



The RTOS Chameleon for Linux

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2007-01-24

Hard Real-Time for Linux – But How?

- Which RT-Linux technology?
 - Co-scheduling?
 - ...or native real-time Linux?
- Which kernel
 - Always latest 2.6?
 - Or also older revisions?
 - ...or even keep 2.4?
- How to port from \$RTOS to Linux?
 - Migrate to POSIX API?
 - ...or emulate the legacy API?
- How to create and maintain RT-optimised drivers?

Presentation Outline



- Xenomai Approach
 - Provided APIs
 - Real-Time Driver Model
 - Architectures
 - New RT-Technologies
- Related Open Source Projects
- Application Example
- Summary & Prospects

The Xenomai Approach

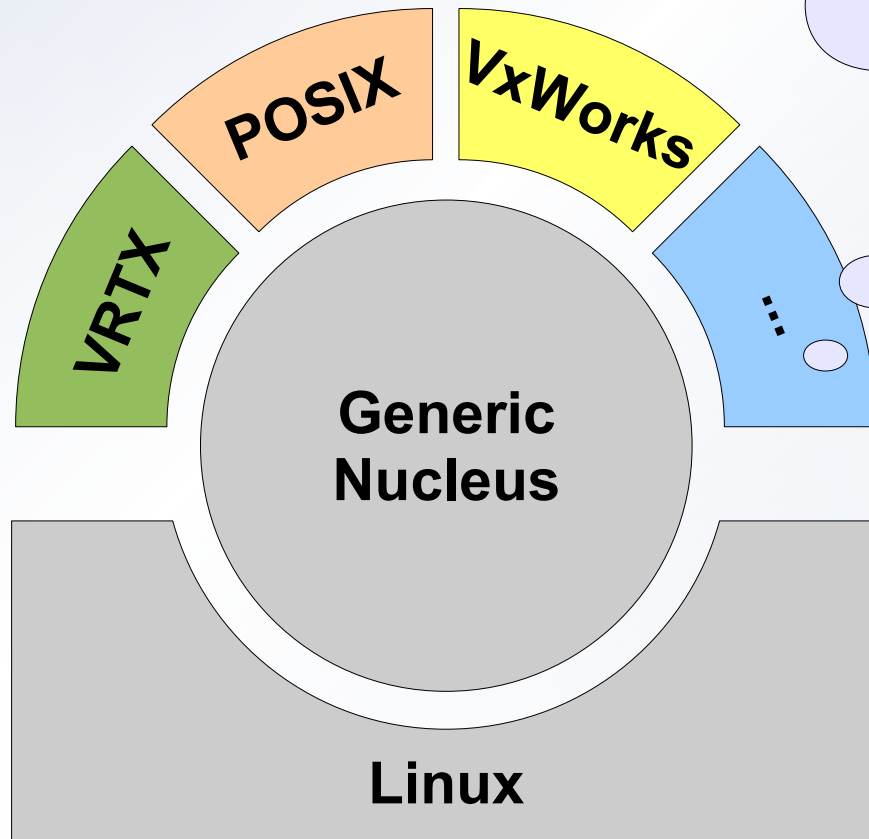
- Generic RT-core (“nucleus”)
 - RTOS APIs provided via “skins”
 - Includes hard-RT Linux technology (“I-pipe”)
 - Kernel-independent
 - Light-weight
 - **But:** Highly integrated in Linux environment
 - Portability framework for older kernels (2.4 and 2.6)
 - Generic RT-driver model across all skins
- ➔ Our goal:

Real-Time APIs for any Linux

(OK, almost any)

What Skin Do You Prefer?

