Revised budget allocations for fixed-priority-scheduled periodic resources

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Revised budget allocations for fixed-priority-scheduled periodic resources

Martijn M. H. P. van den Heuvel · Pieter J. L. Cuijpers · Johan J. Lukkien · Nathan Fisher

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1 Introduction

Hierarchical scheduling frameworks (HSFs) facilitate a decoupling of development of individual components from their integration on a shared uniprocessor platform. The periodic resource models of Shin and Lee (2008) and Easwaran et al (2007), characterizing periodic resource allocations to components, are complemented with novel methods to abstract timing requirements in the hierarchy of schedulers. HSFs provide temporal isolation between components by allocating a guaranteed resource share, i.e. a budget, to each component.

Dewan and Fisher (2010a) claim a unique, fully polynomial approximation scheme (FPTAS) to calculate a budget for a given task set and resource period. The special case where the approximation parameter $k = \infty$ should yield an exact budget, which is computed more efficiently than the exhaustive search proposed by Shin and Lee (2008). We show that Dewan and Fisher (2010a) may yield optimistic budgets and we propose a correction for their algorithm.

2 System Model

We use the explicit-deadline periodic resource (EDP) model of Easwaran et al (2007) to specify guaranteed processor allocations to components. The timing interface of a component $C$ is specified by a triple $(\Pi, \Theta, \Delta)$, where $\Pi \in \mathbb{Z}^+$ denotes its period, $\Theta \in \mathbb{R}^+$ its budget and $\Delta \in \mathbb{R}^+$ is the relative deadline.
of the EDP resource with $\Theta \leq \Delta \leq \Pi$. The periodic resource model $\Gamma$, proposed by Shin and Lee (2008), is a specialization of the EDP resource $\Omega$ with characteristics $\Gamma(\Pi, \Theta) = \Omega(\Pi, \Theta, \Pi)$.

A component $C$ contains a set $T$ of $n$ sporadic tasks $\tau_1, \ldots, \tau_n$. Each task $\tau_i \in T$ is characterized by a triple $(T_i, E_i, D_i)$, where $T_i \in \mathbb{R}^+$ denotes its minimum inter-arrival time, $E_i \in \mathbb{R}^+$ its worst-case computation time, and $D_i \in \mathbb{R}^+$ its relative deadline, where $0 < E_i \leq D_i \leq T_i$. We assume that tasks are given in priority order, i.e. $\tau_1$ has the highest priority and $\tau_n$ the lowest.

The sufficient schedulability condition presented by Dewan and Fisher (2010a) deems a task set $T$ schedulable on an EDP resource $\Omega$, if

$$\forall 1 \leq i \leq n \exists t \in \hat{S}_i(k) : \hat{rbf}(i, t, k) \leq \text{sbf}_{\Omega}(t),$$

(1)

where the supply bound function $\text{sbf}_{\Omega}(t)$ computes the minimum processor supply for any interval of length $t$, i.e.

$$\text{sbf}_{\Omega}(t) = \max \left\{ 0, \left( h(\Omega, t) - 1 \right) \Theta, t - (h(\Omega, t) + 1)(\Pi - \Theta) + (\Pi - \Delta) \right\} ,$$

(2)

with $h(\Omega, t) = \left\lceil \frac{t - (\Delta - \Theta)}{\Pi} \right\rceil$ and the cumulative requested processor time by task $\tau_i$ using approximation parameter $k$ is:

$$\hat{rbf}(i, t, k) \overset{\text{def}}{=} E_i + \sum_{1 \leq j < i} \delta(j, t, k)$$

and $\delta(j, t, k)$ is defined as

$$\delta(j, t, k) \overset{\text{def}}{=} \begin{cases} E_j & \text{if } t \leq (k - 1)T_j \\ E_j + t \cdot E_j & \text{otherwise} \end{cases}$$

(3)

and the ordered set of testing points is defined as

$$\hat{S}_i(k) \overset{\text{def}}{=} \{ t = b \cdot T_a \mid a = 1, \ldots, i - 1; \ b = 1, \ldots, k; \ t \in (0, D_i] \} \cup \{0, D_i\} .$$

(4)

For the special case where $k = \infty$, the schedulability condition in (1) specializes to the exact schedulability condition of Easwaran et al (2007).

**Problem statement:** Given a task set $T$, a period $\Pi$, a deadline $\Delta$ and parameter $k$, we want to determine the minimum budget $\Theta_{\text{min}}$ satisfying Equation (1).

