA_RESTART;
    sig.sa_handler=trop_tard;
    sigemptyset(&sig.sa_mask);
    sigaction(SIGALRM,&sig,NULL);
    ti.it_value.tv_sec=capacite;
    ti.it_value.tv_nsec=0;
    ti.it_interval.tv_sec=0; // here timer is not
    ti.it_interval.tv_nsec=0; // automatically restarted
    timer_settime(monTimer,0,&ti,NULL);
    printf("Begin\n");
    while(go>0)
        printf("I am working .......
");
        printf("Unblocked by timer : deadline missed ..\n");
    } int go=1;
    void too_late(int sig){
        printf("Signal %d received\n",sig);
        go=0;
    }
```

Execution:

```
Begin
I am working ..... I am working ..... Signal 14 received
I am working ..... I am working ..... Unblocked by timer : deadline
I am working ..... I am working ..... missed ..
```
3.4.2 Xenomai Time services

API Timer Management System

API:

- void `rt_timer_spin` (RTIME ns) : busy clock
- int `rt_timer_set_mode` (RTIME nstick) : TM_ONESHOT or period time

Hardware level:

- oneshot
- periodic

3.5 Synchronization

3.5.1 Mutex

Mutex

- Optimized Semaphores to implement critical section.
- Waiting queue manager : depends of scheduling policy (SCHED_FIFO, SCHED_OTHER, ...). Default behaviour : threads are waked in decreasing order of priority
- Behaviour is defined by a set of attributes, main parameters are:

<table>
<thead>
<tr>
<th>Attribute name</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>protocol</td>
<td>Inheriting Protocol used</td>
</tr>
<tr>
<td>pshared</td>
<td>Inter-process or inter-thread mutex</td>
</tr>
<tr>
<td>ceiling</td>
<td>Priority ceiling</td>
</tr>
</tbody>
</table>

Rationale

Programming mechanism that can block a thread while a condition is not true.[3mm]

- Solution is based on a mutex and a Var Cond
- Waking signal has no memory : if nothing is waiting for the condition, waking signal is lost (≠ counting semaphores).
- Waiting queue management : depend on scheduling policy (SCHED_FIFO, SCHED_OTHER, etc ...). Default behaviour : threads are waked in decreasing order of priority.
Mutex

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_mutex_init</td>
<td>Initialize a mutex.</td>
</tr>
<tr>
<td>pthread_mutex_lock</td>
<td>Lock the mutex in blocking manner eventually.</td>
</tr>
<tr>
<td>pthread_mutex_trylock</td>
<td>Non blocking try to lock the mutex</td>
</tr>
<tr>
<td>pthread_mutex_unlock</td>
<td>Release the mutex lock.</td>
</tr>
<tr>
<td>pthread_mutex_destroy</td>
<td>Destruct the mutex.</td>
</tr>
<tr>
<td>pthread_mutexattr_init</td>
<td>Initialize an attribute structure</td>
</tr>
<tr>
<td>pthread_mutexattr_setATT</td>
<td>Set attribute ATT.</td>
</tr>
<tr>
<td>pthread_mutexattr_getATT</td>
<td>Get attribute ATT value.</td>
</tr>
</tbody>
</table>

ATT is one of the attributes of the mutex.

API

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_cond_init</td>
<td>Initialize a variable.</td>
</tr>
<tr>
<td>pthread_cond_destroy</td>
<td>Destruct a variable.</td>
</tr>
<tr>
<td>pthread_cond_wait</td>
<td>Wait a waking signal coming from a condition.</td>
</tr>
<tr>
<td>pthread_cond_signal</td>
<td>Signal that a condition is true to one thread</td>
</tr>
<tr>
<td>pthread_cond_broadcast</td>
<td>Signal that a condition is true to all threads</td>
</tr>
</tbody>
</table>

3.5.2 Variable Conditionnal

Mechanism

A classical program where a thread modify a variable : a mutex is used (var_mutex) and a condition is used (var_cond).

```c
pthread_mutex_lock(&var_mutex);
/* Modify the variable in critical section */
var = .... ;

/* If the condition is fulfilled, we alert the blocked thread */
if(condition(var))
    pthread_cond_signal(&var_cond);

pthread_mutex_unlock(&var_mutex);
```

Mechanism

Classical program that wait for a variable to be modified :

```c
pthread_mutex_lock(&var_mutex);
while(!condition(var))
{
    /* If the condition is not true,
    wait */
    pthread_cond_wait(&var_cond, &var_mutex);
}
/* use the variable in critical section */
.....

pthread_mutex_unlock(&var_mutex);
```
Attention pthread_cond_wait is making some implicit lock and unlock of the mutex.

Example

```c
int y=2, x=0;
pthread_mutex_t mut;
pthread_cond_t cond;
void* th(void* arg)
{
    int cont=1;
    while (cont){
        pthread_mutex_lock(&mut);
        x++;
        printf("x++\n");
        if (x > y){
            pthread_cond_signal(&cond);
            cont=0;
        }
        pthread_mutex_unlock(&mut);
    }
}
```

Example

```c
int main(int argc , char* argv){
    pthread_t id;
    pthread_mutex_init(&mut, NULL);
    pthread_cond_init(&cond, NULL);
    pthread_mutex_lock(&mut);
    pthread_create(&id, NULL, th, NULL);
    while (x <= y)
        pthread_cond_wait(&cond, &mut);
    printf("x>y is true\n");
    pthread_mutex_unlock(&mut);
}
```

Execution:

```
++
++
++
x>y is true
```

### 3.5.3 Counting Semaphore

**Counting semaphore**

- Semaphore: waiting queue + counter.
- No management of priority inversion: case must be treated in developer level.
- Used for synchronization and inter-process or inter-thread mutual exclusion.
• Waiting queue management: depend on scheduling policy (SCHED_FIFO, SCHED_OTHER, etc...). Default behaviour: threads are waked in decreasing order of priority.

• Two kind of semaphore: named and unnamed semaphore.

### Counting Semaphore

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>sem_open</td>
<td>Connection to a named semaphore.</td>
</tr>
<tr>
<td>sem_close</td>
<td>Disconnection to a named semaphore.</td>
</tr>
<tr>
<td>sem_unlink</td>
<td>Destruction of a named semaphore.</td>
</tr>
<tr>
<td>sem_init</td>
<td>Initialisation of an unnamed semaphore.</td>
</tr>
<tr>
<td>sem_destroy</td>
<td>Destruction of an unnamed semaphore.</td>
</tr>
<tr>
<td>sem_post</td>
<td>Freeing a semaphore.</td>
</tr>
<tr>
<td>sem_wait</td>
<td>Acquiring a semaphore.</td>
</tr>
<tr>
<td>sem_trywait</td>
<td>Non blocking acquiring of a semaphore.</td>
</tr>
</tbody>
</table>

### Counting Semaphore Example

```c
#include <pthread.h>
#include <semaphore.h>

sem_t sem;

int main(int argc, char* argv[]){
    pthread_t id;
    struct timespec delay;
    sem_init(&sem,0,0);
    pthread_create(&id, NULL, th, NULL);
    deli.tv_sec=4; deli.tv_nsec=0;
    nanosleep(&delay, NULL);
    printf("main thread %d : free from the other thread \n", pthread_self());
    sem_post(&sem);
    pthread_exit(NULL);
}

void * th(void * arg)
{
    printf("thread %d waiting\n", pthread_self());
    sem_wait(&sem);
    printf("thread %d unblocked \n", pthread_self());
}
```

### Execution

```
thread 4 waiting
main thread 1 : free from the other thread
thread 4 unblocked
```
3.5.4 Xenomai Native API Synchronisation tools

API Mutexes

```c
int rt_mutex_create (RT_MUTEX *mutex, const char *name)
int rt_mutex_acquire (RT_MUTEX *mutex, RTIME timeout)
int rt_mutex_release (RT_MUTEX *mutex)
```

API Condition variables

```c
int rt_cond_create (RT_COND *cond, const char *name)
int rt_cond_signal (RT_COND *cond)
int rt_cond_broadcast (RT_COND *cond)
int rt_cond_wait (RT_COND *cond, RT_MUTEX *mutex, RTIME timeout)
```

API Counting Semaphores

