

***TASKING***<sup>®</sup>

***Using the TASKING RTOS for  
TriCore***

Copyright © 2016 Altium BV.

All rights reserved. You are permitted to print this document provided that (1) the use of such is for personal use only and will not be copied or posted on any network computer or broadcast in any media, and (2) no modifications of the document is made. Unauthorized duplication, in whole or part, of this document by any means, mechanical or electronic, including translation into another language, except for brief excerpts in published reviews, is prohibited without the express written permission of Altium BV. Unauthorized duplication of this work may also be prohibited by local statute. Violators may be subject to both criminal and civil penalties, including fines and/or imprisonment. Altium, TASKING, and their respective logos are trademarks or registered trademarks of Altium Limited or its subsidiaries. All other registered or unregistered trademarks referenced herein are the property of their respective owners and no trademark rights to the same are claimed.

# Table of Contents

Manual Purpose and Structure .....	vii
1. Introduction to the RTOS Kernel .....	1
1.1. Real-time Systems .....	1
1.2. Real-time Operating System .....	1
1.3. ISO 17356 .....	2
1.3.1. Operating System (OS) .....	2
1.3.2. Communication (COM) .....	3
1.3.3. Implementation Language (OIL) .....	3
1.3.4. Run Time Interface (ORTI) .....	3
1.3.5. The ISO 17356 Documentation .....	3
1.4. The TASKING RTOS .....	3
1.4.1. Why Using the TASKING RTOS? .....	4
2. Getting Started .....	5
2.1. What is an RTOS Project? .....	5
2.2. Creating an RTOS Project .....	7
2.3. Configuring the RTOS Objects and Attributes .....	8
2.4. Generate RTOS Code .....	10
2.5. TASKING RTOS Configurator Preferences .....	11
2.6. Edit the Application Files .....	11
2.7. Set the Project Options .....	12
2.8. How to Build an RTOS Application .....	13
2.9. How to Debug an RTOS Application .....	13
3. RTOS Objects and Attributes .....	15
3.1. What are the OIL System Objects? .....	15
3.1.1. Standard and Non-Standard Attributes .....	15
3.1.2. Overview of System Objects and Attributes .....	15
3.1.3. Non-Standard Attributes for the TriCore .....	17
4. Startup Process .....	19
4.1. Introduction .....	19
4.2. System Boot .....	19
4.3. The main() Module .....	20
4.3.1. What are Application Modes? .....	20
4.4. RTOS Initialization .....	20
4.5. Shut-down Process .....	21
4.6. API Service Restrictions .....	23
5. Task Management .....	25
5.1. What is a Task? .....	25
5.2. Defining a Task in the C Source .....	25
5.3. The States of a Task .....	26
5.4. The Priority of a Task .....	26
5.4.1. Virtual versus Physical Priorities .....	27
5.4.2. Fast Scheduling .....	29
5.5. Activating and Terminating a Task .....	29
5.6. Scheduling a Task .....	32
5.6.1. Full-preemptive Tasks .....	32
5.6.2. Nonpreemptive Tasks .....	33
5.6.3. Scheduling Policy .....	33
5.7. The Stack of a Task .....	36

## Using the *TASKING RTOS* for *TriCore*

5.8. C Interface for Tasks .....	37
6. Events .....	39
6.1. Introduction .....	39
6.2. Adding Events .....	39
6.3. Using Events .....	40
6.4. The C Interface for Events .....	44
7. Resource Management .....	47
7.1. Key Concepts .....	47
7.2. What is a Resource? .....	48
7.3. The Ceiling Priority Protocol .....	55
7.3.1. Priority Inversion .....	55
7.3.2. Deadlocks .....	56
7.3.3. Description of The Priority Ceiling Protocol .....	56
7.4. Grouping Tasks .....	58
7.5. The Scheduler as a Special Resource .....	61
7.6. The C Interface for Resources .....	62
8. Alarms .....	63
8.1. Introduction .....	63
8.2. Counters .....	63
8.2.1. What is a Counter? .....	63
8.2.2. The RTOS System Counter .....	64
8.3. What is an Alarm? .....	66
8.4. The C Interface for Alarms .....	71
9. Interrupts .....	73
9.1. Introduction .....	73
9.2. The ISR Object .....	73
9.2.1. The ISR Non-Standard Attribute LEVEL .....	74
9.3. Defining an Interrupt in the C Source .....	74
9.4. The Category of an ISR Object .....	74
9.5. Nested ISRs .....	75
9.6. ISRs and Resources .....	76
9.7. ISRs and Messages .....	78
9.8. Interrupt Disable/Enable Services .....	79
9.8.1. Disable/Enable All Interrupts .....	79
9.8.2. Suspend/Resume All Interrupts .....	81
9.8.3. Suspend/Resume OS Interrupts .....	82
9.9. The C Interface for Interrupts .....	83
10. Communication .....	85
10.1. Introduction .....	85
10.2. Basic Concepts .....	86
10.3. Configuring Messages .....	87
10.4. Message Transmission .....	90
10.4.1. Sending a Message .....	90
10.4.2. How to Define the Data Type of a Message .....	90
10.4.3. Receiving a Message .....	91
10.4.4. Initializing Unqueued Messages .....	94
10.4.5. Long versus Short Messages .....	97
10.5. Message Notification .....	97
10.5.1. Notification Example: Activate Task .....	98
10.5.2. Notification Example: Set Event .....	100

10.5.3. Notification Example: Flag .....	100
10.5.4. Notification Example: Callback .....	103
10.6. Starting and Ending the COM .....	104
10.6.1. Starting the COM .....	104
10.6.2. Starting the COM Extension .....	105
10.6.3. Stopping the COM .....	105
10.7. The C Interface for Messages .....	106
11. Error Handling .....	107
11.1. Introduction .....	107
11.2. Error Handling .....	107
11.2.1. Standard Versus Extended Status .....	107
11.2.2. Fatal Errors .....	108
11.2.3. The ErrorHook Routine .....	108
11.2.4. The COMErrorHook Routine .....	112
11.3. Debug Routines .....	114
11.4. RTOS Configuration Examples .....	115
12. Debugging an RTOS Application .....	117
12.1. Introduction .....	117
12.2. How to Debug the System Status .....	117
12.3. How to Debug Tasks .....	119
12.4. How to Debug Resources .....	120
12.5. How to Debug Alarms .....	121
12.6. How to Debug ISRs .....	121
12.7. How to Debug Messages .....	122
12.8. How to Debug Contexts .....	122
12.9. How to Debug Stacks .....	123
13. Implementation Parameters .....	125
13.1. Introduction .....	125
13.2. Functionality Implementation Parameters .....	125
13.3. Performance Implementation Parameters .....	127
13.3.1. ISR Latency .....	127
13.3.2. Context Switch Latency .....	128
13.3.3. System Timer Latency .....	129



# Manual Purpose and Structure

## Manual Purpose

This manual aims to provide you with the necessary information to build real-time applications using the RTOS (Real Time Operating System) micro kernel delivered with the toolset. This kernel implements designated parts of the ISO 17356 standard.

After reading the document, you should:

- know how the RTOS is implemented by Altium,
- understand the benefits of using the RTOS,
- know how to build real-time RTOS applications,
- be able to customize RTOS settings in the Eclipse IDE to your project needs,
- be familiar with the most relevant RTOS concepts,
- know how to debug RTOS applications.

This manual assumes that you have already read the User's Manual of the toolset documentation. The manual leads you through the hottest topics of configuring and building RTOS applications, overview of the functionality, design hints, debugging facilities and performance.

This manual expects you to have gone through the main topics of the online ISO 17356 standard documents. These documents should be, in fact, a constant reference during the reading of this manual. Please refer to <http://www.iso.org/>.

## Manual Structure

### **Chapter 1, *Introduction to the RTOS Kernel***

Provides an introduction to the RTOS real-time multitasking kernel and provides a high-level introduction to real-time concepts.

### **Chapter 2, *Getting Started***

Contains an overview of the files (and their interrelations) involved in every RTOS application and includes a self explanatory diagram of the development process as a whole. Describes also how you can build your very first RTOS application guiding you step by step through the process.

### **Chapter 3, *RTOS Objects and Attributes***

Describes the available RTOS objects and attributes you can configure in the TASKING RTOS Configurator.

## **Using the TASKING RTOS for TriCore**

### **Chapter 4, Startup Process**

Opens the black-box of what happens in the system since application reset until the first application task is scheduled and describes how you can interact with the start-up process by customizing certain Hook Routines.

### **Chapter 5, Task Management**

Explains how the RTOS manages tasks ( scheduling policies, tasks states, ..) and describes how you can declare TASK objects in the TASKING RTOS Configurator in order to optimize your task configuration.

### **Chapter 6, Events**

Explains how the RTOS may synchronize tasks via events and describes how you can declare EVENT objects in the TASKING RTOS Configurator in order to optimize your event configuration.

### **Chapter 7, Resource Management**

Explains how the RTOS performs resource management (resource occupation, ceiling priority protocol, internal resources,..) and describes how you can declare RESOURCE objects in the TASKING RTOS Configurator in order to optimize your resource configuration.

### **Chapter 8, Alarms**

Describes how the RTOS offers alarm mechanisms based on counting specific recurring events and describes how you can declare these objects in the TASKING RTOS Configurator in order to optimize your alarm configuration.

### **Chapter 9, Interrupts**

Describes how you can declare ISR objects in the TASKING RTOS Configurator in order to optimize the interrupt configuration.

### **Chapter 10, Communication**

Describes the communication services to offer you a robust and reliable way of data exchange between tasks and/or interrupt service routines and how you can declare MESSAGE and COM objects in the TASKING RTOS Configurator.

### **Chapter 11, Error Handling**

Helps you to understand the available debug facilities and error checking possibilities. Describes which services and mechanisms are available to handle errors in the system and how you can interact with them by means of customizing certain Hook Routines.

### **Chapter 12, Debugging an RTOS Application**

Explains how you can debug RTOS information and describes in detail all the information that you can obtain.



**Chapter 13, *Implementation Parameters***

The implementation parameters provide detailed information concerning the functionality, performance and memory demand. From the implementation parameters you can obtain information about the impact of the RTOS on your application.



# Chapter 1. Introduction to the RTOS Kernel

This chapter provides an introduction to the RTOS real-time multitasking kernel and provides a high-level introduction to real-time concepts.

## 1.1. Real-time Systems

A real-time system is used when there are rigid timing requirements on the operations of a processor to perform certain tasks. Real-time applications perform an action or give an answer to an external event in a timely and predictable manner. They cover a wide range of tasks with different time dependencies.

The timing requirements of actions usually differ between real-time applications; what may be fast for one application may be slow or late for another. In all cases, there should be well-defined time requirements.

The concept of *predictability* for real-time applications generally means that a task or set of tasks must always be completed within a predetermined amount of time. Depending on the situation, an unpredictable real-time application can result in loss of data or loss of deadlines.

There are two flavors of real-time systems:

- A *hard real-time* system must guarantee that critical tasks complete on time. Processing must be done within the defined constraints or the system will fail.
- A *soft real-time* system is less restrictive. In a soft real-time system, failure to produce the correct response at the correct time is also undesirable but not fatal.

Many real-time applications require high I/O throughput while still guaranteeing a fast response time to asynchronous external events. The ability to schedule tasks rapidly and implement secure communication mechanisms among multiple tasks becomes crucial.

Real-time applications are usually characterized by a blend of requirements. Some parts of the application may consist of hard, critical tasks which must meet their deadlines. In reality, most applications consist of tasks with both hard and soft real-time constraints. The key to a successful real-time application is your ability to accurately define application requirements at every point in the program.

## 1.2. Real-time Operating System

As explained, most applications consist of tasks with both hard and soft real-time constraints. If these tasks are single purposed, you could implement them as semi-independent program segments. Still you would need to embed the processor allocation logic inside the application tasks. Implementations of this kind typically take the form of a control loop that continually checks for tasks to execute. Such techniques suffer from numerous problems and do not represent a solution for regular real-time applications. Besides, they complicate the maintenance and reusability of the software.

A Real Time Operating System (RTOS) is a dedicated operating system fully designed to overcome the time constraints of a real-time system. An RTOS, like any other operating system, provides an environment in which you can execute programs in a convenient and structured manner, but without the risk of failing the real-time constraints.

## Using the *TASKING RTOS* for *TriCore*

In general, the benefits of using an RTOS are:

- An RTOS eliminates the need for processor allocation in the application software.
- Modifications, or additions of completely new tasks can be made in the application software without affecting critical system response requirements.
- Besides managing task execution, most real-time operating systems also provide facilities that include task communication, task synchronization, timers, memory management etc.
- An RTOS hides the underlying hardware specific concerns to the user offering a run-time environment that is completely independent of the target processor.
- Easy migration to other targets (provided that the RTOS vendor offers support for these other processor families).

### 1.3. ISO 17356

ISO 17356 is the open interface for embedded automotive applications. Although the ISO 17356 standards were originally developed for the automotive industry, the resulting specifications describe a small real-time OS ideal for most embedded systems that are statically defined, i.e. with no dynamic (run-time) allocation of memory.

The ISO 17356 specification consists of several documents:

- OS - operating system
- COM - communication
- NM - network monitoring (not discussed in this manual)
- OIL - implementation language

An ISO 17356 implementation refers to a particular implementation of one or more of the standards. These standards tend to define the minimum requirements for a compliant system but individual implementations can vary because of different processor requirements and/or capabilities.

#### 1.3.1. Operating System (OS)

The specification of the OS covers a pool of services and processing mechanisms. The operating system controls the real-time execution in concurrent executing applications and provides you with a dedicated programming environment. The architecture of the OS distinguishes three processing levels: an interrupt level, a logical level for operating system activities and a task level. The interrupt level is assigned higher priorities than the task level.

In addition to the management of the processing levels, the operating system offers also system services to manage tasks, events, resources, counters, alarms, and to handle errors. You can consider system services as library functions in C.

### **1.3.2. Communication (COM)**

The communication specification provides interfaces for the transfer of data within vehicle networks systems. This communication takes place between and within network stations (CPUs). This specification defines an interaction layer and requirements to the underlying network layer and/or data link layer. The interaction layer provides the application programming interface (API) of COM to support the transfer of messages within and between network stations. For network communication, the interaction layer uses services provided by the lower layers. CPU-internal communication is handled by the interaction layer only.

### **1.3.3. Implementation Language (OIL)**

To reach the original goal of having portable software, a way of describing an RTOS system is defined in the standardized OIL implementation language.

### **1.3.4. Run Time Interface (ORTI)**

To provide debugging support on the level of RTOS objects, it is necessary to have debuggers that are capable of displaying and debugging RTOS components. The ORTI specification provides an interface for debugging and monitoring tools to access RTOS objects in target memory. Tools can evaluate internal data structures of RTOS objects and their location in memory. ORTI consists of a language to describe kernel objects (KOIL: Kernel Object Interface Language) and a description of RTOS objects and attributes.

### **1.3.5. The ISO 17356 Documentation**

Information about the ISO standards is available online at <http://www.iso.org/>.

The TASKING RTOS is implemented to follow:

- OS Version 2.2.2
- COM Version 3.0.3
- OIL Version 2.5
- ORTI Version 2.1.1

## **1.4. The TASKING RTOS**

The TASKING RTOS is a real-time, preemptive, multitasking kernel, designed for time-critical embedded applications and is developed by Altium.

The TASKING RTOS supports a subset (internal communication) of COM3.0.

The RTOS is written in ISO C and assembly and is delivered as source code together with the TASKING RTOS Configurator.

For every RTOS application the RTOS source code is compiled (after some mandatory configurational input from the application developer) and linked as object files with your application.

### **1.4.1. Why Using the TASKING RTOS?**

The benefits of using the RTOS to build embedded applications are listed below:

- High degree of modularity and ability for flexible configurations.
- The dynamic generation of system objects is left out. Instead, generation of system objects is done in the system generation phase. The user statically specifies the number of tasks, resources, and services.
- Error checks within the operating system are omitted to not affect the speed of the overall system unnecessarily. However, a system version with extended error checks is available. It is intended for the test phase and/or for less time-critical applications.
- The interface between the application software and the operating system is defined by system services with well defined functionality. The interface is identical for all implementations of the operating system on various processor families.
- For better portability of application software, the ISO 17356 standard defines a language for a standardized configuration information. This language "OIL" supports a portable description of all RTOS specific objects such as "tasks" and "alarms".

# Chapter 2. Getting Started

This chapter contains an overview of the files (and their interrelations) involved in every RTOS application and includes a self explanatory diagram of the development process as a whole. It also describes also how you can build your very first RTOS application guiding you step by step through the process.

## 2.1. What is an RTOS Project?

An RTOS project is a normal project where you add a file written in the OIL language to the project (**File » New » TASKING RTOS Configuration**). This file has the extension `.tskoil` and contains the specific details of the system configuration. We refer to it as the 'application OIL file'. For more information about the RTOS objects and attributes, see [Chapter 3, RTOS Objects and Attributes](#).

Note that apart from the RTOS part in your project you can still use a Pin Mapper and/or Software Platform document in your project. See the RTOS example that is delivered with the product.

Only one of the project files can have the extension `.tskoil`. You can use the TASKING RTOS Configurator in Eclipse to modify the OIL file. When you are finished you can generate the RTOS code. This will copy the RTOS sources into the project and generate the configuration files. When you build the project these files will be compiled with the project source and linked into the application program.

The configuration files are generated by the TASKING OIL compiler (**toctc**). The OIL compiler uses the application OIL file together with the implementation OIL file from the RTOS Eclipse plugin.

The RTOS code is only rebuilt upon changes in the OIL file. When you save changes to the OIL file, the configuration files and RTOS source can be generated automatically.

In your application source code files you must include the standard OS and COM interfaces (`rtos/rtos.h`) to compile.

The following table lists the files involved in an RTOS project:

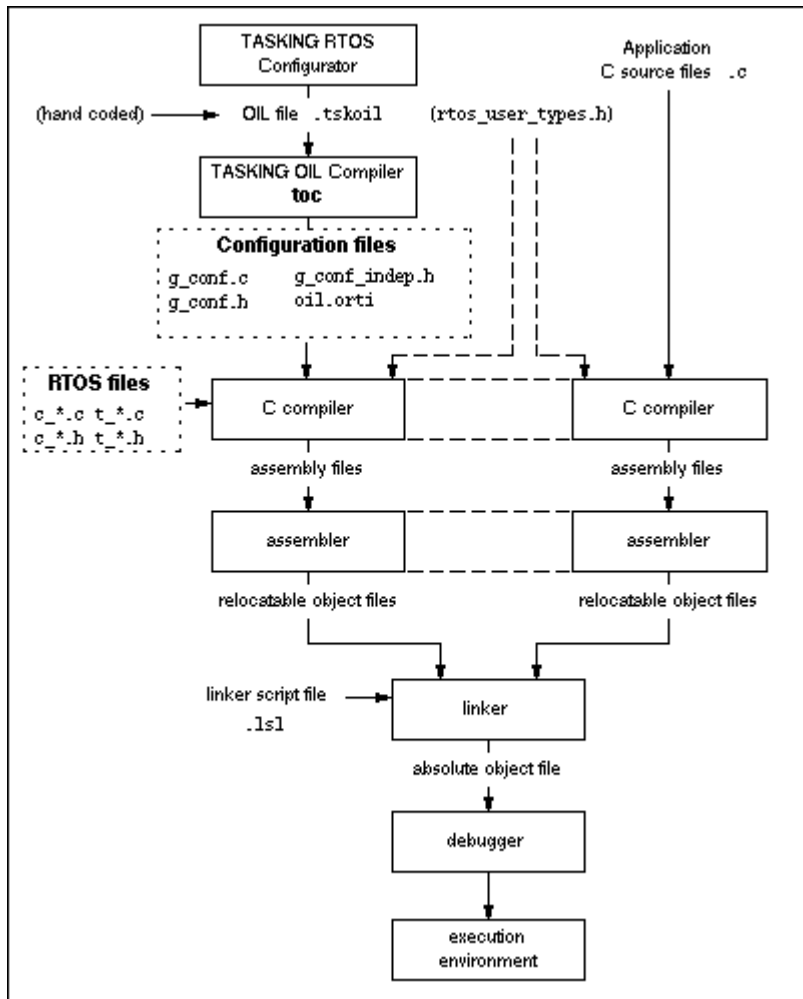
Extension	Description
<b>Application source files</b>	
<code>*.c / *.h / *.asm</code>	C source files, header include files and optional hand coded assembler files are used to write the application code. These files must be part of your project and are used to build application objects.
<code>rtos_user_types.h</code>	You need to write <code>rtos_user_types.h</code> when you use messages with non basic CDATATYPE attributes.
<b>The application OIL file and the configuration files</b>	
<code>user.tskoil</code>	You must write exactly one application OIL file to configure the RTOS code. It is the only <code>.tskoil</code> file of the project and contains the input for the TASKING OIL Compiler (TOC).

## Using the TASKING RTOS for TriCore

Extension	Description
<code>g_conf.c</code> <code>g_conf.h</code> <code>g_conf_indep.h</code> <code>flag.h</code> <code>oil.orti</code>	These configuration files are intermediate files (ISO C) generated by the TOC compiler after processing the OIL file. The files ( <code>g_*</code> ) are compiled together with the RTOS source files to build the RTOS objects of the project. The file <code>flag.h</code> is an extra interface for the application software. The file <code>oil.orti</code> is the run-time debug interface. They are rebuilt when you change your OIL file.
<b>RTOS source files</b>	
<code>c_*.c</code> <code>c_*.h</code> <code>t_*.c</code> <code>t_*.h</code>	The source code files of the RTOS are located in <code>\$(PRODDIR)/ctc/rtos/</code> . They are used by all the RTOS projects to build their RTOS libraries. They should never be removed or modified. When you generate RTOS code for your application, these files are copied to the <code>rtos</code> directory in your project.
<code>rtos.h</code>	The RTOS application interface <code>rtos.h</code> is located in <code>\$(PRODDIR)/ctc/rtos</code> and constitutes the only interface for your code as an RTOS user. It is copied to your the <code>rtos</code> directory in your project.
<b>Implementation OIL file</b>	
<code>rtos_impl.oil</code>	The implementation OIL file, which is present in the RTOS Eclipse plugin, is used by the TASKING OIL compiler for all RTOS applications. It imposes how and what can be configured in this current RTOS release. It should never be removed or modified.



The following figure shows the relation between the files in an RTOS project and the development process.



## 2.2. Creating an RTOS Project

1. First make sure you have an existing project. This is explained in the *Getting Started* manual of the toolset. In this example we assume you have a project called `myproject`.
2. From the **File** menu, select **New » TASKING RTOS Configuration**.  
*The New TASKING RTOS Configuration wizard appears.*
3. Select the **Project** folder for the RTOS configuration file: type the name of your project (`myproject`) or click the **Browse** button to select a project.

## Using the TASKING RTOS for TriCore

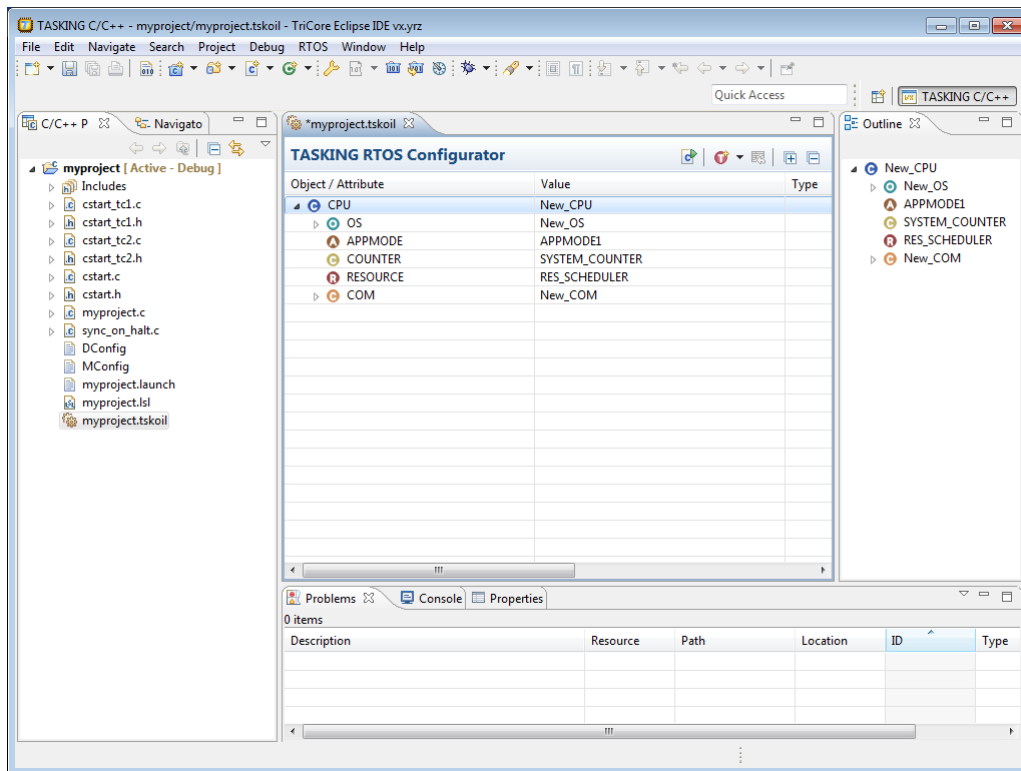
4. In the **File name** field, enter a name for the RTOS configuration file, for example `myproject.tskoil` and click **Finish**.

