Dependable resource sharing for compositional real-time systems
van den Heuvel, M.M.H.P.; Bril, R.J.; Lukkien, J.J.

Published in:

DOI:
10.1109/RTCSA.2011.29

Published: 01/01/2011

Document Version
Publisher’s PDF, also known as Version of Record (includes final page, issue and volume numbers)

Please check the document version of this publication:
• A submitted manuscript is the author's version of the article upon submission and before peer-review. There can be important differences between the submitted version and the official published version of record. People interested in the research are advised to contact the author for the final version of the publication, or visit the DOI to the publisher's website.
• The final author version and the galley proof are versions of the publication after peer review.
• The final published version features the final layout of the paper including the volume, issue and page numbers.

Link to publication

Citation for published version (APA):

General rights
Copyright and moral rights for the publications made accessible in the public portal are retained by the authors and/or other copyright owners and it is a condition of accessing publications that users recognise and abide by the legal requirements associated with these rights.

• Users may download and print one copy of any publication from the public portal for the purpose of private study or research.
• You may not further distribute the material or use it for any profit-making activity or commercial gain
• You may freely distribute the URL identifying the publication in the public portal

Take down policy
If you believe that this document breaches copyright please contact us providing details, and we will remove access to the work immediately and investigate your claim.
Dependable resource sharing for compositional real-time systems

Martijn M. H. P. van den Heuvel, Reinder J. Bril and Johan J. Lukkien
Department of Mathematics and Computer Science
Technische Universiteit Eindhoven (TU/e)
Den Dolech 2, 5600 AZ Eindhoven, The Netherlands

Abstract

Hierarchical scheduling frameworks (HSFs) have been extensively investigated as a paradigm for facilitating temporal isolation between components that need to be integrated on a single shared processor. In the presence of shared resources, however, temporal isolation may break when one of the accessing components executes longer than specified during global resource access. The ability to confine such temporal faults makes the HSF more dependable. As a solution we propose a stack-resource-policy (SRP)-based synchronization protocol for HSFs, named Hierarchical Synchronization protocol with Temporal Protection (HSTP).

When a component exceeds its specified critical-section length, HSTP enforces a component to self-donate its own budget to accelerate the resource release. In addition, a component that blocks on a locked resource may donate budget. The schedulability of those components that are independent of the locked resource is unaffected. HSTP efficiently limits the propagation of temporal faults to resource-sharing components by disabling local preemptions in a component during resource access. We finally show that HSTP is SRP-compliant and applies to existing synchronization protocols for HSFs.

1. Introduction

Many real-time embedded systems implement increasingly complex and safety-critical functionality while their time to market and cost is continuously under pressure. This has resulted in standardized component-based software architectures, e.g. the AUTomotive Open System ARchitecture (AUTOSAR), where each component can be analysed and certified independently of its performance in an integrated system. Hierarchical scheduling frameworks (HSFs) have been investigated as a paradigm for facilitating such a decoupling [1] of development of individual components from their integration. HSFs provide temporal isolation between components by allocating a budget to each component. A component that is validated to meet its timing constraints when executing in isolation will therefore continue meeting its timing constraints after integration or admission on a shared uniprocessor platform.

An HSF without further resource sharing is unrealistic, however, since components may for example use operating system services, memory mapped devices and shared communication devices which require mutually exclusive access. Extending an HSF with such support makes it possible to share logical resources between arbitrary tasks, which are located in arbitrary components, in a mutually exclusive manner. A resource that is used in more than one component is denoted as a global shared resource. A resource that is only shared by tasks within a single component is a local shared resource. If a task that accesses a global shared resource is suspended during its execution due to the exhaustion of its budget, excessive blocking periods can occur which may hamper the correct timeliness of other components [2].

To accommodate resource sharing between components, three synchronization protocols [3], [4], [5] have been proposed based on the stack resource policy (SRP) [6]. Each of these protocols describes a run-time mechanism to handle the depletion of a component’s budget during global resource access. In short, two general approaches are proposed: (i) self-blocking before accessing a shared resource when the remaining budget is insufficient to complete a critical section [4], [5] or (ii) overrun the budget until the critical section ends [3]. However, when a task exceeds its specified worst-case critical-section length, i.e. it misbehaves during global resource access, temporal isolation between components is no longer guaranteed. The protocols in [3], [4], [5] therefore break the temporal encapsulation and fault-containment properties of an HSF without the presence of complementary protection.

A common practice to temporal protection is based on watchdog timers, which (i) trigger the termination of a misbehaving task, (ii) release all its locked resources and (iii) call an error handler to execute a roll-back strategy [7]. For some shared resources, e.g. network devices, it may be advantageous to continue a critical section, because interrupting and resetting a busy device can be time consuming. In addition, an eventual error handler needs to be constrained, so that it does not interfere with independent components.

A solution to confine temporal faults to those components that share global resources is considered in [8]. Each task is assigned a dedicated budget per global resource access and this budget is synchronous with the period of that task. After depletion of this budget, a critical section is discontinued until its budget replenishes and the task will therefore miss
its deadline. To improve reliability, they propose a donation mechanism for tasks that encounter a locked resource, so that a critical section can continue and both the blocking as well as the resource-locking task may still meet their deadlines. However, in [8] they allow only a single task per component.

The first problem is to limit the propagation of temporal faults in HSFs, where multiple concurrent tasks are allocated a shared budget, to those components that share a global resource. However, when a critical-section exceeds its specified length, a component may nevertheless have remaining budget apart from the budget assigned to that critical section. The second problem is to allocate these unused budgets to accelerate a resource release before a resource-sharing component blocks on the locked resource. We aim to increase the reliability of resource-sharing components, while preserving the schedulability of independent components, by self-donations of the remaining budget of a resource-locking component itself and, next, by budget donations from others to critical sections.

Contributions. To achieve temporal isolation between components, even when resource-sharing components misbehave, we propose a modified SRP-based synchronization protocol, named Hierarchical Synchronization protocol with Temporal Protection (HSTP). It supports fixed-priority as well as earliest-deadline-first (EDF) scheduled systems and it complements existing synchronization protocols [3], [4], [5] for HSFs. We efficiently achieve fault-containment by disabling preemptions of other tasks within the same component during global resource access. Secondly, we allow a cascaded continuation of a critical section via self-donations as long as a component has remaining budget, or via budget donations from dependent components. Thirdly, we present HSTP’s analysis and show that sufficiently short critical sections can execute with local preemptions disabled and preserve system schedulability. Finally, we evaluate HSTP’s implementation in a real-time operating system.

Organization. The remainder of this paper is organized as follows. Section 2 describes related works. Section 3 presents our system model. Section 4 presents our dependable resource-sharing protocol, HSTP, including a donation mechanism that enhances the reliability of inter-dependent components. Section 5 presents HSTP’s corresponding schedulability analysis. Section 6 discusses HSTP’s implementation and investigates its corresponding system overhead. Finally, Section 7 concludes this paper.