```c
int rt_sem_create (RT_SEM *sem, const char *name,
                  unsigned long icount, int mode)
int rt_sem_p (RT_SEM *sem, RTIME timeout)
int rt_sem_v (RT_SEM *sem)
int rt_sem_broadcast (RT_SEM *sem)
```

3.6 Messages and Communication

3.6.1 Signals

**Real-Time Signals**

*Signal*: event delivered in asynchronous way to a process/thread (software interruption).

- Blocked signals (or masked) pending or delivered.
- Default behaviour can be modified by user.
- One signal register for each thread/process.

**Real-Time Signals**

Existing mechanism in POSIX.1 but with the following issues:

- Implementation pending signal register = unsafe delivery (possible loss).
- Emitting order not respected when they are delivered.
- Does not contain many information and few of them are available for user: not adapted to IPC implementation.
- Not efficient (slow: high latency).
Real-Time Signals: POSIX Interface

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>kill</td>
<td>Emission of a signal.</td>
</tr>
<tr>
<td>sigaction</td>
<td>Connection of a handler to a signal.</td>
</tr>
<tr>
<td>sigemptyset</td>
<td>Initialize with all signals disabled (mask all signals).</td>
</tr>
<tr>
<td>sigfillset</td>
<td>Initialize with all signals enabled (unmask all signals).</td>
</tr>
<tr>
<td>sigaddset</td>
<td>Add a signal in the set (unmask this signal).</td>
</tr>
<tr>
<td>sigdelset</td>
<td>Remove a signal from the set (mask this signal).</td>
</tr>
<tr>
<td>sigismember</td>
<td>Check if the signal is enabled in the set.</td>
</tr>
<tr>
<td>sigsuspend</td>
<td>Block a process until a signal is received.</td>
</tr>
<tr>
<td>sigprocmask</td>
<td>Install a mask.</td>
</tr>
</tbody>
</table>

Signals: Non RT Example

```c
void handler(int sig){
    printf("Signal %d received\n",sig);
}

int main(int argc, char * argv[]){
    struct sigaction sig;
    sig.sa_flags=SA_RESTART;
    sig.sa_handler=handler;
    sigemptyset(&sig.sa_mask);
    sigaction(SIGUSR1,&sig,NULL);
    while(1); // program computes !!
}
```

Execution:

```
$ sig &
$ kill -USR1 14090
Signal 10 received
```

Real-Time signals: POSIX Extended

Range of new signals numbered from SIGRTMIN to SIGRTMAX (that represent a minimum of RTSIG_MAX signals)

- Possibility to use a value linked to this signal.
- No loss of signal: using of a queue for pending signals.
- Ordered delivery: respecting scheduling policy chosen + priority linked to a signal \(\Rightarrow\) SIGRTMIN has the highest priority.
- Emitted with a kill, sigqueue, with a timer or by an asynchronous IO.

Real-Time Signals: POSIX Extended

Complementary interfaces of POSIX.4:

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>sigqueue</td>
<td>Emit a real-time signal.</td>
</tr>
<tr>
<td>sigwaitinfo</td>
<td>Wait for a signal without handler execution</td>
</tr>
<tr>
<td>sigtimedwait</td>
<td>Idem above + timeout on blocking time.</td>
</tr>
</tbody>
</table>
Real-Time Signals : RT Example

```c
int main(int argc, char * argv[]){
    struct sigaction sig;
    union sigval val;
    int cpt;
    sig.sa_flags=SA_SIGINFO;
    sig.sa_sigaction=handler;
    sigemptyset(&sig.sa_mask);
    if(sigaction(SIGRTMIN,&sig,NULL)<0)
        perror("sigaction ");
    for (cpt =0; cpt <5; cpt ++){
        struct timespec delai;
        delai.tv_sec=1; delai.tv_nsec=0;
        val.sival_int=cpt;
        sigqueue(0,SIGRTMIN,val);
        nanosleep(&delai,NULL);
    }
}
```

RealTime Signals : RT Example

```c
void handler (int sig, siginfo_t *sip, void *uap)
{
    printf("Received signal %d, val = %d \n",
        sig,sip->si_value.sival_int);
}
```

Execution :

```
\$rt - sig
Received signal 38, val = 0
Received signal 38, val = 1
Received signal 38, val = 2
Received signal 38, val = 3
Received signal 38, val = 4
```

3.6.2 Mail Queue

Mechanism

With UNIX, Communication mechanism is the pipeline (named or not) ⇒
too abstract for real-time constraints.[2mm]

Mail queues in POSIX.4 have the same features :

- Priority in emission/reception.
- Can work in Non-blocking
- Can preallocate resources.
- Can communicate in Inter-Process and Inter-Thread mode.
- Unfortunately, priority inversion issues are not addressed.
### API

<table>
<thead>
<tr>
<th>Function</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>mq_open</td>
<td>Creation or connection to a queue.</td>
</tr>
<tr>
<td>mq_unlink</td>
<td>Destruction of a queue.</td>
</tr>
<tr>
<td>mq_receive</td>
<td>Reception of the oldest and the most important mail.</td>
</tr>
<tr>
<td>mq_send</td>
<td>Emission of a mail with a given priority</td>
</tr>
<tr>
<td>mq_close</td>
<td>Disconnection to a queue.</td>
</tr>
<tr>
<td>mq_notify</td>
<td>Notification that there is a new mail.</td>
</tr>
<tr>
<td>mq_setattr</td>
<td>Set attributes of the queue.</td>
</tr>
<tr>
<td>mq_getattr</td>
<td>Get attributes of the queue.</td>
</tr>
</tbody>
</table>

### Example

```c
/* Emission with a priority 1 (from 0 to MQ_PRIO_MAX) */
mq_send(id, buff, 100, 1);
pthread_create(&tid, NULL, consumer, NULL);
pthread_exit(NULL);
}

void* consumer(void* arg){
    mqd_t id;
    char buff [100];
    id=mq_open("/myqueue", O_RDONLY);
    mq_receive(id, buff, 100, NULL);
    printf("msg = %s\n", buff);
    mq_unlink("/myqueue");
    pthread_exit(NULL);
}
```

### Example

```c
#include <pthread.h>
#include <mqueue.h>
int main(int argc, char* argv[])
{
    pthread_t tid;
    mqd_t id;
    char buff [100];
    struct mq_attr attr;
    attr.mq_maxmsg=100;
    attr.mq_flags=0;
    attr.mq_msgsize=100;
    id=mq_open("/mafile", O_CREAT|O_WRONLY, 444,&attr);
    strcpy(buff,"Hi!!");
    ...
}
```

### 3.6.3 Xenomai Native API

API Event flags groups
• Synchronizing object based on a long word structure.
• Any bit in the word can be used as a user flag
• Task oriented signal mechanism
• Conjunctive or Disjunctive

**API Event flags groups**

```c
int rt_event_create (RT_EVENT *event, const char *name,        
unsigned long ivalue, int mode)
int rt_event_signal (RT_EVENT *event, unsigned long mask)
int rt_event_wait (RT_EVENT *event, unsigned long mask,        
unsigned long *mask_r, int mode, RTIME timeout)
int rt_event_clear (RT_EVENT *event, unsigned long mask,        
unsigned long *mask_r)
```

**API Messages queue**

```c
int rt_queue_create (RT_QUEUE *q, const char *name,        
size_t poolsize, size_t qlimit, int mode)
void * rt_queue_alloc (RT_QUEUE *q, size_t size)
int rt_queue_free (RT_QUEUE *q, void *buf)
int rt_queue_send (RT_QUEUE *q, void *mbuf, size_t size, int mode)
int rt_queue_write (RT_QUEUE *q, const void *buf, size_t size, int mode)
ssize_t rt_queue_receive (RT_QUEUE *q, void **bufp, RTIME timeout)
ssize_t rt_queue_read (RT_QUEUE *q, void *buf, size_t size, RTIME timeout)
```

**API Messages pipe**

```c
int rt_pipe_create (RT_PIPE *pipe, const char *name,        
int minor, size_t poolsize)
ssize_t rt_pipe_receive (RT_PIPE *pipe,        
RT_PIPE_MSG **msgp, RTIME timeout)
ssize_t rt_pipe_read (RT_PIPE *pipe, void *buf, size_t size, RTIME timeout)
ssize_t rt_pipe_send (RT_PIPE *pipe, RT_PIPE_MSG *msg,        
size_t size, int mode)
ssize_t rt_pipe_write (RT_PIPE *pipe, const void *buf, size_t size, int mode)
ssize_t rt_pipe_stream (RT_PIPE *pipe, const void *buf, size_t size)
RT_PIPE_MSG * rt_pipe_alloc (RT_PIPE *pipe, size_t size)
int rt_pipe_free (RT_PIPE *pipe, RT_PIPE_MSG *msg)
int rt_pipe_flush (RT_PIPE *pipe, int mode)
```

**Example : Pipe Kernel side**

