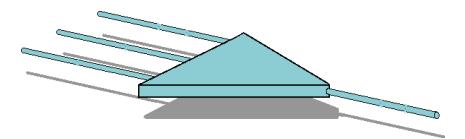


Global Scheduling of Periodic Tasks in a Decentralized Real-time Control System

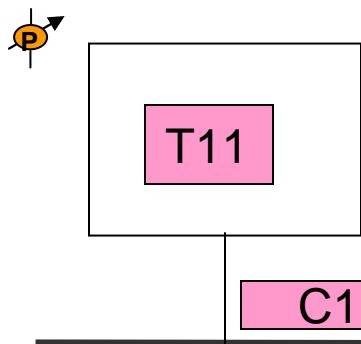
4. Würzburger Workshop
"IP Netzmanagement, IP Netzplanung und Optimierung"
Würzburg, Germany
27-28 July, 2004



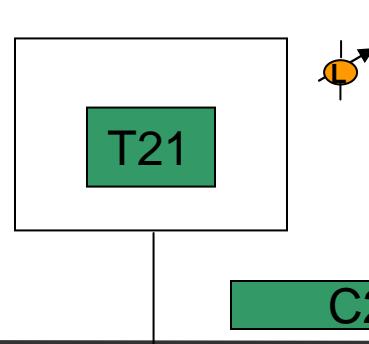
Decentralized real-time control system

A system with loosely coupled nodes, which co-process and communicate with each other to provide the required system control functionality **on time**.

