

Priority-driven Scheduling of Periodic Tasks

Advanced Operating Systems (M) Tutorial 2

Tutorial Outline

- Review of lectured material
- Worked examples
- Question and answer

Review of Lectures

Priority-Driven Scheduling of Periodic Tasks

- Rate- and deadline-monotonic; earliest deadline first; least slack time
- Maximum schedulable utilisation.
 - Of fixed priority systems: non-optimal; behaviour when maximum schedulable utilisation exceeded
 - Of dynamic priority systems: optimality
- More general schedulability tests
 - Critical instants and time-demand analysis
 - Conceptual understanding of the process; graphical visualisation of time demand
- Outline of practical factors
 - Impact of blocking time, context switch overhead, etc., on schedulability
- Outline of POSIX scheduling API for real-time tasks

Key Learning Outcomes

- Understanding of when and how to use priorityscheduling
 - Rate monotonic
 - Deadline monotonic
 - Earliest deadline first
 - Least slack time
- Understanding how to prove that a system can be scheduled
 - Maximum schedulable utilisation for a range of algorithms
 - Time-demand analysis

Proving Schedulability: Example 1

• Can the system of five independent, preemptable, tasks T_1 =(1.0, 0.25), T_2 =(1.25, 0.1), T_3 =(1.5, 0.3), T_4 =(1.75, 0.07) and T_5 =(2.0, 0.1) be scheduled using the rate monotonic algorithm?

Proving Schedulability: Example 2

• Can the system of three independent preemptable periodic tasks T_1 =(8, 3), T_2 =(9, 3) and T_3 =(15, 3) be scheduled using the rate monotonic algorithm?

Proving Schedulability: Example 3

• Can the system of three independent preemptable periodic tasks T_1 =(8, 4), T_2 =(12, 4) and T_3 =(20, 4) be scheduled using the rate monotonic algorithm or the EDF algorithm?

Proving Schedulability: Examples

 Aim of the examples has been to demonstrate how to determine whether a system can be scheduled, show when it is necessary to simulate a system

Question and Answer