```c
#include <sys/types.h>
#include <fcntl.h>
#include <string.h>
#include <stdio.h>
#include <native(pipe.h>)
#define TASK_PRI0 0 /* Highest RT priority */
#define TASK_MODE T_FPU/T_CPU(0) /* Uses FPU, bound to CPU #0 */
#define TASK_STKSZ 4096 /* Stack size (in bytes) */

RT_TASK task_desc;
```
RT_PIPE pipe_desc;

void task_body(void){
RT_PIPE_MSG *msgout, *msgin;
int err, len, n;
for (;;) {
    /* ... */
    len = sizeof("Hello");
    /* Get a message block of the right size in order to
     * initiate the message-oriented dialog with the
     * user-space process. */
    msgout = rt_pipe_alloc(len);
    if (!msgout)
        fail();
}

Example: Pipe Kernel side

#include <native/pipe.h>
RT_PIPE pipe_desc;
int init_module (void)
{
    int err;
    /* Connect the kernel-side of the message pipe to the
    special device file /dev/rtp7. */
    err = rt_pipe_create(&pipe_desc,"MyPipe",7,NULL);
    ...
}

Example: Pipe User side

From a regular Linux process:
#include <native/pipe.h>
int main (int argc, char *argv[])
{
    /* Open the Linux side of the pipe. */
    int pipe_fd = open("/dev/rtp7",O_RDWR);
    /* ou grace au service de registres */
    pipe_fd = open("/proc/xenomai/registry/native/pipes/MyPipe",O_RDWR);
    ...  
    /* Write a message to the pipe. */
    write(pipe_fd,"hello world",11);
    ...
}

3.7 IO Control
3.7.1 Memory

Memory Management
A shared time system leads to possible time indeterminism because:
• Dynamic memory allocation.
• Page swap: swapin=swapout.

Solution: limit dynamic memory allocation and lock pages in central memory (POSIX.4 Interface):
• mlockall()=munlockall(): lock/unlock swap with all memory pages of this process.
• mlock()=munlock(): lock/unlock a range of addresses.

Warning: mlock() is not portable (because there is no memory model in POSIX standard).

API Memory heap

```c
int rt_heap_create (RT_HEAP *heap, const char *name, size_t heapsize, int mode)
int rt_heap_alloc (RT_HEAP *heap, size_t size, RTIME timeout, void **blockp)
int rt_heap_free (RT_HEAP *heap, void *block)
```

3.7.2 IO

Posix AIO
• aio_read
• aio_write
• aio_return, aio_error
• aio_cancel
• aio_fsync
• aio_suspend

Example:

```c
sa.sa_sigaction = aioSigHandler;
if (sigaction(IO_SIGNAL, &sa, NULL) == -1) errExit("sigaction");
aiocb.aio_nbytes = BUF_SIZE;
aiocb.aio_reqprio = 0;
aiocb.aio_offset = 0;
aiocb.aio_sigevent.sigev_notify = SIGEV_SIGNAL;
aiocb.aio_sigevent.sigev_signo = IO_SIGNAL;
aiocb.aio_sigevent.sigev_value.sival_ptr = &ioValue;
aio_read(&aiocb);
err = aio_error(&aiocb);
switch (err) {
    case 0:          printf("I/O succeeded\n"); break;
    case EINPROGRESS: printf("In progress\n"); break;
    case ECANCELED:   printf("Canceled\n"); break;
    default:          errMsg("aio_error"); break;
}
aio_return(&aiocb);
```
API Interrupt management

```c
int rt_intr_create(RT_INTR *intr, const char *name, unsigned irq,
                    rt_isr_t isr, rt_iack_t iack, int mode);[Kernel]
int rt_intr_create(RT_INTR *intr, const char *name, unsigned irq, int mode);[User]
int rt_intr_enable(RT_INTR *intr);
int rt_intr_disable(RT_INTR *intr);
int rt_intr_wait(RT_INTR *intr, RTIME timeout);
```

Example : User Interruption

```c
#include <sys/mman.h>
#include <native/task.h>
#include <native/intr.h>

#define IRQ_NUMBER 7 /* Intercept interrupt #7 */
#define TASK_PRIO 99 /* Highest RT priority */
#define TASK_MODE 0 /* No flags */
#define TASK_STKSZ 0 /* Stack size (use default one) */

RT_INTR intr_desc;
RT_TASK server_desc;

void irq_server(void *cookie){
    for (;;) {
        /* Wait for the next interrupt on channel #7. */
        err = rt_intr_wait(&intr_desc, TM_INFINITE);
        if (!err) {
            /* Process interrupt. */
        }
    }
}
```

Example : User Interruption

```c
int main(int argc, char *argv[]){
    int err;
    mlockall(MCL_CURRENT|MCL_FUTURE);
    err = rt_intr_create(&intr_desc,"MyIrq", IRQ_NUMBER, 0);
    err = rt_task_create(&server_desc,
                          "MyIrqServer",
                          TASK_STKSZ,
                          TASK_PRIO,
                          TASK_MODE);
    if (!err)
        rt_task_start(&server_desc,&irq_server,NULL);
    void cleanup(void){
        rt_intr_delete(&intr_desc);
        rt_task_delete(&server_desc);
    }
```
4 OS Driver Programming

4.1 First Idea : From Scratch

4.1.1 Example

RobModex

- ISA Card
  - 0x100 : Base Address
  - 0x01 - 0x04 : Timer (IRQ 5)
  - 0x05 - 0x08 : DAC1
  - 0x09 - 0x12 : DAC2
  - 0x13 - 0x14 : 2 Wheel Encoder Registers

Closed Loop PID
Figure 25: IRQ Process

variables qmes, qdes
error(k) =
error_cumul(k) =
error_diff(k) =
qcons =
oldeerror = error

4.1.2 x86 example

Simple IRQ x86

- 0x20
  - Command Register
  - Status Register

- 0x21
  - Int Mask Register

- Internal Registers
  - Int. Req. Reg.
  - In Service Register

- System Memory
  - Interrupt Vector Table (4 bytes)
Figure 26: Interruption Recent Mechanism more complex

- Byte 0: Offset Low Address of the **Interrupt Routine** (Handler)
- Byte 1: Offset High Address of the IR
- Byte 2: Segment Low Address of the IR
- Byte 3: Segment High Address of the IR Offset

**Piece of code:**

```c
#define IMR 0x21
void _install_int_function (int IRQn,
void interrupt (*_new_int_function)())
{
  int inter = IRQn + 8;
  _disable(); // disable interrupts
  // save the old interrupt vector
  _old_int_function = _dos_getvect (inter);
  // install the new interrupt vector
  _dos_setvect (inter, _new_int_function);
  // save the state of the 8259A IMR register
  _old_mask = inportb(IMR);
  // Set new value for IMR register
  outportb(IMR, _old_mask & _interrupt_mask(IRQn));
  _enable(); // enable interrupts
}
```

**I/O APIC**: Advanced Programmable Interrupt Controller

**IRQ**
Figure 27: Intel SMP Interrupt Systems
Bus: ISA

- Ax: Addresses
- Dx: Data
- IRQs: 3, 4, 5, 6, 7
- AEN: DMA

Bus: ISA

```c
#define ISAADDR
short data;
void interrupt _new_int_function()
{
  _disable(); // disable interrupts
data = inb(ISAADDR); // getDataFromISA
  // that the ISA Component has requested
  _end_interrupt();
  _enable(); // enable interrupts again
}
```

Digital/Analog Converter

RobModex Application

```c
#define ISAADDR ......
short data;
void interrupt _new_int_function()
{
  _disable(); // disable interrupts
data = inb();
  outb((byte)0x3b0, (byte)0x01);