*A new RTOS configuration file is added to the project with extension `.tskoil`, and it is opened automatically in the TASKING RTOS Configurator.*

Note that if you right-click on a project name and select **New » TASKING RTOS Configuration** the project name and file name are already filled in.

## 2.3. Configuring the RTOS Objects and Attributes

When you have added a new RTOS configuration file, the TASKING RTOS Configurator initially looks similar to this:





You use the TASKING RTOS Configurator to add and/or change RTOS objects and attributes. You can add tasks, events, resources, alarms, interrupts, messages and counters.

As an example, make changes to this RTOS configuration as follows:

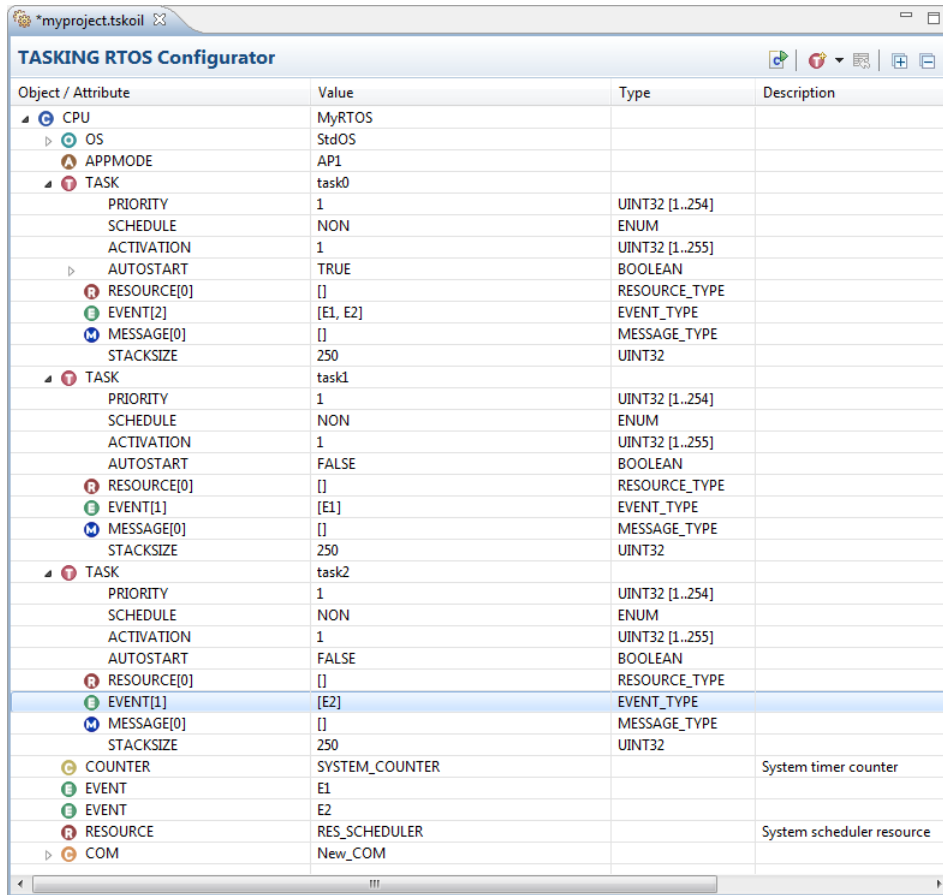
1. From the **RTOS** menu, select **New » TASK**.

*The New TASK Object dialog appears.*

2. In the **Name** field enter `task0` and click **OK**.  
*TASK task0 is added to the configuration.*
3. Repeat steps 1 and 2 to add tasks `task1` and `task2`.
4. From the **RTOS** menu, select **New » EVENT**.  
*The New EVENT Object dialog appears.*
5. In the **Name** field enter `E1` and click **OK**.  
*EVENT E1 is added to the configuration.*
6. Repeat steps 4 and 5 to add event `E2`.
7. Click on the `New_CPU` value and change it to `MyRTOS`.
8. Click on the `New_OS` value and change it to `StdOS`.
9. Expand the `OS` object and change the `ORTI` attribute from `FALSE` to `TRUE`.  
*This will provide the debugger with as much RTOS debug information as possible via the ORIT interface.*
10. Click on the `APPMODE1` value and change it to `AP1`.
11. Expand `TASK task0` and change `AUTOSTART` to `TRUE`.  
*The APPMODE[0] attribute appears.*
12. Click in the `Value` field of `APPMODE[0]` and click on the **Browse** button .  
*The Select APPMODE Objects dialog appears.*
13. Select `AP1` and click **OK**.  
*APPMODE[0] is changed into APPMODE[1] indicating it contains 1 APPMODE object.*
14. Click in the `Value` field of `EVENT[0]` and click on the **Browse** button .  
*The Select EVENT Objects dialog appears.*
15. Select `E1` and `E2` and click **OK**.  
*EVENT[0] is changed into EVENT[2] indicating it contains 2 EVENT objects.*
16. Repeat steps 13 and 14 to add `EVENT E1` to `task1`, and add `EVENT E2` to `task2`

## Using the TASKING RTOS for TriCore

The TASKING RTOS Configurator view now looks similar to this:




17. From the **File** menu, select **Save** (Ctrl+S) or click .

*The file will be saved and a question appears if you want to generate the RTOS code.*

18. Click **Yes** to generate the RTOS code.

*An `rtos` directory with the RTOS code is generated in your project directory.*

## 2.4. Generate RTOS Code

Once you have changed the RTOS configuration file, you can generate the RTOS code. As seen in the previous example, this can be done automatically each time you save the configuration. At any time you can also click the **Generate Code** button (.

## 2.5. TASKING RTOS Configurator Preferences

You can use the Preferences dialog in Eclipse to specify how the TASKING RTOS Configurator should operate.

### To set preferences

1. From the **Window** menu, select **Preferences**.

*The Preferences dialog appears.*

2. Select **TASKING » TASKING RTOS Configurator**.

*The TASKING RTOS Configurator page appears.*

3. Set your preferences and click **OK**.

You can set the following preferences:

### Generate code on save

By default the TASKING RTOS Configurator asks if you want to generate code when you save a document (**Prompt**). You can choose to do this automatically (**Always**) or **Never**.

## 2.6. Edit the Application Files

Once the RTOS source code is in your project directory you can use it in your application files. In order to get a working project, you must edit at least the main source file. It is not necessary to pay attention to the exact contents of the file at this moment.

### Edit the user source code

1. As an example, type the following C source in the file `myproject.c`:

```
#include <rtos.h>

DeclareTask(task0);
DeclareTask(task1);
DeclareTask(task2);
DeclareEvent(E1);
DeclareEvent(E2);

DeclareAppMode(AP1);

int main(void)
{
    StartOS(AP1);
    return 0;
}
```

## Using the TASKING RTOS for TriCore

```
TASK (task0)
{
    EventMaskType event;
    ActivateTask(task1);
    while(1)
    {
        WaitEvent(E1 | E2);
        GetEvent(task0, &event);
        if (event & E1)
        {
            ActivateTask(task2);
        }
        else if (event & E2)
        {
            ActivateTask(task1);
        }
        ClearEvent(E1 | E2);
    }
}

TASK (task1)
{
    SetEvent(task0, E1);
    TerminateTask();
}

TASK (task2)
{
    SetEvent(task0, E2);
    TerminateTask();
}
```

2. From the **File** menu, select **Save** (Ctrl+S) or click .

*The file will be saved.*

## 2.7. Set the Project Options

In order for your application to find the RTOS files, the `rtos` directory and the `rtos/Configuration` directory must be in the list of include paths. When you generate the RTOS source code, these paths are added to your project options automatically, if they were not present already. You can check the project include paths as follows.

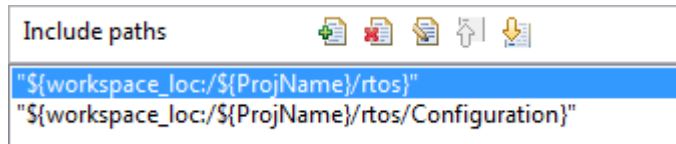
1. From the **Project** menu, select **Properties for**

*The Properties dialog appears.*

2. In the left pane, expand **C/C++ Build** and select **Settings**.


In the right pane the Settings appear.

3. On the Tool Settings tab, expand **C/C++ Compiler** and select **Include Paths**.
4. Make sure the following paths are present:



## 2.8. How to Build an RTOS Application

Once you have generated the RTOS code and created your application, you are ready to build the RTOS application. This is the same as building any other C/C++ project.

- From the **Project** menu, select **Build project** ()

## 2.9. How to Debug an RTOS Application

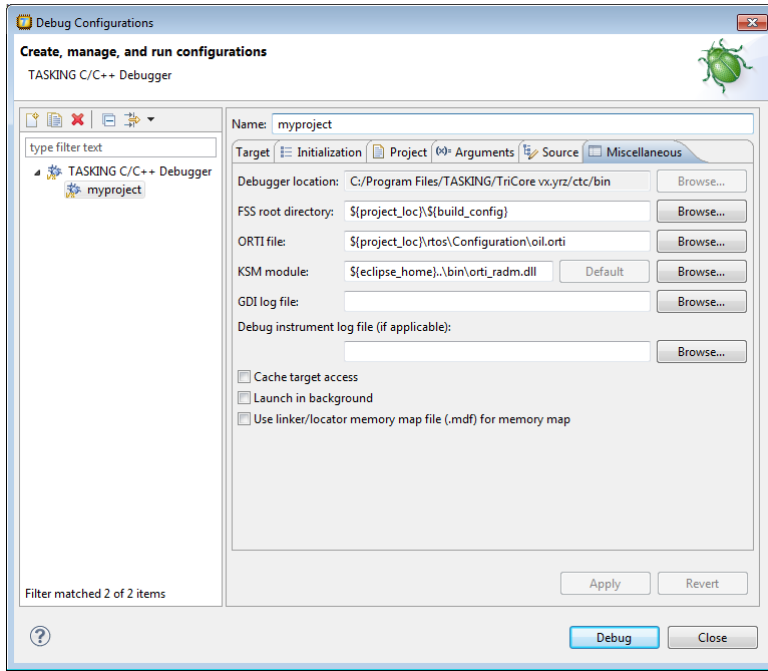
The debugger has special support for debugging real-time operating systems (RTOSs). This support is implemented in an RTOS-specific shared library called a *kernel support module* (KSM) or *RTOS-aware debugging module* (RADM). Specifically, the TASKING VX-toolset ships with a KSM (`orti_radm.dll`). The TASKING OIL compiler creates an Run Time Interface (ORTI) file (`oil.orti`) in the `rtos/Configuration` folder.

If you want as much RTOS debug information as possible via the ORTI interface, you must set the `ORTI` attribute in the OS object of the RTOS configuration file to `TRUE`. In step 9 in [Section 2.3, Configuring the RTOS Objects and Attributes](#) we already did this.

You need to specify the ORTI file on the **Miscellaneous** tab while configuring a customized debug configuration:

1. From the **Debug** menu, select **Debug Configurations...**  
*The Debug Configurations dialog appears.*
2. In the left pane, select the configuration you want to change, for example, **TASKING C/C++ Debugger » myproject**.
3. Open the **Miscellaneous** tab.

## Using the TASKING RTOS for TriCore



4. In the **ORTI file** field, specify the name of the ORTI file (`oil.orti`).

*The **KSM module** field will automatically be filled with the file `orti_radm.dll` in the `bin` directory of the toolset.*

5. Click **Debug** to start the debugger.

To start kernel debugging you can use the **ORTI** menu entry in the **Debug** menu. **Debug » ORTI » RTOS** allows inspection of all RTOS resources including system status, tasks, contexts, stacks and resources.

For example, to show the tasks:

- From the **Debug** menu, select **ORTI » RTOS » Tasks**.

*The RTOS: Tasks view appears.*

Object	Priority	State	Stack	Context	Current Activations
task0	0	SUSPENDED	s_task0	c_task0	0
task1	0	SUSPENDED	s_task1	c_task1	0
task2	0	SUSPENDED	s_task2	c_task2	0



# Chapter 3. RTOS Objects and Attributes

This chapter describes the available RTOS objects and attributes you can configure with the TASKING RTOS Configurator.

## 3.1. What are the OIL System Objects?

Every version of OIL language defines syntactically and semantically a set of OIL system objects. These objects are defined in the ISO standard. One of the system objects is CPU. This serves as a container for all other objects. Objects are defined by their attributes.

### 3.1.1. Standard and Non-Standard Attributes

Every OIL system object has attributes that can hold values. According to the OIL standard, each object has at least a minimum mandatory set of attributes, called the *standard attributes*. Besides the standard attributes, an ISO 17356 implementation may define additional attributes (*non-standard attributes*) for any OIL system object.

To configure a system for a specific ISO 17356 implementation you need to instantiate and/or define OIL objects and assign values to their attributes.

An ISO 17356 implementation can limit the given set of values for object attributes.

Since the non-standard attributes are ISO 17356 implementation specific they are not portable. However, there are two reasons to justify non-standard attributes:

- they can address platform specific features
- they can provide extra configuration possibilities for a certain target

### 3.1.2. Overview of System Objects and Attributes

The following table shows the list of system objects with their standard attributes as defined by OIL2.5 and the non-standard attributes for the TriCore. The non-standard attributes are marked italic.

Because the TASKING RTOS supports only internal communication, the subset of objects and standard attributes differs from the OIL2.5 definition:

- MESSAGE object (TASKING RTOS differs)
- NETWORK MESSAGE object (not present in TASKING RTOS)
- COM object (TASKING RTOS differs)
- IPDU object (not present in TASKING RTOS)

In addition to the attributes listed in the table below, there are a number of non-standard attributes which are not included in this table. These extra attributes all start with the keyword `WITH_AUTO` and take `AUTO`

## Using the TASKING RTOS for TriCore

as their default value (you can search for them in the file `rtos_impl.oil`). This subset of attributes can be considered as internals of the implementation and are not user configurable. Instead, their values are calculated at generation time.

OIL system object	Description	Standard attributes <i>Non-standard attributes</i>
CPU	The CPU on which the application runs under the RTOS control. Container of all the other objects.	
OS	The OS that runs on the CPU. All system objects are controlled by OS.	STATUS STARTUPHOOK ERRORHOOK SHUTDOWNHOOK PRETASKHOOK POSTTASKHOOK USEGETSERVICEID USEPARAMETERACCESS USERESSCHEDULER LONGMSG ORTI RUNLEVELCHECK SHUTDOWNRETURN IDLEHOOK IDLELOWPOWER USERTOSIMER
APPMODE	Defines different modes of operation for the application.	Has no attributes
TASK	The task handled by the OS.	PRIORITY SCHEDULE ACTIVATION AUTOSTART RESOURCE [ ] EVENT [ ] MESSAGE [ ] STACKSIZE
ISR	Interrupt service routines supported by OS.	CATEGORY RESOURCE [ ] MESSAGE [ ] LEVEL
RESOURCE	The resource that can be occupied by a task.	RESOURCEPROPERTY
COUNTER	The counter represents hardware/software tick source for alarms.	MAXALLOWEDVALUE TICKSPERBASE MINCYCLE
EVENT	The event on which tasks may react.	MASK

OIL system object	Description	Standard attributes Non-standard attributes
ALARM	The alarm is based on a counter and can either activate a task or set an event or activate an alarm-callback routine.	COUNTER ACTION AUTOSTART
MESSAGE	The message is defined in COM and defines a mechanism for data exchange between different entities (tasks or ISRs)	MESSAGEPROPERTY NOTIFICATION
COM	The communication subsystem. The COM object has standard attributes to define general properties for the interaction layer.	COMERRORHOOK COMUSEGETSERVICEID COMUSEPARAMETERACCESS COMSTARTCOMEXTENSION COMAPPMODE [ ] COMSTATUS

### 3.1.3. Non-Standard Attributes for the TriCore

This section describes the non-standard attributes, which are specific for the TriCore.

Please refer to the ISO 17356 documentation for the semantics of all standard attributes.

#### OS object

Attribute	Description
IDLEHOOK	The IDLEHOOK attribute specifies the name of a user definable hook routine that will be called from the idle task. The IDLESTACKSIZE sub-attribute specifies the size of the stack used by the hook routine.
IDLELOWPOWER	When the IDLELOWPOWER is set, the idle task will enter low power mode by executing the <code>wait</code> instruction. When both IDLEHOOK and IDLELOWPOWER are set, the IDLEHOOK is executed first, before entering wait mode.
LONGMSG	The LONGMSG boolean attribute determines whether Category 2 ISRS are suspended during the copy of messages from the RTOS buffers to the application or vice versa. If set to TRUE, the RTOS expects long messages, so the interrupts will not be suspended. This is at the cost of extra handling. The default value is FALSE.
ORTI	With the ORTI attribute you can request the RTOS to provide the debugger with as much RTOS debug information as possible via the ORTI interface. If you set this attribute to TRUE, the run-time performance suffers from extra overhead that should be avoided in final production. (If you set this attribute to FALSE, not all debug information will be available to the debugger). The type of ORTI is BOOLEAN. It has a default value of FALSE.

Attribute	Description
SHUTDOWNRETURN	When the SHUTDOWNRETURN attribute of the OS object is TRUE, after the <code>ShutdownOS()</code> routine has finished it returns to <code>main()</code> just after the call to <code>StartOS()</code> . If SHUTDOWNRETURN is FALSE, the function does not return. The MULTISTART boolean sub-attribute specifies whether the system is allowed to start the RTOS more than once (undergoing application resets via the usage of <code>ShutdownOS()</code> ). It has a default value of TRUE. See <a href="#">Section 4.5, Shut-down Process</a> in <a href="#">Chapter 4, Startup Process</a> .
USERTOSTIMER	The USERTOSTIMER is a parametrized boolean attribute which determines whether ALARM OIL objects based on the system counter have been configured in the system. If set to TRUE, the RTOS provides the interrupt framework for the timer unit and the application provides its initialization. In this case, you must set the sub-attribute RTOSTIMERPRIO to the interrupt priority. This priority must be in the range of ISR category 2. Priority 1 is the lowest priority. The type of RTOSTIMERPRIO is UINT32. The default value is 1. You can choose any of the timers T2, T3, T4, T5 or T6 for the RTOSTIMER. The default is T3. Set the OSCLOCKHZ to the frequency of OS ticks in Hz. Set CPUCLOCKMHZ to the processor clock frequency in MHz. The default value for USERTOSTIMER is FALSE.

### TASK object

Attribute	Description
STACKSIZE	The STACKSIZE attribute specifies the size of the stack area (in bytes) to allocate for the task. Note that interrupts of category 1 may use this stack area. The type of this attribute is UINT32. The default value is 250. See <a href="#">Section 5.7, The Stack of a Task</a> .

### ISR object

Attribute	Description
LEVEL	The LEVEL attribute specifies the priority level of the interrupt. The type of this attribute is UINT32. The default value is 1.

# Chapter 4. Startup Process

This chapter explains what happens inside the system from application reset until the first application task is scheduled and describes how you can interact with the startup process by adding certain Hook Routines.

## 4.1. Introduction

This chapter details the various phases the system undergoes from CPU reset until the first application task is scheduled. You can interact with this process via the Hook Routines and the Application Modes.

The startup process includes the following phases:

- System boot
- C entry point `main()`
- StartOS
- RTOS initialization phase: Hook Routines

After the startup process the first task is scheduled. When the startup has no tasks, the system idle task is scheduled.

## 4.2. System Boot

When the processor first starts up, it always looks at the same place in the system ROM memory area for the start of the system boot program. The boot code runs sequentially until it reaches the point where it jumps to the label `main`. This code runs in the absence of the operating system.

In general, embedded systems differ so much from each other that the boot code tends to be almost unique for each process. You can create the system boot in two ways:

- Reuse the standard startup code provided by the toolset and enhance it (if necessary) to suit the specific needs of your hardware. The standard startup code merely contains what is necessary to get the system running. It is easy configurable via Project Properties dialog.
- You may decide to create the system boot code if some board specific actions need to be taken at a very early stage. Some of the most common actions are:
  - Initialization of critical microprocessor registers (including standard pointers like the stack pointer).
  - Initialization of specific peripheral registers for your unique hardware design.
  - Initialization of all global variables.
  - Distinguish the source of processor reset (hard or soft reset, power-on reset, watchdog, ...).
  - Addition of some power-on tests.

## Using the TASKING RTOS for TriCore

- Call the label `main()` to start the application.

### 4.3. The `main()` Module

At the moment of arriving in `main()` only minimal controller initialization has occurred. At this point the application can run extra (application-specific) initialization routines before the RTOS starts. This code cannot call RTOS system services.

The RTOS is started using the `StartOS()` routine:

```
void StartOS(AppModeType);
```

The `AppModeType` application mode parameter for the `StartOS()` routine is one of the `APPMODE` application modes defined in the TASKING RTOS Configurator or `OSDEFAULTAPPMODE`, which is a define supplied by the RTOS which maps to the first application mode.

#### 4.3.1. What are Application Modes?

Application Modes allow you (as a matter of speaking) to have "multiple" applications in one single image. Application Modes allow application images to structure the software running in the processor depending on external conditions. These conditions must be tested by the application software upon system reset. The difference in functionality between applications that start in different modes is determined by:

- Which tasks and which alarms automatically start after the RTOS initialization.
- Mode-specific code (the mode can be detected at run-time by using the system service `GetActiveApplicationMode`).

You can set the `AUTOSTART` attribute to `TRUE` for a task in the TASKING RTOS Configurator, and then add the application mode object. There is no limit on the number of Application Mode objects. See [Chapter 13, Implementation Parameters](#), for the maximum number of application modes in this implementation.

### 4.4. RTOS Initialization

This section shows what happens inside the system from the moment that you call `StartOS()` until the first application task is scheduled and explains how you can intervene in this process.

The RTOS performs the following actions during the initialization process:

1. The RTOS initializes some internal data structures on the basis of what is stated in the RTOS configuration file. In particular, it prepares autostarting tasks and alarms to start running.
2. The RTOS hardware timer is initialized when the `USERTOSTIMER` attribute of the OS object is set to `TRUE`.

The unit of time is the system tick (defined as the interval between two consecutive hardware clock interrupts). The implementation parameter `OSTICKDURATION` defines the length (in nanoseconds) of the system tick.

Not all applications need a system counter (only those with ALARM objects based on the system counter). You determine this with the non-standard attribute USERTOSTIMER.

When you set USERTOSTIMER to TRUE, you need to set some extra attributes. For the TriCore AURIX for example, you need to choose one of the GPT120 timers T2 .. T6 for RTOSTIMER. Set RTOSTIMERPRIO to the interrupt priority. Set OSCLOCKHZ to the frequency of OS ticks in Hz and set CPUCLOCKMHZ to the processor clock frequency in MHz.

3. The RTOS calls the hook routine `StartupHook()` (provided that you have assigned the value TRUE to the STARTUPHOOK attribute of the OS object in the RTOS configuration):

```
void StartupHook(void);
```

If the STARTUPHOOK attribute of the OS object is set but you do not define the `StartupHook()` routine in your source, the linking phase fails because it encounters an unresolved external.

During the lifetime of the `StartupHook` routine all the system interrupts are disabled and you have only restricted access to system services. The only available services are `GetActiveApplicationMode()` and `ShutdownOS()`.

You should use this hook routine to add initialization code which strongly relies on the current selected Application Mode.

```
void StartupHook(void)
{
    AppModeType mode = GetActiveApplicationMode();
    // .
    // . code for StartupHook
    // .
    return;
}
```

4. The RTOS enables all system interrupts.
5. The RTOS executes the highest priority task ready to execute.

If you define the AUTOSTART attribute as FALSE for all TASK objects in the RTOS configuration, the system enters directly into an RTOS-defined idle state. The system then waits for external events or alarms based on the system counter.

## 4.5. Shut-down Process

The operating system can be shut-down by the `ShutdownOS()` routine:

```
void ShutdownOS(StatusType error);
```

## Using the TASKING RTOS for TriCore

You can directly request the `ShutdownOS()` routine. In this case, you must define your own set of shut-down reasons: error codes. The application can define its own error codes in the range 64 .. 255. For example:

```
#define E_APP_ERROR1    64
#define E_APP_ERROR2    65
...
...
#define E_APP_ERROR192  255
```

(0-63 are reserved for the RTOS code)

As soon as your application encounters a fatal error, the `ShutdownOS()` routine must be called with an appropriate error code. For example:

```
ShutdownOS(E_APP_ERROR1);
```

The `ShutdownOS()` routine can also be reached internally by the operating system in case the RTOS encounters an internal fatal error.

See the file `rtos.h` in the `rtos` directory of your project for a list of system error codes. They start with `E_OS_` or `E_OK` if there are no errors.

When the `SHUTDOWNRETURN` attribute of the OS object is `TRUE`, after the `ShutdownOS()` routine has finished it returns to `main()` just after the call to `StartOS()`. If `SHUTDOWNRETURN` is `FALSE`, the function does not return.

`SHUTDOWNRETURN` has a sub-attribute `MULTISTART`. When `MULTISTART` is set to `TRUE` (the default) you can restart the operating system by calling `StartOS()`. The global variables of the operating system are then reset to their initial values. When `MULTISTART` is set to `FALSE` you cannot call `StartOS()` again because the operating system variables have not been reset.

From the `ShutdownOS()` routine, the RTOS calls the hook routine `ShutdownHook()`, provided that you have assigned the value `TRUE` to the `SHUTDOWNHOOK` attribute of the OS object in the RTOS configuration.

```
void ShutdownHook(StatusType error);
```

If the `SHUTDOWNHOOK` attribute is set but you do not define the `ShutdownHook()` routine in your source, the linking phase fails because it encounters an unresolved external.