2. Related work

Our basic idea is to use two-level SRP to arbitrate access to global resources, similar as [3], [4], [5]. In literature several alternatives are presented to accommodate task communication in reservation-based systems. De Niz et al. [8] support resource sharing between reservations based on the immediate priority ceiling protocol (IPCP) [9] in their fixed-priority preemptively scheduled (FPPS) Linux/RK resource kernel and use a runtime mechanism based on resource containers [10] for temporal protection against misbehaving tasks. Steinberg et al. [11] showed that these resource containers are expensive and efficiently implemented a capacity-reserve donation protocol to solve the problem of priority inversion for tasks scheduled in a fixed-priority reservation-based system. A similar approach is described in [12] for EDF-based systems and termed bandwidth-inheritance (BWI). BWI regulates resource access between tasks that each have their dedicated budget. It works similar to the priority-inheritance protocol [9], i.e. when a task blocks on a resource it donates its remaining budget to the task that causes the blocking. BWI does not require a-priori knowledge of tasks, i.e. precalculated ceilings are unnecessary. BWI has been extended with the Clearing Fund Protocol (CFP) [13], which makes a task pay back its inherited bandwidth, if necessary. All these approaches assume a one-to-one mapping from tasks to budgets, and inherently only have a single scheduling level.

In HSFs a group of concurrent tasks, forming a component, are allocated a budget [14]. A prerequisite to enable independent analysis of interacting components and their integration is the knowledge of which resources a task will access [4], [5], [15]. When a task accesses a global shared resource, one needs to consider the priority inversion between components as well as local priority inversion between tasks within the component. To prevent budget depletion during global resource access, three synchronization protocols have been proposed based on SRP [6], i.e. HSRP [3], SIRAP [4] and BROE [5]. Although HSRP [3] originally does not integrate into HSFs due to the lacking support for independent analysis of components, Behnam et al. [15] lifted this limitation. However, these three protocols, including their implementations in [16], [17], assume that components respect their timing contract with respect to global resource sharing. In this paper we smooth and limit the unpredictable interferences caused by contract violations to the components that share the global resource.

3. Real-time scheduling model

We consider a two-level HSF using the periodic resource model [1] to specify guaranteed processor allocations to components. The global scheduler and each individual component may apply a different scheduling algorithm. As scheduling algorithms we consider EDF, an optimal dynamic uniprocessor scheduling algorithm, and the deadline-monotonic (DM) algorithm, an optimal fixed-priority uniprocessor scheduling algorithm. We use an SRP-based synchronization protocol to arbitrate mutually exclusive access to global shared resources.

3.1. Compositional model

A system contains a set $R$ of $M$ global logical resources $R_1$, $R_2$, ..., $R_M$, a set $C$ of $N$ components $C_1$, $C_2$, ..., $C_N$, a set $B$ of $N$ budgets for which we assume a periodic resource model [1], and a single shared processor. Each component $C_n$ has
a dedicated budget which specifies its periodically guaranteed fraction of the processor. The remainder of this paper leaves budgets implicit, i.e. the timing characteristics of budgets are taken care of in the description of components.

The timing characteristics of a component \( C_i \) are specified by means of a triple \( < P_i, Q_i, \lambda_i > \), where \( P_i \in \mathbb{R}^+ \) denotes its period, \( Q_i \in \mathbb{R}^+ \) its budget, and \( \lambda_i \) the set of maximum access times to global resources. The maximum value in \( \lambda_i \) is denoted by \( X_i \), where \( 0 < Q_i + X_i \leq P_i \). The set \( R_i \) denotes the subset of \( M_i \) global resources accessed by component \( C_i \). The maximum time that a component \( C_i \) executes while accessing resource \( R_i \in R_i \) is denoted by \( X_{si} \), where \( X_{si} \in \mathbb{R}^+ \cup \{0\} \) and \( X_{si} > 0 \Leftrightarrow R_i \in R_i \).

### 3.1.1. Processor supply

The processor supply refers to the amount of processor allocation that a component \( C_i \) can provide to its workload. The supply bound function \( \text{sbf}_{\Gamma_i}(t) \) of the periodic resource model \( \Gamma_i(P_i, Q_i) \), that computes the minimum supply for any interval of length \( t \), is given by [1]:

\[
\text{sbf}_{\Gamma_i}(t) = \begin{cases} 
    t - (k + 1)(P_i - Q_i) & \text{if } t \in V^{(k)} \\
    (k - 1)Q_i & \text{otherwise}
\end{cases}
\]

where \( k = \max \left( \left\lceil \frac{t - (P_i - Q_i)}{P_i} \right\rceil, 1 \right) \) and \( V^{(k)} \) denotes an interval \( [(k + 1)P_i - 2Q_i, (k + 1)P_i - Q_i] \).

### 3.1.2. Task model

Each component \( C_i \) contains a set \( T_i \) of \( n_i \) sporadic tasks \( \tau_{si}, \tau_{s2}, \ldots, \tau_{sn_i} \). Timing characteristics of a task \( \tau_{si} \in T_i \) are specified by means of a triple \( < T_{si}, E_{si}, D_{si} > \), where \( T_{si} \in \mathbb{R}^+ \) denotes its minimum inter-arrival time, \( E_{si} \in \mathbb{R}^+ \) its worst-case computation time, \( D_{si} \in \mathbb{R}^+ \) its (relative) deadline, where \( 0 < E_{si} \leq D_{si} \leq T_{si} \).

We assume that period \( P_i \) of component \( C_i \) is selected such that \( 2P_i \leq T_{si} \) (\( \forall \tau_{si} \in T_i \)), because this efficiently assigns a budget to component \( C_i \) [1]. The worst-case execution time of task \( \tau_{si} \) within a critical section accessing \( R_i \) is denoted \( c_{si} \), where \( c_{si} \in \mathbb{R}^+ \cup \{0\} \), \( E_{si} \geq c_{si} \), and \( c_{si} > 0 \Leftrightarrow R_i \in R_i \).

### 3.2. Synchronization protocol

Traditional synchronization protocols such as PCP [9] and SRP [6] can be used for local resource sharing in HSFs [18]. This paper focuses on arbitrating global shared resources using SRP. To be able to use SRP in an HSF for synchronizing global resources, its associated ceiling terms need to be extended and excessive blocking must be prevented.

### 3.2.1. Preemption levels

Each task \( \tau_{si} \) has a static preemption level equal to \( \pi_{si} = 1/D_{si} \). Similarly, a component has a preemption level equal to \( \Pi_i = 1/P_i \), where period \( P_i \) serves as a relative deadline. If (components or tasks) have the same calculated preemption level, then the smallest index determines the highest preemption level.

### 3.2.2. Resource ceilings

With every global resource \( R_i \), two types of resource ceilings are associated; a global resource ceiling \( RC_i \) for local scheduling and a local resource ceiling \( rc_{si} \) for local scheduling. These ceilings are statically calculated values, which are defined as the highest preemption level of any component or task that shares the resource. According to SRP, these ceilings are defined as:

\[
RC_i = \max(\Pi_{X_i}, \max(\{\pi_i \mid R_i \in R_i\})) \quad \text{(2)}
\]

\[
rc_{si} = \max(\pi_{si}, \max(\{\pi_i \mid c_{si} > 0\}) \quad \text{(3)}
\]

We use the outermost \( \max \) in (2) and (3) to define \( RC_i \) and \( rc_{si} \) in those situations where no component or task uses \( R_i \).

### 3.2.3. System and component ceilings

The system and component ceilings are dynamic parameters that change during execution. The system ceiling is equal to the highest global resource ceiling of a currently locked resource in the system. Similarly, the component ceiling is equal to the highest local resource ceiling of a currently locked resource within a component. Under SRP a task can only preempt the currently executing task if its preemption level is higher than its component ceiling. A similar condition for preemption holds for components.