- POSIX
- Native (clean RTAI-like API)
- VxWorks
- VRTX
- pSOS+
- μ ITRON
- RTAI
- RTDM

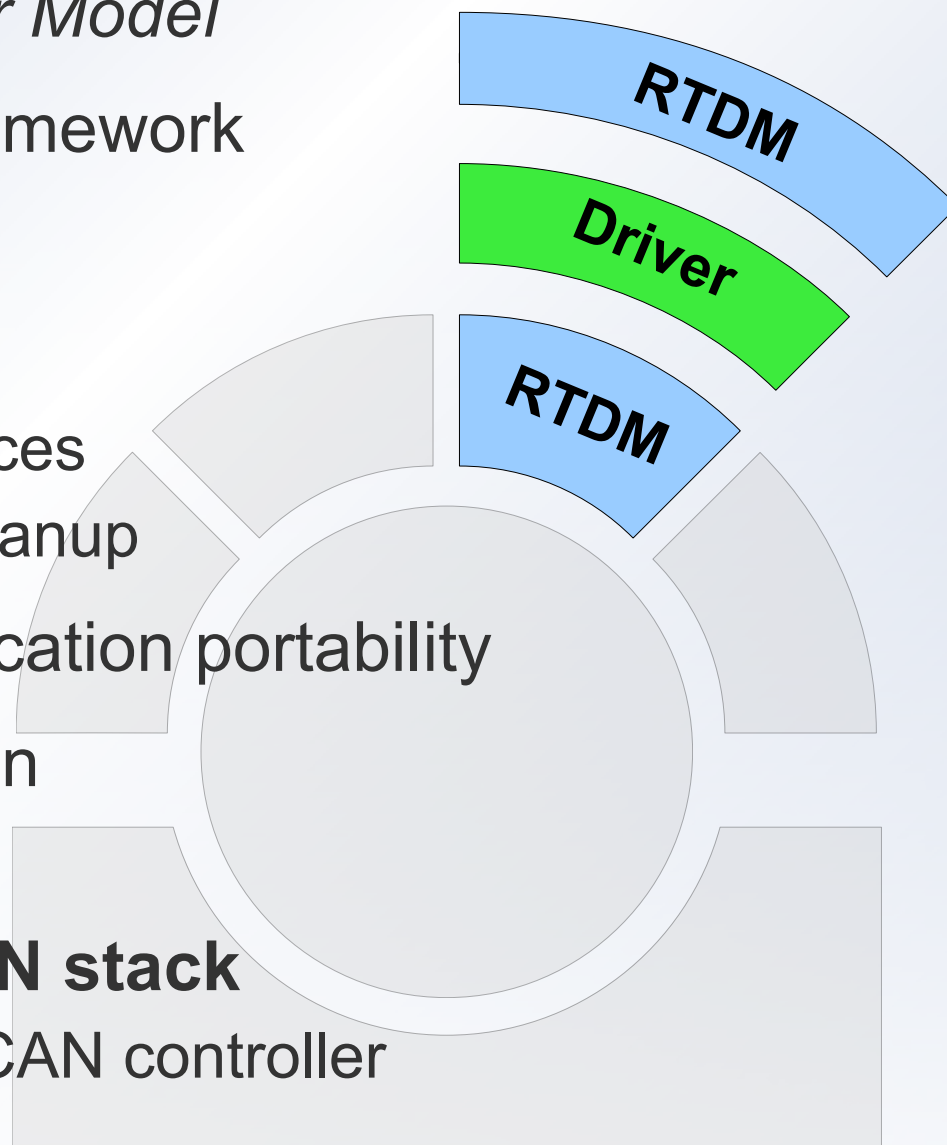


Avionics
ARINC 653?
Automotive
OSEK?
AUTOSAR?