### 3 Revisiting existing budget-allocation algorithms

We present a counter example, considering the optimism in the algorithm by Dewan and Fisher (2010a) for fixed-priority-scheduled components. For EDF-scheduled components, Fisher and Dewan (2009) presented a fundamentally different FPTAS compared to the FPTAS for fixed-priority scheduling reconsidered in this paper.

**Counter example:** Consider a fixed-priority-scheduled component $C_1$ with a period $\Pi_1 = \Delta_1 = 67$ and with two tasks $\tau_1 = (169, 1.5, 169)$ and $\tau_2 = (177, 34, 177)$. For this example, Dewan and Fisher (2010a) yield an optimistic budget of 18.5 time units. The required budget for component $C_1$ is,
however, 20.33 time units. Task $\tau_2$ therefore violates (1), because $\forall t \in \hat{S}_2(\infty) : rbf(2, t, \infty) > sbf_{[67, 18.5, 67]}(t)$.

Since the algorithm by Dewan and Fisher (2010a) fails the exact schedulability test (for $k = \infty$) in (1), their budget allocations are optimistic. Fortunately, the source of optimism by Dewan and Fisher (2010a) can be found in their proofs (see the internal report by Dewan and Fisher (2010b)).

Lemma 12 of Dewan and Fisher (2010b) presents a budget candidate, $\Theta_{\min}$, for each consecutive pair of values $t_a$ and $t_{a+1}$ in the testing set $\hat{S}_i(k)$ of task $\tau_i$. The definition of $\Theta_{\min}$ is only valid for a specific domain of $l_1$ and $l_2$ values, i.e. $[1, [l_2] - 1], [l_2]; [l_2], [l_1]$, and $[[l_1] + 1, \infty]$, and the values of $l_1$ and $l_2$ each reconstruct an $h_{(a,t)}$. Lemma 11 and the corollaries 1, 2 and 3 subsequently capture these three regions. Corollary 4 only calculates $\Theta_{\min}$ at the boundaries of the regions defined by $l_1$ and $l_2$. However, Dewan and Fisher (2010b) have forgotten the remaining case in Corollary 4, i.e. $[l_2] > [l_1]$. This also leaves Lemma 12 incomplete.

Reconsidering the example: task $\tau_2$ has a testing set of $\{0, 169, 177\}$ according to (4). This task requires two iterations: one considering interval $[0, 169]$ and one considering interval $[169, 177]$. For interval $[169, 177]$, the algorithm picks the smallest candidate from the following values: $\{20.33; 37; 37; 18.5\}$ which results in 18.5 time units. This value is finally promoted as the optimal budget for component $C_1$. Since in this iteration $[l_2] > [l_1]$, the last two budget candidates in the budget-candidate set correspond to an undefined interval. Both values should therefore be discarded, so that 20.33 is returned which coincides with the optimal solution found by an exhaustive search.

4 A revised FPTAS for budget allocations

Algorithm 1 presents a revised FPTAS to calculate budgets for fixed-priority-scheduled tasks on an EDP resource. The final proof of correctness of this algorithm depends on the correctness of $\Theta_{\min}$ as defined by Dewan and Fisher (2010a) in Lemma 4 and Lemma 5. By including the missing case in the corollaries and lemmas and straightforwardly extending the proofs, we obtain an if-statement at the lines 11-17. As a result, $\Theta_{[l_1]}$ and $\Theta_{[l_2]}$ are only conditionally computed. Algorithm 1 (with $k = \infty$) can be used to obtain an exact budget for a given task set and resource period.
Algorithm 1 FPMinimumBudget($T$, $\Pi$, $\Delta$, $k$)

1: $\Theta^{\text{min}} \leftarrow \Pi \cdot \sum_{\tau_i \in T} \tau_i$
2: for all $\tau_i \in T$ do
3:   $\Theta^i \leftarrow \infty$
4: for all $t_a, t_{a+1} \in \tilde{S_i}(k)$ do
5:   $D_{t_a} \leftarrow \hat{rbf}(i, t_a, k) + \sum_{j < i \land t_a \mod T_j = 0} E_j$
6:   $l_1 = \frac{(t_{a+1} - \Delta) + \sqrt{((t_{a+1} - \Delta)^2 + 4D_{t_{a+1}}\Pi)}}{2\Pi}$
7:   $l_2 = \frac{(t_a - \Delta) + \sqrt{((t_a - \Delta)^2 + 4D_{t_a}\Pi)}}{2\Pi}$
8: if $l_2 \leq l_1$ then
9:   $\Theta_{[1]}^i \leftarrow \frac{D_{t_a} + \alpha(\tau_i \land H - \Delta - t_a)}{l_1^{[1]} + \alpha}$
10: end if
11: else
12:       $\Theta_{[2]}^i \leftarrow \frac{D_{t_a} + \alpha(\tau_i \land H - \Delta - t_a)}{l_2^{[2]} + \alpha}$
13: end for
14: end for
15: \textbf{return} $\Theta^{\text{min}}$