  _end_interrupt();
  _enable(); // enable interrupts again
}
```
Figure 28: ISA Port
4.1.3 From scratch approach

Conclusion

- More Complex = More code
- No-reusability of pieces of code

4.2 Second Idea: Operating System Approach

4.2.1 Introduction

Context

- OS Hardware
- Native Robot SW
State of Art

- **OS Hardware**
  - Linux, WindowsCE, VxWorks

- **Native Robot SW**
  - Xenomai, RTAI, RTLinux, OROCOSRT

- **MiddleWare**
  - RoSta Robotics Standards: OROCOS, Microsoft Robotics Studio, URBI, Robotic Operating System (ROS), ORCA, MARIE...

- **Communication Framework**
  - OROCOS, Microsoft Robotics Studio, URBI, Robotic Operating System, OpenJaus

### 4.2.2 Linux Kernel Introduction

**History**

Creator: Linus Torvalds for personal reasons

- understand Operating System
• funding no cheap OS present on the market place
• Minix had too many limits

Main initial choices taken by Linus
• using GNU licenses tools compiler and tools
• share sources on Internet
• GNU GPL License used
• collaborative work ⇒ quick emergence of a developer community

Key dates
• First stable version (1.0) in 1994 ;
• POSIX compatibility added in version 1.2 (1995) ;
• Support Multi Processors (SMP) and portability improvement in versions 2.0 (1996) ;
• Improvement of general performances, increase of number of platform and number of supported devices in versions 2.2 (1999) ;
• Increasing performances with SMP architectures and network layer in versions 2.4 (2001).
• wide set of improvements internally and in the API (pre-emptive, 64 bit/embedded architectures, unified devices management, ...) (2003).

Features
• Monolithic Kernel
• UNIX type architecture all files concept
• MultiTasks
• MultiUsers
• MultiProcessors
• Multiplatform
Properties

- Dynamic load of kernel modules
- Inter Processes memory protection
- Load of executable on demand
- Page sharing between each executable
- Dynamic cache size management
- Shared libraries supported
- ...

4.3 Linux Kernel

4.3.1 Main Concepts

User/Kernel World

Material protection using CPU mechanisms.

Two distinct worlds

- Kernel space where all is permitted even the worst
- User space where possibilities are restricted with safety mechanisms (ex: memory access)

Schema

User/Kernel Transitions

Three kind of transitions user/kernel :

- system calls ;
- interruptions ⇒ Interruption controller in the kernel ;
- exceptions (ex : illegal memory access , illegal instructions ...).

Limited number of entry points in the kernel (190) for users ⇒ system calls ;

Each user process can be divided in two main parts :

- a kernel part ⇒ System calls (ex : open(), read()...);
- a User part ⇒ all the other things (ex : management, algorithms...).
Rationale

Main rule
"Always try to bring complexity outside of the kernel"

Consequences

- kernel must stay as small as possible
- system calls must be limited in their numbers
- all the complexity are in the library called `libc` or
- in user software
Motivations

### Kernel device drivers or user mode software?

**Kernel device drivers:**
- Direct Access: Memory and devices;
- quickness (less software layers);
- manage concurrent accesses to devices;
- manage access rights.

**User software solution:**
- keep complexity outside of the kernel;
- software are running in safe mode;
- easy to debug.

Ex: Ghostscript (printers), Sane (scanners)...

### Kernel Structures

Many structures are commonly used in the kernel:
- Complex structures (ex: task_struct defined in `<linux/sched.h>`);
- complex linked lists (ex: structures list vm_area_struct organised as AVL tree - `<linux/mm.h>`);
- pseudo-objects composed of pointers on functions structures as a method of it (ex: module structure defined in `<linux/module.h>`).

### 4.3.2 Components and mechanisms

#### Memory management

**Kernel address space**
- linear view of the RAM no segments
- no check of illegal accesses

**User address space**
- virtual dont represent real memory
- private for each process
- in advance allocation real allocation when really in use
- no size limit except hardware ones sometimes software if it dosnt fit the hardware (ex: DOS)
Memory Translation Virtual-Real

Virtual Address

Segment Number  Displacement

Segmentation table

<table>
<thead>
<tr>
<th>information fields</th>
<th>Base Address (or NIL)</th>
</tr>
</thead>
<tbody>
<tr>
<td>...</td>
<td>...</td>
</tr>
</tbody>
</table>

Addition

Real Address

Virtual Address

Page Number  Displacement

Page table

<table>
<thead>
<tr>
<th>information fields</th>
<th>Block number (or NIL)</th>
</tr>
</thead>
<tbody>
<tr>
<td>...</td>
<td>...</td>
</tr>
</tbody>
</table>

Process

Elementary Execution Unit of the Operating System
Two kinds
• **process** based on a copy of resources coming from father process improved with the use of copy on write mechanisms or vfork

• **thread** share the maximum part of the resources coming from the main process ⇒ context switch accelerated

**Scheduling**

Pre-emptive Multi-task:
Kernel is pre-emptive itself (from 2.6 version);
UNIX Policy to share CPU time between each processes;
Real-Time API in POSIX.1b;
Linux is nevertheless a real-time kernel:

• Execution time not **predictive**;

• non-determinist system. Priorities management (41 normal levels + 99 real-time levels).

**Interruption management**

Linked to a device (ex : bus, interface, timer...);
Material interruptions can pre-empt a process even if it work in kernel mode;
Two phases computing:

• top-half : high-speed part and critical (ex : acknowledge an interruption for a device), and

• bottom-half : slow part in a queue of tasks that is emptied by the scheduler (ex : processing associated to the interruption). Possibility to share IRQ.

**Mutual Exclusion**

Linux Kernel is re-entrant and pre-emptive;
There is consequently many possible concurrencies:

• between each CPU (SMP architecture);

• between Interruption Controller and System Calls;

• between different System Calls (because of explicit or implicit pre-emption);

⇒ Blocking mechanism (locking) for protection:

• global variables,

• non-re-entrant functions,

• critical hardware accesses.
File Systems
Fundamental of every UNIX based systems;
Two main kind:

- real: Associated to a real storage device (ex. hdd, CDROM ...);
- virtual: emulates a storage device to have access to advantages of files mechanisms (ex: drivers, /proc ...).

File System
Abstraction layer to implement writing mechanism with file system (VFS):
- can be based on every bloc device;
- basic mechanism are present: * open()/close(), read()/write(), lseek()...; *inheriting generic mechanisms if not implemented.
- need of specific tools (ex: formatting, check, tuning...)

Network
One of the big asset of Linux system; Many devices and protocols are supported; Divided in two set of sub-systems:

- driver of interfaces that fit with physical level (1) and Data level (2) of OSI Model (ex: Ethernet, Token Ring, PPP...);
- Protocols corresponding to layers Net (3) and Transport (4) (ex: TCP, IP, IPX, Appletalk...).

Network
Interface drivers use device drivers to have access to them; Communication between device drivers, interface drivers and protocols is done with packets (ex: structure sk_buff defined in <linux/skbuff.h>);
IP layer integrate route tables and name resolution.

Modules
Dynamic Kernel Modules: object files (.o/.ko) implementing a functionality of the kernel;
Used to reduce the size of the Kernel and bring it more flexibility;
We can load and unload in dynamic way (during run-time) a new functionality (ex: driver, protocol, file system...)
Module Dependencies management with modprobe tool;
Management of dynamic link edition with insmod.
**Device drivers**

Piece of software plugged in the kernel to bring an interface between kernel and hardware devices;

There must be two different interfaces:

- one for users that is generic and stable;
- one to communicate with the kernel.

With Linux, user interface is provided as a special file;

So we are able to use classic system call like `open()`, `read()`, `write()`;

Can be implemented as a module dynamically linked "on demand" or statically compiled in the kernel.

**4.3.3 Developing environment**

**Distribution**

Sources archives in files `linux-X.Y.Z.tar.bz2`

- **X** = VERSION (~ 4 5 years) : number of version ;
- **Y** = PATCHLEVEL (~ 1 2 years) : number of sub-version (even ⇒ stable, odd ⇒ unstable);
- **Z** = SUBLEVEL (~ 1 6 months) : number of sub-sub-version.

Update patches in files like `patch-X.Y.Z+1.bz2`, [6mm] Files `.sign` to check signature of archives and patches  
Ex for signature :

```
gpg -keyserver wukeyserver.pgp.net -recv-keys 0xS17D0F0E
```

```
gpg -verify linux-X.Y.Z.tar.bz2.sign linux-X.Y.Z.tar.bz2
```

**TreeView**

Documentation/ : documentation related to the kernel and its sub-systems  
(ex : sound/, DocBook/...);

arch/ : specific part for architectures (ex : alpha/, arm/, i386/...);

drivers/ : device drivers (ex : usb/, net/...);

fs/ : file systems (ex : xt2/, fat/...) et VFS;

include/ : headers files (ex : asm-i386/, linux/, net/...);

init/ : initialisation process (boot) of the kernel;

ipc/ : inter-processes communication mechanisms (ex : shared memories, semaphores...);

kernel/ : core of the system (ex : scheduler, signals...);

lib/ : mini C library to be used in the kernel (ex : strcmp(), sprintf())

mm/ : memory management;

net/ : interfaces and network protocols (ex : ethernet/, ipv4/...);

scripts/ : useful scripts for configuration and compilation of the kernel.
TreeView

In 2.6 version, new directories: crypto: generic API cryptography and their implementations; security: security mechanisms running in the kernel and implementations (SELinux); sound: sound sub-systems (in drivers before).

4.4 Tools

4.4.1 Dev. tools

Compilation

Only supported tools for compilation:

- GCC (with its specific optimization set...);
- GNU Make (syntax...).

Lower versions of tools ⇒ Documentation/Changes;

Use optimization flag -O of GCC to have inline in headers interpreted.

Ex Makefile

Ex: Makefile