During the lifetime of the `ShutdownHook()` routine all system interrupts are disabled and the only available service is `GetActiveApplicationMode()`.

You can define any system behavior in this routine, including not returning from the function at all. In any case, you should always check for both application and RTOS error codes. Typical actions would be:

- If you run with a debugger, you can set a breakpoint in this routine to study the nature of the possible shutdown reasons.



- In absence of a debugger, use a logging mechanism (be aware that ISR2 are disabled when this routine is called).
- In case a fatal error is encountered, you should force the system to shut down (or hardware reset). All RTOS errors are (by definition) fatal and you should decide whether any of your own application errors should also be considered fatal (if any).

## 4.6. API Service Restrictions

System services are called from tasks, interrupt service routines, hook routines, and alarm callbacks. Depending on the system service, there may be restrictions regarding the availability. See the following table.

Service	Task	ISR cat 1	ISR cat 2	Error hook	Pre task hook	Post task hook	Startup hook	Shut down hook	alarm callback
ActiveTask	✓		✓						
TerminateTask	✓								
ChainTask	✓								
Schedule	✓								
GetTaskID	✓		✓	✓	✓	✓			
GetTaskState	✓		✓	✓	✓	✓			
DisableAllInterrupts	✓	✓	✓						
EnableAllInterrupts	✓	✓	✓						
SuspendAllInterrupts	✓	✓	✓	✓	✓	✓			
ResumeAllInterrupts	✓	✓	✓	✓	✓	✓			
SuspendOSInterrupts	✓	✓	✓						✓
ResumeOSInterrupts	✓	✓	✓						✓
GetResource	✓		✓						
ReleaseResource	✓		✓						
SetEvent	✓		✓						
ClearEvent	✓								
GetEvent	✓		✓	✓	✓	✓			
WaitEvent	✓								
GetAlarmBase	✓		✓	✓	✓	✓			
GetAlarm	✓		✓	✓	✓	✓			
SetRelAlarm	✓		✓						
SetAbsAlarm	✓		✓						
CancelAlarm	✓		✓						

*Using the TASKING RTOS for TriCore*

Service	Task	ISR cat 1	ISR cat 2	Error hook	Pre task hook	Post task hook	Startup hook	Shut down hook	alarm callback
GetActiveApplicationMode	✓		✓	✓	✓	✓	✓	✓	
StartOS									
ShutdownOS	✓		✓	✓			✓		

# Chapter 5. Task Management

This chapter explains how the RTOS manages tasks (scheduling policies, tasks states, ..) and describes how you can add TASK objects to the TASKING RTOS configuration.

## 5.1. What is a Task?

A task is a semi-independent program segment with a dedicated purpose. Most modern real-time applications require multiple tasks. A task provides the framework for the execution of functions. The RTOS provides concurrent and asynchronous execution of tasks. The scheduler organizes the sequence of task execution including a mechanism which is active when no other system or application function is active: the idle-mechanism.

A task has a static priority, is or is not preemptable, can or cannot enter the waiting state, is or is not the only owner of a priority level, and so on.

## 5.2. Defining a Task in the C Source

To configure a task, you must declare a TASK object in the TASKING RTOS Configurator of the project. An example is given in [Section 2.3, Configuring the RTOS Objects and Attributes](#). See [Section 3.1.2, Overview of System Objects and Attributes](#) for an overview of the possible attributes. See the ISO 17356 documentation for detailed information about all possible attributes of a task and how to use them.

With the macro `TASK` you can define a task in your application. Use the same name as the name of the TASK object in the RTOS configuration as parameter to this macro.

A task must not return. Instead of a `return` statement, end the code of a task with the system service `TerminateTask()` or `ChainTask()`. For example, to define the task `TaskT`:

```
TASK(TaskT)
{
    .
    . code for task 'TaskT'
    .
    TerminateTask();
}
```

If a task is needed as a parameter to a system service, for example `ActivateTask()`, you need to declare the task first with `DeclareTask()`.

```
DeclareTask(TaskT);

void fnc( void )
{
    ActivateTask(TaskT);
}
```

## 5.3. The States of a Task

A task goes through several different states during its lifetime. A processor can only execute one instruction at a time. So, even when several tasks are competing for the processor at the same time, only one task is actually running. The RTOS is responsible of saving and restoring the context of the tasks when they undergo such state transitions.

A task can be in one of the following states:

Task state	Description
running	The CPU is now assigned to the task and it is executing the task. Only one task can be in this state at any point in time.
ready	All functional prerequisites for a transition into the running state exist, and the task only waits for allocation of the processor. The scheduler decides which ready task is executed next.
waiting	A task cannot continue execution because it has to wait for at least one event.
suspended	In the suspended state the task is passive and can be activated.

## 5.4. The Priority of a Task

The scheduler decides on the basis of the task priority (precedence) which is the next of the ready tasks to be transferred into the running state. The value 0 is defined as the lowest priority of a task and it is reserved for the idle task.

To enhance efficiency, a dynamic priority management is not supported. Accordingly the priority of a task is defined statically: you cannot change it during execution.

In special cases the operating system can treat tasks with a lower priority as tasks with a higher priority. See [Section 7.3, \*The Ceiling Priority Protocol\*](#), in [Chapter 7, \*Resource Management\*](#).

An application can have more than one task with the same priority. The RTOS uses a first in, first out (FIFO) queue for each priority level containing all the ready tasks within that priority. Some facts about the ready-queues are listed below:

- Every ready-queue corresponds to a priority level.
- Tasks are queued, in activation order, in the ready-queue that corresponds to their static priority.
- All the tasks that are queued must be in the ready state.
- Since the waiting tasks are not in any ready queue, they do not block the start of subsequent tasks with identical priority.
- The system priority corresponds to the highest priority among all of the non-empty ready-queues.
- The running task is the first task in the ready-queue with the system priority.
- A task being released from the waiting state is treated like the newest task at the end of the ready-queue of its priority.

- The following fundamental steps are necessary to determine the next task to be processed:
  1. The scheduler searches for all tasks in the ready/running state.
  2. From the set of tasks in the ready/running state, the scheduler determines the set of tasks with the highest priority.
  3. Within the set of tasks in the ready/running state and of highest priority, the scheduler finds the oldest task.

### 5.4.1. Virtual versus Physical Priorities

We define *virtual priority* of a task as "the priority of a task as it is given in the RTOS configuration".

We define *physical priority* of a task as "the real run-time priority of the task".

Let us think of an application with three TASK objects defined such that:

```
TASK T1 { PRIORITY = 6; .. };
TASK T2 { PRIORITY = 4; .. };
TASK T3 { PRIORITY = 4; .. };
```

The "ready-to-run" array comprises all the ready queues of the system. In such a system there will be two "ready-queues" in the "ready-to-run" array, one per priority level.

The following figure shows the "ready-to-run" array where T1 is running and tasks T2 and T3 are ready (T2 being the oldest).

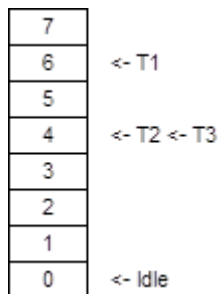


Figure 5.1. Virtual ready-to-run array

Now, what would, in terms of functionality, be the differences between this configuration and the next systems?

#### System A

```
TASK T1 { PRIORITY = 3; .. };
TASK T2 { PRIORITY = 1; .. };
TASK T3 { PRIORITY = 1; .. };
```

## Using the TASKING RTOS for TriCore

### System B

```
TASK T1 { PRIORITY = 17; .. };  
TASK T2 { PRIORITY = 9; .. };  
TASK T3 { PRIORITY = 9; .. };
```

The equivalent "ready-to-run" arrays of such systems would then be:

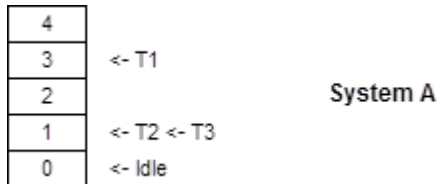


Figure 5.2. Virtual ready-to-run array for System A

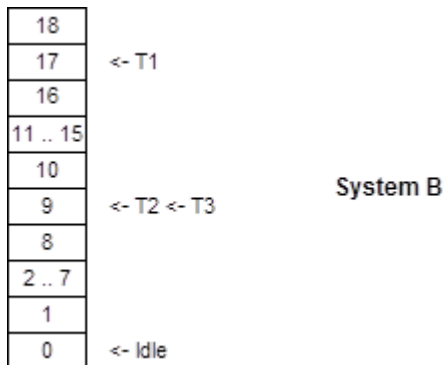


Figure 5.3. Virtual ready-to-run array for System B

There are no functional differences. As soon as T1 undergoes the wait or terminate transition, T2 is scheduled. T2 can only be preempted by T1. T3 only runs after T2 undergoes a wait or terminate transition.

However, it is easy to infer from the diagrams that system A has the better run-time response of the system. In system B, for instance, there are 15 "useless" priority levels defined in the system. Besides these levels can never hold a ready task, the scheduler also wastes CPU cycles in checking them. And RAM area has been allocated for them. In a hard real-time system, these unnecessary checks must be avoided.

Since all this information can be interpreted beforehand by the RTOS code, all these configurations will end up in the same physical "ready-to-run" array:

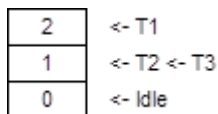


Figure 5.4. Virtual ready-to-run array for System A and System B

Internally, the RTOS code deals always with "physical priorities". The maximum size of the "ready-to-run" array determines the upper limit for the number of physical priorities.

## 5.4.2. Fast Scheduling

Every physical priority level holds a "ready-queue". You can define multiple tasks with the same priority. However, if you define only one task per priority level, the scheduler becomes faster. In this situation the RTOS software does not have to deal with "ready-queues" but merely with pointers to the task control blocks.

Whenever possible, you should try to define only one TASK object with the same value for its PRIORITY attribute. You will benefit not only from better run-time responses but also from smaller RAM and ROM sizes.

## 5.5. Activating and Terminating a Task

Tasks must be properly activated and terminated. You can activate tasks directly from a task or interrupt level. To activate a task, use the system service:

```
StatusType ActivateTask(TaskType task);
```

A task is activated by the RTOS code when:

- An alarm expires (with its attribute ACTION set to ACTIVATETASK).
- A message has been sent (with its attribute NOTIFICATION set to ACTIVATETASK).
- You configured a task to be activated during the RTOS startup. You must set the attribute AUTOSTART to TRUE and indicate under which application mode(s) the task must autostart.

APPMODE	AppModel
TASK	autoT
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	TRUE
APPMODE[1]	[AppModel]

And the RTOS needs to be started in your C source:

```
DeclareAppMode(AppModel);
```

```
int main(void)
{
    StartOS(AppModel);
    return 0;
}
```

## Using the TASKING RTOS for TriCore

After activation, the task is ready to execute from the first statement. The RTOS does not support C-like parameter passing when starting a task. Those parameters should be passed by message communication or by global variables. See [Chapter 10, Communication](#).

A task can be activated once or multiple times. The maximum number of activations is defined in the RTOS configuration with the attribute ACTIVATION of the TASK object.

If you try to activate a task which is in suspended mode, the RTOS will move the task into the ready state.

If you try to activate a task which is not in suspended mode (the task is ready, waiting or running - self activation -), the RTOS will do the following, depending on the current number of activations:

- If the maximum number of activations, as specified by the ACTIVATION attribute, has not been reached yet, the RTOS queues this activation request for further processing.
- If the maximum number of activations has been already reached, the system service returns E\_OS\_LIMIT as error code.

Upon termination of a task, the RTOS checks for previous activation requests. If such a requests exist, the RTOS will set the task to ready. Furthermore, if this task still has the highest priority of the system (which is normally the case unless another task with higher priority has been activated or awoken from an ISR2 or an alarm), the RTOS will immediately start this task again (with the initial context).

## Example of activating a task

▲ T TASK	Activate
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	5
AUTOSTART	FALSE
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250
▲ T TASK	Init
PRIORITY	2
SCHEDULE	FULL
ACTIVATION	1
▶ AUTOSTART	TRUE
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250

C source file:

```
TASK (Activate)
{
    TerminateTask();
}
```



```

TASK (Init)
{
    int i;
    StatusType ret;

    /* 'Activate' task 5 times */
    for (i = 0; i < 5; i++)
    {
        ret = ActivateTask(Activate);
        if(ret != E_OK)
        {
            /* never here - always E_OK */
            while(1);
        }
    }

    /*
     * try to activate five more times,
     * this will fail because maximum number of
     * activations is set to 5 in the RTOS Configuration
     */
    for (i = 0; i < 5; i++)
    {
        ret = ActivateTask(Activate);
        if (ret != E_OS_LIMIT)
        {
            /* never here - returns E_OS_LIMIT due to
             * maximum number of activations reached
             */
            while(1);
        }
    }

    TerminateTask();
}

```

## Terminating a task

You must explicitly terminate a task with one of the system services:

```
void TerminateTask(void);
```

or:

```
void ChainTask(TaskType);
```

If the return instruction is encountered at task level, the behavior is undefined.

## Using the TASKING RTOS for TriCore

Situations like demonstrated in the example should be avoided:

```
TASK (TaskT)
{
    unsigned char var = readPulse();
    switch (var)
    {
        case READY:
            sendSignal();
            TerminateTask();
            break;
        case NONREADY:
            TerminateTask();
            break;
        default:
            break;
    }
    return;
}
```

Although apparently innocuous, the behavior of the whole system is completely undefined if `var` does not equal to `READY` or `NONREADY`. In that case the switch reaches `default` where the function is not properly terminated.

Be aware that calling `TerminateTask` from interrupts or from hook routines can bring the system to a complete undefined state. You can call `TerminateTask` only from task level. See also

## 5.6. Scheduling a Task

A task can be scheduled with one of the following scheduling policies: full-preemptive and nonpreemptive scheduling. You must assign a scheduling policy to every task in your RTOS configuration, setting the attribute `SCHEDULE` of a `TASK` object to either `FULL` or `NON`.

TASK	schedule
PRIORITY	1
SCHEDULE	NON
ACTIVATION	NON
AUTOSTART	FULL
RESOURCE[0]	

### 5.6.1. Full-preemptive Tasks

Full-preemptive scheduling means that the running task can be rescheduled at any moment by the occurrence of trigger conditions preset by the operating system. The running task enters the ready state, as soon as a higher-priority task becomes ready.

The rescheduling points for full-preemptive scheduling are:

- Successful termination of a task.

- Successful termination of a task with activation of a successor task (`ChainTask`).
- Activating a task at task level.
- Explicit wait call if a transition into the waiting state takes place.
- Setting an event to a waiting task at task level.
- Release of resource at task level.
- Return from interrupt level to task level.

If the tasks in the system are all full-preemptive, the scheduling policy of the system as whole is fully preemptive. During interrupt service routines no rescheduling is performed.

### 5.6.2. Nonpreemptive Tasks

Nonpreemptive scheduling means that task switching is only performed via an explicitly defined system services.

The explicit rescheduling points for nonpreemptive tasks are:

- Successful termination of a task.
- Successful termination of a task with explicit activation of a successor task.
- Explicit call of the scheduler.
- A transition into the waiting state.

If the tasks in the system are all nonpreemptive, the scheduling policy of the system as a whole is said to be nonpreemptive.

Be aware of the special constraints that nonpreemptive scheduling imposes on possible timing requirements while designing your TASK objects. A nonpreemptive task prevents all other tasks from CPU time so their execution time should be extremely short.

### 5.6.3. Scheduling Policy

In the most general case, the system runs with the so-called mixed preemptive scheduling policy (full-preemptive and nonpreemptive tasks are mixed). The current scheduling policy depends on the preemption properties of the running task: nonpreemptive or full-preemptive. If the running task has its SCHEDULE attribute set to FULL in the RTOS configuration, the scheduling policy is fully preemptive. Otherwise the scheduling policy will be nonpreemptive.

Typically an application will operate in mixed preemptive mode where most of the tasks can be safely preempted while the nonpreemptive tasks constitute only a small subset among all tasks.

The code below shows the behavior of the system with a mixed-preemptive policy.

## Using the TASKING RTOS for TriCore

RTOS configuration:

▲ APPMODE	AppModel
▲ T TASK	T1
PRIORITY	4
SCHEDULE	FULL
ACTIVATION	1
AUTOSTART	FALSE
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250
▲ T TASK	T2
PRIORITY	2
SCHEDULE	FULL
ACTIVATION	1
AUTOSTART	FALSE
R RESOURCE[0]	[]
E EVENT[1]	[eT2_nP1]
M MESSAGE[0]	[]
STACKSIZE	250
▲ T TASK	nP1
PRIORITY	3
SCHEDULE	NON
ACTIVATION	1
▲ AUTOSTART	TRUE
▲ APPMODE[1]	[AppModel]
R RESOURCE[0]	[]
E EVENT[1]	[eT2_nP1]
M MESSAGE[0]	[]
STACKSIZE	250
▲ T TASK	nP2
PRIORITY	4
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250
C COUNTER	SYSTEM_COUNTER
E EVENT	eT2_nP1

C source file:

```
/* Like all other RTOS objects you need to declare
   tasks before you can use them in your code */
DeclareTask(T1);
DeclareTask(T2);
DeclareTask(nP1);
```

```

DeclareTask(nP2);
DeclareEvent(eT2_nP1);

TASK(T1)
{
    TerminateTask();
}

TASK(T2)
{
    /* To nP1 */
    SetEvent(nP1,eT2_nP1)
    TerminateTask();
}

TASK(nP1)
{
    /* T1, T2, nP2 are activated but they cannot preempt the running task */
    ActivateTask(T1);
    ActivateTask(T2);
    ActivateTask(nP2);
    /* ... */

    /* This call allows CPU scheduling to tasks with higher priority */
    Schedule();
    /* 1. T1 runs first and terminates */
    /* 2. nP2 runs and terminates */
    /* 3. nP1 resumes execution */
    /* <--- An ISR activates T1 */
    /* ... */

    WaitEvent(eT2_nP1);
    /* 1. T1 runs next and terminates */
    /* 2. T2 runs. It sets 'eT2_nP1' to trigger again 'nP1' */
    /* ... */

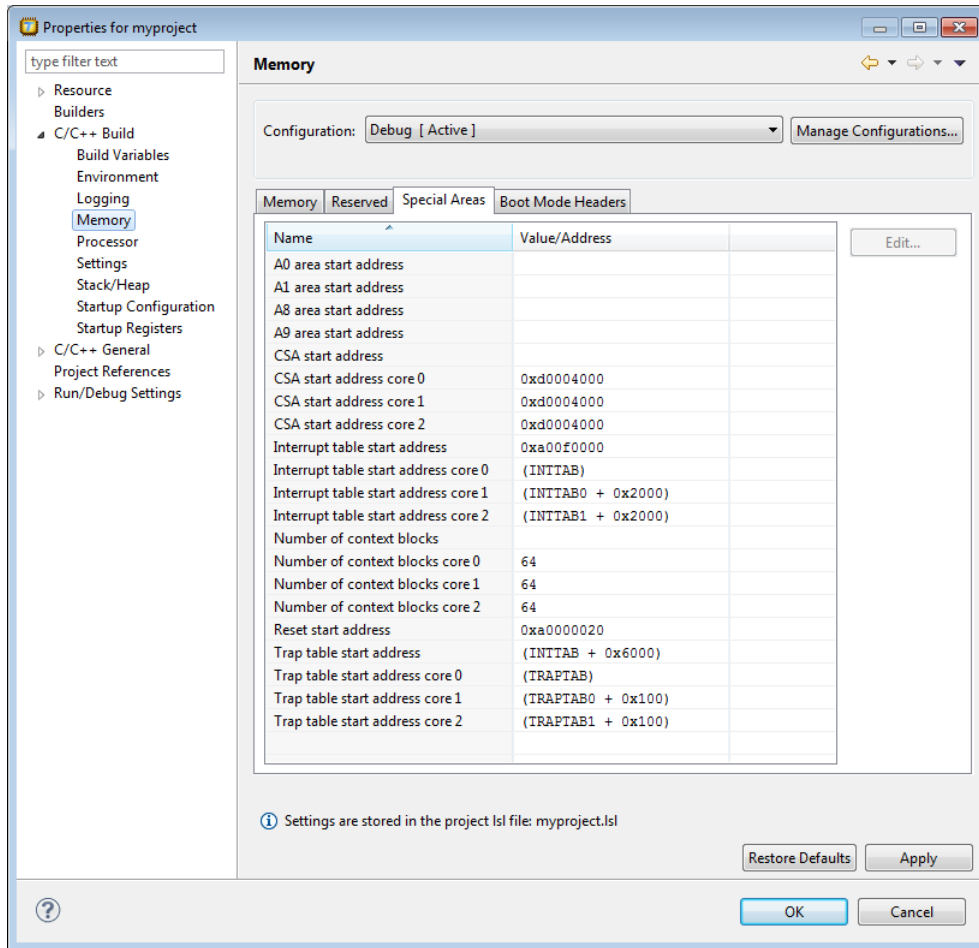
    /* To T2 */
    TerminateTask();
}

TASK(nP2)
{
    TerminateTask();
}

```

## 5.7. The Stack of a Task

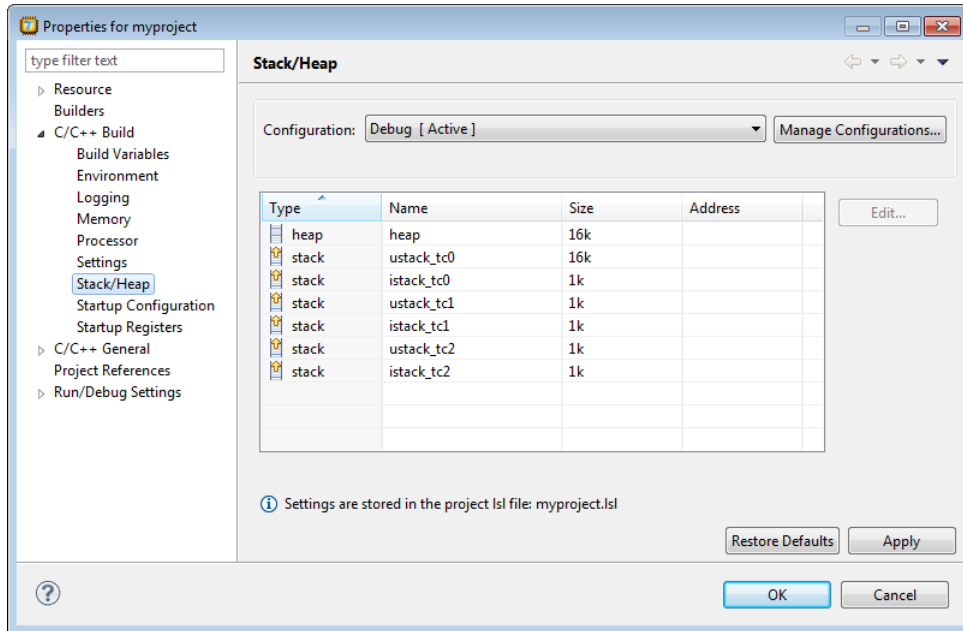
Each task has its own data stack. All tasks en ISRs share from the processor context pool (CSA). The size of the context pool is specified in the Special Areas tab of the Memory pane in the Properties dialog of the project. The number of context blocks for core0 is 64 by default.



The stack size of a task is specified by the STACKSIZE attribute of a TASK object. You can change it in the TASKING RTOS configurator. The default value is 250 bytes per task.

The user stack is used for `cstart` and the part of `main()` before `StartOS()` is called. RTOS objects also use the user stack, for example `ustack_tc0`. Interrupts are on the interrupt stack, for example

istack\_tc0. Most system services run via a system call on the interrupt stack. The idle task runs on its own stack.



## 5.8. C Interface for Tasks

You can use the following data types, constants and system services in your C sources to deal with task related issues.

Element	C Interface
Data Types	TaskType TaskRefType TaskStateType TaskStateRefType
Constants	RUNNING WAITING READY SUSPENDED INVALID_TASK

## Using the *TASKING RTOS* for TriCore

Element	C Interface
System Services	DeclareTask ActivateTask TerminateTask ChainTask Schedule GetTaskID GetTaskState

Please refer to the ISO 17356 documentation for a detailed description.



# Chapter 6. Events

This chapter explains how the RTOS may synchronize tasks via events and describes how you can declare EVENT objects in the RTOS Configurator in order to optimize your event configuration.

## 6.1. Introduction

Events are available as a synchronization method between tasks and between events and tasks. They differentiate basic from extended tasks. Basically, every extended task has a private array of binary semaphores. The array index corresponds with a bit position in an event mask. Thus, waiting on an event mask implies a wait operation on multiple semaphores at a time.

You can:

- set an event from any task or from a Category 2 ISR (`SetEvent`)
- clear (or wait for) an event only from the running task (`ClearEvent/WaitEvent`)
- check which events have been set for a given task from any task, from a Category 2 ISR or from one of the following hook routines: `ErrorHook`, `PreTaskHook` and `PostTaskHook` (`GetEvent`)

Since this implementation does not deal with external communication the scope of the events limits to one application.

## 6.2. Adding Events

You can add or remove an EVENT in the RTOS Configurator.

1. From the **RTOS** menu, select **New » EVENT**.

*The New EVENT Object dialog appears.*

2. In the **Name** field enter the name of the event.
3. Optionally enter a **Description**.
4. Click **OK**.

*The event is added to the configuration.*

You cannot assign a mask value to an EVENT object. The RTOS Configurator always calculates this value internally.