References

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Compositional Service Trees

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Analytical Software Design: Introduction and Industrial Experience Report

10/02 F.E.J. Kruseman Aretz
Design and correctness proof of an emulation of the floating-point operations of the Electrologica X8. A case study
<table>
<thead>
<tr>
<th>Date</th>
<th>Authors</th>
<th>Title</th>
</tr>
</thead>
<tbody>
<tr>
<td>10/03</td>
<td>Luca Aceto, Matteo Cimini, Anna Ingolfsdottir, MohammadReza Mousavi and Michel A. Reniers</td>
<td>On Rule Formats for Zero and Unit Elements</td>
</tr>
<tr>
<td>10/04</td>
<td>Hamid Reza Asaadi, Rantin Khosravi, MohammadReza Mousavi, Neda Noroozi</td>
<td>Towards Model-Based Testing of Electronic Funds Transfer Systems</td>
</tr>
<tr>
<td>10/05</td>
<td>Reinder J. Bril, Uğur Keskin, Moris Behnam, Thomas Nolte</td>
<td>Schedulability analysis of synchronization protocols based on overrun without payback for hierarchical scheduling frameworks revisited</td>
</tr>
<tr>
<td>10/06</td>
<td>Zvezdan Protić</td>
<td>Locally unique labeling of model elements for state-based model differences</td>
</tr>
<tr>
<td>10/07</td>
<td>C.G.U. Okwudire and R.J. Bril</td>
<td>Converting existing analysis to the EDP resource model</td>
</tr>
<tr>
<td>10/08</td>
<td>Muhammed Atif, Sjoerd Cranan, MohammadReza Mousavi</td>
<td>Reconstruction and verification of group membership protocols</td>
</tr>
<tr>
<td>10/09</td>
<td>Sjoerd Cranan, Jan Friso Groote, Michel Reniers</td>
<td>A linear translation from LTL to the first-order modal µ-calculus</td>
</tr>
<tr>
<td>10/10</td>
<td>Mike Holenderski, Wim Cools, Reinder J. Bril, Johan J. Lukkien</td>
<td>Extending an Open-source Real-time Operating System with Hierarchical Scheduling</td>
</tr>
<tr>
<td>10/11</td>
<td>Eric van Wyk and Steffen Zschaler</td>
<td>1st Doctoral Symposium of the International Conference on Software Language Engineering (SLE)</td>
</tr>
<tr>
<td>10/12</td>
<td>Pre-Proceedings</td>
<td>3rd International Software Language Engineering Conference</td>
</tr>
<tr>
<td>10/13</td>
<td>Faisal Kamiran, Toon Calders and Mykola Pechenizki</td>
<td>Discrimination Aware Decision Tree Learning</td>
</tr>
<tr>
<td>10/14</td>
<td>J.F. Groote, T.W.D.M. Kouters and A.A.H. Osaierwanna</td>
<td>Specification Guidelines to avoid the State Space Explosion Problem</td>
</tr>
<tr>
<td>10/15</td>
<td>Daniel Trivellato, Nicola Zannone and Sandro Etalle</td>
<td>GEM: a Distributed Goal Evaluation Algorithm for Trust Management</td>
</tr>
<tr>
<td>10/17</td>
<td>L. Aceto, A. Birgisson, A. Ingolfsdottir, and M.R. Mousavi</td>
<td>Decompositional Reasoning about the History of Parallel Processes</td>
</tr>
<tr>
<td>10/18</td>
<td>P.D. Mosses, M.R. Mousavi and M.A. Reniers</td>
<td>Robustness os Behavioral Equivalence on Open Terms</td>
</tr>
<tr>
<td>10/19</td>
<td>Harsh Beohar and Pieter Cuijpers</td>
<td>Desynchronisability of (partial) closed loop systems</td>
</tr>
<tr>
<td>11/01</td>
<td>Kees M. van Hee, Natalia Sidorova and Jan Martijn van der Werf</td>
<td>Refinement of Synchronizable Places with Multi-workflow Nets - Weak termination preserved!</td>