### 3.2.4. Prevent excessive blocking

HSRP [3] uses an overrun mechanism [15] when a budget depletes during a critical section. If a task \( \tau_{si} \in T_i \) has locked a global resource when its component’s budget \( Q_i \) depletes, then component \( C_i \) can continue its execution until task \( \tau_{si} \) releases the resource. To distinguish this additional amount of required budget from the normal budget \( Q_i \), we refer to \( X_i \) as an overrun budget. These budget overruns cannot take place across replenishment boundaries, i.e. the analysis guarantees \( Q_i + X_i \) processor time before the relative deadline \( P_i \) of component \( C_i \) [3], [15].

SRAP [4] uses a self-blocking approach to prevent budget depletion inside a critical section. If a task \( \tau_{si} \) wants to enter a critical section, it enters the critical section at the earliest instant so that it can complete the critical section before the component’s budget depletes. If the remaining budget is insufficient to lock and release a resource \( R_i \) before depletion, then (i) the task blocks itself until budget replenishment and (ii) the component ceiling is raised to prevent tasks \( \tau_{sj} \in T_i \) with a preemption level lower than the local ceiling \( rc_{si} \) to execute until the requested critical section has been finished.

BROE [5] uses an other self-blocking variant than SRAP uses. Contrary to SRAP and HSRP, BROE only works with a global EDF scheduler. Its major advantage is that when the remaining budget of a component is insufficient to complete a critical section, it discards this remainder without violating the periodic resource supply [1]. BROE does therefore not waste processor resources during self-blocking and it is also unnecessary to allocate overrun budgets to components.

In this paper we ignore the relative strengths of the mechanisms presented by the protocols in [3], [4], [5], [15]. We focus on mechanisms to extend these existing protocols with
dependability attributes and merely investigate their relative complexity with respect to our mechanisms.

4. Dependable resource sharing

Dependability encompasses many quality attributes [7], i.e. amongst others: safety, integrity, reliability, availability and robustness. Temporal faults can have catastrophic consequences, making the system unsafe. These temporal faults may cause improper system alterations, e.g. due to unexpectedly long blocking or an inconsistent state of a resource. Hence, it affects system integrity. Without any protection a self-blocking approach [4], [5] may miss its purpose under erroneous circumstances, i.e. a task still overruns its budget to complete its critical section. Even an overrun approach [3], [15] must guarantee a maximum duration of the overrun situation. Otherwise, overruns can hamper temporal isolation and resource availability to other components due to unpredictable blocking effects. A straightforward implementation of the overrun mechanism, e.g. as implemented in the ERIKA kernel [19], where a task is allowed to indefinitely overrun its budget as long as it locks a resource, is therefore unreliable. The extent to which a system tolerates such unforeseen interferences defines its robustness.

4.1. Resource monitoring and enforcement

A common approach to ensure temporal isolation and prevent propagation of temporal faults within the system is to group tasks that share resources into a single component [18]. However, this might be too restrictive and leading to large, incoherent component designs, which violates the principle of HSFs to independently develop components. Since a component defines a coherent piece of functionality, a task that accesses a global shared resource is critical with respect to all other tasks in the same component.

To guarantee temporal isolation between components, the system must monitor and enforce the length of a global critical section to prevent a malicious task to execute longer in a critical section than assumed during system analysis [8]. Otherwise such a misbehaving task may increase blocking to components with a higher preemption level, so that even independent components may suffer, as shown in Figure 1.

To prevent this effect we introduce a resource-access budget \( q_s \) in addition to a component’s budget \( Q_s \), where budget \( q_s \) is used to enforce critical-section lengths. When a resource \( R_l \) gets locked, \( q_s \) replenishes to its full capacity, i.e. \( q_s \leftarrow X_{sl} \). To monitor the available budget at any moment in time, we assume the availability of a function \( Q^\text{rem}_s(t) \) that returns the remaining budget of \( Q_s \). Similarly, \( q^\text{rem}_s(t) \) returns the remainder of \( q_s \) at time \( t \). If a component \( C_s \) executes in a critical section, then it consumes budget from \( Q_s \) and \( q_s \) in parallel, i.e. depletion of either \( Q_s \) or \( q_s \) forbids component \( C_s \) to continue its execution. We maintain the following invariant to prevent budget depletion during resource access:

\[ \text{Invariant 1: } Q^\text{rem}_s(t) \geq q^\text{rem}_s(t). \]

The way of maintaining this invariant depends on the chosen policy to prevent budget depletion during global resource access, e.g. by means of SIRAP [4], HSRP [3] or BROE [5]. For ease of presentation we will first complement HSRP’s overrun mechanism with a mechanism for temporal protection. In Section 5.4 we show how our resulting protocol, HSTP, applies to both SIRAP’s and BROE’s self-blocking mechanisms.

4.1.1. Fault containment of critical sections. Existing SRP-based synchronization protocols in [4], [5], [15] make it possible to choose the local resource ceilings, \( rc_{sl} \), according to SRP [6], see (3). In [20], [21] techniques are presented to trade-off preemptiveness against resource holding times. Given their common definition for local resource ceilings, a resource holding time, \( X_{sl} \), may also include the interference of tasks with a preemption level higher than the resource ceiling. Task \( \tau_{si} \) can therefore lock resource \( R_l \) longer than specified, because an interfering task \( \tau_{sj} \) (where \( \pi_{sj} > rc_{sl} \)) exceeds its computation time, \( E_{sj} \).

To prevent this effect we choose to disable preemptions for other tasks within the same component during critical sections, i.e. similar as HSRP [3] we choose local resource ceilings by \( \forall R_l \in R_s : rc_{sl} = \pi_{sl} \). As a result \( X_{sl} \) only comprises task execution times within a critical section, i.e.

\[ X_{sl} = \max_{1 \leq l \leq n_s} c_{sl}. \]  

Since \( X_{sl} \) is enforced by budget \( q_s \), temporal faults are contained within a subset of resource-sharing components.

4.1.2. Maintaining SRP ceilings. To enforce that a task \( \tau_{si} \) resides no longer in a critical section than specified by \( X_{sl} \), a resource \( R_l \in R \) maintains a state locked or free. We introduce an extra state busy to signify that \( R_l \) is locked by a misbehaving task. When a task \( \tau_{si} \) tries to exceed its maximum critical-section length \( X_{sl} \), we update SRP’s system ceiling by mimicking a resource unlock and mark the resource busy until it is released. Since we decrease the system ceiling after \( \tau_{si} \) executes for a duration of \( X_{sl} \) in a critical section to resource \( R_l \), we can no longer guarantee absence of deadlocks. Nested critical sections to global shared resources are therefore unsupported². One may alternatively aggregate

\[ 2. \text{We allow nesting of a (sequence of) global resource access(es) inside local critical sections.} \]
global resource accesses into a simultaneous lock and unlock of a single artificial resource [22]. Many protocols, or their implementations, lack deadlock avoidance [8], [11], [12], [17]. Although it seems attractive from a schedulability point of view to release the component ceiling when the critical-section length is exceeded, i.e. similar to the system ceiling, this would break SRP compliance, because a task may block on a busy resource instead of being prevented from starting its execution. Our approach therefore preserves the SRP property to share a single, consistent execution stack per component [6]. At the global level tasks can be blocked by a depleted budget, so that components cannot share an execution stack anyway.