The maximum number of events supported by this implementation is 32. If you define more EVENT objects in your RTOS configuration than the maximum number supported an error is issued.

## 6.3. Using Events

### WaitEvent

A task may enter the waiting state and allow other tasks the CPU time until a certain event occurs. Thus events form the criteria for the transition of tasks from the running state into the waiting state. The transition is performed with the system service:

```
StatusType WaitEvent(EventMaskType);
```

You can call `WaitEvent` (and `ClearEvent`) only from tasks for events that are listed in the attribute `EVENT` of the task.

The following RTOS configuration specifies that task `Task1` can only wait for `Event1` and `Event2`:

TASK	Task1
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	1
AUTOSTART	TRUE
RESOURCE[0]	[]
EVENT[2]	[Event1, Event2]
MESSAGE[0]	[]
STACKSIZE	250
COUNTER	SYSTEM_COUNTER
EVENT	Event1
EVENT	Event2
EVENT	Event3

If task `Task1` attempts to wait for another event than `Event1` or `Event2`, the system service `WaitEvent` fails:

C source file:

```
TASK(Task1)
{
    StatusType ret;

    /* TASK waits for allowed event */
    ret = WaitEvent(Event1);
    if (ret != E_OK)
    {
        LogError(OSServiceID_WaitEvent, ret);
        TerminateTask();
    }

    /* CPU has been given to other task(s) */

    /* From another TASK/ISR/ALARM the event
    * 'E1' has been set for this task.
    */
}
```

```

    * Now 'T1' can resume execution
    */

/* TASK attempts to wait on an event that is not
 * in the EVENTS list attribute of the TASK
 */

ret = WaitEvent(Event3);
if (ret != E_OK)
{
    /* 'E3' is not owned by 'T1' */
    LogError(OSServiceID_WaitEvent, ret);
    TerminateTask();
}

/* ... */

TerminateTask();}

```

When the scheduler moves the task from the ready to the running state, the task resumes execution at the following immediate instruction.

A task can wait for several events at a time:

```
WaitEvent(Event1 | Event2 | ...);
```

The task does not undergo the transition if just one of the events has occurred. In this case the service immediately returns and the task remains in the running state. Only when all the events are cleared for the calling task, the invoking task is put into the waiting state.

`WaitEvent()` can only be invoked from the task level of an extended task, never from interrupt level or a hook routine.

## SetEvent

You can set an event (equivalent to "an event occurs") to a specific task directly with the system service:

```
StatusType SetEvent(TaskType, EventMaskType);
```

If you need to trigger an event for more than one task you need to call `SetEvent()` for each combination of task and event. You can set multiple events for a task at the same time.

An event can be set indirectly by the RTOS code upon expiration of an alarm (the ACTION attribute of the alarm must be set to SETEVENT and the event must be added to the TASK object) or when a message is transmitted (the NOTIFICATION attribute of the message must be set to SETEVENT).

Events can be set from interrupt level.

You cannot set events to suspended tasks.

## Using the TASKING RTOS for TriCore

You can set several events at a time for a waiting task or ready task:

```
SetEvent( Task1, Event1 | Event2 | ... )
```

If `Task1` is waiting for any of the triggered events it will enter the ready state. If the task is ready, the events remain set. You can clear the events with `ClearEvent()`.

## GetEvent

You can check which events have been set for a given task with the system service:

```
StatusType GetEvent(TaskType, EventMaskRefType);
```

You can call this service to distinguish which event triggered the task and then take the corresponding action. This service can be called from a hook routine or from interrupt level.

```
TASK(Task2)
{
    StatusType      ret;
    EventMaskType   events;
    TaskType        id;

    /* Wait for any of the three events */
    ret = WaitEvent(Event1 | Event2 | Event3);
    if (ret != E_OK)
    {
        LogError(OSServiceID_WaitEvent, ret);
        TerminateTask();
    }

    /* Which events are pending */
    ret = GetTaskID(&id);
    if (ret != E_OK)
    {
        LogError(OSServiceID_GetTaskID, ret);
        TerminateTask();
    }

    ret = GetEvent(id, &events);
    if (ret != E_OK)
    {
        LogError(OSServiceID_GetEvent, ret);
        TerminateTask();
    }

    /* handle events */
    if (events & Event1)
    {
        Action1();
    }
    if (events & Event2)
```

```

    {
        Action2();
    }
    if (events & Event3)
    {
        Action3();
    }

    TerminateTask();
}

```

Every time `Task2` gets activated (events are all cleared) it waits for one of the three events. When running again, it uses `GetEvent()` to find out which events have triggered the task.

## ClearEvent

You can clear events yourself with the system service:

```
StatusType ClearEvent(EventMaskType);
```

You can call `ClearEvent` (and `WaitEvent`) only from tasks for events that are listed in the attribute `EVENT` of the task. Never from a hook routine or an interrupt.

Adding this service to the previous example you can build a simplified version of an event handler task:

```

TASK(eventHandler)
{
    StatusType    ret;
    EventMaskType events;
    TaskType      id;

    while(1)
    {
        /* Wait for any of the three events */
        ret = WaitEvent(Event1 | Event2 | Event3);
        if (ret != E_OK)
        {
            LogError(OSServiceID_WaitEvent, ret);
            TerminateTask();
        }

        /* Which events are pending */
        ret = GetTaskID(&id);
        if (ret != E_OK)
        {
            LogError(OSServiceID_GetTaskID, ret);
            TerminateTask();
        }

        ret = GetEvent(id, &events);
        if (ret != E_OK)

```

## Using the TASKING RTOS for TriCore

```
    {
        LogError(OSServiceID_GetEvent, ret);
        TerminateTask();
    }

    /* Clear events */
    ClearEvent(events);

    /* handle events */
    if (events & Event1)
    {
        Action1();
    }
    if (events & Event2)
    {
        Action2();
    }
    if (events & Event3)
    {
        Action3();
    }
}

TerminateTask();
}
```

### DeclareEvent

Like all other RTOS objects you need to declare the event before using it in your source:

```
DeclareEvent(Event1);

TASK (TaskT)
{
    ...
    WaitEvent(Event1);
}
```

## 6.4. The C Interface for Events

You can use the following data types and system services in your C sources to deal with event related issues.

Element	C Interface
Data Types	EventMaskType EventMaskRefType
Constants	-

<b>Element</b>	<b>C Interface</b>
System Services	DeclareEvent SetEvent ClearEvent GetEvent WaitEvent

Please refer to the ISO 17356 documentation for a detailed description.





# Chapter 7. Resource Management

This chapter explains how the RTOS may synchronize tasks via resources and describes how you can declare RESOURCE objects in the RTOS Configurator.

## 7.1. Key Concepts

### Critical code

A critical code section is a piece of software that must be executed atomically to preserve data integrity and hardware integrity. Critical code sections handle for example:

- access to shared variables.
- most manipulations of linked lists.
- code that increment counters

An example of critical code is:

```
g = g + 1;
```

If global variable `g` is initially set to zero and two processes both execute this code, as a result the value of `g` should be incremented to 2. If Process A executes the code and then Process B does, the result will be correct. However, if A executes and, during the increment instruction, process B also executes the same code, `g` may only be incremented to 1.

### Mutex

A software entity that prevents multiple tasks from entering the critical section. Acquiring mutexes guarantees serialized access to critical regions of code and protects the calling task from being preempted in favor of another task (which also attempts to access the same critical section), until the mutex is dropped.

### Priority inversion

A lower priority task preempts a higher priority task while it has acquired a lock. (See also [Section 7.3.1, Priority Inversion.](#))

### Deadlock

The impossibility of task execution due to infinite waiting for mutually locked resources. (See also [Section 7.3.2, Deadlocks.](#))

Since OS is meant to operate in a critical environment (like the automobile industry) both priority inversion and deadlocks are unacceptable.

## 7.2. What is a Resource?

Resources are used to coordinate concurrent access of several tasks with different priorities to shared resources. During these processes, the RTOS guarantees that two tasks or interrupt routines do not occupy the same resource at the same time.

A resource is equivalent to what the literature commonly refers to as semaphores or mutexes.

Resources are an abstract mechanism for protecting data accesses by multiple tasks or ISRs. A resource request effectively locks the corresponding data against concurrent access by another task. This is usually called a mutex lock. It is implemented by temporarily raising the priority of the calling task so that possible other contending lock requests cannot actually happen during the duration of the lock. This mechanism is also known as the Priority Ceiling Protocol (see [Section 7.3, The Ceiling Priority Protocol](#)). The important aspect of this particular mutex implementation is that the resource request never waits. This makes it specially suitable for ISRs. In this regard, the priority levels are internally expanded to include all maskable interrupt levels on top of the highest real priority level.

Some general ideas are listed below:

1. You must define resources for critical sections that you encounter in the system which are liable to concurrency problems.

2. You configure resources in your RTOS configuration:

1. From the **RTOS** menu, select **New » RESOURCE**.

*The New RESOURCE Object dialog appears.*

2. In the **Name** field enter the name of the resource.

3. Optionally enter a **Description**.

4. Click **OK**.

*The resource is added to the configuration.*

3. In the RTOS Configurator you can configure a task or an interrupt service routine to own a resource (a task or an interrupt service routine owning a resource means that they can occupy and release the resource).

### Example

Let us assume that `Task1`, `Task2` and an asynchronous interrupt service routine named `IsrA`, need to update the same global counter `acounter`. You must configure a new **RESOURCE** object and define `Task1`, `Task2` and `IsrA` as owners of the resource.

RTOS configuration:

▲ T	TASK	Task1
	PRIORITY	1
	SCHEDULE	FULL
	ACTIVATION	1
▷	AUTOSTART	TRUE
R	RESOURCE[1]	[Resource1]
E	EVENT[0]	[]
M	MESSAGE[0]	[]
	STACKSIZE	250
▲ T	TASK	Task2
	PRIORITY	2
	SCHEDULE	FULL
	ACTIVATION	1
▷	AUTOSTART	TRUE
R	RESOURCE[1]	[Resource1]
E	EVENT[0]	[]
M	MESSAGE[0]	[]
	STACKSIZE	250
▲ T	ISR	IsrA
	CATEGORY	2
R	RESOURCE[1]	[Resource1]
M	MESSAGE[0]	[]
	LEVEL	1
C	COUNTER	SYSTEM_COUNTER
R	RESOURCE	RES_SCHEDULER
▲ R	RESOURCE	Resource1
	RESOURCEPROPERTY	STANDARD

The following source code makes sure that the counter update does not suffer from concurrency problems.

C source file:

```
volatile int acounter;

TASK(Task1)
{
    GetResource(Resource1);
    acounter--;
    ReleaseResource(Resource1);
    TerminateTask();
}

TASK(Task2)
{
    GetResource(Resource1);
    acounter--;
    ReleaseResource(Resource1);
}
```

## Using the *TASKING RTOS* for *TriCore*

```
    TerminateTask();
}

ISR( IsrA)
{
    GetResource( Resource1 );
    acounter++;
    ReleaseResource( Resource1 );
}
```

4. Try to avoid superfluous resource definitions. A resource that is owned by only one task is useless. It decreases the performance of the system because:

- Memory is allocated with the configuration data for a useless resource.
- Execution speed decreases because of useless system services around not even real critical code.
- Longer internal searches of the RTOS.

So, a resource should be owned by at least two tasks, by a task and an interrupt service routine or by two interrupt service routines.

5. You should define only one **RESOURCE** object for all the critical sections accessed by the same occupiers.

Let us assume that a second counter `scounter` needs to be updated globally by these three actors. There is no need yet to change the RTOS configuration.

```
TASK ( Task1)
{
    GetResource( Resource1 );
    scounter--;
    ReleaseResource( Resource1 );
    ...
    GetResource( Resource1 );
    acounter--;
    ReleaseResource( Resource1 );
    ...
}

TASK ( Task2)
{
    GetResource( Resource1 );
    acounter--;
    scounter--;
    ReleaseResource( Resource1 );
}

ISR ( IsrA)
{
    GetResource( Resource1 );
```

```

    acounter++;
    scounter++;
    ReleaseResource(Resource1);
}

```

But in case this second global counter needs to be updated by a third task `Task3` and a second ISR `IsrB` then change the RTOS configuration:

▲ T TASK	Task1
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	1
▶ AUTOSTART	TRUE
R RESOURCE[2]	[Resource1, Resource2]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250
▲ T TASK	Task2
PRIORITY	2
SCHEDULE	FULL
ACTIVATION	1
▶ AUTOSTART	TRUE
R RESOURCE[2]	[Resource1, Resource2]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250
▲ T TASK	Task3
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
R RESOURCE[1]	[Resource2]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250
▲ I ISR	IsrA
CATEGORY	2
R RESOURCE[1]	[Resource1]
M MESSAGE[0]	[]
LEVEL	1
▲ I ISR	IsrB
CATEGORY	2
R RESOURCE[1]	[Resource2]
M MESSAGE[0]	[]
LEVEL	2
C COUNTER	SYSTEM_COUNTER
R RESOURCE	RES_SCHEDULER
▶ R RESOURCE	Resource1
▶ R RESOURCE	Resource2

## Using the *TASKING RTOS* for *TriCore*

C source file:

```
TASK (Task1)
{
    ...
    GetResource(Resource1);
    scounter--;
    ReleaseResource(Resource1);
    ...
    GetResource(Resource2);
    acounter--;
    ReleaseResource(Resource2);
    ...
}

TASK (Task2)
{
    ...
    GetResource(Resource2);
    acounter--;
    ReleaseResource(Resource2);
    GetResource(Resource1);
    scounter--;
    ReleaseResource(Resource1);
    ...
}

TASK (Task3)
{
    ...
    GetResource(Resource2);
    scounter--;
    ReleaseResource(Resource2);
    ...
}

ISR (IsrA)
{
    ...
    GetResource(Resource2);
    acounter--;
    ReleaseResource(Resource2);
    GetResource(Resource1);
    scounter--;
    ReleaseResource(Resource1);
    ...
}

ISR (IsrB)
{
    ...
    GetResource(Resource2);
    scounter--;
    ReleaseResource(Resource2);
}
```

```

    ...
}

```

6. You cannot use the system services `TerminateTask`, `ChainTask`, `Schedule`, and/or `WaitEvent` while a resource is being occupied.

```

ISR (Task1)
{
    ...
    GetResource(Resource1);
    acounter--;
    /* This is forbidden - even if Event1 is
       owned by Task1 */
    WaitEvent(Event1);
    ReleaseResource(Resource1);
    ...
}

```

7. The RTOS assures you that an interrupt service routine is only processed under the condition that all resources that might be needed by that interrupt service routine are released.

```

TASK (Task2)
{
    ...
    GetResource(Resource2);
    /* IsrA and IsrB disabled */
    acounter++;
    ReleaseResource(Resource2);
    GetResource(Resource1);
    /* IsrA disabled */
    scounter--;
    ReleaseResource(Resource1);
    ...
}

```

8. Make sure that resources are not still occupied at task termination or interrupt completion since this scenario can lead the system to undefined behavior. You should always encapsulate the access of a resource by the calls `GetResource` and `ReleaseResource`. Avoid code like:

```

GetResource(Resource1);
...
switch ( condition )
{
    case CASE_1 :
        do_something1();
        ReleaseResource(Resource1);
        break;
    case CASE_2 : /* WRONG: no release here! */
        do_something2();
        break;
    default:

```

## Using the TASKING RTOS for TriCore

```
    do_something3();
    ReleaseResource(Resource1);
}
```

9. You should use the system services `GetResource` and `ReleaseResource` from the same functional call level. Even when the function `foo` is corrected concerning the LIFO order of resource occupation like:

```
void foo( void )
{
    ReleaseResource( Resource1 );
    GetResource( Resource2 );
    /* some code accessing resource Resource2 */
    ...
    ReleaseResource( Resource2 );
}
```

there still can be a problem because `ReleaseResource(Resource1)` is called from another level than `GetResource(Resource1)`. Calling the system services from different call levels can cause problems.

10. There is no need to define `RESOURCE` objects to protect critical code which can only be accessed by tasks with the same priority. The reason is simple: the RTOS does not have round-robin scheduling of tasks at the same priority level, we can conclude that two (or more) tasks, with same priority, accessing critical code will not suffer concurrency problems.

This is the basic idea behind the concept of the *ceiling priority protocol*.

11. Be careful using nested resources since the occupation must be performed in strict last-in-first-out (LIFO) order (the resources have to be released in the reversed order of their occupation order).

```
TASK(Task1)
{
    GetResource(Resource1);
    ...
    GetResource(Resource2);
    ...
    ReleaseResource(Resource2);
    ReleaseResource(Resource1);
}
```

The following code sequence is incorrect because function `foo` is not allowed to release resource `Resource1`:

```
TASK(incorrect)
{
    GetResource( Resource1 );
    /* some code accessing resource Resource1 */
    ...
    foo();
    ...
}
```



```

    ReleaseResource( Resource2 );
}

void foo()
{
    GetResource( Resource2 );
    /* code accessing resource Resource2 */
    ...
    ReleaseResource( Resource1 );
}

```

- 12 The RTOS does not allow nested access to the same resource. In the rare cases where you need nested access to the very same resource, it is recommended to use a second resource with the same behavior (so-called linked resources).

You can configure linked resources in your RTOS configuration like:

▲ R RESOURCE	ResourceS
RESOURCEPROPERTY	STANDARD
▲ R RESOURCE	ResourceL
▲ RESOURCEPROPERTY	LINKED
R LINKEDRESOURCE	ResourceS

- 13 Like all other RTOS objects you need to declare a resource before using it in your C source:

```

DeclareResource(Resource1);

TASK (Task1)
{
    GetResource(Resource1)
    ...
}

```

## 7.3. The Ceiling Priority Protocol

The ceiling priority protocol is used in order to eliminate priority inversion and deadlocks.

### 7.3.1. Priority Inversion

A typical problem of common synchronization mechanisms is priority inversion. This means that a lower-priority task delays the execution of higher-priority task.

Let us assume three tasks T1, T2 and T3 with increasing priorities (T1 has the lowest priority and T3 the highest). T1 is running and the others are suspended. All tasks are fully preemptable.

Let us assume that T1 and T3 share resource R. Theoretically, the longest time that T3 can be delayed should be the maximum time that T1 locks the resource R.

## **Using the *TASKING RTOS* for *TriCore***

However let us see what happens in the following time sequence:

1. T1 occupies the resource R.
2. T2 and T3 are activated.
3. T3 preempts T1 and immediately requests R.
4. As R is occupied T3 enters the waiting state.
5. The scheduler selects T2 as the running task.
6. T1 waits till T2 terminates or enters the waiting state.
7. T1 runs again and releases R.
8. T3 immediately preempts T1 and runs again.

Although T2 does not use resource R, it is in fact delaying T3 during its lifetime. So a task with high priority sharing a resource with a task with low priority can be delayed by tasks with intermediate priorities. That should not happen.

### **7.3.2. Deadlocks**

Deadlocks are even more serious when locking resources causes a conflict between two tasks. Each task can lock a resource that the other task needs and neither of the two is allowed to complete.

Imagine what would happen in the following scenario:

1. Task T1 occupies the resource R1.
2. Task T2 preempts T1.
3. Task T2 occupies resource R2.
4. Task T2 attempts to occupy resource R1 and enters the waiting state.
5. Task T1 resumes, attempts to occupy resource R2 and enters the waiting state.
6. This results in a deadlock. T1 and T2 wait forever.

With a properly designed application you can avoid deadlocks but this requires strict programming techniques. The only real safe method of eliminating deadlocks is inherent to the RTOS itself. This RTOS offers the priority ceiling protocol to avoid priority inversion and deadlocks.

### **7.3.3. Description of The Priority Ceiling Protocol**

The principles of the ceiling priority protocol can be summarized as follows:

- At system generation, the RTOS assigns to each resource a ceiling priority. The ceiling priority is set at least to the highest priority of all tasks that access a resource or any of the resources linked to this resource. The ceiling priority must be lower than the lowest priority of all tasks that do not access the resource, and which have priorities higher than the highest priority of all tasks that access the resource.

- If a task requires a resource, and its current priority is lower than the ceiling priority of the resource, the priority of the task will be raised to the ceiling priority of the resource.
- If the task releases the resource, the priority of this task will be reset to its original (rescheduling point).

The problem of priority inversion is eliminated since only one task is actually capable of locking a resource. Referring to the example in [Section 7.3.1, Priority Inversion](#):

1. T1 gets the resource and the RTOS raises its priority to the ceiling priority of the resource R.
2. T3 is activated and remains in the ready state (at least while T1 locks resource R) since its priority is never higher than the current priority of the system. Remember that T1 can neither terminate nor wait for an event at this phase.
3. T2 is also activated and remains in the ready state.
4. T1 finally releases the resource. The RTOS reverts its priority to its normal static level. This is a point of rescheduling: T3 starts running.
5. T3 terminates and T2 starts running.
6. T2 terminates and T1 resumes running.

The only drawback is that T2 is inhibited by a lower priority task, T1. But this occurs only during the locking time which can be calculated and/or minimized. The latency time in this scenario for T2 is far less than for T3 in the previous case.

Deadlock is also easily eliminated because T2 cannot preempt T1. T1 must occupy and release (LIFO) R1 and R2 before T2 attempts to take R2.

### Ceiling Priority Protocol at Interrupt levels

The extension of the ceiling priority protocol to interrupt levels is also simple in this implementation:

Suppose that a resource R is owned by the interrupt service routines ISR1...ISRn and tasks T1 .. Tn. Let P be the maximum interrupt priority level of these ISRs.

When task Tj occupies R, Tj behaves as a nonpreemptive task and all the ISR interrupts with priority P (and lower) are temporarily disabled (all R owners included). Thus, while Tj owns the resource, it can only be preempted by interrupts with a priority higher than P. Since Tj runs as nonpreemptable, even if high priority tasks are activated from an ISR2 interrupt with higher priority than P, they will not be scheduled until Tj releases resource R.

When the task Tj releases R, the priority of this task is reset to its original (rescheduling point). Possible pending interrupts (with priority P or lower) and/or higher priority ready tasks (activated by interrupts with priority higher than P) are now allowed to execute.

When the interrupt service routine ISRj gets resource R, all other ISR interrupts with priority P (and lower) are temporarily disabled (this includes all other R owners) until R is released. The RTOS must handle possible nested accesses to resources at different priority levels.

## 7.4. Grouping Tasks

### What is a group of Tasks?

The RTOS allows tasks to combine aspects of preemptive and nonpreemptive scheduling by defining groups of tasks.

For tasks which have the same or lower priority as the highest priority within a group, the tasks within the group behave like nonpreemptive tasks. For tasks with a higher priority than the highest priority within the group, tasks within the group behave like preemptive tasks.

### How to group Tasks

You can use an internal resource to define explicitly a group of tasks (or equivalently: a group of tasks is defined as the set of tasks which own the same internal resource).

▲ R RESOURCE	in_resource
RESOURCEPROPERTY	INTERNAL

The RTOS automatically takes the internal resource when an owner task enters the running state (not when the task is activated). As a result, the priority of the task is automatically changed to the ceiling priority of the resource. At the points of rescheduling the internal resource is automatically released (the priority of the task is set back to the original).

In the following configuration all the tasks are initially suspended. An event triggers the task `in_1` to activate. The idle task is preempted and the task `in_1` will start execution. Because it owns the internal resource `in_resource`, the task starts running with the ceiling priority of `in_resource` (3) instead of with its static priority (1). This is the starting point in next example.

## Example

RTOS configuration:

▲ T	TASK	in_1
	PRIORITY	1
	SCHEDULE	FULL
	ACTIVATION	1
▷	AUTOSTART	TRUE
R	RESOURCE[1]	[in_resource]
E	EVENT[0]	[]
M	MESSAGE[0]	[]
	STACKSIZE	250
▲ T	TASK	in_2
	PRIORITY	2
	SCHEDULE	FULL
	ACTIVATION	1
	AUTOSTART	FALSE
R	RESOURCE[1]	[in_resource]
E	EVENT[0]	[]
M	MESSAGE[0]	[]
	STACKSIZE	250
▲ T	TASK	in_3
	PRIORITY	3
	SCHEDULE	NON
	ACTIVATION	1
	AUTOSTART	FALSE
R	RESOURCE[1]	[in_resource]
E	EVENT[0]	[]
M	MESSAGE[0]	[]
	STACKSIZE	250
▲ T	TASK	out_1
	PRIORITY	2
	SCHEDULE	FULL
	ACTIVATION	1
	AUTOSTART	FALSE
R	RESOURCE[0]	[]
E	EVENT[0]	[]
M	MESSAGE[0]	[]
	STACKSIZE	250
▲ T	TASK	out_2
	PRIORITY	4
	SCHEDULE	FULL
	ACTIVATION	1
	AUTOSTART	FALSE
R	RESOURCE[0]	[]
E	EVENT[0]	[]
M	MESSAGE[0]	[]
	STACKSIZE	250

## Using the TASKING RTOS for TriCore

C source file:

```
DeclareTask(in_1);
DeclareTask(in_2);
DeclareTask(in_3);
DeclareTask(out_1);
DeclareTask(out_2);

int out_1_cnt;
int out_2_cnt;
int in_1_cnt;
int in_2_cnt;
int in_3_cnt;

TASK (out_1)
{
    out_1_cnt++;
    TerminateTask();
}

TASK (out_2)
{
    out_2_cnt++;
    TerminateTask();
}

TASK (in_1)
{
    in_1_cnt++;
    ActivateTask(out_1);
    /* in_1 runs; out_1 is ready */
    ActivateTask(in_3);
    /* in_1 runs: in_3 is ready */
    ActivateTask(out_2);
    /* out_2 has run */
    /* in_1 resumes execution */
    Schedule();
    /* in_3 and out_1 have run */
    TerminateTask();
}

TASK (in_2)
{
    in_2_cnt++;
    TerminateTask();
}

TASK (in_3)
{
    in_3_cnt++;
```

```

    TerminateTask();
}

```

Features of internal resources are:

- A task can belong exclusively to a one group of tasks therefore owning a maximum of one internal resource.
- Internal resources cannot be occupied and/or released in the standard way by the software application but they are managed strictly internally within a clearly defined set of system functions.

