Time-Driven Systems
(following Jane Liu, Real-Time Systems)
**Time-Driven Scheduling**

properties:

- decisions, which job to execute next at specific time instants
- these are chosen a priori (before system begins execution)
- schedule is computed off line

typically “restrictive” assumptions: “deterministic” systems

- fixed number of tasks in systems
- with a priori fairly well known parameters (fixed inter-release times)
- tasks must be ready at their release times
- usually used for safety-critical, hard real-time systems !!!
Deriving a Schedule

sufficient to find schedule for hyperperiod ...
which is called a cyclic schedule

eample: Tasks: \((P_i, e_i)\):
\((4,1)\)  \((5,1.8)\)  \((20,1)\)  \((20,2)\)

- Hyperperiod: 20
- arbitrary possible schedule for one Hyperperiod:

Unused parts can be used for aperiodic jobs
Executing a Schedule

store all decision points \((t_i, T(t_i))\) in table.

Do

- set timer to next decision point
- run current job in table
- wait for timer

Done

“cyclic schedule”

note: scheduling decisions at instants in time (not events!)

contrast:
- priority driven systems scheduling decisions at events
Frames

Scheduling decisions only at periodic instants of time
no preemption within frames (in the normal case)
check for violations etc. at frame borders
frame size ?
Frame Size $f$

1: At least one period should be multiple of $f$
2: $f \geq \max(e_i)$ (avoids preemption)
3: one full frame (two boundaries) between release time ($t'$) and deadline ($D$) for each job in all periods to enable the scheduler checks before deadline

\[ t \quad t+f \quad t+2f \]

\[ t' \quad t'+D \]
Frame Size $f$

1: At least one period should be multiple of $f$
2: $f \geq \max(e_i)$ (avoids preemption)
3: one full frame (two boundaries) between release time ($t'$) and deadline ($D$) for each job in all periods to enable the scheduler checks before deadline

more critical case: $t' > t$: $t + 2f \geq t' + D$
Examples

(4,1) (5,1.8) (20,1) (20,2)

(4,1) (5,2) (20,5)
Slices

decompose jobs in slices
subroutines
cut messages into segments ...

(4,1) (5,2) (20,5);
cut (20,5) in (20,1) (20,3) (20,1)
Frame size: 4

Problems:
→ If T1 in Job 2 does not fully use its wcet, T2 runs early
→ If T2 (Job 3, in 13,15) overruns, scheduler detects at 16
Alternative

better:
(4,1) (5,2) (20,5);
cut (20,5) in (20,1) (20,1) (20,2) (20,1)
frame: 2
A Cyclic Executive

Current time \( t := 0 \); current frame \( k := 0 \);

at every \( f \) time units DO

- get jobs, slices from cyclic schedule
  \( t := t + f \); \( k := t \mod \text{hyperperiod} \);
- if last jobs, slices have not completed properly, do something
  execute things ... 

Take care about aperiodic jobs

DONE
Accommodating Aperiodic Jobs

Use time not allocated to slices
objective: improve response time of aperiodic jobs
“slack stealing”: execute aperiodic jobs before periodic
Accommodating Sporadic and Aperiodic Jobs

assumptions: deadline, wcet: \(S(d,e)\) known, jobs preemptable

example:
  Remove defective part from conveyer belt ... if possible
  Otherwise stop the belt.

At execution time:
  Acceptance test:
    \[\text{sum(slack times in all frames before } d) \geq e\]
  Generate “slices” that fit in frames
  Static: put slices in frames
  Dynamic: queue according to EDF (after succ. acceptance test!)
Practicalities

Frame overruns ...
incomplete test ...
transient faults ...
what to do:
transpose overrunning job
  (may be ok for robust controllers)
suspend overrunning job/slice and resume it in next frame
  where it has allocation
continue overrunning job into next frame
Mode Changes

Task system static per “operational mode”.
example: aircraft control: taxi, start, fly, land
Precomputation of all envolved schedules.
Reconfiguration when mode changes.
cyclic schedule must be exchanged
code and data of new tasks must be brought in
use old schedule during reconfiguration, then switch
hard/soft mode changes ...
Additional Topics

conceptually simple:
• precedence constraints
• no concurrency control mechanisms
e.g. mutexes (no priority inversion problem)
• known cache interference (context switching)
• several processors (if global time available)
not so simple, but feasible (later in this lecture):
communication on shared bus
time division multiple access (TDMA)
replica determinism
reintegration of nodes after faults
deriving a schedule in the general case is NP-Hard
Important Variant: Time Partitioned Systems
Summary

Static ... Mode changes
conceptually simple
easy to test, validate, certify.

Fixed inter-release times