Drive Hardware in Real-Time

RTDM – The Real-Time Driver Model

- Lean driver development framework
- POSIX I/O Model
- "Set-top box" for Linux
 - RTDM: time-critical services
 - Linux: non-RT setup/cleanup
- Device profiles ensure application portability
- Xenomai-independent design
 - ➔ RTAI integrates RTDM too
- Example: Integrated **RT-CAN stack**
 - ➔ Socket-based API for any CAN controller



Permanent Work in Progress

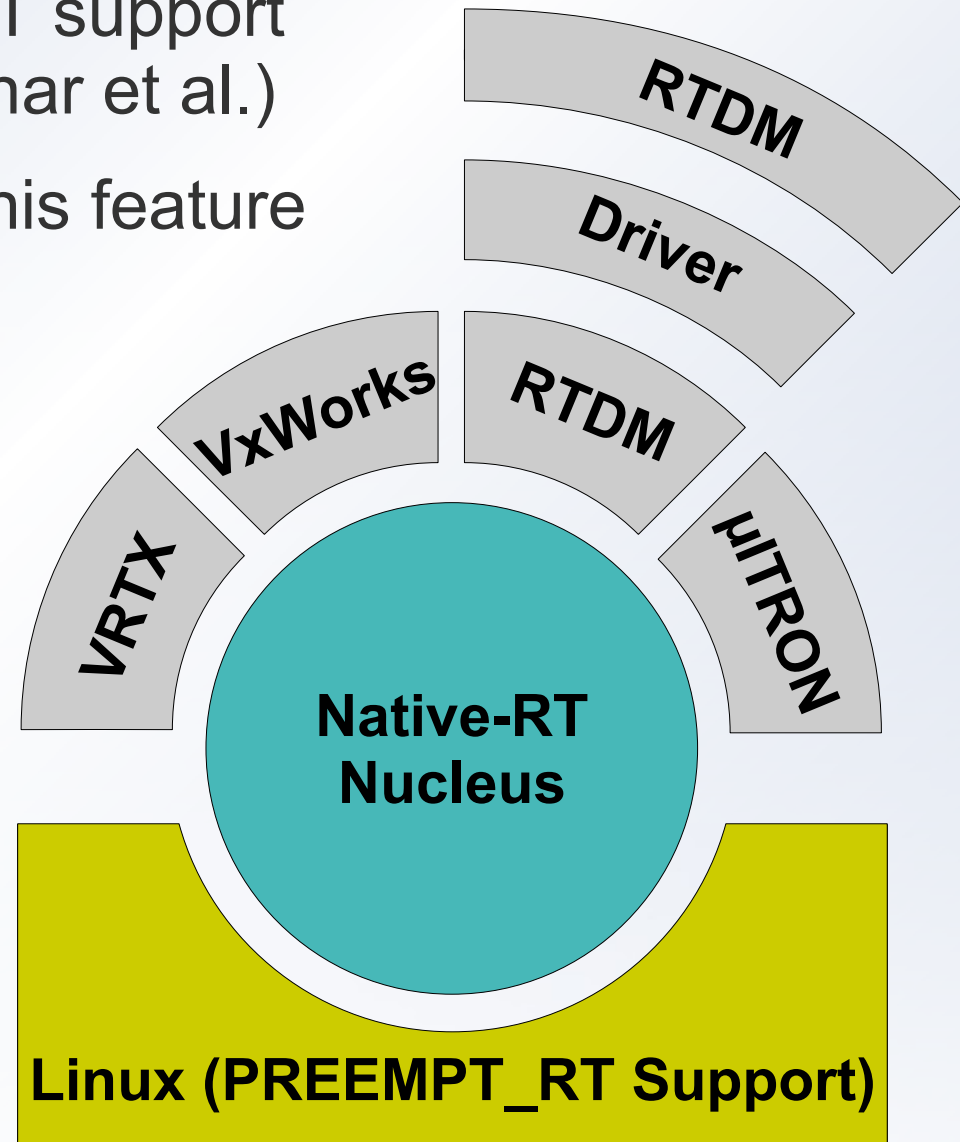
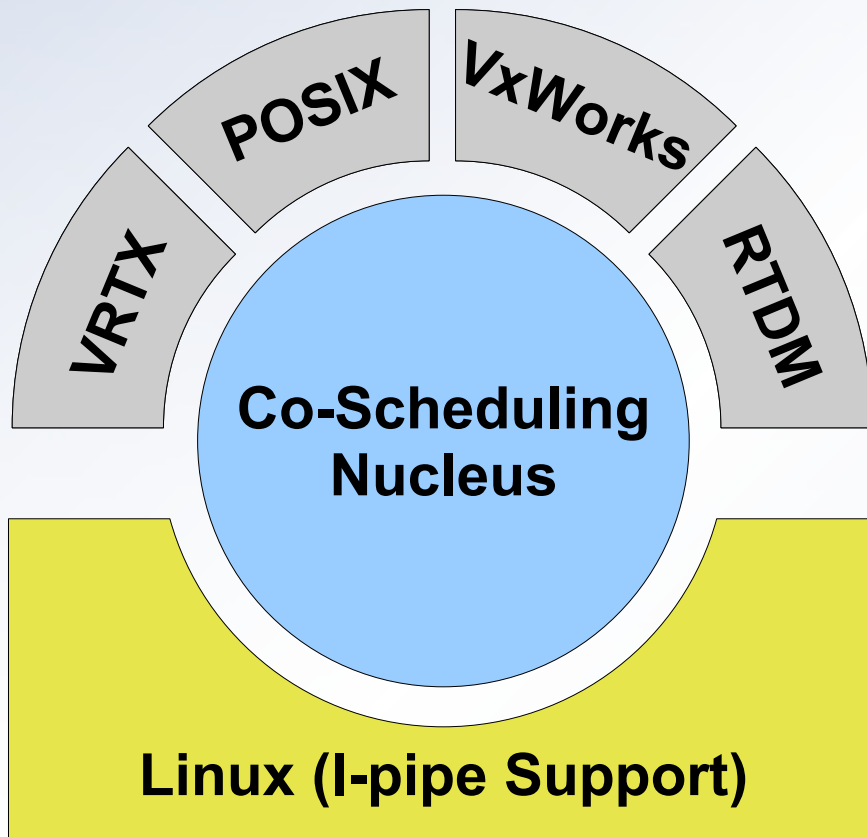