4.1.3. Repetitive self-donation to resource-access budgets. A component that accesses a resource \( R_t \) maintains a dedicated resource-access budget \( q_s \) synchronous to its normal budget \( Q_s \), i.e. similar to [8]. Since critical sections are often shorter than budget \( Q_s \), a component may still have remaining budget \( Q_s^{\text{rem}}(t) > 0 \) when \( q_s \) depletes. Contrary to [8], when \( q_s \) depletes we repeatedly replenish it by a self-donation of \( X_{sl} \) until budget \( Q_s \) is exhausted. Although we need to decrease the system ceiling before replenishing \( q_s \) to avoid excessive blocking durations to other components, we may again increase the system ceiling for a duration of \( X_{sl} \) as soon as component \( C_s \) is selected by the global scheduler to continue its execution. This increases the likelihood that a resource-using component meets its deadline despite a misbehaving critical section and it reduces the likelihood that a resource-sharing component encounters a busy resource. Our resource-access budgets are therefore more reliable and robust than those in [8] are.

4.2. HSTP with self-donation

We specify four rules to manipulate a component’s budget \( q_s \) when a resource is locked or unlocked and change the way budgets \( Q_s \) and \( q_s \) are replenished and depleted. This scheme defines HSTP, a protocol that maintains temporal protection between components during global resource access.

4.2.1. Lock resource. Upon an attempt of task \( \tau_{si} \in T_s \) to lock resource \( R_t \in R_s \) at time \( t_i \), we raise the component ceiling independent of whether or not \( R_t \) is free.

If resource \( R_t \) is free, then \( \tau_{si} \) locks the resource and \( q_s \) replenishes, i.e. \( q_s \leftarrow X_{sl} \). Component \( C_s \) now runs in parallel on budget \( Q_s \) and \( q_s \). We need to guarantee that \( C_s \)’s normal budget \( Q_s \) does not deplete during global resource access. We therefore first save \( C_s \)’s remaining budget as \( Q_s^{\text{rem}}(t_i) \) and then provide an overrun budget \( Q_s^{\text{rem}}(t_i) \leftarrow X_{sl} \).

By virtue of SRP, a resource \( R_t \) can never be locked when a task \( \tau_{si} \) attempts to lock it. If there exists a task \( \tau_{nj} \in T_n \) which currently holds \( R_t \) busy, then we immediately deplete the remaining budget of \( C_s \), i.e. \( Q_s^{\text{rem}}(t_i) \leftarrow 0 \). After the budget \( Q_s \) of component \( C_s \) has replenished, the blocked task \( \tau_{si} \) again tests whether or not resource \( R_t \) is free.

4.2.2. Unlock resource. If task \( \tau_{si} \in T_s \) unlocks a resource \( R_t \in R_s \) at time \( t_f \), then the component and system ceilings are decreased according to the rules of SRP and resource \( R_t \) is marked free. Moreover, component \( C_s \) no longer consumes budget \( q_s \) and we need to restore \( C_s \)’s budget. When a budget overrun has occurred, i.e. \( Q_s^{\text{rem}}(t) < X_{sl} - q_s^{\text{rem}}(t) \), then component \( C_s \) is suspended on its depleted budget \( Q_s \). Otherwise, component \( C_s \) continues within its remaining budget, i.e. we restore \( Q_s \) with \( \max(0, Q_s - (X_{sl} - q_s^{\text{rem}}(t))) \).

4.2.3. Budget depletion. If component \( C_s \)’s budget \( Q_s \) or \( q_s \) depletes and all resources \( R_t \in R_s \) are free, then nothing changes compared to default budget-depletion policies. However, if a task \( \tau_{si} \) holds a resource \( R_t \in R_s \) so that \( q_s \) has been depleted, then (i) resource \( R_t \) is marked busy; (ii) the system ceiling is decreased according to the rules of unlocking an SRP resource and (iii) the budget \( Q_s \) of component \( C_s \) is restored with \( \max(0, Q_s^{\text{rem}} - X_{sl}) \).

These actions guarantee that \( \tau_{si} \) can overrun at most an amount \( X_{sl} \) and a component \( C_s \) can therefore at most request \( Q_s + X_{sl} \) processor time during each period \( P_s \). If no other component \( C_t \) can preempt based on its preemption level \( \Pi_t \) > \( \Pi_s \), after decreasing the system ceiling, the system ceiling can be raised again for a duration of \( X_{sl} \) without increasing the blocking times that component \( C_t \) may experience. Since the component ceiling is persistently raised during global resource access, other tasks in \( T_s \) than the resource-accessing one cannot execute. Hence, as long as a resource \( R_t \) is kept locked or busy by component \( C_s \), task \( \tau_{si} \) may entirely consume the remaining budget \( Q_s^{\text{rem}}(t) \) with a raised component and system ceiling via self-donations, if it decreases the system ceiling after every \( X_{sl} \) and performs a global preemption test.

4.2.4. Budget replenishment. If component \( C_s \)’s budget \( Q_s \) replenishes, it is guaranteed that at most one resource \( R_t \in R_s \) is kept busy via component \( C_s \) and the corresponding resource-access budget \( q_s^{\text{rem}}(t) = 0 \). If component \( C_s \) does not keep any resource busy, then nothing changes compared to default budget-replenishment policies. Otherwise, we restrict the replenishment of component \( C_s \), so that it may continue its critical section, i.e. (i) the budget to be restored upon unlocking, \( Q_s^{\text{rem}} \), replenishes to \( Q_s \); (ii) the budgets \( q_s \) and \( Q_s \) that allow continuing resource access to \( R_t \) replenish with \( X_{sl} \) and (iii) a resource lock is mimicked by raising the system ceiling according to SRP. Hence, component \( C_s \) continues its execution with a raised system ceiling.

4.2.5. Final remarks. A component \( C_s \) may block on a busy resource \( R_t \) at a time \( t_i \) and subsequently \( R_t \) can become free at a time \( t_f \) before the replenishment of \( C_s \)’s budget, \( Q_u \). If we signal component \( C_s \) to continue its execution within \( Q_s^{\text{rem}}(t_b) \) at time \( t_f \), we can no longer guarantee the provisioning of budget \( Q_u \) within its period boundaries \( P_u \) due to the self-suspension interval \( [t_b, t_f] \) of budget \( Q_u \). This introduces unpredictable interferences and scheduling anomalies to other components in the system [23]. We can therefore either let a
blocking task spinlock on a busy resource, so that it consumes its component’s budget, or suspend a blocking component until its replenishment before allowing this component to resume its execution, similar to [8].

### 4.3. HSTP extended with third-party donations

The basic HSTP specification in Section 4.2 immediately depletes the budget of a component \( C_u \) upon an attempt at time \( t_b \) to lock a busy resource \( R_l \). As a result, all remaining budget, \( Q_u^{\text{rem}}(t_b) \), of the blocking component \( C_u \) is discarded until its next replenishment. Since \( C_u \) is unable to consume its budget due to the raised component ceiling, \( C_u \) may alternatively donate its budget to the misbehaving component \( C_s \) with the aim to reduce the waiting time on the busy resource \( R_l \). In this section we complement HSTP with a donation mechanism.