Determining the most appropriate range for the priorities of tasks owning an internal resource, becomes a key factor in the design. In most cases, this range of priorities should be reserved exclusively for the members of the group. Otherwise, low priority tasks in the group could delay tasks outside the group with higher priority. This is exactly what has happened in the previous example: `out_1` was delayed by `in_1`.

## 7.5. The Scheduler as a Special Resource

The scheduler can be considered as a special resource that can be locked by the running task. As a result, while the running task has locked the scheduler, it behaves like a nonpreemptive task (with the same rescheduling points).

If you plan to use the scheduler as a resource, you must first set the attribute `USERESSCHEDULER` to `TRUE` in the OS object of your RTOS configuration. C source code then can look as follows:

```

TASK(Task1)
{
    ...
    /* preemptable */
    GetResource(RES_SCHEDULER);
    /* I am non-preemptable */
    ReleaseResource(RES_SCHEDULER);
    /* preemptable */
    ...
}

```

- You can neither define nor configure this resource. It is a system resource that is added by the RTOS Configurator automatically.
- You do not need to add it to the resource list of any task.
- Interrupts are received and processed irrespective of the state of the resource.

## 7.6. The C Interface for Resources

You can use the following data types, constants and system services in your C sources to deal with resource related issues.

Element	C Interface
Data Types	ResourceType
Constants	RES_SCHEDULER
System Services	DeclareResource GetResource ReleaseResource

Please refer to the ISO 17356 documentation for a detailed description.



# Chapter 8. Alarms

This chapter describes how the RTOS offers alarm mechanisms based on counting specific recurring events and describes how you can add these objects in the RTOS Configurator in order to specify your alarm configuration.

## 8.1. Introduction

The RTOS provides services for processing recurring events. A recurring event is an abstract entity which has been defined in the scope of a particular application. Each application monitors its events, therefore, differently. A "wheel has rotated five more degrees" or "routine  $\epsilon$  has been called" could be examples of recurring events.

Each of these recurring events can be registered in a dedicated counter (a COUNTER object). You must increment this counter each time the associated event occurs. In the 'wheel' example, you probably increment the counter in an interrupt service routine. In the 'routine' example, you increment the counter in the body of  $\epsilon$ .

Based on these counters, you can install alarms. "Activation of a specific task every time the wheel rotates 180 degrees" or "setting an event when routine  $\epsilon$  has been called ten times" are examples of such alarms.

We say that an alarm expires when the counter reaches a preset value. You can bind specific actions to alarms and the RTOS will execute these actions upon expiration of the alarms.

## 8.2. Counters

### 8.2.1. What is a Counter?

A counter is an abstract entity directly associated with a recurring event. The counter registers happenings of its event (ticks) in a counter value (which must be incremented every time the event takes place).

The only way to interact with a counter is via `IncrementCounter()`.

Assume that your application needs to monitor the rotation of a wheel. Your application software, project agreement, works with one degree as the atomic unit in the system. You can define a COUNTER object in the RTOS configuration to represent the rotated angle:

COUNTER	sensorC
MAXALLOWEDVALUE	359
TICKSPERBASE	1
MINCYCLE	5

MAXALLOWEDVALUE is set to 359 since this corresponds to one complete full turn (360 degrees is equivalent to 0 degrees).

MINCYCLE depends on the application sensibility and/or the hardware itself. In this example, your application cannot log any action that happens before the wheel has rotated five degrees.

## Using the TASKING RTOS for TriCore

You build the application regardless of the hardware interface that shall, eventually, monitor the wheel rotation. Ideally the dependency on such a device should be minimized.

Suppose three different sensors S1, S2, S3 are candidates for the hardware interface. They all interface equally with your chip (the pulse is converted into an external I/O hardware interrupt). But they send the pulses at different rates, S1 every quarter of a degree, S2 every half a degree and S3 every degree.

The impact of this on your application is minimal. You only need to modify the TICKSPERBASE attribute of your RTOS configuration. This attribute defines how many ticks are requested to increase the counter unit by one. Hence, the value for the attribute must be 4 (if S1), 2 (if S2) and 1 (if S3).

If we select S2, the RTOS configuration for COUNTER would look as follows:

COUNTER	sensorC
MAXALLOWEDVALUE	359
TICKSPERBASE	2
MINCYCLE	5

After RTOS code generation, the attribute values of counter `sensorC` are available to your application as constants:

```
OSMAXALLOWEDVALUE_sensorC : 359
OSTICKSPERBASE_sensorC    : 2
OSMINCYCLE_sensorC       : 5
```

If the counter demands hardware or software initialization, you can use the `StartUpHook()` routine to place the initialization code.

You are responsible for detecting the recurring events of your own counters and, as a follow-up, notifying the RTOS. You must inform the RTOS about the arrival of a new sensor tick with the system service:

```
DeclareCounter(sensorC);
```

```
ISR (sensorHandler)
{
    IncrementCounter(sensorC);
    ...
}
```

`sensorHandler` must be ISR Category 2.

See [Section 9.3, Defining an Interrupt in the C Source](#).

### 8.2.2. The RTOS System Counter

The RTOS always offers a counter that is derived from a hardware timer. This counter is known as the system counter. You can neither define nor configure this counter in the RTOS configuration. It is a counter that is always present in the RTOS configuration and is called `SYSTEM_COUNTER`.

The unit of time is the system tick (as the interval between two consecutive hardware clock interrupts).

The RTOS parameter OSTICKDURATION defines the length (in nanoseconds) of the system tick. If you want to time certain actions in your application, you must declare an alarm with the system counter as a counter:

COUNTER	SYSTEM_COUNTER
ALARM	Alarm1
COUNTER	SYSTEM_COUNTER
ACTION	ACTIVATETASK
AUTOSTART	FALSE

If you plan to use the system counter, i.e. if you define ALARM objects that are based on the SYSTEM\_COUNTER, you first need to set the non-standard attribute of the OS object USERTOSTIMER to TRUE.

OS	New_OS
STATUS	EXTENDED
STARTUPHOOK	FALSE
ERRORHOOK	TRUE
SHUTDOWNHOOK	TRUE
PRETASKHOOK	FALSE
POSTTASKHOOK	FALSE
USEGETSERVICEID	TRUE
USEPARAMETERACCESS	TRUE
USERESCHEDULER	TRUE
LONGMSG	FALSE
ORTI	TRUE
RUNLEVELCHECK	TRUE
SHUTDOWNRETURN	TRUE
IDLEHOOK	FALSE
IDLELOWPOWER	FALSE
USERTOSTIMER	TRUE
RTOSTIMERPRIO	1
RTOSTIMER	T3
OSCLOCKHZ	1000
CPCLOCKMHZ	200

The RTOSTIMERPRIO sub-attribute specifies the interrupt priority. The RTOS needs this information to build the interrupt framework. The timer interrupt behaves as a Category 2 ISR (See [Section 9.4, The Category of an ISR Object](#) to learn what Category 1 and Category 2 interrupts are).

For TriCore GPT120 you can set RTOSTIMER to one of the timers T2, T3, T4, T5 or T6. T6 has an auto reload capability. The other timers are reloaded in the interrupt handlers. T6 is the most accurate timer.

You are not allowed to call the `IncrementCounter()` system service to increase the system counter.

You can use the following system constants related to the system counter in your application:

- OSMAXALLOWEDVALUE

This value determines the upper limit for the timer value unit.

## Using the TASKING RTOS for TriCore

- OSTICKSPERBASE

This value determines how many clock ticks constitute a timer unit.

- OSMINCYCLE

This value represents an absolute minimum for the possible expiring times of system alarms. You can set alarms which actions are meant to happen after OSMINCYCLE time units.

- OSTICKDURATION

The timer duration in nanoseconds.

## 8.3. What is an Alarm?

An alarm is a counter based mechanism to provide services to activate tasks, set events or call specific routines when the alarm expires. When you set an alarm, you basically state two things: (1) a preset value for the counter and (2) the action to be triggered when the counter reaches that value.

1. Alarm have an associated counter. Multiple alarms can be associated to the same counter.

▲ COUNTER	sensorC
MAXALLOWEDVALUE	100
TICKSPERBASE	2
MINCYCLE	1
▲ ALARM	sensorAA
COUNTER	sensorC
▶ ACTION	ACTIVATETASK
AUTOSTART	FALSE
▲ ALARM	sensorAE
COUNTER	sensorC
▶ ACTION	SETEVENT
AUTOSTART	FALSE

2. In the RTOS configuration you must configure the action to be performed when the alarm expires. This information is permanent: it is not possible to change the associated action to an alarm at run-time.
3. You can configure an alarm to set a specific event when the alarm expires. In that case, you must specify which event is set and to which task.

▲ ALARM	sensorAE
COUNTER	sensorC
▶ ACTION	SETEVENT
EVENT	sensorE
TASK	sensorT
AUTOSTART	FALSE

When the alarm reaches the preset value, the RTOS code sets event `sensorE` to task `sensorT`. If task `sensorT` waits for such an event (normal case) this becomes a point of rescheduling.

4. You can configure an alarm to activate a certain task when it expires:

ALARM	sensorAA
COUNTER	sensorC
ACTION	ACTIVATETASK
TASK	sensorT
AUTOSTART	FALSE

When the alarm reaches the preset value, the RTOS code will try to activate task `sensorT`. If task `sensorT` is in the suspended state, this becomes a point of rescheduling.

5. You can configure an alarm to run a callback routine when it expires.

ALARM	sensorAC
COUNTER	sensorC
ACTION	ALARMCALLBACK
CALLBACK	sensorCB
AUTOSTART	FALSE

A callback must be defined in the application source like:

```
ALARMCALLBACK(sensorCB)
{
    /* application processing */
}
```

The processing level of a callback is an Interrupt Service Routine level and runs with Category 2 interrupts disabled. Therefore the RTOS expects very short code for the callback routines.

6. You can use the system service `SetRelAlarm()` to predefine a counter value for an alarm to expire relative to the actual counter value:

```
StatusType SetRelAlarm(AlarmType alarm,
                       TickType increment, TickType cycle);
```

When this system service is invoked, the alarm is set to expire at the current value of the counter plus an increment (if the alarm is not in use, obviously). The increment value must be at least equal to the `MINCYCLE` attribute of the associated counter.

The `cycle` parameter determines whether the alarm is periodic or not. If not zero, the alarm is restarted upon expiration with `cycle` as a new time-out interval (at least equal to the `MINCYCLE` attribute of the associated counter). If `cycle` equals to zero, the alarm will not be restarted.

This service can be called at task or interrupt level but not from hook routine level. Below you will find an example of how to install an alarm that will activate task `sensorT` every 90 degrees:

```
SetRelAlarm(sensorAA, 90, 90);
```

## Using the TASKING RTOS for TriCore

7. You can use the system service `SetAbsAlarm()` to predefine a counter value for an alarm to expire in absolute terms:

```
Type SetAbsAlarm(AlarmType alarm, TickType increment, TickType cycle);
```

When this system service is invoked the alarm is set to expire at an specific absolute value of the counter (if the alarm is not in use, obviously). The `cycle` determines whether the alarm is periodic or not. If not zero, the alarm is restarted upon expiration with `cycle` as a new time-out interval. If `cycle` equals to zero, the alarm will not be restarted.

This service can be called at task or interrupt level but not from hook routine level.

Below you find an example of how to install an alarm that sets event `sensorE` to task `sensorT` exactly when the wheel angle is 0 or 180 degrees:

```
SetAbsAlarm(sensorAE, 0, 180);
```

8. You can configure an alarm to run at startup. Normally, these are periodic alarms carrying out periodic actions required by the application. Even before the first tasks have been scheduled, the alarm is already running to expiration.

You must set the attribute `AUTOSTART` to `TRUE`. The sub-attributes `ALARMTIME` and `CYCLETIME` behave the same as `increment` and `cycle` for the `SetRelAlarm()` system service. You must indicate also under which application modes the alarm should autostart.

The following example counts the total number of turns:

RTOS configuration:

APPMODE	AppModeA
TASK	sensorT
COUNTER	SYSTEM_COUNTER
COUNTER	sensorC
MAXALLOWEDVALUE	359
TICKSPERBASE	1
MINCYCLE	1
ALARM	sensorAC
COUNTER	sensorC
ACTION	ALARMCALLBACK
CALLBACK	no_turns_callback
AUTOSTART	TRUE
CYCLETIME	359
APPMODE[1]	[AppModeA]
ALARMTIME	359

The alarm will autostart if the environment is correct:

C source file:

```
DeclareAppMode(AppModeA);
```

```

volatile int no_turns;

ALARMCALLBACK(no_turns_callback)
{
    no_turns++;
}

int main(void)
{
    StartOS(AppModeA);
    return 0;
}

```

9. You can use a combination of the system services `GetAlarm()` and `CancelAlarm()` to set time-outs associated to actions.

```

StatusType GetAlarm(AlarmType, TickRefType);

StatusType CancelAlarm(AlarmType);

```

With the `GetAlarm()` routine you can check whether the alarm has already expired or not. With the `CancelAlarm()` routine you actually cancel a running alarm.

The following example shows how to set a time-out associated with an action:

```

TASK(sensorT)
{
    TickType tick;
    ...
    /* start alarm */
    SetRelAlarm(sensorAE,90,0);
    /* indicate I am waiting Action */
    WaitAction();
    /* wait for the event: It is set when the action
       has completed or by the alarm */
    WaitEvent(sensorE);
    /* the event has been set */
    GetAlarm(sensorAE,&tick);
    if (tick)
    {
        /* Action was completed */
        CancelAlarm(sensorAE);
    }
    else
    {
        /* Timeout */
    }
    ...
    TerminateTask();
}

```

## Using the TASKING RTOS for TriCore

10. You can use the system counter as a generator for software timers. A software timer basically guarantees the application that a certain action will occur after a certain period. If (1) the action is short enough to be the body of a callback function and (2) the time period in which the action must occur is  $t$  milliseconds, and (3) assuming that an alarm `SoftwareTimer` has been already declared, the next system call will take care of executing the callback code in exactly  $t$  milliseconds.

```
SetRelAlarm(SoftwareTimer, (t/OSTICKDURATIONINMSCS), 0);
```

11. You can use `SetRelAlarm()`, `WaitEvent()` and `ClearEvent()` to create an RTOS version of a standard delay service.

RTOS configuration:

TASK	task_1
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	1
AUTOSTART	TRUE
RESOURCE[0]	[]
EVENT[1]	[delay_event]
MESSAGE[0]	[]
STACKSIZE	250
COUNTER	SYSTEM_COUNTER
ALARM	delay_task_1
COUNTER	SYSTEM_COUNTER
ACTION	SETEVENT
EVENT	delay_event
TASK	task_1
AUTOSTART	FALSE
EVENT	delay_event

C source file:

```
DeclareAlarm(delay_task_1);
DeclareEvent(delay_event);
DeclareTask(task_1);

TASK(task_1)
{
    ...
    /* delay the system one second */
    SetRelAlarm(delay_task_1, 1000000000 / OSTICKDURATION, 0);
    WaitEvent(delay_event);
    ClearEvent(delay_event);
    ...
    TerminateTask();
}
```

Note that an alarm with a `SETEVENT` action sets the specified event in the specified task. So, for each task that needs to wait for a specific event, you need to create a separate alarm.



12 Like all other RTOS objects you need to declare an alarm before using it in your source in order to compile your module:

```
DeclareAlarm(Alarm1);

TASK (Task1)
{
    CancelAlarm(Alarm1)
    ...
}
```

## 8.4. The C Interface for Alarms

You can use the following data types and system services in your C sources to deal with alarm related issues.

Element	C Interface
Data Types	TickType TickRefType AlarmBaseType AlarmBaseRefType AlarmType
Constants	OSMAXALLOWEDVALUE_x ('x' is a counter name) OSTICKSPERBASE_x ('x' is a counter name) OSMINCYCLE_x ('x' is a counter name) OSMAXALLOWEDVALUE OSTICKSPERBASE OSMINCYCLE OSTICKDURATION SYSTEM_COUNTER
System Services	DeclareAlarm DeclareCounter GetAlarmBase GetAlarm IncrementCounter SetRelAlarm SetAbsAlarm CancelAlarm

Please refer to the ISO 17356 documentation for a detailed description.



# Chapter 9. Interrupts

This chapter describes how you can declare ISR objects in the application OIL file in order to optimize the interrupt configuration.

## 9.1. Introduction

An interrupt is a mechanism for providing immediate response to an external or internal event. When an interrupt occurs, the processor suspends the current path of execution and transfers control to the appropriate Interrupt Service Routine (ISR). The exact operation of an interrupt is so inherently processor-specific that they may constitute a major bottleneck when porting applications to other targets.

In most of the embedded applications the interrupts constitute a critical interface with external events (where the response time often is crucial).

## 9.2. The ISR Object

Among the typical events that cause interrupts are:

- Overflow of hardware timers
- Reception/Transmission of data
- External events
- Reset

Please check the documentation of your core to find out the interrupt sources of the core you are using.

Every interrupt has to be associated with a piece of code called Interrupt Service Routine (or: ISR). The architecture defines a specific code address for each ISR, which may be stored in the Interrupt vector Table (IVT) or in the interrupt controller.

### Defining an ISR object in the OIL file

If your application uses, for example, an external interrupt, you define one ISR object in your RTOS configuration:

1. From the **RTOS** menu, select **New » ISR**.

*The New ISR Object dialog appears.*

2. In the **Name** field enter the name of the interrupt, for example `interrupt_x`.
3. Optionally enter a **Description**.
4. Click **OK**.

*The interrupt is added to the configuration.*

ISR	interrupt_x
CATEGORY	1
RESOURCE[0]	[]
MESSAGE[0]	[]
LEVEL	1

You normally place the initialization code for the ISR objects in the `StartupHook` routine.

### 9.2.1. The ISR Non-Standard Attribute LEVEL

The non-standard attribute `LEVEL` is the TriCore interrupt priority level. The type of the `LEVEL` attribute is `UINT32`. The default priority is 1. You have to make sure that interrupts of Category 2 (including RTOS timer) have a lower priority number than interrupts of Category 1.

## 9.3. Defining an Interrupt in the C Source

To define an interrupt service routine, you must use the macro `ISR` in your application software. You must pass the name of the related ISR object, as specified in the RTOS configuration, as parameter to the macro:

```
ISR(interrupt_x)
{
    /* ... code ... */
};
```

The RTOS uses this macro to encapsulate the implementation-specific formatting of the routine definition (`interrupt_x` is the identity of the ISR related object and has `IsrType` type). The C name of the function that correspond to the interrupt service routine is created by prepending the tag `_os_u_`. The function can then be viewed with the debugger using the mingled name: `_os_u_interrupt_x`.

Migration to another platform should have almost no impact on your application source code. You remain unaware of how the interrupt framework is built internally, i.e. how the RTOS dispatches the execution flow to `_os_u_interrupt_x()` when an external interrupt is generated.

## 9.4. The Category of an ISR Object

Interrupts can be divided into category 1 and 2.

### Category 1

These ISRs cannot use system services. The internal status of the RTOS before and after the interrupt always prevails. After the ISR has finished, processing continues exactly at the same instruction where the interrupt occurred.

ISRs of this category have the least overhead and since they can always run concurrently with the RTOS code, they are hardly disabled. They execute normally at high priorities and have small handlers.

An example could be a serial interrupt that provides `printf` functionality.

ISR	isrSerial1
CATEGORY	1
RESOURCE[0]	[]
MESSAGE[0]	[]
LEVEL	1

## Category 2

These ISRs can use a subset of system services. Thus the internal status of the RTOS might have been altered after the ISR has been served. Now, after the ISR's handler, processing may (or may not) continue exactly at the same instruction where the interrupt did occur. If no other interrupt is active and the preempted task does not have the highest priority among the tasks in the "ready-to-run array" anymore, rescheduling will take place instead.

ISRs of this category have the most overhead and because they cannot always run concurrently with the RTOS code (they access internals of the RTOS via their system services), they are constantly enabled/disabled.

An example could be a serial interrupt receiving characters and storing them in a buffer. When a 'end-of-frame' character is received, a message is sent to a task in order to process the new frame.

ISR	isrSerial2
CATEGORY	2
RESOURCE[0]	[]
MESSAGE[0]	[]
LEVEL	1

These interrupts typically require a task to be activated, an event to be set, or a message to be sent. The list of available system services follows:

ActivateTask	GetTaskID	DisableAllInterrupts
GetTaskState	GetResource	EnableAllInterrupts
ReleaseResource	SetEvent	SuspendAllInterrupts
GetEvent	GetAlarmBase	ResumeAllInterrupts
GetAlarm	SetRelAlarm	SuspendOSInterrupts
SetAbsAlarm	CancelAlarm	ResumeOSInterrupts
GetActiveApplicationMode	ShutdownOS	

## 9.5. Nested ISRs

RTOS interrupts are normally maskable interrupts. A running ISR can be preempted if the incoming ISR has been configured with higher hardware priority. The maximum run-time depth of nested interrupt levels depends on the processor itself (check your manual). However, there are some premises that always prevail:

- All pending interrupts must be processed before returning to task level.

## Using the *TASKING RTOS* for *TriCore*

- Re-scheduling can take place only upon termination of Category 2 ISRs.

The combination of these premises leads to the golden rule:

- Re-scheduling from interrupt level (the RTOS resuming execution somewhere else than where the system was preempted by the first incoming ISR) can take place only upon termination of a Category 2 ISR at first nesting level.

TriCore Category 2 interrupts must have a lower priority LEVEL number than Category 1 interrupts. The RTOS timer is also treated as a Category 2 interrupt and, therefore, must also have a lower priority LEVEL number than Category 1 interrupts.














## 9.6. ISRs and Resources

In [Chapter 7, \*Resource Management\*](#), it was described how we can use resources to avoid concurrency problems when several tasks and/or ISRs have access to the same critical code section. If your ISR demands manipulation of a certain critical section, which access is controlled by resource R, you need to add R to the list of resources owned by the ISR.

Category 1 ISRs cannot own resources.

If `IsrL1` and `IsrL2` are ISR objects that update the same counter (increased by one unit in `IsrL2` and decreased by one unit in `IsrL1`) in their handlers, they must own the same resource `ResourceR`. A task `TaskT` can also be activated to output the value.

RTOS configuration:

▲  TASK	TaskT
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	1
AUTOSTART	FALSE
 RESOURCE[1]	[ResourceR]
 EVENT[0]	[]
 MESSAGE[0]	[]
STACKSIZE	250
▲  ISR	IsrL1
CATEGORY	2
 RESOURCE[1]	[ResourceR]
 MESSAGE[0]	[]
LEVEL	1
▲  ISR	IsrL2
CATEGORY	2
 RESOURCE[1]	[ResourceR]
 MESSAGE[0]	[]
LEVEL	2
 COUNTER	SYSTEM_COUNTER
 RESOURCE	RES_SCHEDULER
▶  RESOURCE	ResourceR

C source file:

```

DeclareTask(TaskT);
DeclareResource(ResourceR);

int global_counter;

ISR(IsrL1)
{
    GetResource(ResourceR);
    global_counter--;
    ReleaseResource(ResourceR);
}

ISR(IsrL2)
{
    GetResource(ResourceR);
    global_counter++;
    ReleaseResource(ResourceR);
}

TASK(TaskT)
{
    int local_counter;

```

## Using the TASKING RTOS for TriCore

```
GetResource(ResourceR);
local_counter = global_counter;
ReleaseResource(ResourceR);

printf("%d\n", local_counter);

TerminateTask();
}
```

## 9.7. ISRs and Messages

Chapter 10, *Communication* describes how an ISR object might be defined as a sender and/or a receiver of messages. In both cases the ISR object must own the message. You can use messages to pass information between interrupt service routines, like you pass arguments to a function.

In the RTOS configuration you can use the standard attribute MESSAGE (a multiple reference of type MESSAGE\_TYPE) to add messages to the list of messages owned by the ISR.

### Example

Suppose that an ISR object `isrSender` sends a message to another ISR object `isrRec`. Your RTOS configuration and C source file now look like follows.

RTOS configuration:

ISR	recISR
CATEGORY	2
RESOURCE[0]	[]
MESSAGE[1]	[recMsg]
LEVEL	2
ISR	sendISR
CATEGORY	2
RESOURCE[0]	[]
MESSAGE[1]	[sendMsg]
LEVEL	1
COUNTER	SYSTEM_COUNTER
RESOURCE	RES_SCHEDULER
COM	New_COM
MESSAGE	recMsg
MESSAGEPROPERTY	RECEIVE_UNQUEUED_INTERNAL
SENDINGMESSAGE	sendMsg
INITIALVALUE	1
NOTIFICATION	NONE
MESSAGE	sendMsg
MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	int
NOTIFICATION	NONE



C source file:

```

DeclareMessage (sendMsg) ;
DeclareMessage (recMsg)

ISR (sendISR)
{
    int data;

    data = GetData();
    SendMessage (sendMsg, &data);
}

ISR (recISR)
{
    int data;

    ReceiveMessage (recMsg, &data);
    ProcessData (data);
}

```

## 9.8. Interrupt Disable/Enable Services

A number of interrupt disable/enable functions are available. These services always come in pairs:

Critical code	Services	Suspended ISRs
very short (no nesting)	DisableAllInterrupts EnableAllInterrupts	ISR1s and and ISR2s
very short (nesting)	SuspendAllInterrupts ResumeAllInterrupts	ISR1s and and ISR2s
short (nesting)	SuspendOSInterrupts ResumeOSInterrupts	ISR2s
long	GetResource ReleaseResource	Only ISR2s owning the resource

In the following sections these pairs are described into more detail.