```
CC = gcc
CCOPTS = -Wall -Wstrict-prototypes -O2
KSRC = /lib/modules/$(shell uname -r)/build
MODVERSIONS = -DMODVERSIONS
MODVERSIONS += -include $(KSRC)/include/linux/modversions.h
CFLAGS = -I$(KSRC)/... $(CCOPTS) -DMODULE $(MODVERSIONS)
CFLAGS += -D__KERNEL__
%
%.o : %.c
 $(CC) $(CFLAGS) -c $< -o $@
```

C Language and C library

No libC for kernel programming;

Useful Functions in the directory lib/ of kernel sources;

Coding standards described in Documentation/CodingStyle;

It is advised to split big C files into many smaller files with well defined functions inside (ex: software layer);

Object files (.o) can then be merged in one module (one module_init()...) with the linker;

Ex:

```
>ld -r part1.o part2.o -o module.o
```
Patches
Collecting modifications in one or more files;
Must keep the original file or directories;
Ex: creation of a patch

```
> diff -urN <orig> <dest> > patch_<description>
```

Ex: using the patch

```
> cd <origine>
> patch -p1 < patch_<description>
```

4.4.2 Debugging

Console
Kernel function printk() to send information in standard output (console);
Multiple levels of debugging are defined in <linux/kernel.h> (ex: KERN_EMERG,
KERN_INFO...);
Messages are logged by syslogd daemon (entry kern.*);
dmesg software display and check the round buffer used by printk();
Prototype:
- int printk(const char *fmt, ...);

KGDB
kgdb patch for the kernel (http://kgdb.sourceforge.net);
Need of a second machine:
- link the target with a serial connection;
- use GDB-client to debug the target.
Easy to use and quick way to debug (source mode debugging).

KDB
Embedded in the kernel debugging tool;
Developed by SGI (http://oss.sgi.com/projects/kdb/);
It includes:
- A set of user commands that allow to debug the kernel and real-time
  kernels;
- a kernel debugger in assembly mode (not in source mode)
Useful debugger but hard to use because of its complexity.
Profiling
It is possible to analyse time spent by each function of the kernel:

- boot parameter: \texttt{profile=n};
- binary information in \texttt{/proc/profile};
- can become readable with \texttt{readprofile} tool.

Allow to identify:

- structural misbehaviour;
- to be optimised parts of the driver.

2.6 kernel provides Oprofile, a more powerful kernel/user profiler.

Other possibilities
On request Debugging:

- virtual file in \texttt{/proc};
- system call \texttt{ioctl()}.  

GDB debugging read only mode the virtual file \texttt{/proc/kcore};
Using Linux User Mode for hardware independent parts;
Analysing outputs of the software with \texttt{strace};
In oops case, analysing et interpretation with \texttt{ksymoops} tool (use the file \texttt{System.map}).

4.4.3 Practical
Practical

- Get sources of a linux kernel on www.kernel.org
  - Extract kernel sources: \texttt{tar xvfj linux-X.Y.Z.tar.bz2}
  - Go to the root of the sources: \texttt{cd linux-X.Y.Z}
- Apply some patches: \texttt{patch -p1 < /path/to/patch-foo}
- Configure the kernel: \texttt{make xconfig}
  - Compile (2.4 kernel): \texttt{make dep clean bzImage modules}
  - Compile (2.6 kernel): \texttt{make}
- Install: \texttt{make modules_install install}
- Reboot.
4.5 User Space Mechanisms

4.5.1 Review

- Threads
- Signals
- Systems Calls
- Hardware access

4.5.2 System Calls

**ioctl**

ioctl : Devices Control

```c
#include <sys/ioctl.h>
int ioctl(int d, int request, ...)
```

Example:

- 0x00000606 LPGETIRQ int *
- 0x00000608 LPWAIT int
- 0x00000609 LPCAREFUL int
- 0x0000060A LPABORTOPEN int

**syscall**

```c
#include <syscall.h>
#include <unistd.h>
#include <stdio.h>
#include <sys/types.h>
int main(void) {
    long ID1, ID2;
    /*-----------------------------*/
    /* direct system call */
    /* SYS_getpid (func no. is 20) */
    /*-----------------------------*/
    ID1 = syscall(SYS_getpid);
    printf("syscall(SYS_getpid)=%ld\n", ID1);
    /*-----------------------------*/
    /* "libc" wrapped system call */
    /* SYS_getpid (Func No. is 20) */
    /*-----------------------------*/
    ID2 = getpid();
    printf("getpid()=%ld\n", ID2);
    return(0);
}
```

Extract from "/usr/include/bits/syscall.h"
4.5.3 Hardware access

Input/Output Ports and Authorization

Address range used by present devices on IO bus (ex : controlling registers);

We can access these ports from the kernel with functions :

- \texttt{in\{b,w,l\}() / out\{b,w,l\}()} : read/write 1, 2 or 4 octets on an IO port,
- \texttt{in\{b,w,l\}_p() / out\{b,w,l\}_p()} : read/write 1, 2 or 4 octets on an IO port and
  pause until the I/O completes,
- \texttt{ins\{b,w,l\}() / outs\{b,w,l\}()} : read/write sequences of 1, 2 or 4 octets on IO
  ports.

To be authorize to access data in user space you have to ask for permission
with the functions :

- \texttt{int ioperm(unsigned long from, unsigned long num, int turn_on)} : only
  the first 0x3ff I/O ports can be specified in this manner.
- \texttt{int iopl(int level)} : changes the I/O privilege level of the calling process,
  Warning !! not advised.

Prototypes

Prototypes x86 (\texttt{<asm/io.h>}) :

- \texttt{unsigned char inb (unsigned short port)} ;
- \texttt{void outb (unsigned char byte, unsigned short port)} ;
- \texttt{unsigned char insb (unsigned short port, void *addr, unsigned long count)} ;
- \texttt{void outsb (unsigned short port, void *addr, unsigned long count)} ;
Mapping addresses
Memory
- mmap
- mremap
- mprotect

IO In some cases, it is mandatory to map addresses range of IO in linear address space of the kernel (ex: PCI ⇒ addresses > PAGE_OFFSET):
- ioremap() : map physical addresses range to a linear address range (similar to vmalloc()),
- iounmap() : free an address range already mapped.

Memory Mapping
```c
#include <sys/mman.h>
#include <sys/stat.h>
#include <fcntl.h>
#include <stdio.h>
#include <stdlib.h>
#include <unistd.h>

int main(int argc, char *argv[]){
    char *addr;
    int fd;
    struct stat sb;
    off_t offset, pa_offset;
    size_t length;
    ssize_t s;
    fd = open(argv[1], O_RDONLY);
    if (fstat(fd, &sb) == -1) /* To obtain file size */
        offset = atoi(argv[2]);
    pa_offset = offset & ~(sysconf(_SC_PAGE_SIZE) - 1);
    /* offset for mmap() must be page aligned */
    if (argc == 4) {
        length = atoi(argv[3]);
        if (offset + length > sb.st_size)
            length = sb.st_size - offset;
        /* Can’t display bytes past end of file */
    } else {
        /* No length arg => display to end of file */
        length = sb.st_size - offset;
    }
    addr = mmap(NULL, length + offset - pa_offset,
                PROT_READ, MAP_PRIVATE, fd, pa_offset);
    s = write(STDOUT_FILENO, addr + offset - pa_offset, length);
    exit(EXIT_SUCCESS);
}
```
Kernel Services
/sys : system / driver status information

```
> cat /sys/bus/usb/devices/usb4/4-2/product
USB-PS/2 Optical Mouse
```

/proc : Hardware Status Information

```
> cat /proc/iomem
... fec00000-fec00fff : IOAPIC 0
... fee00000-fee00fff : Local APIC
... >cat /proc/ioports
0000-001f : dma1
0020-0021 : pic1
0040-0043 : timer0
0050-0053 : timer1
0060-0060 : keyboard
...```

4.6 Kernel/Hardware Interface

4.6.1 Devices

IO Port Reservation
Drivers can access IO ports that are not there own devices (ex : probing) ;
In order to avoid conflicts, kernel can reserve ports for drivers :

- int request_region() : reserve a IO port ;
- check_region() : check if the port is not yet reserved (deprecated in 2.6) ;
- release_region() : free an IO port.

List of ports already reserved appears in /proc/ioports.

Memory Reservation
To avoid conflicts, kernel can reserve IO memory region for some device driver :

- request_mem_region() : reserve one memory range of adress,
- check_mem_region() : check if the region is already reserved (deprecated in 2.6),
- release_mem_region() : free this region.