#### 4.3.1. Attempt to lock a busy resource

When component \( C_u \) encounters a busy resource at time \( t_b \), it can repeatedly donate \( X_{ul} \) to misbehaving component \( C_s \) until \( Q_s \) is depleted with the aim to reduce its waiting time on resource \( R_l \). Such a donation from donor \( C_u \) to donatee \( C_s \) (i) mimics a resource lock by raising the system ceiling, (ii) saves donor \( C_u \)’s remaining budget as \( Q_u^{\text{rem}}(t_b) \), (iii) saves donatee \( C_s \’s \) remaining budget as \( Q_s^{\text{rem}}(t_b) \), and (iv) allocates budget \( Q_s^{\text{rem}}(t_b) \) to critical section of component \( C_s \). Due to the raised system ceiling, component \( C_s \) effectively runs at the resource-ceiling’s preemption level \( RC_l \). It is therefore unnecessary to change the deadline or priority of the donatee, because all components that may use \( R_l \) are blocked by the system ceiling.

#### 4.3.2. Unlock resource

If an erroneous component \( C_s \) unlocks resource \( R_l \) at time \( t_f \) while consuming a donation, then any remaining resource-access budget \( Q_s^{\text{rem}}(t_f) \) is donated back to donor \( C_u \), i.e. \( Q_u^{\text{rem}}(t_f) \leftarrow \max(0, Q_u^{\text{rem}}(t_f) - (X_{ul} - Q_s^{\text{rem}}(t_f))) \). Donatee \( C_s \) has consumed a part of the donated budget, \( X_{ul} = Q_s^{\text{rem}}(t_f) \), in the place of donor \( C_u \). This part is accounted to donor \( C_u \) rather than to donatee \( C_s \), so that the budget of donatee \( C_s \) is restored to \( Q_s^{\text{rem}}(t_f) \leftarrow Q_s^{\text{rem}}(t_f) \). As a result both resource-sharing components \( C_s \) and \( C_u \) may resume execution within their restored budgets.

#### 4.3.3. Budget depletion

When a donated budget \( X_{ul} \) is depleted by donatee \( C_s \), the system ceiling is decreased and \( X_{ul} \) is subtracted from donor \( C_u \)’s budget, i.e. \( Q_u^{\text{rem}}(t) \leftarrow \max(0, Q_u^{\text{rem}}(t) - X_{ul}) \). The budget of donor \( C_u \) is restored with its original value \( Q_u^{\text{rem}}(t) \leftarrow Q_u^{\text{rem}}(t) \). If donor \( C_u \) gets re-selected for the global scheduler for execution and resource \( R_l \) is still busy, it may again donate \( X_{ul} \) to component \( C_s \).

#### 4.3.4. Budget replenishment

During the consumption of donated budget \( X_{ul} \) from donor \( C_u \), the budget of donatee \( C_s \) itself can get replenished. The replenishment of budget \( Q_s \) remains unchanged compared to Section 4.2.4. However, we can only replenish a depleted resource-access budget, i.e. \( q_s^{\text{rem}}(t) = 0 \). Otherwise, component \( C_s \) may cause double blocking to other components, i.e. \( X_{ul} + X_{sl} \) instead of \( X_{ul} \), see Figure 2. How to avoid this effect is unclearly described in [8], however. Because it is unattractive to account for double blocking in the system analysis, we avoid this blocking.

The key to the solution to avoid the double-blocking problem is to allow preemption before replenishing \( q_s \). We can either choose to immediately deplete \( q_s^{\text{rem}}(t) > 0 \) or we can defer replenishment until \( q_s \) depletes. Note that the first alternative is less reliable, because the donor will not receive any of its donation back. However, in both cases the system ceiling must be decreased according to SRP’s rules and the global scheduler must be called prior to replenishing \( q_s \).

### 4.4. Donation policies

When a component depletes its resource-access budget or blocks on a busy resource, it cannot continue its execution. We allow two alternative budget-donation policies, symmetrically for a donatee \( C_s \) via self-donation or a third-party donor \( C_u \):

#### 4.4.1. At-once donation

A component \( C_u \) may (self-)donate its remaining budget \( Q_u^{\text{rem}}(t) \) at once to a donatee \( C_s \) using BWI [8], [12]. However, component \( C_s \) must consume such donations in the place of donor \( C_u \) [24], i.e. at the donor’s preemption-level rather than at the resource-ceiling level. This requires multiple budgets per component and migration of tasks to enable the execution of tasks over several budgets [8], which is costly [11] and breaks SRP’s stack-sharing property. Hence, at-once donation causes additional run-time penalties compared to a regular two-level HSF implementation.

#### 4.4.2. Repetitive donation

Similar to the misbehaving component \( C_s \), the blocking component \( C_u \) may entirely donate its remaining budget \( Q_u^{\text{rem}}(t) \) with a raised system ceiling if it decreases the system ceiling after every \( X_{sl} \) and performs a preemption test to avoid double blocking. As a result, after a preemption test the component with the highest preemption level, which is ready to execute, resumes its execution, so that a donatee always receives donated budget from the resource-dependent component with the highest preemption level.

Similar to at-once donation, however, a component \( C_u \) may (repetitively) donate its budget to a component \( C_s \) with a
depleted resource-access budget \( q_s \), although donatee \( C_s \) has remaining budget \( Q^\text{res}_s(t) > 0 \). An advantage of repetitive self-donations is that it reduces the number of such unnecessary donations to third-parties, because a replenished component can be prevented by the system ceiling from starting its execution and donation for a duration of \( X_{st} \); see Figure 3.

![Diagram](image)

**Fig. 3.** Repetitive consumption of remaining budget can reduce unnecessary donations from blocking components. In this example component \( C_1 \) arrives an infinitesimal amount of time, \( \epsilon \), after the first depletion and preemption test of \( C_2 \), so that donation is deferred until component \( C_2 \) depletes its replenished budget \( q_2 = X_{2t} \).

Given the repetitive donation policy, the following lemma follows from our HSTP specification:

**Lemma 1:** At each time instant \( t \) there is at most one donor component \( C_u \) per donatee \( C_s \) and each component \( C_s \) can only execute a single global critical section.

**Proof:** As long as a resource \( R \) is kept locked or busy by component \( C_s \), its component ceiling prevents all other tasks within the component from starting their execution. By absence of nested critical sections, no other resource \( R_k \) can be kept locked or busy by the same component \( C_s \).

A component \( C_u \) which attempts to lock \( R_l \) may donate a budget of length \( X_{ul} \) and immediately raises the system ceiling. Hence, other \( R_l \)-sharing components \( C_t \) cannot preempt while donatee \( C_s \) consumes the donated budget \( X_{ul} \).

In the remainder of this paper we use the repetitive-donation policy, because it eliminates donations at arbitrary moments in time, which increases the reliability of a system. Secondly, it eliminates transitive donations, so that we need to track at most a single donor component within the context of a donatee.

### 5. Dependable and compositional analysis

We presented a synchronization protocol, HSTP, which enables a dependable execution of components that exceed their specified resource holding times. Contrary to [8], a mechanism to monitor blocking times is unnecessary, because we will show that HSTP complies to SRP’s blocking times. To make HSTP applicable in HSFs we reuse the analysis results presented in [4], [15], so that we obtain independent analysis for individual components and their integration. To summarize, the HSTP specification implies the following system invariant:

**Invariant 2:** If component \( C_s \) executes on the processor and holds resource \( R_l \) locked or busy, then either (i) the system ceiling is raised to \( RC_l \) or (ii) \( C_s \) has the highest preemption level \( \Pi_s \geq \Pi_u \) among all components \( C_u \) that share \( R_l \) and are ready to execute (i.e. \( q^\text{rem}_u(t) > 0 \)).