### 9.8.1. Disable/Enable All Interrupts

You can use the following system services to disable/enable all maskable interrupts:

```

void DisableAllInterrupts(void);

void EnableAllInterrupts(void);

```

the `DisableAllInterrupts()` service disables globally all interrupts (by clearing/setting a global enable/disable bit or by raising the processor priority level above all possible interrupt levels).

## Using the TASKING RTOS for TriCore

The `EnableAllInterrupts()` service does the opposite, it restores the saved state in the previous routine.

You can call these services from Category 1 ISR and Category 2 ISR and from the task level, but not from hook routines.

These services are intended to encapsulate a critical section of the code (no maskable interrupts means no scheduling which in its turn means no concurrency). It is a much faster and costless alternative to the `GetResource/ReleaseResource` routines.

```
TASK(TaskT)
{
    ...
    DisableAllInterrupts();
    /* critical code section */
    EnableAllInterrupts();
    ...
}
```

The critical area should be extremely short though, since the system as a whole is on hold (even Category 1 ISRs are disabled!). `DisableAllInterrupts()` must always precede the critical section and immediately after the section, `EnableAllInterrupts()` must follow.

Avoid situations like below:

```
ISR(WrongISR)
{
    DisableAllInterrupts();
    if (A)
    {
        EnableAllInterrupts();
        doSomething();
    }
    else
    {
        ...
    }
    return;
}
```

This causes the system to be outbalanced when returning from ISR if `A` is zero.

Also, no service calls are allowed within this critical section. You must avoid code like below:

```
TASK(TaskT)
{
    ...
    DisableAllInterrupts();

    /* critical code section */
    SetEvent(TaskB,EventE);          /* not allowed */
}
```

```

    EnableAllInterrupts();
    ...
}

```

You should be careful when building library functions which are potential users of these services, since nested calls are never allowed. Avoid situations like below:

```

static void f(void)
{
    DisableAllInterrupts();
    otherThings();
    EnableAllInterrupts();
    return;
}

```

```

TASK(TaskT)
{
    ...
    DisableAllInterrupts();
    someThings();
    f();
    EnableAllInterrupts();
    ...
    return;
}

```

As a rule of thumb you should try to avoid function calls while in the critical section.

## 9.8.2. Suspend/Resume All Interrupts

You can use the following system services to suspend/resume all maskable interrupts:

```
void SuspendAllInterrupts(void);
```

```
void ResumeAllInterrupts(void);
```

They enhance the previous pair `DisableAllInterrupts()/EnableAllInterrupts()` in order to allow nesting. In case of nesting pairs of calls, the interrupt recognition status saved by the first call of `SuspendAllInterrupts()` is restored by the last call of the `ResumeAllInterrupts()` service.

```

static void f(void)
{
    /* nothing happens with the status */
    SuspendAllInterrupts();
    otherThings();
    /* status is not yet restored */
    ResumeAllInterrupts();
    return;
}

```

```
TASK(TaskT)
```

## Using the TASKING RTOS for TriCore

```
{
    ...
    /* status is saved now */
    SuspendAllInterrupts();
    someThings();
    f();
    /* status is restored now */
    ResumeAllInterrupts();
    ...
    return;
}
```

The considerations for the pair `DisableAllInterrupts / EnableAllInterrupts` apply here too.

### 9.8.3. Suspend/Resume OS Interrupts

The previous pairs disabled all maskable interrupts, including your Category 1 ISRs, while in the critical code section. However, theoretically there is no need to disable the Category 1 ISRs in order to prevent concurrency problems (they are never a rescheduling point).

If you do not want to disable a Category 1 ISR while executing certain critical code, you can use the following pair to encapsulate the section instead:

```
void SuspendOSInterrupts(void);
```

```
void ResumeOSInterrupts(void);
```

This pair suspends and resumes only category 2 ISRs between the calls (with nesting support). Note that the overhead in code with this pair is normally bigger.

RTOS configuration:

▶ TASK	TaskT
▲ ISR	IsrC1
CATEGORY	1
RESOURCE[0]	[]
MESSAGE[0]	[]
LEVEL	2
▲ ISR	IsrC2
CATEGORY	2
RESOURCE[0]	[]
MESSAGE[0]	[]
LEVEL	1

C source file:

```
TASK(TaskT)
{
    ...
    SuspendOSInterrupts();
    /* critical code */
    /* IsrC1 is enabled */
    /* IsrC2 is disabled */
}
```

```

    ResumeOSInterrupts();
    ...
    TerminateTask();
}

```

The considerations for the pair `DisableAllInterrupts / EnableAllInterrupts` apply here too. Like the pair `SuspendAllInterrupts / ResumeAllInterrupts`, nesting is allowed.

## 9.9. The C Interface for Interrupts

You can use the following data types and system services in your C sources to deal with interrupt related issues.

Element	C Interface
Data Types	-
Constants	-
System Services	EnableAllInterrupts DisableAllInterrupts ResumeAllInterrupts SuspendAllInterrupts ResumeOSInterrupts SuspendOSInterrupts

Please refer to the ISO 17356 documentation for a detailed description.



# Chapter 10. Communication

This chapter describes the communication services to offer you a robust and reliable way of data exchange between tasks and/or interrupt service routines and how you can declare MESSAGE and COM objects in the TASKING RTOS Configurator.

## 10.1. Introduction

In most of the embedded applications the interrupts constitute a critical interface with external events (where the response time often is crucial).

Although the COM and OS standards could be mutually exclusive, this RTOS combines them both. In the RTOS Configurator you can configure both the OS and the COM objects. Both the OS and the COM APIs are included in the system header file `rtos.h`. You must include this header file in your C source to compile your application.

As was stated in [Chapter 1, \*Introduction to the RTOS Kernel\*](#), this implementation supports only a subset (internal communication) of COM3.0.3. In internal communication the interprocess communication is limited to a single microcontroller where a physical network does not exist.

This COM implementation provides all the features defined by the ISO 17356 standard for the Communication Conformance Class CCCB.

Without the benefit of communication services, the only possibility for tasks and interrupt service routines to share data is the usage of global data. Although this mechanism might be extremely effective in some cases, it fails to satisfy the most general case. The communication services offer you a robust and reliable way to exchange data.

### The conformance class CCCB

The main purpose of conformance classes is to ensure that applications that were built for a particular conformance class are portable across different RTOS implementations and CPUs featuring the same level of conformance class. The CCCB conformance class

- Does not offer support for external communication.
- Supports both unqueued/queued messages.
- Supports `SendMessage/ReceiveMessage` routines.
- Incorporates Notification Mechanisms (only Class 1).
- Supports `GetMessageStatus()` API.

Within this conformance class only the interaction layer is implemented and not the network and/or data link layers. This implementation allows you the transfer of data between tasks and/or interrupt service routines within the same CPU.

## 10.2. Basic Concepts

This section presents some basic concepts and definitions.

### One sender sends a message to one or more receivers

This is the leading principle of the communication mechanism. Throughout the documentation and source code examples, etc. you will find sentences like "the task `TaskA` sends message `M` to tasks `TaskB` and `TaskC` and to the interrupt service routine `ISRA`". In this case, for the message `M`, `TaskA` is the sender and `TaskB`, `TaskC` and `ISRA` are the receivers. This situation is taken as an example for the rest of this section.

### Message

The message is the physical application data that is exchanged between a sender and its receivers. A message can have zero (or more) senders and zero (or more) receivers.

Messages are equal to data, i.e. bits. It has no direct OIL representation. The set 'sender(s) of a message', 'message data' and 'receiver(s) of a message' represents a closed unit of communication. On both the sender and receiver sides there must be an agreement about the type of the exchange message data.

### Sender of a message

A `TASK` (or an `ISR`) object can be allowed to send a particular message. A `TASK` (or an `ISR`) object, for example, can be a sender for message `M1`, a receiver for message `M2`, and none of both for message `M3`.

In the example, `TaskA` prepares the data and uses the system service `SendMessage()` to start the transmission to the receivers.

### Receiver of a message

A `TASK` (or an `ISR`) object can be allowed to receive a particular message. A `TASK` (or an `ISR`) object, for example, can be a receiver for message `M1`, a sender for message `M2`, and none of both for message `M3`.

In the example, `TaskB`, `TaskC` and `ISRA` use the system service `ReceiveMessage()` to receive the data sent by `TaskA`.

### Unqueued Receive Message

On the receiving side an unqueued message is not consumed by reading; it returns the last received value each time it is read.

If in the example the message `M` is unqueued for `TaskB` and `ISRA`, both will read from the same buffer on the receive side when using `ReceiveMessage()`. The buffer is overwritten for both `TaskB` and `ISRA` only when `TaskA` sends new data (`ReceiveMessage()` keeps reading the same value meanwhile). More than one receiver can read from the same unqueued buffer.



## Queued Receive Message

On the receiving side a queued message can only be read once (the read operation removes the oldest message from the queue).

If in the example the message  $M$  is queued for  $\text{TaskC}$ , there will be a dedicated receive queue buffering the messages for  $\text{TaskC}$  (every queued receiver has its own receive queue). The queue size for a particular message is specified per receiver. If a receive queue is full and a new message arrives, the message is lost for this receiver. Obviously to prevent this situation, the average processing time of a message should be shorter than the average message interarrival time.

## Send Message Object

The send message object is the internal container where the data is stored on the sending side, every time that a sender of the message attempts to send the message.

In the example there will be only one send message object for  $\text{TaskA}$ .

## Receive Message Object

The receive message object is the internal container where the data is stored on the receiving side. The message object is available for an arbitrary number of receivers if the message is unqueued, or for only one receiver when queued.

In the example there will be two receive message objects, one for  $\text{TaskB}$  and  $\text{ISRA}$  (which size is the size of the transmitted data) and a second one for  $\text{TaskC}$  (which size is the size of the transmitted data times the size of the queue).

## Symbolic Name

A symbolic name is the application identification for a message object (send or receive).

A symbolic name identifies either a send message object or a received message object for an unqueued receive message or a received message object for a queued receive message. In fact, the symbolic name becomes an alias for the container.

## 10.3. Configuring Messages

For every message you must define one symbolic name on the sending side. On the receiver side you define symbolic names for receivers that do not queue the message. Remember that more than one receiver can read from the same receive object. However, you must define a symbolic name for each receiver that queues the message.

The phases of message configuration are shown below, with help of the example in the previous section.

1. Isolate all the messages in the system.

$M$  has been identified as the only message for the system.

2. Identify the Send Message Object for every message.

## Using the TASKING RTOS for TriCore

$M$  has one Send Message Object, let us call it `sendM`.

### 3. Configure the Send Message Objects in the RTOS Configurator.

You configure a send message object by defining a MESSAGE object with the value for its MESSAGEPROPERTY set to `SEND_STATIC_INTERNAL`.

In this case (and assuming that the type of the transmitted data is the built-in type integer):

MESSAGE	sendM
MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	int
NOTIFICATION	NONE

### 4. Configure the senders of the messages.

The senders of the message  $M$  are those TASK and/or ISR objects that can use the system service `SendMessage()` to send the message  $M$  to its receivers (if any).

With the standard attribute MESSAGE (a multiple reference of type MESSAGE\_TYPE) in the TASK/ISR objects you can add messages to the list of messages owned by the TASK or ISR.

In order to define the TASK `TaskA` as a sender of message  $M$  you only need to add `sendM` to the message list of the `TaskA` object:

TASK	TaskA
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	1
AUTOSTART	TRUE
RESOURCE[0]	[]
EVENT[0]	[]
MESSAGE[1]	[sendM]
STACKSIZE	250

### 5. Identify the Receive Message Objects for every message.

$M$  has two receive message objects. Let us call them `recMU` and `recMQ`.

### 6. Configure the Receive Message Objects in the RTOS Configurator.

You configure an unqueued receive message object by defining a MESSAGE object with its value for its MESSAGEPROPERTY set to `RECEIVE_UNQUEUED_INTERNAL`.

You configure a queued receive message object by defining a MESSAGE object with its value for its MESSAGEPROPERTY set to `RECEIVE_QUEUED_INTERNAL`. The sub-attribute `QUEUESIZE` defines the length of the receive queue.

In both cases, the sub-attribute `SENDINGMESSAGE` defines which is the related Send Message Object. In our example:

▲ M MESSAGE	recMQ
▲ MESSAGEPROPERTY	RECEIVE_QUEUED_INTERNAL
M SENDINGMESSAGE	sendM
QUEUE SIZE	5
NOTIFICATION	NONE
▲ M MESSAGE	recMU
▲ MESSAGEPROPERTY	RECEIVE_UNQUEUED_INTERNAL
M SENDINGMESSAGE	sendM
INITIALVALUE	0
NOTIFICATION	NONE

7. Configure the receivers of the messages.

The receivers of the message `M` are those `TASK` and/or `ISR` objects which can use the system service `ReceiveMessage()` to read the transmitted data of message `M`.

To define the `TASK` `TaskB` and the `ISR` `ISRA` as unqueued receivers for message `M` you need to add `recMU` to the message list of the `TaskB` and `ISRA` objects. And to define the `TASK` `TaskC` as a queued receiver for message `M` you need to add `recMQ` to the message list of the `TaskC` object:

▲ T TASK	TaskB
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[1]	[recMU]
STACKSIZE	250
▲ T TASK	TaskC
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[1]	[recMQ]
STACKSIZE	250
▲ I ISR	ISRA
CATEGORY	2
R RESOURCE[0]	[]
M MESSAGE[1]	[recMU]
LEVEL	1

## 10.4. Message Transmission

### 10.4.1. Sending a Message

Sending a message requires the transfer of the application message data to all the receiving message objects. This process is done automatically for internal communication.

You now can use the following system service to send a message:

```
StatusType SendMessage(MessageIdentifier msg,  
                        ApplicationDataRef data);
```

*msg* a Send Message Object in your file with value SEND\_STATIC\_INTERNAL for its MESSAGEPROPERTY attribute. *msg* must belongs to the MESSAGE list of the sender.

*data* points to the application data to be transmitted.

In our example this could lead to the following C source code:

```
DeclareMessage(sendM);
```

```
TASK (TaskA)  
{  
    int data;  
    ...  
    data = getData();  
    SendMessage(sendM, &data);  
    ...  
    TerminateTask();  
}
```

When you return from the `SendMessage()` system service, the data has already been transmitted (i.e. copied) into the receive message objects.

### 10.4.2. How to Define the Data Type of a Message

When the value of the sub-attribute CDATATYPE for a SEND\_STATIC\_INTERNAL message does not correspond to a basic type, you need to add an extra header file in the project that contains the type definition (the RTOS software needs this information to build its internal buffers). The name of the file is hard coded in the RTOS code as `rtos_user_types.h` and its location must be the project folder.

Let us assume that you want to send a message whose layout can be divided into a header (first byte), payload (next 26 bytes), and CRC (last byte). You must edit the file `rtos_user_types.h` with the type definitions:

```
#ifndef RTOS_USER_TYPES_H  
#define RTOS_USER_TYPES_H  
  
#define PAYLOADSIZE 26
```

```
typedef struct mystruct_s {
    unsigned char header;
    unsigned char payload[PAYLOADSIZE];
    unsigned char crc;
} mystruct_t;

#endif /* ifndef RTOS_USER_TYPES_H */
```

If you configure a MESSAGE object like:

MESSAGE	sendM
MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	mystruct_t
NOTIFICATION	NONE

but you fail to provide the type definition for `mystruct_t` in the `rtos_user_types.h` file, the RTOS code will not compile.

At system generation time, the attribute `LENGTH` of a MESSAGE object stores the size in bytes of the indicated `CDATATYPE` attribute (`sizeof(mystruct_t)`). This is done automatically by the RTOS tools. Thus, since the `LENGTH` of the message is known by the RTOS, a call to `SendMessage()` copies `LENGTH` number of bytes into the receive objects (starting at `data`).

### 10.4.3. Receiving a Message

To receive a message, use the following system service:

```
StatusType ReceiveMessage(MessageIdentifier msg,
                          ApplicationDataRef data);
```

<i>msg</i>	a Receive Message Object in your file which MESSAGEPROPERTY attribute has either RECEIVE_UNQUEUED_INTERNAL or RECEIVE_QUEUED_INTERNAL as value. <i>msg</i> must belong to the MESSAGE list of the receiver.
<i>data</i>	points to where the application receives the data.

When the application calls the `ReceiveMessage()` system service, the message object's data are copied to the application buffer pointed to by `data`.

#### Queued messages

If the MESSAGEPROPERTY of `msg` is RECEIVE\_QUEUED\_INTERNAL, `msg` refers to a queue receive message object (queued message).

A queued message behaves like a FIFO (first-in first-out) queue. When the queue is empty, no message data will be provided to the application and the function returns `E_COMM_NOMSG`. When the queue is not empty and the application receives the message, the application is provided with the oldest message data and removes this message data from the queue. If new message data arrives and the queue is not full, this new message is stored in the queue. If new message data arrives and the queue is full, this

## Using the TASKING RTOS for TriCore

message is lost and the next `ReceiveMessage` call on this message object returns the information that a message has been lost (`E_COM_LIMIT`).

```
TASK (TaskC)
{
    mystruct_t data;
    StatusType ret;
    ...
    ret = ReceiveMessage(recMQ,&data);

    if (ret == E_COM_NOMSG || ret == E_COM_ID)
    {
        /* 'data' contains no valid data */
        /* Queue is empty (no new messages) or wrong symbolic name */
        /* or wrong message ID, message ID of a SEND_STATIC_INTERNAL */
        /* or task is not owner of the message */
        LogError(ret);
    }

    else
    {
        /* 'data' contains valid data */
        if (ret == E_COM_LIMIT)
        {
            /* but a message has been lost */
        }
        else
        {
            /* everything is ok */
        }
        processMsg(&data);
    }
    TerminateTask();
}
```

A separate queue is supported for each receiver and messages from these queues are consumed independently. In the configuration below, messages read by one of the tasks are removed from the queue and are no longer available to the other tasks.

TASK	TaskC
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
RESOURCE[0]	[]
EVENT[0]	[]
MESSAGE[1]	[recMQ]
STACKSIZE	250
TASK	TaskD
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
RESOURCE[0]	[]
EVENT[0]	[]
MESSAGE[1]	[recMQ]
STACKSIZE	250

Should our sender `TaskA` transmit the message to a new queue receiver `TaskD`, a new queue receive message object must be added to the configuration. If you want both tasks to read the same messages, you need to duplicate the receive message:

TASK	TaskD
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
RESOURCE[0]	[]
EVENT[0]	[]
MESSAGE[1]	[recMQD]
STACKSIZE	250
ISR	ISRA
COUNTER	SYSTEM_COUNTER
RESOURCE	RES_SCHEDULER
COM	New_COM
MESSAGE	recMQ
MESSAGEPROPERTY	RECEIVE_QUEUED_INTERNAL
SENDINGMESSAGE	sendM
QUEUESIZE	5
NOTIFICATION	NONE
MESSAGE	recMQD
MESSAGEPROPERTY	RECEIVE_QUEUED_INTERNAL
SENDINGMESSAGE	sendM
QUEUESIZE	5
NOTIFICATION	NONE

### Unqueued messages

Unqueued messages have their MESSAGEPROPERTY set to RECEIVE\_UNQUEUED\_INTERNAL.

Unqueued messages do not use the FIFO mechanism. The application does not consume the message during reception of message data but a message can be read multiple times by an application once it has been received. If no message has been received since the application started, the application receives the message value set at initialization. Unqueued messages are overwritten by new messages that arrive.

```
TASK (TaskB)
{
    mystruct_t data;
    StatusType ret;

    ret = ReceiveMessage(recMU,&data);
    ...

    if (ret != E_OK)
    {
        /* an error occurred */
    }
    else
    {
        /* message has been read */
        processMsg(&data);
    }
    ...
    TerminateTask();
}
```

Contrary to queue receive message objects, the addition of new receivers for an unqueued message is straightforward. You only need to add the `recMU` message object to the MESSAGE list of the new receivers in the RTOS configuration:

TASK	TaskD
PRIORITY	1
SCHEDULE	NON
ACTIVATION	1
AUTOSTART	FALSE
RESOURCE[0]	[]
EVENT[0]	[]
MESSAGE[1]	[recMU]
STACKSIZE	250

#### 10.4.4. Initializing Unqueued Messages

What are the mechanisms offered to ensure the validity of the received data? What if you try to receive a message even before the data has been sent? Do receivers need to wait until senders send their first data?



For queued messages you can ensure the validity of the received messages by verifying that the return value of `ReceiveMessage()` differs from `E_COM_NOMSG` (no message available from the queue).

You should consistently check the returned status when receiving queued messages.

For unqueued messages, however, this mechanism is not available.

There is a workaround for it which uses Notification Mechanisms. See [Section 10.5.3, Notification Example: Flag](#). A better practice is to initialize the unqueued receive message object before any receiver tries to read it.

For instance, if your receiver reads physical addresses (pointers) from an unqueued receive message object, you should make sure that this message object is initialized with a significant value (for instance, non-allowed address zero). Possible receivers know they must discard all messages until a non zero value is found.

This implementation only supports initialization of unqueued messages where the CDATATYPE has an (unsigned) integer size (`sizeof(int)`):

1. Assign a value to the INITIALVALUE sub-attribute in the MESSAGE object:

▲ M MESSAGE	recMU
▲ MESSAGEPROPERTY	RECEIVE_UNQUEUED_INTERNAL
M SENDINGMESSAGE	sendM
INITIALVALUE	3
NOTIFICATION	NONE
▲ M MESSAGE	sendM
MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	int
NOTIFICATION	NONE

To guarantee that `recMU` cannot be received before its container has been initialized with the value 3, this initialization is performed in the `StartCOM()` routine. See [Section 10.6.1, Starting the COM](#), for more information regarding the COM hook routine `StartCOM()`.

Note that the RTOS configuration only allows the specification of a limited range of unsigned integer initialization values. This means that the RTOS configuration can only be used to initialize messages that correspond to (unsigned) integer types within the RTOS configuration's range of values. Thus the following RTOS configuration makes no sense:

▲ M MESSAGE	recMU
▲ MESSAGEPROPERTY	RECEIVE_UNQUEUED_INTERNAL
M SENDINGMESSAGE	sendM
INITIALVALUE	3
NOTIFICATION	NONE
▲ M MESSAGE	sendM
MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	mystruct_t
NOTIFICATION	NONE

## Using the TASKING RTOS for TriCore

2. Let the `StartCOM()` routine initialize the unqueued message with the default value zero. Again this applies only when the messages correspond to (unsigned) integer types.
3. You can always use the following system service to initialize messages that are too large or too complex for their initial value to be specified in the RTOS configuration:

```
StatusType InitMessage(SymbolicName msg, ApplicationDataRef DataRef);
```

Although you can call the `InitMessage()` routine at any point in the application's execution after `StartCOM()`, the safest practice is to initialize all unqueued messages in the hook routine `StartCOMExtension()`.

See [Section 10.6.2, Starting the COM Extension](#), for more information regarding the COM hook routine `StartCOMExtension()`.

```
#include "rtos.h"
#include "rtos_user_types.h"

StatusType StartCOMExtension(void)
{
    mystruct_t data;
    StatusType ret;
    COMApplicationModeType mode;
    int i;

    /* prepare the default message */
    mode = GetCOMApplicationMode();
    if (mode == ComModeA)
    {
        data.header = 'A';
    }
    else
    {
        data.header = 'a';
    }

    for (i = 0; i < PAYLOADSIZE; i++)
    {
        data.payload[i] = data.header + i;
    }
    data.crc = 0;

    /* initialize the receive message object recMU */
    ret = InitMessage(recMU, &data);
    if (ret != E_OK)
    {
        /* log an error */
    }

    return E_OK;
}
```

You can also use `InitMessage()` to reset your unqueued messages at any moment (after you have called `StartCOM()` and before you call `StopCOM()`).

### 10.4.5. Long versus Short Messages

Sending a message involves the copying of data from an application buffer into (at least one) receive message objects. Reversely, receiving a message involves the copying of data from a receive message object into an application buffer.

Concurrency problems to protect critical data are resolved inside the RTOS code by means of temporarily suspending all Category 2 ISRs (and the system timer).

While copying to/from unqueued receive message objects we need always protection against concurrency, thus Category 2 ISRs must be always disabled during the copy process. As a simple mental exercise, imagine what would happen if a `SendMessage` call is preempted by another `SendMessage`. After the two calls, the buffer data are corrupted (a mix of both messages).

While copying to/from queued receive message objects, concurrency problems can be avoided without real need to disable Category 2 ISRs (implementing locks in every member of the message queue). So, keeping interrupts enabled while copying the messages is certainly possible. Extra software is needed to handle locks in the queue. If the messages to be copied are very long, you simply cannot allow interrupts to be disabled during the whole copy process. However, if messages are so short that interrupts can be easily disabled during the copy process, this extra handling should be best avoided.