</tr>
<tr>
<td>11/02</td>
<td>M.F. van Amstel, M.G.J. van den Brand and L.J.P. Engelen</td>
<td>Using a DSL and Fine-grained Model Transformations to Explore the boundaries of Model Verification</td>
</tr>
<tr>
<td>11/05</td>
<td>Jan Friso Groote and Jan Lanik</td>
<td>Semantics, bisimulation and congruence results for a general stochastic process operator</td>
</tr>
<tr>
<td>11/06</td>
<td>P.J.L. Cuijpers</td>
<td>Moore-Smith theory for Uniform Spaces through Asymptotic Equivalence</td>
</tr>
<tr>
<td>11/07</td>
<td>F.P.M. Stappers, M.A. Reniers and S. Weber</td>
<td>Transforming SOS Specifications to Linear Processes</td>
</tr>
<tr>
<td>11/08</td>
<td>Debyjoti Bera, Kees M. van Hee, Michiel van Oseh and Jan Martijn van der Werf</td>
<td>A Component Framework where Port Compatibility Implies Weak Termination</td>
</tr>
<tr>
<td>11/09</td>
<td>Tsesuren Batsauri, Reinder J. Bril and Johan Lukkien</td>
<td>Model, analysis, and improvements for inter-vehicle communication using one-hop periodic broadcasting based on the 802.11p protocol</td>
</tr>
<tr>
<td>Page</td>
<td>Authors</td>
<td>Title</td>
</tr>
<tr>
<td>------</td>
<td>---------</td>
<td>-------</td>
</tr>
<tr>
<td>11/10</td>
<td>Neda Noroozi, Ramtin Khosravi, Mohammad Reza Mousavi and Tim A.C. Willemse</td>
<td>Synchronizing Asynchronous Conformance Testing</td>
</tr>
<tr>
<td>11/11</td>
<td>Jeroen J.A. Keiren and Michel A. Reniers</td>
<td>Type checking mCRL2</td>
</tr>
<tr>
<td>11/12</td>
<td>Muhammad Atif, Mohammad Reza Mousavi and Ammar Osaiweran</td>
<td>Formal Verification of Unreliable Failure Detectors in Partially Synchronous Systems</td>
</tr>
<tr>
<td>11/13</td>
<td>J.F. Groote, A.A.H. Osaiweran and J.H. Wesselius</td>
<td>Experience report on developing the Front-end Client unit under the control of formal methods</td>
</tr>
<tr>
<td>11/15</td>
<td>John Businge, Alexander Serebrenik and Mark van den Brand</td>
<td>Eclipse API Usage: The Good and The Bad</td>
</tr>
<tr>
<td>11/17</td>
<td>M.F. van Amstel, A. Serebrenik and M.G.J. van den Brand</td>
<td>Visualizing Traceability in Model Transformation Compositions</td>
</tr>
<tr>
<td>11/18</td>
<td>F.P.M. Stappers, M.A. Reniers, J.F. Groote and S. Weber</td>
<td>Dogfooding the Structural Operational Semantics of mCRL2</td>
</tr>
<tr>
<td>12/01</td>
<td>S. Cranen</td>
<td>Model checking the FlexRay startup phase</td>
</tr>
<tr>
<td>12/02</td>
<td>U. Khadim and P.J.L. Cuijpers</td>
<td>Appendix C / G of the paper: Repairing Time-Determinism in the Process Algebra for Hybrid Systems ACP</td>
</tr>
<tr>
<td>12/03</td>
<td>M.M.H.P. van den Heuvel, P.J.L. Cuijpers, J.J. Lukkien and N.W. Fisher</td>
<td>Revised budget allocations for fixed-priority-scheduled periodic resources</td>
</tr>
<tr>
<td>12/04</td>
<td>Ammar Osaiweran, Tom Fransen, Jan Friso Groote and Bart van Rijnsoever</td>
<td>Experience Report on Designing and Developing Control Components using Formal Methods</td>
</tr>
<tr>
<td>12/05</td>
<td>Sjoerd Cranen, Jeroen J.A. Keiren and Tim A.C. Willemse</td>
<td>A cure for stuttering parity games</td>
</tr>
<tr>
<td>12/06</td>
<td>A.P. van der Meer</td>
<td>CIF MSOS type system</td>
</tr>
</tbody>
</table>