**Lemma 2:** The HSTP specification in Section 4.2 and Section 4.3 implies Invariant 2.

**Proof:** If component \( C_s \) executes and keeps resource \( R_l \) locked or busy, then \( q^\text{rem}_s(t) > 0 \) and the system ceiling equals \( RC_l \). Hence, no \( R_l \)-sharing component can preempt.

Similarly, if component \( C_s \) received \( X_{st} \) from a donor \( C_u \), then \( C_s \) executes with a raised system ceiling (\( RC_l \)) and keeps resource \( R_l \) busy. For donor \( C_u \) holds: \( q_u = 0 \), so that it is suspended and other \( R_l \)-sharing components cannot preempt.

Hence, component \( C_s \) has the highest preemption level among all ready components that share \( R_l \).

### 5.1. SRP-compliant blocking

When a task exceeds its maximum duration inside a critical section, only components that are involved in the interaction are affected. Although we decrease SRP’s system ceiling when a task exceeds its specified critical-section length, HSTP has the same calculation of the global blocking terms as SRP.

**Theorem 1:** Invariant 2 guarantees that a component \( C_s \) does not suffer more blocking or interference on unused resources \( R_l \), i.e. \( R_l \notin \mathcal{R}_s \), compared to SRP.

**Proof:** As long as the busy state of a resource \( R_l \) is unreached, i.e. \( R_l \) is either free or locked, our protocol strictly follows SRP. Given Lemma 1, we need to consider only a single busy resource \( R_l \) for each component in the system.

Consider an erroneous component \( C_s \) that exceeds its worst-case critical-section length \( X_{st} \) for resource \( R_l \). Component \( C_s \) may receive a donation from \( C_w \) with a lower preemption level \( \Pi_w < \Pi_s \) or component \( C_h \) with a higher preemption level \( \Pi_h > \Pi_w \). We can therefore have independent components \( C_t \) with \( R_l \notin \mathcal{R}_t \) at four different preemption levels:

1) \( C_t \) with \( \Pi_t > \Pi_h > \Pi_s > \Pi_w \);
2) \( C_t \) with \( \Pi_h > \Pi_t > \Pi_s > \Pi_w \) blocked by \( C_w \) or \( C_s \) and preempted by \( C_h \);
3) \( C_t \) with \( \Pi_h > \Pi_s > \Pi_t > \Pi_w \) blocked by \( C_w \) and preempted by \( C_s \) and \( C_h \);
4) \( C_t \) with \( \Pi_h > \Pi_s > \Pi_w > \Pi_t \) preempted by \( C_w \), \( C_s \) and \( C_h \).

Without loss of generality, we may restrict ourselves to an artificial system comprising each of these cases, i.e. a system \( C_1, \ldots, C_7 \in \mathcal{C} \) with a single shared resource \( R_l \in \mathcal{R}_2 \cap \mathcal{R}_4 \cap \mathcal{R}_6 \) and \( R_l \notin \mathcal{R}_1 \cup \mathcal{R}_5 \cup \mathcal{R}_7 \) and resource ceiling \( RC_l = \Pi_2 \). Furthermore, \( C_1 \) keeps \( R_l \) busy after it has executed for \( X_{st} \) with a raised system ceiling. We now prove the theorem by contradiction, i.e. assume there exists an independent component \( C_1, C_3, C_5 \) or \( C_7 \) that can experience more than one blocking occurrence and additional interference in the presence of HSTP while this cannot happen with SRP.

Because \( C_1 \) has \( \Pi_1 > RC_l \), it cannot be blocked by (or suffer interference from) any \( R_l \)-sharing component (case 1). After the system ceiling is decreased, component \( C_2 \) can preempt according to its preemption level, \( \Pi_2 > \Pi_4 \). If component \( C_2 \) tries to access \( R_l \), it may donate at most \( X_{2t} \) to component \( C_4 \). This is already accounted as interference for
C_3 \ldots C_7. Hence, C_3, C_5 and C_7 do not suffer more blocking or more interference from C_2 (case 2).

If component C_6 tries to access R_1 it may donate at most \( X_{6l} \) to C_4, which will block C_3 and C_5 no longer than \( X_{6l} \). This donation, \( X_{6l} \), is accounted as interference for C_7 and blocking for C_2 \ldots C_5. Hence, C_3, C_5 and C_7 do not suffer more blocking or more interference from C_6 (case 3).

Although component C_4 may consume the remainder of its budget \( Q_4^{\text{rem}} \) while it keeps \( R_1 \) busy, the interference for component C_7 remains the same compared to SRP (case 4).

By contradiction and using Lemma 2 we conclude that HSTP preserves SRP’s blocking properties.

Since Theorem 1 has shown that HSTP complies to SRP’s blocking term, we can safely reuse existing global analysis for component integration [1], [4], [15] without the implicit assumption that tasks behave according to their contract.

5.2. Global analysis under temporal protection

In line with our specification, we first first present the global analysis of components based on HSTP and an overrun mechanism. In Section 5.4 we adapt this analysis for SIRAP and BROE which apply a self-blocking mechanism.

The following sufficient schedulability condition holds for global EDF-based systems [25]:

\[
\forall t > 0 : B(t) + \text{dbf}_{\text{EDF}}(t) \leq t. \tag{5}
\]

The blocking term, \( B(t) \), is defined in [25] according to SRP. The demand bound function \( \text{dbf}_{\text{EDF}}(t) \) computes the total processor demand of all components in the system for every time interval of length \( t \), i.e.

\[
\text{dbf}_{\text{EDF}}(t) = \sum_{C_i \in C} \left\lfloor \frac{t}{P_{si}} \right\rfloor (Q_{si} + O_{si}(t)) \tag{6}
\]

A component \( C_s \), using an overrun mechanism to prevent budget depletion during global resource access, demands \( O_{si}(t) \) more resources in its worst-case scenario, demands

\[
O_{si}(t) = \begin{cases} X_s & \text{if } t \geq P_s \\ 0 & \text{otherwise} \end{cases} \tag{7}
\]

For global FPPS the following sufficient condition holds:

\[
\forall 1 \leq s \leq N : \exists t \in [0, P_s] : B_s + \text{dbf}_{\text{FPPS}}(t, s) \leq t, \tag{8}
\]

where the blocking term, \( B_s \), is defined as in [6] and \( \text{dbf}_{\text{FPPS}}(t, s) \) denotes the worst-case cumulative processor request of \( C_s \) for a time interval of length \( t \) [1], i.e.

\[
\text{dbf}_{\text{FPPS}}(t, s) = Q_s + O_s + \sum_{1 \leq r < s} \left\lfloor \frac{t}{P_r} \right\rfloor (Q_r + O_r). \tag{9}
\]

A component \( C_s \), using an overrun mechanism, demands \( O_s = X_s \) more resources in its worst-case scenario [15].

5.3. Local analysis for donating components

By filling in task characteristics in the dbf of (5) and (8) and replacing their right-hand sides by (1), i.e. replace \( t \) for \( \text{dbf}_{\text{FPPS}}(t, s) \), the same schedulability analysis holds for tasks within a component as for components at the global level. The processor supply to a component, as specified by (1), is only affected when the component blocks on a busy resource.

Inherent to HSFs, however, the local schedulability of tasks in \( T_s \) is only guaranteed when all tasks \( \tau_{si} \in T_s \) respect their timing characteristics. For example, when a task \( \tau_{si} \) exceeds its worst-case execution time, all other tasks in \( T_s \) may miss their deadline, even when tasks are independent. A similar argument applies when a task shares mutually non-preemptive resources, i.e. a task may unpredictably block for an unbounded duration on a busy resource. It may be useful for a task to test whether a resource is busy, so that a task can compensate by providing a reduced functionality [7].