If you set the non-standard attribute `LONGMSG` to `TRUE`, Category 2 ISRs are enabled while the copy process of queued messages and extra software (i.e. run-time performance) is needed. If set to `FALSE`, Category 2 ISRs are disabled but no extra software is needed.

## 10.5. Message Notification

So far you know how to send and receive messages. The question that still remains is: how does the receiver know that the sender has just sent a new message?

For queued messages the receiver can survive by constantly checking the receive queue. For unqueued messages the receivers have no means to know whether a new message has arrived or whether it is still the old one. There must be ways to synchronize senders and receivers.

For this notification mechanisms are defined as a follow up of the transmission and/or reception of a message. For internal communication only Notification Class 1 is supported which means that as soon as the message has been stored in the receive message object, a notification mechanism is invoked automatically.

The following notification mechanisms are provided:

### Callback routine

A callback routine provided by the application is called.

## Flag

A flag is set. The application can check the flag with the `ReadFlag` API service. Resetting the flag is performed by the application with the `ResetFlag` API service. Additionally, calls to `ReceiveMessage` also reset the flag.

## Task

An application task is activated.

## Event

An event for an application task is set.

The notification mechanism can be defined only for a receiver message object. With these mechanisms you can synchronize the copy of data into the receive message object with the receiver.

Since Notifications occur before returning from `SendMessage()`, this system service becomes a rescheduling point for the RTOS. Thus the application may or may not return immediately from the system service (imagine what happens if a higher priority task is activated).

### 10.5.1. Notification Example: Activate Task

Imagine an application with a serial line command handler. The race condition for the reception of the command is the arrival of a line feed. At that moment the serial ISR object `serialRx` must send a message to a TASK object called `commandHandler` with the new command. The task `commandHandler` interprets the given commands and has the highest priority.

A possible RTOS configuration for this system is shown below:

TASK	commandHandler
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	3
AUTOSTART	TRUE
RESOURCE[0]	[]
EVENT[0]	[]
MESSAGE[1]	[recCommand]
STACKSIZE	250
TASK	initTask
ISR	SerialRx
CATEGORY	2
RESOURCE[0]	[]
MESSAGE[1]	[sendCommand]
LEVEL	1
COUNTER	SYSTEM_COUNTER
RESOURCE	RES_SCHEDULER
COM	New_COM
MESSAGE	recCommand
MESSAGEPROPERTY	RECEIVE_QUEUED_INTERNAL
SENDINGMESSAGE	sendCommand
QUEUESIZE	3
NOTIFICATION	ACTIVATETASK
TASK	commandHandler
MESSAGE	sendCommand
MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	mycommand_t
NOTIFICATION	NONE

The sender message object of the command message is `sendCommand`. The only owner of the sender object is `SerialRx`, it is the only sender. When the race condition is met, the command message is sent with the last buffered command from the ISR code. The command is copied to all the receiver objects, in this case only `recCommand`. And since there is a Notification mechanism defined for this receive object, the task `commandHandler` is also activated. Upon return from the ISR code the `commandHandler` task is running. This task receives the oldest message of the `recCommand` queue message object and interprets it.

This method is safe. The only problem that could arise would be an overrun in the ISR receive buffer in case the execution time in the ISR code `SendMessage()` exceeds the minimal interarrival time between two consecutive interrupts.

It is worth noting here that this design should always match the maximum number of task activations for the `CommandHandler` task with the size of the queue of message object `recCommand`.

## 10.5.2. Notification Example: Set Event

Consider the OIL configuration below:

▲ T TASK	commandHandler
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	3
▶ AUTOSTART	TRUE
R RESOURCE[0]	[]
E EVENT[1]	[commandEvent]
M MESSAGE[1]	[recCommand]
STACKSIZE	250
▶ T TASK	initTask
▲ I ISR	SerialRx
CATEGORY	2
R RESOURCE[0]	[]
M MESSAGE[1]	[sendCommand]
LEVEL	1
C COUNTER	SYSTEM_COUNTER
E EVENT	commandEvent
R RESOURCE	RES_SCHEDULER
▶ C COM	New_COM
▲ M MESSAGE	recCommand
▲ MESSAGEPROPERTY	RECEIVE_QUEUED_INTERNAL
M SENDINGMESSAGE	sendCommand
QUEUESIZE	3
▲ NOTIFICATION	SETEVENT
T TASK	commandHandler
E EVENT	commandEvent
▲ M MESSAGE	sendCommand
▲ MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	mycommand_t
NOTIFICATION	NONE

In this solution the `commandHandler` task is never in the suspended state, it remains most of the time waiting for event `commandEvent`. The Notification mechanism for `recCommand` sets now `commandEvent` immediately after that the command message was copied to the receive object in the ISR code. Upon return from the ISR, the task `commandHandler` resumes execution, clears the event `commandEvent`, receives and interprets the message before waiting again for the event.

This method is far less safe than the previous one. Apart from the previous problem there is a second drawback. If the cycle "clear event, receive message, interpret message, wait event" is longer than the minimum time between the arrival of two consecutive serial commands, events could sometimes get lost and some commands would not be processed.

## 10.5.3. Notification Example: Flag

Associated with a receive message object, a flag will be set when a new message overwrites the container. It remains set until the application explicitly resets the flag or calls `ReceiveMessage()`.

Although theoretically available for all messages, the Notification Flag mechanism normally applies only to unqueued messages. The drawback is that when the flag is set, all you know is that at least one message arrived since the `ReceiveMessage()` call. But you never can tell how many messages you might have lost in between. But it does solve the problem of uninitialized unqueued messages.

Next you will find another configuration for the previous problem:

RTOS configuration:

TASK	commandHandler
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	3
AUTOSTART	TRUE
RESOURCE[0]	[]
EVENT[1]	[delay]
MESSAGE[1]	[recCommand]
STACKSIZE	250
TASK	initTask
ISR	SerialRx
CATEGORY	2
RESOURCE[0]	[]
MESSAGE[1]	[sendCommand]
LEVEL	1
COUNTER	SYSTEM_COUNTER
ALARM	commandHandlerAlarm
COUNTER	SYSTEM_COUNTER
ACTION	SETEVENT
EVENT	delay
TASK	commandHandler
AUTOSTART	FALSE
EVENT	delay
RESOURCE	RES_SCHEDULER
COM	New_COM
MESSAGE	recCommand
MESSAGEPROPERTY	RECEIVE_QUEUED_INTERNAL
SENDINGMESSAGE	sendCommand
QUEUESIZE	3
NOTIFICATION	FLAG
FLAGNAME	commandFlag
MESSAGE	sendCommand
MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	mycommand_t
NOTIFICATION	NONE

In the C source below, the task `commandHandler` checks every POLL (10 milliseconds), the flag associated with the receive object `recCommand`. If the flag is set, the task receives the message, otherwise

## Using the TASKING RTOS for TriCore

it enters again the waiting state for the next POLL. The drawback is that this requires a task specific alarm with ACTION set to SETEVENT.

You can check the status of the Flag with the following API:

```
FlagValue ReadFlag_flagname(void);
```

If the returned value is COM\_TRUE, the Flag was set: a new message has been received.

C source file:

```
#include "rtos.h"
#include "rtos_user_types.h"

/* poll time in nano seconds */
#define POLL 1000000

DeclareTask(commandHandler);
DeclareMessage(recCommand);
DeclareEvent(delay);
DeclareAlarm(commandHandlerAlarm);

TASK (commandHandler)
{
    mycommand_t data;
    StatusType ret;

    while(1)
    {
        ret = ReadFlag_commandFlag();
        if (ret == COM_TRUE )
        {
            ReceiveMessage(recCommand,&data);
            processMsg(&data);
        }
        else
        {
            SetRelAlarm(commandHandlerAlarm,
                (POLL)/(OSTICKDURATION),0);
            WaitEvent(delay);
            ClearEvent(delay);
        }
    }
    TerminateTask();
}
```

This solution is even less safe. It assumes that the minimum average interarrival time between two consecutive commands is at least greater than POLL plus the code execution overhead in the while loop.



## 10.5.4. Notification Example: Callback

Callback routines can run on task level or interrupt level. This restricts the usage of system services in the callback routine to the services that are allowed at both task level and ISR2 level.

In the RTOS configuration you set the NOTIFICATION to COMCALLBACK and you specify a CALLBACKROUTINENAME.

▲ T TASK	sender
PRIORITY	1
SCHEDULE	FULL
ACTIVATION	1
AUTOSTART	FALSE
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[1]	[sendCommand]
STACKSIZE	250
C COUNTER	SYSTEM_COUNTER
▲ A ALARM	senderAlarm
C COUNTER	SYSTEM_COUNTER
▲ ACTION	ACTIVATETASK
T TASK	sender
▷ AUTOSTART	TRUE
R RESOURCE	RES_SCHEDULER
▷ C COM	New_COM
▲ M MESSAGE	recCommand
▲ MESSAGEPROPERTY	RECEIVE_QUEUED_INTERNAL
M SENDINGMESSAGE	sendCommand
QUEUE SIZE	1
▲ NOTIFICATION	COMCALLBACK
CALLBACKROUTINENAME	callback
M MESSAGE[1]	[recCommand]
▲ M MESSAGE	sendCommand
▲ MESSAGEPROPERTY	SEND_STATIC_INTERNAL
CDATATYPE	mycommand_t
NOTIFICATION	NONE

A COM Callback must be defined in your application source as follows:

```
COMCallback(callback)
{
    mycommand_t data;

    ReceiveMessage(recCommand, &data);
    ProcessData(&data);
}
```

## 10.6. Starting and Ending the COM

### 10.6.1. Starting the COM

The RTOS provides you with the following service to start the communication component:

```
StatusType StartCOM(COMApplicationModeType mode);
```

For internal communication this service performs little: basically it sets some internal variables and, if applicable, it initializes all the unqueued receive message objects with the value of their standard attribute INITIALVALUE.

The `StartCOM()` routine supports the possibility of starting the communication in different configurations with the parameter `mode` (like the application modes and `StartOS()`). You can define different modes with the multiple standard attribute `COMAPPMODE` in the `COM` object.

You need to call `StartCOM()` from a task. Be careful: `StartCOM()` must be called before any `COM` activity takes places in the system.

A good practice could be the use of an autostarting task performing some possible extra OS initialization plus calling `StartCOM()`. This task becomes the only "real" autostarting task in the configuration, the "old" other autostarting tasks will be activated directly from this task (which runs non-preemptable).

RTOS configuration

▲ APPMODE	APPMODE1
▲ T TASK	initTask
PRIORITY	2
SCHEDULE	NON
ACTIVATION	1
▲ AUTOSTART	TRUE
▲ APPMODE[1]	[APPMODE1]
R RESOURCE[0]	[]
E EVENT[0]	[]
M MESSAGE[0]	[]
STACKSIZE	250
▶ T TASK	sender
C COUNTER	SYSTEM_COUNTER
▶ A ALARM	senderAlarm
R RESOURCE	RES_SCHEDULER
▲ C COM	New_COM
COMERRORHOOK	TRUE
COMUSEGETSERVICEID	TRUE
COMUSEPARAMETERACCESS	TRUE
COMSTARTCOMEXTENSION	FALSE
COMAPPMODE[2]	[ComModeA, ComModeB]
COMSTATUS	COMEXTENDED

Before you can use the COM application mode in `StartCOM()` you must declare it.

C source file

```
DeclareTask( initTask );
DeclareComAppMode( ComModeA );

TASK( initTask )
{
    StartCOM( ComModeA );
    TerminateTask();
};
```

If you want to get the current COM application mode you can use the function `GetCOMApplicationMode()`.

### 10.6.2. Starting the COM Extension

If you set the standard attribute `COMSTARTCOMEXTENSION` of the COM object in the RTOS configurator to `TRUE`, your user-supplied function `StartCOMExtension()` will be called at the end of the `StartCOM()` routine.

See [Section 10.4.4, \*Initializing Unqueued Messages\*](#) to learn about how to use this hook routine in order to initialize messages that are too large or too complex for their initial value to be specified in the RTOS configurator.

### 10.6.3. Stopping the COM

The `StopCOM()` service is used to stop the communication component:

```
StatusType StopCOM( COMShutdownModeType mode );
```

If the given parameter `mode` equals to `COM_SHUTDOWN_IMMEDIATE`, the service shuts down the communication component immediately. This implementation does not define any other additional shutdown mode for the COM component. Thus, you should always call this service with `COM_SHUTDOWN_IMMEDIATE` as parameter.

`StopCOM()` sets the system ready for a new call to `StartCOM()`.

## 10.7. The C Interface for Messages

You can use the following data types and system services in your C sources to deal with message related issues.

Element	C Interface
Data Types	SymbolicName ApplicationDataRef FlagValue COMApplicationModeType COMShutdownModeType COMServiceIdType LengthRef CalloutReturnType
Constants	COM_SHUTDOWN_IMMEDIATE E_COM_ID E_COM_LENGTH E_COM_LIMIT E_COM_NOMSG
System Services	StartCOM StopCOM GetCOMApplicationMode InitMessage SendMessage ReceiveMessage GetMessageStatus ResetFlag_Flag ReadFlag_Flag COMErrorGetServiceId

Please refer to the ISO 17356 documentation for a detailed description.

# Chapter 11. Error Handling

This chapter helps you to understand the available debug facilities and error checking possibilities. It describes which services and mechanisms are available to handle errors in the system and how you can interfere with them by means of customizing certain Hook Routines.

## 11.1. Introduction

This chapter helps you to understand the available debug facilities and error checking possibilities. You can customize these debug facilities by defining so-called hook routines. The available hook routines are:

```
StartupHook( )  
PreTaskHook( )  
PostTaskHook( )  
ErrorHook( )  
ComErrorHook( )  
ShutdownHook( )
```

Be aware that all hook routines run with all ISR2 interrupts disabled. Therefore you are discouraged to use interrupt driven software based on ISR2 interrupts for the logging mechanisms in these routines (you still can use ISR1 interrupts).

## 11.2. Error Handling

### 11.2.1. Standard Versus Extended Status

Most of the system services have a `StatusType` return type. All services return `E_OK` when no error occurs. However the number of possible return values for each system service depends on the value of the `STATUS` attribute of the OS object. Possible values are `STANDARD` or `EXTENDED`. In both cases a return value from a system service not equal to `E_OK` means that an error has occurred.

It is recommended to select extended status while you are developing the system. In this mode the system services perform extra integrity checks like:

- Service calls from legal location (many services are forbidden at interrupt level or at hook routines).
- Integrity of objects (they must be defined in the OIL file).
- Validity of ranges (passed values might have limited ranges, like you cannot set an alarm to expire after zero cycles).
- Consistency in configuration (a task must own a resource if it attempts to take it, or own a message if it attempts to send/receive it).

All these extra tests are only performed in the extended status mode. To run in extended mode you must set the attribute `STATUS` of the OS object in the RTOS configuration to `EXTENDED`.

## Using the TASKING RTOS for TriCore

When you finish debugging and the application is ready to be released, you could enable the standard mode. Since these tests will not be included in the program you will benefit from smaller images and faster programs. You must then set the attribute STATUS of the OS object in the RTOS configuration to STANDARD.

You should avoid all tests on extended error codes when running in standard mode (redundant code).

So far we have referred to OS, but in an equivalent manner the COM defines also standard and extended error checking modes for the system services of the COM module. You can define this error checking mode for the COM routines by setting the COMSTATUS attribute of the COM object to COMSTANDARD or COMEXTENDED.

### 11.2.2. Fatal Errors

So far we have been speaking about application errors: the RTOS cannot perform the service request correctly but assumes the correctness of its internal data.

If the RTOS cannot assume the correctness of its internal data, it will not return from the system services. The RTOS will call the `ShutdownHook` instead (provided that the standard attribute SHUTDOWNHOOK of the OS OIL object is TRUE). These are Fatal Errors. See also [Section 4.5, Shut-down Process](#).

If your application code contains an error that can be detected only in extended mode, but you run the application exclusively in standard mode, the behavior of the system is undefined. Therefore, it is recommended to run your applications at least once in extended mode.

### 11.2.3. The ErrorHandler Routine

In both standard and extended modes, when a system service returns a `StatusType` value not equal to `E_OK`, the RTOS calls the `ErrorHook()` routine (provided that you set the ERRORHOOK attribute of the OS object to TRUE):

```
void ErrorHook(StatusType);
```

If ERRORHOOK is set but you fail to define the `ErrorHook()` routine in your code, the linking phase will fail due to unresolved externals.

`ErrorHook()` is called at the end of the system service and immediately before returning to the calling function.

The RTOS does not call `ErrorHook` if the failing system service is called from the `ErrorHook` itself (recursive calls never occur). Therefore you can only detect possible errors in OS system services in the `ErrorHook` itself by evaluating directly their return value.

## Macro services inside ErrorHook()

Once inside the `ErrorHook()` routine, the RTOS provides you with mechanisms to access valuable information. With these mechanisms you can check which system service has failed and what its parameters were. You can use the macro services listed in the following table for this purpose.

Macro service	Description
<code>OSErrorGetServiceId()</code>	Provides the system service identifier where the error occurred. The return value of the macro is a service identifier of type <code>OSServiceIdType</code> and its possible values are: <code>OSServiceID_GetResource</code> <code>OSServiceID_ReleaseResource</code> <code>OSServiceID_GetTaskID</code> <code>OSServiceID_StartOS</code> <code>OSServiceID_ActivateTask</code> <code>OSServiceID_TerminateTask</code> <code>OSServiceID_GetTaskState</code> <code>OSServiceID_Schedule</code> <code>OSServiceID_GetActiveApplicationMode</code> <code>OSServiceID_GetSystemTime</code> <code>OSServiceID_GetAlarmBase</code> <code>OSServiceID_GetAlarm</code> <code>OSServiceID_SetRelAlarm</code> <code>OSServiceID_SetAbsAlarm</code> <code>OSServiceID_CancelAlarm</code> <code>OSServiceID_SetEvent</code> <code>OSServiceID_GetEvent</code> <code>OSServiceID_WaitEvent</code> <code>OSServiceID_ClearEvent</code> <code>OSServiceID_ShutdownOS</code> <code>OSServiceID_IncrementCounter</code> The value of the standard attribute of the OS object <code>USEGETSERVICEID</code> must be set to <code>TRUE</code> .
In all cases below the standard attribute of the OS object <code>USEPARAMETERACCESS</code> must be set to <code>TRUE</code> .	
<code>OSError_GetResource_ResID()</code>	Returns the value of parameter <code>ResID</code> of the failing system service <code>GetResource</code> .
<code>OSError_ReleaseResource_ResID()</code>	Returns the value of parameter <code>ResID</code> of the failing system service <code>ReleaseResource</code> .
<code>OSError_StartOS_Mode()</code>	Returns the value of parameter <code>Mode</code> of the failing system service <code>StartOS</code> .
<code>OSError_ActivateTask_TaskID()</code>	Returns the value of parameter <code>TaskID</code> of the failing system service <code>ActivateTask</code> .
<code>OSError_ChainTask_TaskID()</code>	Returns the value of parameter <code>TaskID</code> of the failing system service <code>ChainTask</code> .
<code>OSError_GetTaskState_TaskID()</code>	Returns the value of parameter <code>TaskID</code> of the failing system service <code>GetTaskState</code> .

<b>Macro service</b>	<b>Description</b>
OSError_GetTaskState_State()	Returns the value of parameter State of the failing system service GetTaskState.
OSError_GetAlarmBase_AlarmID()	Returns the value of parameter AlarmID of the failing system service GetAlarmBase.
OSError_GetAlarmBase_Info()	Returns the value of parameter Info of the failing system service GetAlarmBase.
OSError_SetRelAlarm_AlarmID()	Returns the value of parameter AlarmID of the failing system service SetRelAlarm.
OSError_SetRelAlarm_increment()	Returns the value of parameter increment of the failing system service SetRelAlarm.
OSError_SetRelAlarm_cycle()	Returns the value of parameter cycle of the failing system service SetRelAlarm.
OSError_SetAbsAlarm_AlarmID()	Returns the value of parameter AlarmID of the failing system service SetAbsAlarm.
OSError_SetAbsAlarm_start()	Returns the value of parameter start of the failing system service SetAbsAlarm.
OSError_SetAbsAlarm_cycle()	Returns the value of parameter cycle of the failing system service SetAbsAlarm.
OSError_CancelAlarm_AlarmID()	Returns the value of parameter AlarmID of the failing system service CancelAlarm.
OSError_GetAlarm_AlarmID()	Returns the value of parameter AlarmID of the failing system service GetAlarm.
OSError_GetAlarm_Tick()	Returns the value of parameter Tick of the failing system service GetAlarm.
OSError_SetEvent_TaskID()	Returns the value of parameter TaskID of the failing system service SetEvent.
OSError_SetEvent_Mask()	Returns the value of parameter Mask of the failing system service SetEvent.
OSError_GetEvent_TaskID()	Returns the value of parameter TaskID of the failing system service GetEvent.
OSError_GetEvent_Event()	Returns the value of parameter Event of the failing system service GetEvent.
OSError_WaitEvent_Mask()	Returns the value of parameter Mask of the failing system service WaitEvent.
OSError_ClearEvent_Mask()	Returns the value of parameter Mask of the failing system service ClearEvent.
OSError_IncrementCounter_CounterID()	Returns the value of parameter CounterID of the failing system service IncrementCounter.



## Example of ErrorHandler definition

The body of the ErrorHandler routine could look like:

```
void ErrorHandler (StatusType Error )
{
    int32_t Param1=-1,Param2=-1,Param3=-1;
    OSServiceIDType sys = OSErrorGetServiceId();

    switch(sys)
    {
        case OSServiceID_SetRelAlarm:
            Param1 = OSError_SetRelAlarm_AlarmID();
            Param2 = OSError_SetRelAlarm_increment();
            Param3 = OSError_SetRelAlarm_cycle();
            break;
        case OSServiceID_GetEvent:
            Param1 = OSError_GetEvent_TaskID();
            Param2 = OSError_GetEvent_Event();
            break;
        /* all other cases */
        ...
        default:
            break;
    }

    /* (for instance) log error in a circular buffer with
       the last 10 errors */
    errorLog->Param1 = Param1;
    errorLog->Param2 = Param2;
    errorLog->Param3 = Param3;
    errorLog->Error = Error;
    errorLog->sys = sys;
    errorLog++;
    if (errorLog > startLog + sizeof(startLog))
    {
        errorLog = startLog;
    }

    return;
}
```

Please note that all hook routines run with disabled ISR2s. You cannot use ISR2-driven software to log data in these routines; the system will just hang.

## 11.2.4. The **COMErrorHook** Routine

In both **COMSTANDARD** and **COMEXTENDED** modes, when a system service returns a **StatusType** value not equal to **E\_OK** the RTOS calls the **COMErrorHook()** routine (provided that you set the **COMERRORHOOK** attribute of the **COM** object to **TRUE** in your RTOS configuration):

```
void COMErrorHook(StatusType);
```

If **COMERRORHOOK** is set but you fail to define the **COMErrorHook()** routine in your code, the linking phase will fail due to unresolved externals.

**COMErrorHook()** is called at the end of the system service and immediately before returning to the calling function.

The RTOS does not call **COMErrorHook** if the failing system service is called from the **COMErrorHook** itself (recursive calls never occur). Therefore you can only detect possible error in **COM** system services in the **COMErrorHook** itself by evaluating directly their return value.

Once inside the **COMErrorHook()** routine, the RTOS provides you with mechanisms to access valuable information. With these mechanisms you can check which **COM** system service has failed and what its parameters were. You can use the macro services listed in the next table for this purpose.

Macro service	Description
<b>COMErrorGetServiceId()</b>	Provides the system service identifier where the error has been arisen. The return value of the macro is a service identifier of type <b>COMServiceIdType</b> and its possible values are: <b>COMServiceID_StartCOM</b> <b>COMServiceID_StopCOM</b> <b>COMServiceID_GetCOMApplicationMode</b> <b>COMServiceID_InitMessage</b> <b>COMServiceID_SendMessage</b> <b>COMServiceID_ReceiveMessage</b> <b>COMServiceID_GetMessageStatus</b> The value of the standard attribute of the <b>COM</b> object <b>COMERRORGETSERVICEID</b> must be set to <b>TRUE</b>
In all cases below the standard attribute of the <b>COM</b> object <b>COMUSEPARAMETERACCESS</b> must be set to <b>TRUE</b> .	
<b>COMError_StartCOM_Mode()</b>	Returns the value of parameter <b>Mode</b> of the failing system service <b>StartCOM</b> .
<b>COMError_StopCOM_Mode()</b>	Returns the value of parameter <b>Mode</b> of the failing system service <b>StopCOM</b> .
<b>COMError_InitMessage_Message()</b>	Returns the value of parameter <b>Message</b> of the failing system service <b>InitMessage</b> .
<b>COMError_InitMessage_DataRef()</b>	Returns the value of parameter <b>DataRef</b> of the failing system service <b>InitMessage</b> .

Macro service	Description
COMError_SendMessage_Message()	Returns the value of parameter Message of the failing system service SendMessage.
COMError_SendMessage_DataRef()	Returns the value of parameter DataRef of the failing system service SendMessage.
COMError_ReceiveMessage_Message()	Returns the value of parameter Message of the failing system service ReceiveMessage.
COMError_ReceiveMessage_DataRef()	Returns the value of parameter DataRef of the failing system service ReceiveMessage.
COMError_GetMessageStatus_Message()	Returns the value of parameter Message of the failing system service GetMessageStatus.