- Supported architectures

Kernel	2.4	2.6
Architecture		
i386	✓	✓
PPC32	✓	✓
PPC64		✓
ARM		✓
IA64		✓
Blackfin		✓
Simulator	<i>User-Space Application</i>	
x86-64		<i>WIP</i>

Select Your RT-Technology

- Linux incrementally gains RT support (“PREEMPT_RT”, Ingo Molnar et al.)
- Xenomai is going to adopt this feature




Xenomai Featuring...



- RTnet  (RT-networking stack)
- RT-FireWire  (RT-IEEE1394 stack)
- USB4RT, USB20RT  (RT-USB stacks)
- COMEDI over RTDM  (DAC driver framework)

- OROCOS  (RT-middleware)
- RACK  (Robotics RT-middleware)
- CanFestival  (CANopen library)
- Xeno--  (C++ & Python wrapping library)

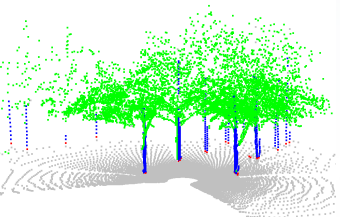
- LTTng  (System event tracing)
- kgdb  (Remote kernel debugger)

- ...

Application Example: Real-Time Robotics



- Modular autonomous service robots
- Research and industrial scenarios
- Real-time 3D ladar sensor
- Low-end x86 IPCs
- RACK, RT-CAN, RTnet, fast UARTs
- Integrates standard hardware/software with strict RT



Summery & Prospects



- Xenomai: RTOS construction kit for Linux
- Portability as major goal
 - Between architectures
 - Between RT-technologies
 - Between kernel versions
- Home for RT-drivers / stacks
- What is the future about?
 - ➔ PREEMPT_RT support, more RTOS skins & drivers, ...
 - ➔ **One stop for RT: kernel, drivers, libs, community**
- And when?
 - ➔ *Counter question: What do you need first?*
 - ➔ **Any contribution/support can accelerate development!**

Thank You!

www.xenomai.org

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