If a task \( \tau_{si} \) in component \( C_s \) exceeds its specified critical-section length with an amount \( c_{sl} \), then its finishing time is potentially delayed. This can be modeled as extra interference of \( c_{sl} \) processor time for task \( \tau_{si} \) as well as all other tasks in the same component, \( \tau_{sj} \in T_s \). For a donor \( C_s \), the situation is symmetrical, i.e. all tasks \( \tau_{si} \in T_s \) of donor \( C_s \) experience \( c_{sl} \) extra interference. Since the local cost of consuming a donation is the same as the local cost of a donation itself, we can consider the longest duration of \( c_{sl} \) for any component \( C_s \in C \) independently, so that all tasks \( \tau_{si} \in T_s \) can still make their deadline. However, a corresponding allocation of budgets to components while maximizing the system robustness is left as a future work.

5.4. HSTP and self-blocking

HSTP also applies to SIRAP and BROE, which cancels the allocation of overrun budgets in (6) and (9), i.e. \( O_{si}(t) = X_s \). When the budget is insufficient to complete a critical section, both protocols postpone the execution of the critical section until sufficient budget \( Q_{s}^{\text{com}}(t) \geq X_{si} \) is guaranteed. This self-blocking condition also applies for donations to third-parties, i.e. we can only donate budget to others when there is sufficient budget to donate. This gives the misbehaving component \( C_s \) the opportunity to resolve its own malicious behaviour until component \( C_u \) has sufficient resources and gets selected for execution.

Consider a misbehaving component \( C_s \) that accesses resource \( R_l \). When component \( C_s \) needs more processor time to complete its critical section than specified by \( X_{si} \), we can repetitively self-donate any remaining budget \( Q_{s}^{\text{com}}(t) > 0 \) to resource-access budget \( q_{ul} \). It is unnecessary to check for sufficient budget before a self-donation. To prevent budget overruns, however, we constrain a self-donation by only providing \( Q_{s}^{\text{com}}(t) \leq X_{si} \), i.e. \( q_{ul} \leftarrow \min(Q_{s}^{\text{com}}(t), X_{si}) \).

Assume that a resource-sharing component \( C_u \) attempts to lock the busy resource \( R_l \) at time \( t_b \). Before donating a budget \( X_{ul} \) to component \( C_s \), a self-blocking mechanism applies
either SIRAP or BROE). The first time instant \( t_i \) at which component \( C_u \) resumes its execution after budget \( Q_u \) has been replenished, is the actual time that a task tries to lock resource \( R_t \). Within time interval \([t_b, t_f]\) the resource may get released. If resource \( R_t \) is busy at time \( t_l \), then, similar to self-donations, component \( C_u \) can repetitively donate budget without further self-blocking to accelerate the resource release.

When a component \( C_u \) starts donating its budget, however, its tasks will miss deadlines, unless it donates slack time.

### 5.4.1. An example

Consider a component \( C_1 \) serviced by BROE [5], see Figure 4, which self-blocks on its budget \( Q_1 \) upon an attempt to lock a busy resource \( R_t \) at time \( t_b \). Within component \( C_1 \) virtual time advances with a rate \( \frac{d_l}{d_b} \).

When the absolute time of the current budget \( Q_1^{\text{rem}}(t_b) \) reaches the virtual time, i.e. component \( C_1 \) was running ahead of absolute time, a replenished budget becomes available at time \( t_a = t_d + \frac{P_1}{Q_1} Q_1^{\text{rem}}(t_b) \) with a deadline \( t_{d_{+1}} = t_a + P_1 \). A replenishment can happen even without self-blocking if the component was lagging behind. After we would have donated \( Q_1^{\text{rem}}(t_b) \), a replenishment happens at \( t_{d_k} \), but with a larger absolute deadline \( t_{d_{k+1}} = t_{d_k} + P_1 \) where \( t_{d_k} < t_{d_{k+1}} \leq t_{d_{k+1}} \).

By retraining a donation at time \( t_b \), potential deadline misses of tasks in \( T_1 \) can be prevented. If the busy resource \( R_t \) is released before component \( C_1 \) continues its execution, it is unnecessary for component \( C_1 \) to donate budget.

![Diagram](image)

**Fig. 4.** Donating \( Q_1^{\text{rem}}(t_b) \) (in grey) instead of self-blocking (in black) can cause unnecessary deadline misses.

### 5.4.2. Gain-time provisioning

Contrary to BROE, SIRAP needs to account for an additional self-blocking term in its local demand bound function of DM-scheduled tasks [4], i.e.\(^3\)

\[
I_{s}(i,t) = b_{si} + \sum_{R_i \in R_s} (c_{si} + \sum_{1 \leq j < l \leq 1} \left\lfloor \frac{t - T_{sj}}{T_{sj}} \right\rfloor c_{sj})), \quad (10)
\]

where the blocking term, \( b_{si} \), for tasks is defined as in [6]. We can similarly adapt (6) for local EDF-scheduling of tasks that share resources arbitrated by SIRAP. Since we disable local preemptions during global resource access, the allocated processor time to a component for self-blocking is unused. We can make this unused processor time available as \textit{gain time} by also donating \( Q_{\text{rem}}(t_b) < X_{si} \), i.e. independent of the self-blocking condition.

### 5.5. Locally non-preemptive critical sections

Local preemptions during global resource access can decrease the required budget to make a task set \( T_s \) schedulable, but this may on its turn adverse the global schedulability of components due to increased resource holding times. In this paper we are not interested in this schedulability trade-off [20], [21], however, but merely in the containment of temporal faults in critical sections. For this purpose we can introduce an intermediate reservation level assigned and allocated to critical sections in order to enforce that blocking times to other components are not exceeded due to locally preempts tasks [8]. Since this approach causes performance penalties [11], HSTP disallows local preemptions during global resource access. In this section we propose an efficient algorithm to check whether off-the-shelf components can be integrated in our dependable resource-sharing framework, which enables a fast design-space exploration during system composition.

We consider a component \( C_s \) with a given interface description \( <P_s, Q_s, X_s> \), where resource ceilings are locally and globally configured according to SRP, i.e. see (2) and (3). We want to check whether executing the global critical sections of component \( C_s \) with local preemptions disabled hampers the schedulability of a task set \( T_s \) for the given periodic resource model \( \Gamma_s(P_s, Q_s) \) of component \( C_s \). In many practical cases local preemptions can be disabled temporary, because the budget \( Q_s \) assigned to a component is typically pessimistic due to abstraction overheads in its calculation [1]. Each task \( \tau_{si} \in T_s \) may therefore finish its execution before its deadline, so that small finalization delays do not cause a deadline miss.

### 5.5.1. Delay tolerance

From our assumption \( 2 P_s \leq T_{si}(\forall \tau_{si} \in T_s) \) we can deduce the following lemma:

Lemma 3: Given \( 2 P_s \leq T_{si}(\forall \tau_{si} \in T_s) \), all tasks \( \tau_{si} \) that are allowed to preempt, can preempt at most once during an access to a global shared resource \( R_t \) by task \( \tau_{si} \).

Proof: The proof for SIRAP and overrun is presented in [26]. The proof for BROE is presented in [27].

Using Lemma 3 we can efficiently calculate how long local preemptions can be disabled without affecting the local schedulability of tasks.