### Example of COMErrorHook definition

The body of the COMErrorHook() routine could look like:

```
void COMErrorHook(StatusType Error)
{
    int32_t Param1=-1,Param2=-1;
    COMServiceIdType sys = COMErrorGetServiceId();

    switch(sys)
    {
    case COMServiceID_InitMessage :
        Param1 = COMError_InitMessage_Message();
        Param2 = COMError_InitMessage_DataRef();
        break;
    case COMServiceID_SendMessage:
        Param1 = COMError_SendMessage_Message();
        Param2 = COMError_SendMessage_DataRef();
        break;
    default:                /* all other cases */
        break;
    }

    /* (for instance) log errors in a circular buffer with
       last ten errors */
    errorLog->Param1 = Param1;
    errorLog->Param2 = Param2;
    errorLog->Error  = Error;
    errorLog->sys    = sys;
    errorLog++;
    if (errorLog > startLog + sizeof(startLog))
    {
        errorLog = startLog;
    }
    return;
}
```

## 11.3. Debug Routines

The RTOS calls two other hook routines, `PreTaskHook` and `PostTaskHook` to enhance your debugging facilities (if in the RTOS configuration you set the attributes `PRETASKHOOK` and `POSTTASKHOOK` of the OS object to `TRUE`).

```
void PreTaskHook(void);
```

```
void PostTaskHook(void);
```

If `PRETASKHOOK/POSTTASKHOOK` is set but you fail to define the `PreTaskHook()` or `PostTaskHook()` routine in your code, the linking phase will fail due to unresolved externals.

`PreTaskHook()` is called by the RTOS after it has switched tasks but before passing control of the CPU to the new task. This allows you to determine which task is about to run.

`PostTaskHook()` is called after the RTOS determines that a switch is to occur but always before the switch actually occurs. This allows you to determine which task has just completed or has been preempted.

In both cases there is still (already) a task in the running state so that you can determine which task is about to be preempted or scheduled with the OS system service `GetTaskId()`.

The body of the `PreTaskHook()` routine could look like:

```
void PreTaskHook (void)
{
    TaskType task;
    TaskStateType state;
    GetTaskID(&task);
    if (task== INVALID_TASK)
    { /* i cannot be here */
        while(1); }
    if ( RUNNING != GetTaskState(task,&state) )
    { /* i cannot be here */
        while(1); }
    /* debug code */
    return;
};
```

Please, always keep in mind that only a limited set of system services are at your disposal from these routines (see [Section 4.6, API Service Restrictions](#)):

<code>GetTaskID</code>	<code>GetEvent</code>
<code>GetTaskState</code>	<code>GetAlarmBase</code>
<code>SuspendAllInterrupts</code>	<code>GetAlarm</code>
<code>ResumeAllInterrupts</code>	<code>GetActiveApplicationMode</code>

## 11.4. RTOS Configuration Examples

To benefit from maximum debug facilities you must set your RTOS configuration as follows:

OS	New_OS
STATUS	EXTENDED
STARTUPHOOK	TRUE
ERRORHOOK	TRUE
SHUTDOWNHOOK	TRUE
PRETASKHOOK	TRUE
POSTTASKHOOK	TRUE
USEGETSERVICEID	TRUE
USEPARAMETERACCESS	TRUE
USERESSCHEDULER	FALSE
LONGMSG	FALSE
ORTI	TRUE
RUNLEVELCHECK	TRUE
SHUTDOWNRETURN	FALSE
IDLEHOOK	FALSE
IDLELOWPOWER	FALSE
USERTOSTIMER	FALSE

COM	New_COM
COMERRORHOOK	TRUE
COMUSEGETSERVICEID	TRUE
COMUSEPARAMETERACCESS	TRUE
COMSTARTCOMEXTENSION	TRUE
COMAPPMODE[2]	[ComModeA, ComModeB]
COMSTATUS	COMEXTENDED

To cut out all debug facilities when releasing the product you must set your RTOS configuration as follows:

OS	New_OS
STATUS	STANDARD
STARTUPHOOK	FALSE
ERRORHOOK	FALSE
SHUTDOWNHOOK	FALSE
PRETASKHOOK	FALSE
POSTTASKHOOK	FALSE
USEGETSERVICEID	FALSE
USEPARAMETERACCESS	FALSE
USERESSCHEDULER	FALSE
LONGMSG	FALSE
ORTI	FALSE
RUNLEVELCHECK	FALSE
SHUTDOWNRETURN	FALSE
IDLEHOOK	FALSE
IDLELOWPOWER	FALSE
USERTOSTIMER	FALSE

## Using the TASKING RTOS for TriCore

COM	New_COM
COMERRORHOOK	FALSE
COMUSEGETSERVICEID	FALSE
COMUSEPARAMETERACCESS	FALSE
COMSTARTCOMEXTENSION	TRUE
COMAPPMODE[2]	[ComModeA, ComModeB]
COMSTATUS	COMSTANDARD

If the size of your image becomes critical you can notably reduce the ROM area size of your application by choosing this configuration. The real-time responses of the system are also enhanced since many run time checks are not performed.

# Chapter 12. Debugging an RTOS Application

This chapter explains how you can easily debug RTOS information and describes in detail all the information that you can obtain.

## 12.1. Introduction

This chapter describes how the debugger can help you to debug your RTOS application.

Often while debugging, you will find situations where having access to certain RTOS information becomes crucial. For instance:

- if you are running code that is shared by many tasks, you may need to know which task is executing at that moment.
- you may need to know the state of your tasks
- you may need to know which event a task is waiting for
- you may need to know the priority of the system once the task has got a resource

To provide debug information, the RTOS uses a universal interface for development tools: ORTI. It describes a set of attributes for system objects and a method for interpreting the obtained data. The types which are defined in the section, are specified to allow the debugger to determine the target memory access method as well as the best way of displaying the retrieved data. In most cases the information that you will require to see is a textual description of an attribute rather than the actual value read from the variable.

The toolset generates at system generation time an ORTI file with rules for the debugger to display valuable kernel information at run time. Every time you make changes in the RTOS configuration, a new ORTI file is generated.

You need to start the debugger every time a new ORTI file is created.

The information provided by the ORTI file (this is the information displayed at run-time by the debugger) is described in the next sections. This information can be both dynamic (stacks, current task, last error) and static (added to help you comprehend the run-time environment).

To view RTOS information, select the appropriate RTOS view from the Debug menu.

- From the **Debug** menu, select **ORTI » RTOS » RTOS view**.

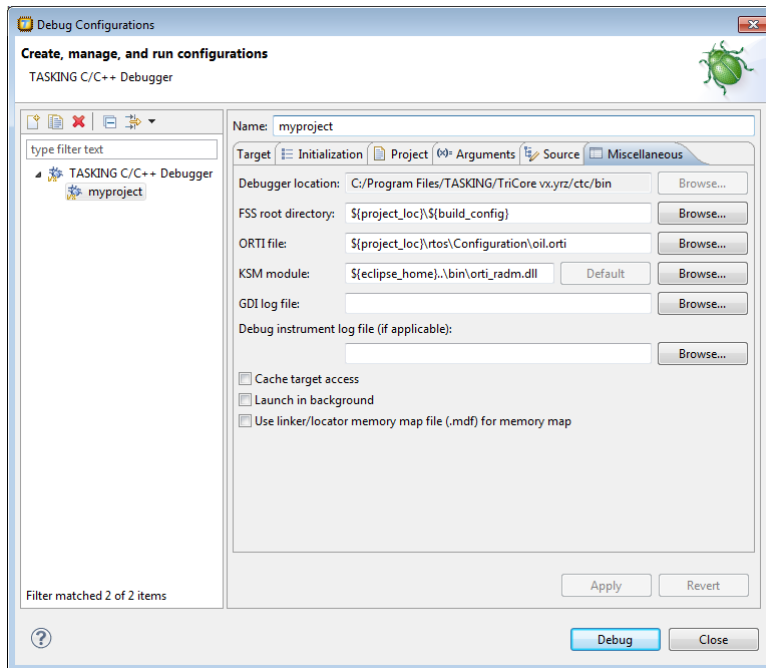
*The RTOS view opens.*

## 12.2. How to Debug the System Status

Before you start debugging, make sure that:

## Using the TASKING RTOS for TriCore

- The system runs in extended mode (the non-standard attribute ORTI of the OS object is set to TRUE) if you aim for a maximum of information. If you need to debug your application in standard mode, you must be aware of the fact that some of the information will be indeterminated.
- The debug configuration options of your project are set:
  1. From the **Debug** menu, select **Debug Configurations...**  
*The Debug Configurations dialog appears.*
  2. In the left pane, select the configuration you want to change, for example, **TASKING C/C++ Debugger » myproject**.
  3. Open the **Miscellaneous** tab.



4. In the **ORTI file** field, specify the name of the ORTI file (`oil.orti`).

*The **KSM module** field will automatically be filled with the file `orti_radm.dll` in the `bin` directory of the toolset.*

5. Click **Debug** to start the debugger.

Every time you stop the debugger you can have a first look at the current status of the system via some general information. This information intends to provide a global and fast description of the system.

- From the **Debug** menu, select **ORTI » RTOS » System Status**.



The RTOS: System Status view shows values for some global status attributes. The status attributes are described in the following table.

System Status	Description
Object	The name of the OS object.
Conformance	One of the conformance classes BCC1, BCC2, ECC1 or ECC2. B=Basic, E=Extended. 2=multiple activation of a task or multiple tasks with the same priority. 1 otherwise.
Running Task	The name of the task that is currently in the running state within the OS object. Idle indicates that no tasks are in the running state (the idle state). NONE is displayed when there is no current task.
Running Task Priority	The current priority of the task referred to by Running Task. The current priority can be different from the static task priority as a result of the priority ceiling protocol. The priority displayed is the priority as defined in the RTOS configuration for the task. NONE is displayed when there is no current task.
Running ISR2	The category 2 ISR that is currently running within the OS object. NO_ISR indicates that no category 2 ISRs are running. N.A. is displayed when no category 2 ISRs are used in the application.
Service Trace	The last entry (or exit) of a system service routine. The possible ENUM values are: XxxYyyExit or XxxYyyEntry (where XxxYyy indicates the name of the system service).
Last Error	The last error code detected. At startup, the error code is initialized with E_OK but once an error occurred it is not set back to E_OK again.
Current APPMODE	The name of the current application mode.
Running Resource	The resource currently being locked by the system. NO_RESOURCE indicates that the system is not locking any resources. N.A. indicates that no resources are used in the application.
Sys Last Error	The system service where Last Error occurred. NONE if no error has been found so far (only if running in extended mode).
CPU RTOS	The time spent by the system executing RTOS code.
CPU Idle	The time spent by the system in the idle state.
CPU User	The time spent by the system executing application code.

## 12.3. How to Debug Tasks

The debugger can display relevant information about all the tasks in the system.

- From the **Debug** menu, select **ORTI » RTOS » Tasks**.

The RTOS: Tasks view shows a list with all the tasks in the system. Every task is described with a set of attributes. The debugger displays the values of these attributes. The task attributes are described in the following table.

Tasks	Description
Object	The name of the task.
Priority	The current priority of the TASK object. The current priority may differ from the static task priority as a result of the priority ceiling protocol. The priority displayed is the priority as defined in the RTOS configuration for the task.
State	The current state of the task (SUSPENDED, READY, RUNNING or WAITING).
Stack	The name of the stack object that the task is currently using.
Context	The name of the context object that the task is currently using.
Current Activations	The number of current activations for the task.
Scheduling	The scheduling policy of the task (NON or FULL).
Wait For Event	"wait mask" of the task: a mask of all the events that the task is waiting for (if any).
Event Set	"set mask" for the TASK object: a mask of all the events that are already set for the task.
Group	Internal resource identifying the group to which this task belongs (if any).
#Runs	The number of times the task has been scheduled.
Service Trace	The last entry (or exit) of a system service routine in code executed by this particular task. The possible ENUM values are: XxxYyyExit or XxxYyyEntry (where XxxYyy indicates the name of the system service).
CPU Task	The time spent by the application code executing in this task.
Stack Used	The number of bytes currently in use for the stack of the task.
Stack Available	The number of bytes still available for the stack of the task.

## 12.4. How to Debug Resources

The debugger can display relevant information about all the resources in the system.

- From the **Debug** menu, select **ORTI » RTOS » Resources**.

*The RTOS: Resources view shows a list with all the resources in the system. Every resource is described with a set of attributes. The debugger displays the values of these attributes. The resource attributes are described in the following table.*

Resources	Description
Object	The name of the resource.
State	The state of a resource (LOCKED/UNLOCKED). (only if running in extended mode)
Locker	The name of the locking task or ISR.

Resources	Description
Priority	This column has two components that state: a) that the resource is used by TASKs only or by both TASKs and ISRs, and b) the priority that will be used when locking the resource. Example: TASK : 6 (for example, two tasks with priority 4 and 6 and no ISRs) ISR : 3 (for example, tasks and two ISRs with priority 1 and 3)
Property	The property of the resource (STANDARD, INTERNAL or LINKED).

## 12.5. How to Debug Alarms

The debugger can display relevant information about all the alarms in the system.

- From the **Debug** menu, select **ORTI » RTOS » Alarms**.

*The RTOS: Alarms view shows values for some global status attributes. The status attributes are described in the following table.*

Alarms	Description
Object	The name of the alarm.
Alarm Time	The time left until the alarm expires.
Cycle Time	The cycle time for cyclic alarms. The value is 0 for non-cyclic alarms.
Action	A string with a description of the action when the alarm expires. For example, <code>ActivateTask TaskA</code> .
Counter	The name of the counter on which the alarm is based.

## 12.6. How to Debug ISRs

The debugger can display information about all the ISRs in the system.

- From the **Debug** menu, select **ORTI » RTOS » ISRs**.

*The RTOS: ISRs view shows a list with all the ISRs in the system. Every ISR is described with a set of attributes. The debugger displays the values of these attributes. The ISR attributes are described in the following table.*

ISRs	Description
Object	The name of the ISR.
Category	The category of the ISR.
#Runs	The number of times the interrupt service routine has executed.
Service Trace	The last entry (or exit) of a system service routine in code executed by this particular interrupt service routine. The possible ENUM values are: <code>XxxYyyExit</code> or <code>XxxYyyEntry</code> (where <code>XxxYyy</code> indicates the name of the system service).

ISRs	Description
CPU ISR	The time spent by the application code executing in this interrupt service routine.
Level	The interrupt priority level.

## 12.7. How to Debug Messages

The debugger can display information only about the receive message objects in the system (since the send messages are routed directly to the receiving side).

- From the **Debug** menu, select **ORTI » RTOS » Messages**.

*The RTOS: Messages view shows a list with all the messages in the system. Every messages is described with a set of attributes. The debugger displays the values of these attributes. The messages attributes are described in the following table.*

Messages	Description
Object	The name of the message.
Message Type	The type of the message: QUEUED or UNQUEUED.
Queue Size	The size of the queue for queued messages. 1 for unqueued messages.
Queue Count	The number of valid messages in the queue. 1 for unqueued messages.
First Element	The address of the first valid message. This message will be received next. If no message is in the queue the value is zero.
Sender	The symbolic name of the sender.

## 12.8. How to Debug Contexts

The CONTEXT object declaration describes a subset of the information (normally the CPU environment) saved by the operating system for a particular task at context switch. A CONTEXT is uniquely attached to a task.

- From the **Debug** menu, select **ORTI » RTOS » Contexts**.

*The RTOS: Contexts view shows a list with all the objects in the system and their context. Every context is described with a set of attributes. The debugger displays the values of these attributes. The context attributes are described in the following table.*

Contexts	Description
Object	The name of the context.
Size	The size (in bytes) of the memory area. This is the size of a single CSA item.
Address	The base address of a memory area containing a subset of the context.
Valid	The validity of the context data (not valid for the running task). NO or YES.

Contexts	Description
PC	The resume execution address for the saved task.
SP	The saved value of the Stack Pointer register.
PCXI	The saved value of the PCXI register.

## 12.9. How to Debug Stacks

The STACK object defines the memory area of any stack in the system.

The debugger can display relevant information about all the saved contexts in the system.

- From the **Debug** menu, select **ORTI » RTOS » Stacks**.

*The RTOS: Stacks view shows a list with all the stacks in the system. Every stack is described with a set of attributes. The debugger displays the values of these attributes. The stack attributes are described in the following table.*

Stacks	Description
Object	The name of the stack.
Size	The size (in bytes) of the memory area allocated for the stack of the task.
Base Address	The lowest address of the task's stack memory area, regardless of the stack direction.
Stack Direction	The direction of growth of the task's stack: UP: stack grows from lower to higher addresses DOWN: stack grows from higher to lower addresses



# Chapter 13. Implementation Parameters

The implementation parameters provide detailed information concerning the functionality, performance and memory demand. From the implementation parameters you can obtain valuable information about the impact of the RTOS on your application.

## 13.1. Introduction

From the implementation parameters you can obtain valuable information regarding the impact of the RTOS on your application. There are three kinds of implementation parameters:

- **Functionality Implementation Parameters.** They relate to the configuration of the system. You should always take them into account when writing your application.
- **Hardware Resources Implementation Parameters.** They evaluate the impact of having a RTOS on the hardware resources of the system (RAM, ROM, interrupts, times, etc).
- **Performance Implementation Parameters.** They measure the real time response of the RTOS. The basic conditions to reproduce the measurement of those parameters are mentioned.

## 13.2. Functionality Implementation Parameters

Parameter	Description	Implementation
MAX_NO_TASK	Maximum number of tasks. Limits the total number of TASK OIL objects in the OIL file.	126 One task is reserved for the system idle task
MAX_NO_ACTIVE_TASK	Maximum number of active tasks (i.e. not suspended) in the system.	127 The most general scenario is when all tasks can be 'active' at any given time, thus all having a stack of their own.
MAX_NO_PRIO_LEVEL	Maximum number of physical priority levels. Limits the total number of TASK OIL objects with different PRIORITY value.	126 The total number of physical priority levels is calculated by the TOC tool after processing the application OIL file.
MAX_TASK_PER_LEVEL	Maximum number of tasks per priority level.	126 The implementation supports the general case, thus allowing many ready task in the same priority level. However, better performance is achieved when no more than one task is assigned statically to the same priority level (smaller context switch latency times).

## Using the TASKING RTOS for TriCore

Parameter	Description	Implementation
MIN_PRIO_LEVEL	Lowest priority level used by the user. No TASK OIL object can be defined with lower priority.	1
MAX_PRIO_LEVEL	Highest priority level used by the user.	254
MAX_NO_ACTIVATIONS	Upper limit for the number of task activations.	255
MAX_NO_EVENTS	Maximum number of events objects (per system/per task). Limits the number of EVENT OIL objects that can be defined in the application OIL file.	32
MAX_NO_COUNTER	Maximum number of counter objects (per system / per task). Limits the number of COUNTER OIL objects that can be defined in the application OIL file.	126
MAX_NO_ALARM	Maximum number of alarm objects (per system / per task). Limits the number of ALARM OIL objects that can be defined in the application OIL file.	127
MAX_NO_APPMODE	Maximum number of application modes. Limits the number of APPMODE objects that can be defined in the application OIL file.	127
MAX_NO_RESOURCE	Maximum number of resource objects (per system / per task). Limits the number of RESOURCE OIL objects that can be defined in the application OIL file.	126
MAX_QUEUE_SIZE	Maximum size for the queues in QUEUE MESSAGE objects.	65535
MAX_DATA_LENGTH	Maximum length of the data in a message (in bytes).	65535
OSTICKDURATION	Time (in nanoseconds) between two consecutive ticks of the hardware system clock.	Configurable between 10 micro seconds and 1 second.
OSMINCYCLE	Minimum allowed number of counter ticks for a cyclic alarm of the system counter.	1
OSTICKSPERBASE	Number of ticks require to reach a specific unit of the system counter.	1



Parameter	Description	Implementation
OSMAXALLOWEDVALUE	Maximum possible allowed value of the system counter in ticks.	4294967295 ( $2^{32}-1$ )
MIN_TIMEOUT	Minimum timeout for an alarm based on the system counter.	OSTICKDURATION* OSMINCYCLE nano seconds
MAX_TIMEOUT	Maximum timeout for an alarm based on the system counter.	((OSMAXALLOWEDVALUE* OSTICKDURATION)/ 1000000000)/(365*3600)) years

## 13.3. Performance Implementation Parameters

### 13.3.1. ISR Latency

ISR latency Time is defined here as the total time spent in serving an interrupt (starting at the time that the interrupt occurred). Four contributions are to be considered.

- ISR Entry Latency
- ISR Application Handler
- ISR Exit Latency
- ISR Priority Latency

#### ISR Entry Latency

ISR Entry Latency is defined here as the time between the occurrence of the interrupt and the start of the application's code that handles the interrupt. In an ideal real-time system, the ISR entry latency is zero, so the application's handler runs immediately after the interrupt has occurred. In a 'real' real-time system other contributions must be considered:

- Both application and RTOS code could be temporarily disabling the interrupt. During this ISR disable time (the bigger contribution of the two for the worst case scenario) the interrupt cannot be handled.

Parameter	Description	Implementation
MAX_RTOS_ISR1_DIS	Maximum time that an ISR1 interrupt is kept disabled by the RTOS code.	TBM
MAX_RTOS_ISR2_DIS	Maximum time that an ISR2 interrupt is kept disabled by the RTOS code.	TBM

- Hardware latency time. Even in ideal conditions an interrupt cannot be immediately served. This time is defined as the time needed by the hardware to execute the longest instruction and the vectoring of the interrupt.

Some RTOS code will always run before execution is dispatched to the application's handler.

## Using the TASKING RTOS for TriCore

Parameter	Description	Implementation
ISR1_ENTRY_LATENCY	RTOS overhead before dispatching execution to an ISR1 handler (almost zero).	TBM
ISR2_ENTRY_LATENCY_0	RTOS overhead before dispatching execution to an ISR2 handler at first nesting level.	TBM
ISR2_ENTRY_LATENCY_N (N >0)	RTOS overhead before dispatching execution to an ISR2 handler at second (or more) nesting level.	TBM

### ISR Application Handler

Contribution of the application handler to the ISR latency.

### ISR Exit Latency

ISR Exit Latency is defined here as the time between the end of the application's handler and the moment where execution is back to task level (or to another interrupt of lower priority).

Parameter	Description	Implementation
ISR1_EXIT_LATENCY	RTOS overhead after an ISR1 handler (almost zero).	TBM
ISR2_EXIT_SWITCH_LATENCY	RTOS overhead after an ISR2 handler (where reasons for re-scheduling have been found).	TBM
ISR2_EXIT_RESUME_LATENCY	RTOS overhead after an ISR2 handler (where no reasons for re-scheduling have been found).	TBM

### ISR Priority Latency

In systems with many interrupt priority levels, an ISR can be temporarily prevented from being handled because other interrupt (with higher priority) needs to be served first.

### 13.3.2. Context Switch Latency

In a full preemptive system, you can constantly expect preemption of the running task. Rescheduling can be performed at task level (when the necessary conditions are met) in the so-called 'rescheduling points' (as a consequence of calling specific system services).

Context Switch Latency Time is defined here as the time between the last instruction of the exiting task and the first of the incoming task through a rescheduling point caused by the call to one of the system services listed in the next table. The table below lists the implementation parameters with regard to the Context Switch Latency for all rescheduling points.

Parameter	Conditions	Implementation
TERMINATE_TASK_LATENCY	Running task meets all conditions for a successful exit.	TBM
CHAIN_TASK_LATENCY	Running task meets all conditions for a successful exit.	TBM

Parameter	Conditions	Implementation
ACTIVATE_TASK_LATENCY	The task given as parameter has a higher priority than the running priority of the system.	TBM
WAIT_EVENT_LATENCY	Running task must own the event given as parameter (which has not been set yet).	TBM
SET_EVENT_LATENCY	Another ready task with priority between the static priority of the running task and the ceiling priority of the resource is ready.	TBM
RELEASE_RESOURCE_LATENCY	Another ready task with priority between the static priority of the running task and the ceiling priority of the resource is ready.	TBM
SCHEDULE_LATENCY	Another task is ready with higher priority than the static priority of the running task.	TBM
INCREMENT_COUNTER_LATENCY	An alarm based on the counter given as parameter (not the system counter) expires and, as a consequence, a task with higher priority is activated or awoken.	TBM

### 13.3.3. System Timer Latency

The RTOS uses a timer interrupt when alarms based on the system timer have been defined in the OIL file.

System Timer Latency Time is defined here as the total time spent by the RTOS in serving this interrupt (starting at the time that the interrupt occurred). Since execution is not dispatched to any application's handler, it makes no sense to define entry and exit latencies.

Four contributions to the System Timer Latency are to be considered:

- System Timer Priority Latency (like [Section 13.3.1, ISR Latency](#)).
- Disable System Timer Latency (see table below).
- Hardware Latency (like [Section 13.3.1, ISR Latency](#)).
- System Timer Resume/Switch Latency (see table below).

Parameter	Conditions	Implementation
RTOS_CLK_DIS	Maximum time that the system counter interrupt is kept disabled by the RTOS code.	TBM
RTOS_CLK_SWITCH_LATENCY	Maximum time between the start of the RTOS timer handler and the moment that system returns from the clock interrupt when none of the system based alarms has expired.	TBM

*Using the TASKING RTOS for TriCore*

Parameter	Conditions	Implementation
RTOS_CLK_RESUME_LATENCY	The time between the start of the RTOS timer handler and the moment that a new task resumes execution as a consequence of the action taken in the alarm.	TBM