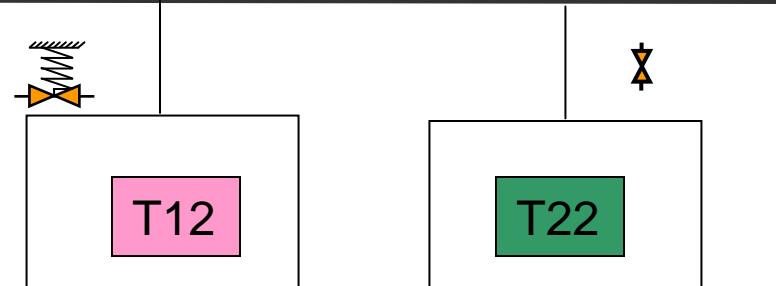
Pressure sensor node



Level sensor node



Broadcast bus

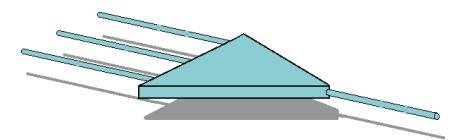


A simple decentralized real-time control system

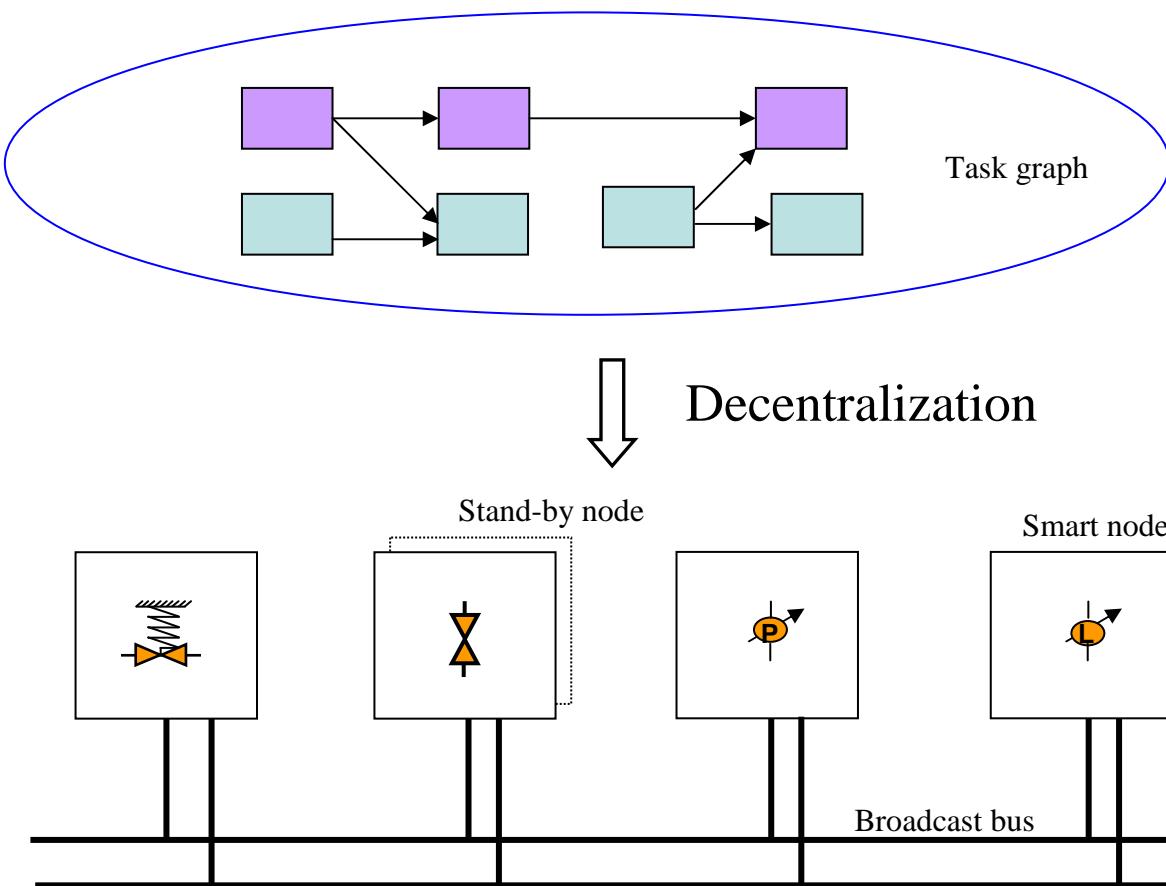
Air vent valve node

Drain valve node

2



Decentralization of real-time control



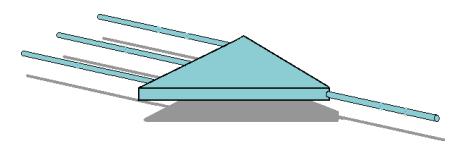
Application model

- Timing constraints
- Precedence constraints
- Fault tolerance requirements

Resource model

- Max. node utilization
- Max. bus utilization

3

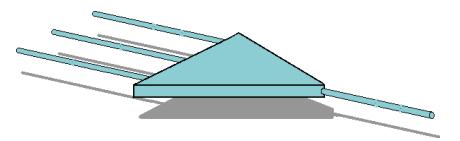


Global scheduling

A plan which defines the space, time and order of execution of tasks and their communications in the node and the bus respectively.

Objective

- Derive a global schedule which has the minimal number of message transfers while not violating the given constraints.

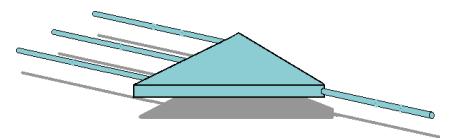


Global scheduling constraints

- No node is utilized above its maximum allowed limit.
- Utilization of the bus is less than the maximum allowed limit.
- Exclusive allocation for fault redundant modules.
- Fixed allocation for resource dependent modules.
- Precedence constraints should not be violated.
- Release times and deadlines should not be violated.

Solution: Mixed Integer Linear Program (MILP)

5



Mixed Integer Linear Program

Assumptions

- Tasks are periodic.
- Nodes are homogeneous.
- Communication within a node takes zero time.

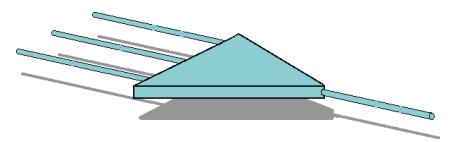
Objective

- Minimize the maximum of all lateness of the given ' m ' periodic tasks distributed over ' n ' nodes.