Listing of memory regions reserved appears in /proc/iomem ;
Prototypes
Prototypes (<asm/io.h> and <linux/ioport.h>):

- void * ioremap (unsigned long offset, unsigned long size);
- void iounmap (void *addr);
- struct resource * request_mem_region (unsigned long start, unsigned long n, const char *name);
- int check_mem_region (unsigned long start, unsigned long n);
- void release_mem_region (unsigned long start, unsigned long n);

Hardware access functions
It is then possible to access to shared memory of IO with the following functions:

- readb,w,l()/writeb,w,l() : read/write respectively 1, 2 ou 4 octets in IO memory;
- memcpy_{from,to}io() : read/write octet continuous block in IO memory;
- memset_io() : fill a specific range of data with a fixed value;
- virt_to_bus()/bus_to_virt() : translate between a virtual linear address and real address on the bus.

Prototypes
x86 prototypes (<asm/io.h>):

- char readb (void *addr);
- void writeb (char byte, void *addr);
- void * memcpy_{from,to}io (void *dest, const void *src, size_t count);
- void * memset_io (void *addr, int pattern, size_t count);
- unsigned long virt_to_phys (volatile void *addr);
- void * phys_to_virt (unsigned long addr);
Kernel memory
Many methods exist in the kernel to allocate memory:

- `kmalloc()/kfree()` : allocate/de-allocate a real continuous memory block in the kernel (GFP_KERNEL ⇒ can sleep, GFP_ATOMIC ⇒ atomic),
- `__get_free_pages()/free_pages()` : allocate/de-allocate an integer number \(2^n\) of continuous real memory pages (idem previous but for biggest needs - limit : 128 ko),
- `vmalloc()/vfree()` : allocate/de-allocate a virtual memory block composed by many discontinuous memory blocks of real memory.

Prototypes
Prototypes (`<linux/slab.h>` et `<linux/vmalloc.h>`):

- `void * kmalloc (size_t size, int flags)`;
- `void kfree (const void *addr)`;
- `unsigned long __get_free_pages (int gfp_mask, unsigned long order)`;
- `void free_pages (unsigned long addr, unsigned long order)`;
- `void * vmalloc (unsigned long size)`;
- `void vfree (void *addr)`;

4.6.2 Interruptions and events

Interruptions and events
Supervision of Input/Output events, I/O often asynchronous and unpredictable (ex : keyboard);

Two methods to supervise I/O:

- active waiting (polling);
- interruptions.

In polling mode, CPU is released with `schedule()` function after each unsuccessful test;

Interruptions et events
Ex : polling

```c
for ( ; ; )
{
  if (read_state(carte) & ETAT_END)
    break;
  schedule();
}
```
In interruptible mode, calling process is asleep and put in a waiting queue; Interruption manager will have to wake the process (or processes according to its policy)

**Interruptions et events**

Interruption manager is called interrupt handler. 

Properties:

- must be fast;
- can’t call sleeping function (ex : kmalloc() non atomic).

For these reasons, interruption management is divided in 2 parts:

- interrupt handler: fast and uninterrupted part, and
- bottom-half: slowest part, manage waiting queue of tasks.

First part can exist without second part but inverse is not possible;

**Interruptions et events**

Interrupt handler is declared with function request_irq();

It is freed by free_irq();

Prototypes (<linux/sched.h>, <linux/interrupt.h>):

- int request_irq (unsigned int irq, irqreturn_t (*handler)(int, void *, struct pt_regs *), unsigned long flags /* SA_SHIRQ */, const char *device, void *dev_id);
- void free_irq (unsigned int irq, void *dev_id);

**Interruptions et events**

When irq arises, function handler() is called;

dev_id field is used to identify devices when IRQ is shared (SA_SHIRQ);

It can be used to send specific structure to driver; List of already declared IRQ is available in /proc/interrupts; Returning code of request_irq must be IRQ_NONE or IRQ_HANDLED.

**Interruptions et events**

Bottom-halves

Kernel functions used to manage asynchronous tasks;

Executed after every return of system call, exception or interrupt handler;

Two possible "implementations":

- tasklets: can run on different CPU but one instance at one time
- softirqs: can run on different CPU and many instances can work in parallel
Interruptions et events

Ex :

```c
void my_routine_bh(unsigned long)
{
    /* ... bottom-half code ... */
}
DECLARE_TASKLET(ma_tasklet, ma_routine_bh, 0);

void my_handler_irq(int irq, void *dev_id, struct pt_regs *regs)
{
    ... tasklet_schedule(& ma_tasklet);
    ...
}
```

4.6.3 Waiting queues

Concepts
A process can wait for a kernel event (ex : data) ; Process is going in a waiting queue and release the CPU When the event arises, processes in the corresponding queue are awaking.

Implementation
Manipulation methods on waiting queue are as follow :

- `wait_event_interruptible_timeout()`: put the running process in sleep mode, in interruptible way or not and with/without time out limit, sleeping process is put in waiting queue

Interruptible Implementation
'Interruptible' version check if a signal has been sent to a process and return an error code in this case (-ERESTARTSYS).

This error code should be propagated as a return of the system call. Initialization of a waiting queue (type `wait_queue_head_t`) :

- during declaration ⇒ DECLARE_WAIT_QUEUE_HEAD(), or
- during execution (runtime) ⇒ init_waitqueue_head().

Prototypes (<linux/wait.h>) :

- DECLARE_WAIT_QUEUE_HEAD (name) ;
- void init_waitqueue_head (wait_queue_head_t *wq) ;

88
Prototypes

Prototypes (<linux/sched.h>, <linux/wait.h>):

- void wait_event (wait_queue_head_t *wq, condition);
- int wait_event_interruptible (wait_queue_head_t *wq, condition);
- int wait_event_interruptible_timeout (wait_queue_head_t *wq, condition, long timeout):
- void wake_up_interruptible (wait_queue_head_t *wq):
- void wake_up_interruptible_nr (wait_queue_head_t *wq, int nr):
- void wake_up_interruptible_all (wait_queue_head_t *wq);

Example

Ex:

```c
static DECLARE_WAIT_QUEUE_HEAD (ma_file) ;

int function_reading ( void *addresse ) {
    ...
    ret = wait_event_interruptible (& ma_file , readb () != 0) ;
    if ( ret $<$ 0)
        return ret ;
    ...
}

void my_handler ( int irq , void *priv , struct pt_regs *regs) {
    ...
    wake_up_interruptible(& my_file) ;
    ...
}
```

4.7 Driver (Module)

4.7.1 Manipulation

Manipulation

Set of tools to manipulate modules ⇒ modutils (kernel 2.4) or module-init-tools (kernel 2.6):

- lsmod : listing of modules loaded in the kernel;
- ins,rmmod : manual insertion/extraction of a module in the kernel;
- modprobe : automatic insertion/extraction of a module in the kernel with dependency resolving (loading all needed modules);
Manipulation

- modinfo : general information about a module (ex : author, description, parameters...);
- depmod : generate a list of dependencies for a set of modules;

Modules are automatically loaded when it is needed according to hotplug mechanism that run modprobe in user mode.

4.7.2 Basic Routines

Basic Macros

Descriptions and parameters managed by dedicated macros (<linux/module.h>):

- MODULE_AUTHOR() ;
- MODULE_DESCRIPTION() ;
- MODULE_LICENSE() ;
- MODULE_PARM() ;
- MODULE_PARM_DESC().

In kernel 2.6, MODULE_PARM() is replaced by (<linux/moduleparam.h>):

- module_param(name, type, perm);

Ex: MODULE_PARM(my_integer, "i") ; MODULE_PARM_DESC(my_integer, "My integer parameter");

Initialisation and release

Macros defined in file <linux/init.h>:

- module_init(): declaration of initialisation function (type int foo(void) ;);
- module_exit(): declaration of quitting function (type void foo(void) ;).

MODULE is a constant that allow the compiler to make the difference between module versus in kernel compilation (no use for you!).

Implementation

The initialisation function must contain all necessary information and computation to initialise a module (ex : allocations, hardware initialisations, resources reservation...);

In the opposite, exiting function must undo all the things done by initialisation one (ex : freeing reserved memory, hardware deactivation, freeing resources...);
routines

Linux uses optimisations of GCC to free in memory some unused part of the code after they have been instantiated (<linux/init.h>):

- **__init**: initialisation functions (freed after finishing module_init())
- **__exit**: exit functions (ignored if statically linked to the kernel)
- **__initdata**: used data in initialisation functions (freed after finishing module_init())
- **__exitdata**: used data in exit functions (ignored if statically linked to the kernel)

Ex:

```c
int __init my_function_init(void)
{
    /* ...code... */
}
module_init(my_function_init);
```

Usage counter

Each module is associated to a usage counter:
- Avoid that a module is unloaded while being used.
- Counter modification is done when the module is called.