We define the \textit{laxity} \( \delta_{si} \) of a task \( \tau_{si} \), such that \( \tau_{si} \) finishes its execution at least \( \delta_{si} \) time units prior to its deadline \( D_{si} \) if it has the entire processor at its disposal. For each resource \( R_t \in R_s \) with a local ceiling \( \kappa_{si} \), we compute the least laxity of all tasks with a preemption level higher than \( \kappa_{si} \). The largest common \textit{delay tolerance} of these preemptions tasks is:

\[
\Delta'_{si} = \left( \min_{i : \pi_{si} > \kappa_{si} : \delta_{si} = D_{si} - \sum_{1 \leq j \leq i} E_{sj}} \right). \quad (11)
\]

Note that each task \( \tau_{sj} \) can only preempt once and all tasks are ordered according to their preemption level, i.e. the lowest index gives the highest preemption level.

The laxity of each task must at least exceed a single blackout duration of its component, i.e. \( \delta_{si} \geq BD_{si}(\forall \tau_{si} \in T_s) \), in order to be schedulable with a periodic processor supply

---

3. For the ease of presentation, Equation 10 assumes that each instant of a task (i.e. a job) accesses a shared resource at most one time.
of $\Gamma_s(P_s, Q_s)$. An additional blackout is impossible in the processor supply of preemtting tasks, because a critical section of length $X_{si}$ is guaranteed to fit within a single budget provisioning by virtue of the protocols in [3], [4], [5]. Tasks may nevertheless have more delay tolerance than required to bridge the blackout duration. We now need to subtract $BD_s$ from the calculated delay tolerance, i.e.

$$\Delta_{si} \leftarrow \Delta_{si}' - BD_s, \quad (12)$$

so that the result is $\Delta_{si} \geq 0$. This final value $\Delta_{si}$ defines the longest time that a task $\tau_{si} \in T_s$ that may preempt during resource access to $R_t$ can be deferred without missing any deadline. By construction the following theorem follows:

**Theorem 2:** Given that a component $C_s$ accessing resource $R_t \in R_s$ with resource ceiling $rc_{sd}$ is schedulable on a component with parameters $(P_s, Q_s, X_s)$ using the periodic resource model $\Gamma_s(P_s, Q_s)$; if $c_{si} \leq \Delta_{si}$, then component $C_s$ can be scheduled on the same component using $\Gamma_s(P_s, Q_s)$ and can execute each critical section of $\tau_{si}$ to $R_t$ with local preemptions disabled, where $\Delta_{si}$ is defined in (12).

**Proof:** Given Lemma 3, all tasks that may preempt a critical section with resource ceiling $rc_{sd}$ finish within a budget of $Q_s + X_s$ and preempt only once. After increasing the resource ceiling, the total required budget to meet the resource demands of $c_{si}$ and the execution times of these tasks that now suffer blocking does not increase. We are given two facts: (i) each task instance may experience only one blocking occurrence under SRP-based resource arbitration [6] and (ii) using the original resource ceiling, each preempting tasks completes its execution at least $\Delta_{si}$ time units prior to its deadline on periodic resource $\Gamma_s(P_s, Q_s)$. Hence, a blocking duration of $c_{si} \leq \Delta_{si}$ cannot cause a deadline miss. $\square$

5.5.2. An algorithm. Theorem 2 makes it possible to exactly determine whether or not all critical sections within a component $C_s$ can be executed with local preemptions disabled by (i) calculating $\Delta_{si}$ using (11) and (12) for each $R_t \in R_s$ and subsequently (ii) apply Theorem 2 on each task to verify $c_{si} \leq \Delta_{si}$. This algorithm has a time complexity of $O(M_s \times n_s)$ for a single component $C_s$ with $M_s$ global shared resources. Note that it only needs to inspect the laxity for interfering tasks, which makes our algorithm much more efficient than the algorithms in [20], [21].

5.5.3. A special case. BROE has a sufficient test, i.e. $\Delta_{si} = \frac{1}{2}BD_s = P_s - Q_s$, for disabling local preemptions of EDF-scheduled task sets [5]. Our algorithm determines exactly which critical sections can execute without local preemptions and it applies to any periodic resource model, independent of the local scheduler, with SRP-based resource arbitration.

6. Evaluation

We have recently extended a commercial real-time microkernel, $\mu$C/OS-II [28], with an HSF and synchronization support by means of SIRAP, HSRP and BROE [16]. In this section we investigate the complexity and overheads of the synchronization primitives of HSTP within our framework.

Because we need to set a budget-expiration timer to track the component’s resource-access budget in every lock operation and we need to cancel the same timer in every unlock operation, HSTP primitives are more expensive than a straightforward two-level SRP implementation. If this budget-depletion timer expires during global resource access, i.e. it is not canceled before expiration, then it executes a handler which implements HSTP’s unlock policy and marks the resource busy. Based on our measurements, the timer manipulations triple the execution times of the lock and unlock operations compared to the implementations of these primitives in [16]. However, this is the price for preventing the propagation of temporal faults to resource-independent components.

The self-donation mechanism can be easily implemented by extending the global scheduler. Upon a context switch the global scheduler must check whether or not the selected component keeps a resource busy and at the same time has a depleted resource-access budget. This if-statement only takes a few instructions in a reservation-based framework and is therefore relatively cheap compared to the cost of context switching itself. Only when a task within the selected component misbehaves by exceeding its critical-section length, the scheduler executes the expensive operations corresponding to locking a resource, i.e. reset a budget-expiration timer for the selected component, update its normal budget and raise the system ceiling.

Third-party donations can be implemented similarly, but in the lock operation rather than in the global scheduler. If a task attempts to lock a busy resource, the lock operation disables all local preemptions, donates budget by setting a new budget-timer for the donatee and raises the system ceiling. As a result the donor component itself is blocked from continuing its execution. These actions are repeated every time the donor task gets selected by the local scheduler to continue its execution, until the requested resource becomes free.

Since Lemma 1 tells that we only need to keep track of at most a single donor at each time instant, each component maintains a single variable to track its current donor. Upon donation, the donor writes its component identifier into this variable. When it contains a valid identifier when a busy resource is unlocked, a donation back to the donor is executed. The variable is cleared when either the resource is freed or the donated budget is depleted.

7. Conclusion

This paper presented HSTP, an SRP-based synchronization protocol, which provides temporal protection between components in which multiple tasks share a budget, even when interacting components exceed their specified critical-section lengths. Prerequisites to dependable resource sharing in HSFs are mechanisms to enforce and monitor critical-section lengths. We followed the choice in [3] to make critical sections non-preemptive for tasks within the same component, because
this makes containment of temporal faults within critical sections efficient. Moreover, sufficiently short critical sections can execute with local preemptions disabled and preserve system schedulability. A reservation-based mechanism to monitor and enforce blocking times is unnecessary, see [8], because HSTP complies to existing SRP-based global analysis for HSFs.

We proposed an SRP-compliant budget donation mechanism. Our repetitive self-donation mechanism, complemented with donations from other components, limits preemptions during global resource access as long as possible and preserves the schedulability of independent components. Moreover, it enhances the reliability of resource-sharing components when one of the components misbehaves by accelerating the resource release. HSTP expands across existing protocols in the context of HSFs [3], [4], [5] and integrating its primitives into a reservation-based kernel is straightforward. Our protocol therefore promises a dependable solution to resource sharing in future safety-critical industrial applications for which temporal and functional correctness is essential.

References