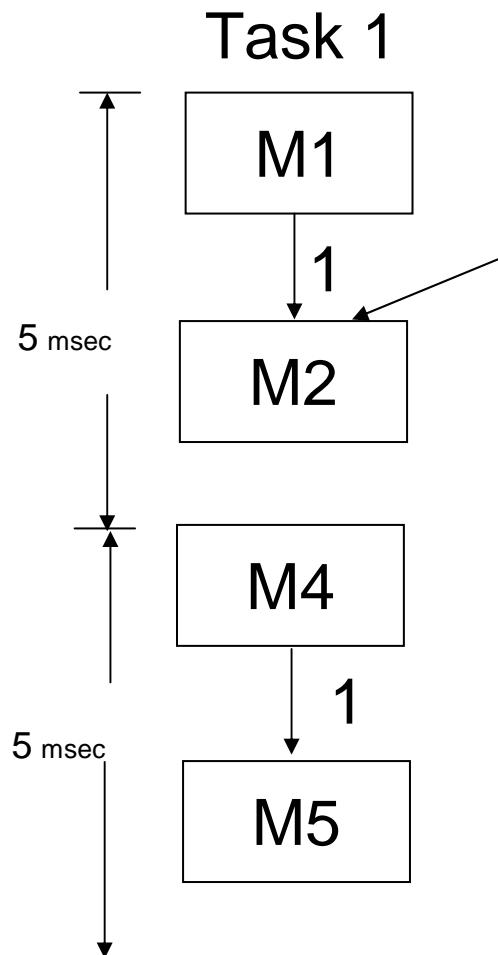
Constraints

- Resource constraints.
- Precedence constraints.
- Timing constraints.

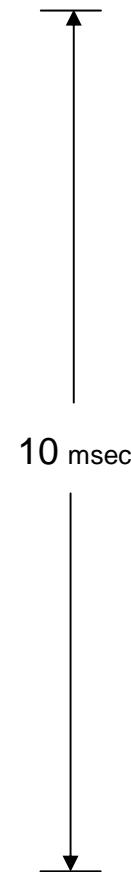
6



Task graph- Example



Task 2



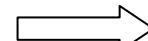
$$H = 10 \text{ msec}$$

$$e_1 = e_2 = e_4 = e_5 = 1 \text{ msec}$$

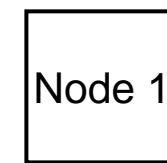
$$e_3 = 3 \text{ msec}$$

$$t = 2 \text{ msec}$$

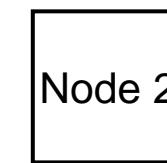
$$10 \text{ msec}$$



$$U_1 = 0.5$$



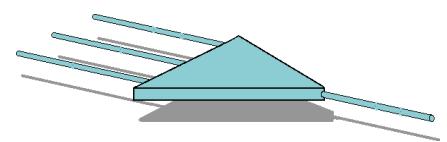
$$U_2 = 0.5$$



$$\text{Bus}$$

$$U_b = 1$$

7



Mixed Integer Linear Program (Contd.)

Objective :

Minimize: M_L (Maximum Lateness)

$M_L \geq (S_k + e_k) - d_{ij}$ (only the leaf modules)

Constraints :

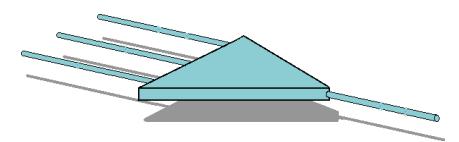
$A[i,k] = 0 \text{ or } 1$ (module assignment)

$\sum_{i=1}^n u[i] \bullet A[i,k] \leq U[k] \text{ , for each } k = 1..n$ (node utilization bound)