The module can be manipulated with functions described in (<linux/module.h>):

- MOD_INC_USE_COUNT: increase the usage counter
- MOD_DEC_USE_COUNT: decrease the usage counter
- MOD_IN_USE: bring the value of the usage counter.

Kernel 2.6 provides instead (<linux/module.h>):

- try_module_get(THIS_MODULE): try to increase the usage counter.
- module_put(THIS_MODULE): decrease the usage counter.
- module_refcount(THIS_MODULE): bring the value of the usage counter.

Symbols

Exported symbols by the kernel are available in /proc/ksyms (/proc/kallsyms in 2.6):
- Used by insmod to do dynamical linking.
- Most of the symbols are exported in kernel/ksyms.c.
- Modules can declare new symbols according to macro EXPORT_SYMBOL() (<linux/module.h>):
  ksym tool give a more precise and readable view of /proc/ksyms.
Integration to kernel sources
  Choose an appropriate directory in kernel tree;
  Create a sub-tree if necessary (ex: many elements);
  In 2.4, edit Config.in and Makefile files of upper directory;
  En 2.6, edit Kconfig et Makefile files of upper directory;
  Add an entry inspired by the other;
  Add a help entry in Documentation/Configure.help (2.6 only, in 2.6 content
  is in Kconfig)
  Syntax is defined in Documentation/kbuild/...;

Implementation basic routines
  In kernel 2.4, while a statical compilation, parameters of a module must be
  defined by macro __setup() (in <linux/init.h>):
  void __setup (char *append, int (*extract) (char *));
  In kernel 2.6, module_param() automatically do this, parameters are di-
rectly given as inline parameter with :\[6mm\] module.param=valeur

Practical
  Creation of the simplest module (HelloWorld);
  Add some parameters to this module;
  Link it to the kernel in a static point of view.

4.7.3  Char Devices

File systems
  You can access to drivers with the use of specials files (device nodes also
called inode);
  A structure file_operations provide a way to define any entry point (<linux/fs.h>)
  ;
  Access classic functions can be overloaded by driver own access functions;

Structure Associated
  Initialisation of structure variables is done with the new C syntax (.var =
value) (in old times a specificity of GCC)
  Some not implemented methods are replaced by default functions (ex: open(), close())
  Others not implemented functions return -EINVAL;
  Ex:

```c
static struct file_operations mondriver_fops = {
  .owner = THIS_MODULE,
  .read = mondriver_read,
  .write = mondriver_write,
  .open = mondriver_open,
  .release = mondriver_release};
```
Majors et minors

Special files are created with command mknod;
A *inode* file is described by a unique identifier (*i_rdev*, of type *kdev_t*, size 16 bits in 2.4, 32 bits in 2.6) separated in two numbers (8+8 / 12+20):
  * major : identifier of the driver kind (ex : IDE, /dev/hd* ⇒ Major=3),
  * minor : identifier of one driver in a set (ex : IDE, /dev/hda1 ⇒ minor=1).
Majors 0 to 255 are reserved;

Majors and minors

List of majors and minors already used is updated in Documentation/devices.txt and `<linux/major.h>`;
Macros MAJOR() and MINOR() allow you to know what are these informations of your inode;
Ex :

```c
static int mndriver_open(struct inode *inode, 
            struct file *file)
{
    unsigned int minor = MINOR(inode-$>$i_rdev);
    /* or file-$>$f_dentry-$>$d_inode-$>$i_rdev */
}
```

Kernel 2.6 have also functions : imajor(inode) and iminor(inode)

Majors and minors

Classical use, a major describes one driver for a specific device;
Minors are used to identify different devices of the same kind or controlled sub-set;
Can manage same maje identical cards with this habit:
  * structures that describes each device (ex : buffers, mutex... );
  * array of structures indexed with minors;
  * n files in /dev with the same major and different minors.

Returning Value

Negative means error defined in `<linux/errno.h>` and `<asm/errno.h>`;
Positive or zero means working;
This standard is used in every functions in the kernel; Error values transmitted between each functions;
**Returning Value**

Ex: invalid argument

```c
if (arg > 3) return -EINVAL ;
```

Ex: error transmission

```c
int ret ;
ret = fonction\_noyau() ;
if (ret < 0) return ret ;
```

### 4.7.4 Memory Management

**Data Transfer kernel/user**

Kernel uses physical or virtual memory;
Processes use their own virtual memory space;
Need to transfer data from/to kernel memory space to/from calling process memory space;
Main functions are:

- `get, put_user()`: transfer a variable from/to user memory space (using with lvalue), and
- `copy_{from,to}_user()`: transfer a buffer from/to user memory space.

**Data Transfer kernel/user**

These functions are all calling function `access_ok()` that checks validity of a user buffer;
This call can be avoided if we used those functions prefixed by `_` (not advised). Prototypes (`<asm/uaccess.h>`):

- `int get_user (lvalue, addr)`;
- `int put_user (expression, addr)`;
- `void copy_{from,to}_user (unsigned long dest, unsigned long src, unsigned long len)`;
- `int access_ok (int type, unsigned long addr, unsigned long size)`;

### 4.7.5 Xenomai a RTOS example

### 4.7.6 Description

**Motivations**

- Linux based (GPL)
- Developing tools (Multi-Interfaces)
• Dynamic community (Forum and mailing list)\(^1\)

**Main Structure**

• Patched Kernel (ADEOS)
• HAL
• nucleus
• Multi-skins
  - RTAI,
  - VXWorks,
  - POSIX,
  - RTDM,
  - pSOS+, 
  - VRTX,
  - uITRON ...

**Architecture**

\(^1\)Quality to be observed when we want to use a free tool in long term point of view
ADEOS - Virtual Domains

```
void realtime_eth_handler (unsigned irq, void *cookie)
{
    rthal_irq_enable(irq);
    rthal_irq_host_pend(irq);
    /* This irq has been marked as pending for Linux */
}
void linux_eth_handler (int irq, void *dev_id, void *cookie, struct pt_regs *regs)
{
    /* process the IRQ normally. */
}
```

ADEOS - Applied to Xenomai

ADEOS - HAL to manage communications

NATIVE API - Main

- Compactness: <100 services
- Orthogonality:
  - developer memory :)
- Non-ambiguity
- More functions combination than more complex functions

- Context independent :
  - Kernel Space
  - User space : privileged

- Small Semantic for localisation : Same names
  - Kernel (ex. xeno_native.ko),
  - User (ex. libnative.so)

**NATIVE API - Services**

- Tasks Management
- Time Service
- Synchronisation tools
- Messages and communication
- Control I/O
- Registers

**NATIVE API - Services**

- Tasks Management
  - Increasing Priorities 1-99

- Time Service
  - Timers,
  - Time,
  - **Alarm**...

- Synchronisation tools
  - Counting Semaphores,
  - Mutex,
  - Conditional Variables,
  - Event Flags
NATIVE API - Services

- Message and communication
  - Inter-tasks synchronous Messages
  - Messages queue
  - Pipes : Message streaming
- I/O control
  - Interruptions
  - Heap memory
  - Memory Access of a device in user space
- Registers
  - Small semantic, developer basis
  - /proc/xenomai/registry/...

NATIVE API - Compilation Flags

```
CFLAGS=$( shell xeno-config --xeno-cflags )
LDFLAGS= -lnative $( shell xeno-config --xeno-ldflags )
```

```
myapp : myapp.c
  $(CC) -o $@ myapp.c $(CFLAGS) $(LDFLAGS)
```

4.7.7 Main Mechanisms

Common Functions

- Create / Delete
- Bind / Unbind ⇒ Registry and binding
- Inquire ⇒ Inquiries

Registry and binding

Multiple processes unified sharing of objects.
In Kernel Space and in User Space (T_PRIMARY).

- "/proc/xenomai/registry”
- int rt_object_bind (RT_OBJECT *obj, const char *name, RTIME timeout)
- static int rt_object_unbind (RT_OBJECT *obj)

Ex:
main1.c:
RT_TASK t;
rt_task_create(&t,"myTask",0,0,0);

main2.c:
RT_TASK *tt;
rt_task_bind(tt,"myTask",(RTIME)10000);
... Execution ...
rt_task_unbind(tt);

Inquiries
State informations of any object.

- int rt_object_inquire (RT_OBJECT *obj, RT_OBJECT_INFO *info)

Ex:

... RT_TASK *curtask;
RT_TASK_INFO curtaskinfo;
curtask=rt_task_self();
rt_task_inquire(curtask,&curtaskinfo);
rt_printf("Task name : %s \n", curtaskinfo.name);
...

RTDK
Introduces a collection of utilities aimed at forming a Real-Time Development Kit for userland usage.

int rt_vfprintf(FILE *stream, const char *format, va_list args);
int rt_vprintf(const char *format, va_list args);
int rt_fprintf(FILE *stream, const char *format, ...);
int rt_printf(const char *format, ...);
int rt_print_init(size_t buffer_size, const char *name);
void rt_print_cleanup(void);
void rt_print_auto_init(int enable);
const char *rt_print_buffer_name(void);

4.7.8 RTDM
Real Time Driver Model RTDM

- User API

- Driver Development API
  - Inter-_driver API
  - Device Registration Services + Synchronisation Services
- Clock Services
- Task Services
- Timer Services
- Synchronisation Services
- Interrupt Management Services
- Non-Real-Time Signalling Services
- Utility Services

• User API
• Driver Development API
  - Inter-Driver API
  - Device Registration Services + Synchronisation Services
  - Clock Services
  - Task Services
  - Timer Services
  - Synchronisation Services
  - Interrupt Management Services
  - Non-Real-Time Signalling Services
  - Utility Services

Real Time Driver Model

• Device Profiles
  - CAN Devices
  - Serial Devices
  - Testing Devices

5 Application

5.1 Examples

5.1.1 Examples

MC2e

• Aim :
  - Surgical Robotics
  - 3rd Hand
- Minimal invasive operation
- Co-manipulation

- Technical notes:
  - Spherical kinematics
  - Force based robot

### MC2e: Tasks Architecture

![MC2e Schematic Diagram](image_url)
MC2e : Synchro Solution

Only one shared memory with all the state and command information. ⇒ leads to only one synchronization mechanism

Monimad : Description

- Aim :
  - Sit-To-Stand
  - Walking
  - disbalance recover
  - Old and Diseased people
  - Assistance
Monimad : Tasks Architecture

Elements :
- CAN Bus
- Force Sensors (Serial, Acquisition card)
- UI

Monimad : Synchro Solutions
Cardiolic: Description

- Aim:
  - Heart Surgery
  - Compensation
  - Visual Servoing

- Technical information:
  - 2000Hz
  - PiezoElectric Actuator
  - High frequency camera

Cardiolic: Tasks Architecture

Elements:
- GUI
- Camera Driver
- Threads
RobModex : Description

- Aim :
  - Pedagogic Solution
  - Polytechnique School of Engineering (Palaiseau)
- Technical
  - Fixed Wheel Structure
  - Usb Camera

RobModex : Tasks
Elements:
- USB Driver
- Threads

RobModex: Synchro Solution

Notice: There is no Synchronization needed

6 Documentations

6.1 Doc

6.1.1 Interface with community

Documentation
The Documentation/ directory in kernel sources;
The documentation Linux project

- LDP "http://www.tldp.org": guides, HOWTOs, FAQs, manpages...

Personal web sites of maintainers (see newsgroups);
Other documents from web (http://www.google.com/linux/).

**Information**

Specialised Mailing Lists (newsgroups http://www.uwsg.indiana.edu/search/):
- linux-kernel,
- kernel-newbies,
- linux-net...;

Week summary of discussions of linux-kernel mailing list:
- Kernel Traffic (http://kt.zork.net/kernel-traffic/), and
- Kernel Notes (http://www.kernelnotes.org).

**Interface with community**

FAQ Linux kernel (http://www.tux.org/lkml/);
Discussion Forums: comp.os.development.kernel...;
Personal email maintainers or authors of a part of source code.

6.1.2 References

**References**

Use the source, Luke!
The answer of all your questions are inside the kernel sources...

**References**

Books - Linux Device Drivers 2nd edition (O'Reilly) http://www.xml.com/1dd/chapter/book/index.html:
- Understanding the Linux Kernel (O'Reilly):
- "Programmation Linux 2.0" (Eyrolles).
References

E-Books - Linux Kernel Internals (kernel 2.4) [http://www.tldp.org/LDP/lki/]:

- Linux Kernel Module Programming Guide (kernels 2.0 et 2.2) [http://www.tldp.org/LDP/lkmpg/]:
- Linux Kernel Hackers’ Guide (kernels 2.0 et 2.2) [http://www.tldp.org/LDP/khg/]:
- The Linux Kernel (kernel 2.0) [http://www.tldp.org/LDP/tlk/]:
- The Linux Programmer’s Guide (API user space) [http://www.tldp.org/LDP/lpg/].

References

Articles and documents

- Articles on how import drivers from 2.4 to 2.6 [http://lwn.net/Articles/driver-porting/]
- Links of kernelnewbies [http://www.kernelnewbies.org/links/]:
- Articles of kerneltrap [http://kerneltrap.org/]:
- Conceptual architecture of Linux Kernel [http://plg.uwaterloo.ca/~itbowman/CS746G/a1/]:
- Concrete architecture of Linux kernel [http://plg.uwaterloo.ca/~itbowman/CS746G/a2/].

References

- http://www.xenomai.org
  - Native-API-Tour-rev-C.pdf
  - Life-with-Adeos-rev-B.pdf
  - RTDM-and-Applications.pdf
6.1.3 Licences

GPL

GNU General Public License (GPL) Maintained et defended by Free Software Foundation (FSF);
Give the right (and it is also a duty !) to copy, modify et redistribute the software only under the same licence terms (GPL).
This rule includes also software linked to codes licensed under GPL;
No free of charge are described, only freedom in using;
It is possible to sell a software under GPL but not to forbid them to modify it and redistribute (free of charge or not).

LGPL

• GNU Lesser General Public License (LGPL) Maintained and defended by Free Software Foundation (FSF);
• Less restricted than GPL ; Possibility to call LGPL code from a non-free program (ex : software under licence incompatible with GPL);
• Used mainly for libraries (ex : GNU libC).

Others

• Licence of Linux kernel is GPL with added terms;
• Core of the kernel is GPL;
• But using and redistribution of binaries only inside are allowed;
• Must fit with standard interfaces of modules;
• A lot of work has been done to clarify the GPL/non GPL frontier : EXPORT_SYMBOL_GPL, MODULE_LICENSE...

Licences

Technically very difficult to provide compatible binary modules because of all possible configurations of the kernel (ex : versions, external patches...); Legal but not advised (no support from community).

6.1.4 Glossary

• API, Application Programming Interface:
• AVL, Adelson-Velskii and Landis : binary tree structure always balanced that allow researches in O(log n) where a classic research is in O(n):
• **BE**, Big-Endian: bytes organization where most significant byte (MSB) are stored before less significant bytes (LSB).

• **DMA**, Direct Memory Access: Mechanism in Computer that bring the ability to avoid the CPU to be used when we want data transfer between central memory and devices;

• **FAQ**, Frequently Asked Questions: the document to be read before asking any question on a mailing list:

• **FSF**, Free Software Foundation: association that aim to defend and promote free-ware (on GPL and LGPL Licenses):

• **GPL**, General Public Licence: free license of Free Software Foundation:

• **IP**, Internet Protocol: (level 3 in OSI Model) based best effort principle,

• **IRQ**, Interrupt ReQuest:

• **ISDN**, Integrated Services Digital Network: numerical network that can transport voice or data:

• **LE**, Little-Endian: bytes organization where less significant byte (LSB) are stored before most significant bytes (MSB),

• **LGPL**, Lesser General Public Licence: free licence of Free Software Foundation mainly used for libraries:

• **OSI**, Open System Interconnect: layer model bringing a conceptual and standardize for exchanging between different operating systems;

• **POSIX**, Portable Operating System for Computer Environment: Unix Standard from IEEE (number 1003.1) that specify system kernel; it is composed of extensions for real-time kernel (1003.1-b) and threads (1003.1-c):

• **PLIP**, Parallel Line Internet Protocol: communication protocol on parallel port used to embed IP communications through parallel lines:

• **PPP**, Point to Point Protocol: communication protocol used to embed communications on serial lines (ex: modem):

• **SLIP**, Serial Line Internet Protocol: communication protocol used to embed IP communications on serial lines (ex: modem);
• SMP, Symmetric Multi-Processing: use of multiple same CPU that share the same resources (memory...) and devices in one operating system \(\Rightarrow\) transparent for users:

• TCP, Transmission Control Protocol: (4th level in OSI model) working in connected mode:

• VFS, Virtual File System: abstraction layer in high level part of the kernel to enable fast writing on file systems;