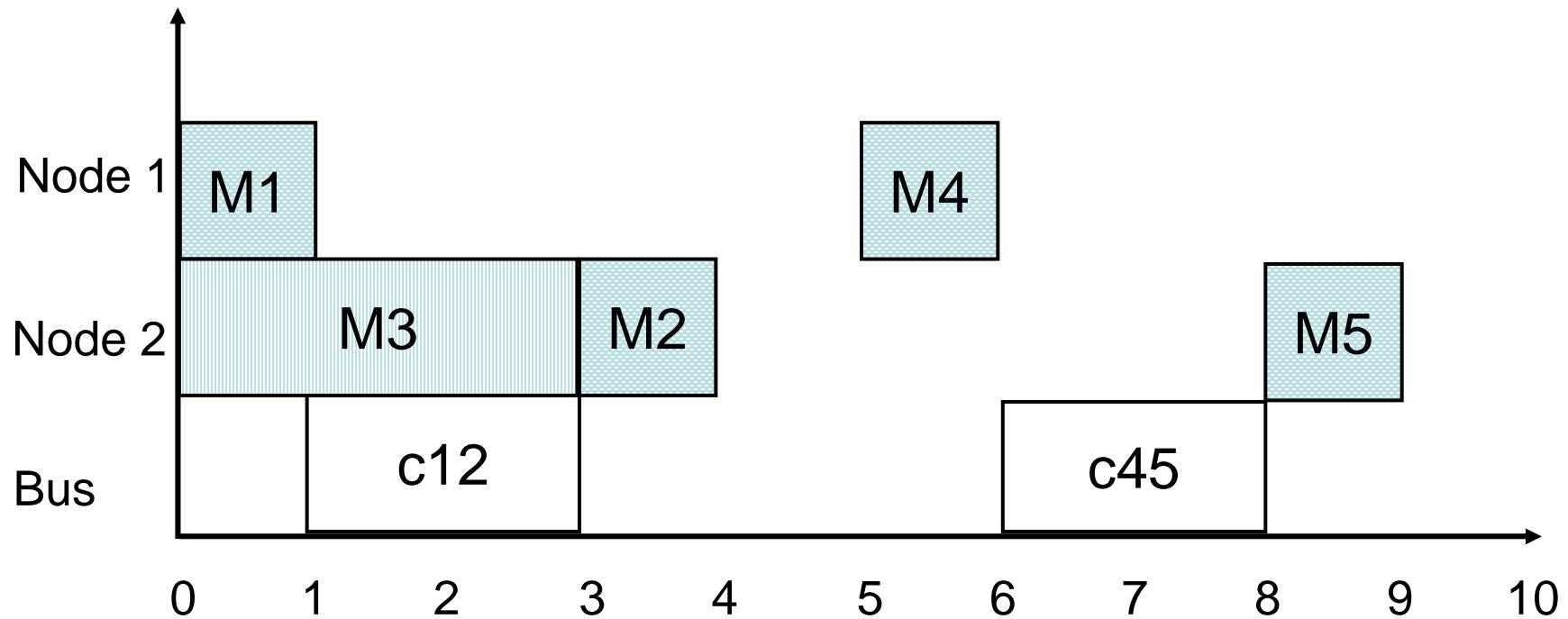
$A[i,k] = 1 \text{ , for each } (i,k) \in R$ (Resource dependency)

$0 \leq 1 - A[i,k] - A[i',k] \leq 1 \text{ , for each } k = 1..n \text{ and } (i,i') \in F$ (Fault redundancy)

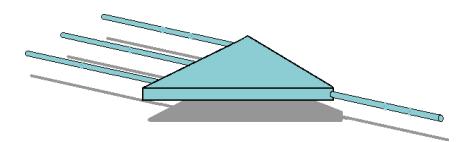
$r_{k'} \leq S_{k'}, S_k + e_k \leq d_k$ (Timing constraints)



Global schedule



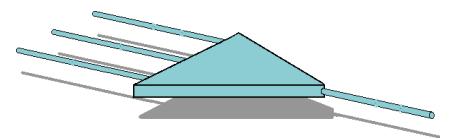
9



References

- S. Thanikesavan and U. Killat. "Global Scheduling of Periodic Tasks in a Decentralized Real-time Control System". **To be published in the IEEE WFCS, September 2004.**
- S. S. H. Barada and N. Baig. "Task matching and scheduling in heterogeneous systems using simulated evolution". (*HCW2001*), April 2001.
- L. K. M. Lin and L. Yang. Heuristic techniques: Scheduling partially ordered tasks in a multi-processor environment with tabu search and genetic algorithms. *ICPADS '00*, 2000.
- C. wen Hsueh and K.-J. Lin. Scheduling real-time systems with end-to-end timing constraints using the distributed pinwheel model. *IEEE Trans. Comput.*, 2001.

10



THANK YOU

