TinyOS – an operating system for sensor nets

- Embedded operating systems
  - How do they differ from desktop operating systems?
- Event-based programming model
  - How is concurrency handled?
  - How are resource conflicts managed?
- Programming in TinyOS
  - What new language constructs are useful?

Embedded Operating Systems

- Features of all operating systems
  - Abstraction of system resources
  - Managing of system resources
  - Concurrency model
  - Launch applications
- Desktop operating systems
  - General-purpose – all features may be needed
  - Large-scale resources – memory, disk, file systems
- Embedded operating systems
  - Application-specific – just use features you need, save memory
  - Small-scale resources – sensors, communication ports

System Resources on Motes

- Timers
- Sensors
- Serial port
- Radio communications
- Memory
- Power management

Abstraction of System Resources

- Create virtual components
  - E.g., multiple timers from one timer
- Allow them to be shared by multiple threads of execution
  - E.g., two applications that want to share radio communication
- Device drivers provide interface for resource
- Encapsulate frequently used functions
- Save device state (if any)
- Manage interrupt handling

Very simple device driver

- Turn LED on/off
  - Parameters:
    - port pin
  - API:
    - on(port_pin) - specifies the port pin (e.g., port D pin 3)
    - off(port_pin)
  - Interactions:
    - only if other devices want to use the same port

Simple device driver

- Turning an LED on and off at a fixed rate
  - Parameters:
    - port pin
    - rate at which to blink LED
  - API:
    - on(port_pin, rate)
      - specifies the port pin (e.g., port D pin 3)
      - specifies the rate to use in setting up the timer (what scale?)
    - off(port_pin)
  - Internal state and functions:
    - keep track of state (on or off for a particular pin) of each pin
    - interrupt service routine to handle timer interrupt
Interesting interactions

- What if other devices also need to use timer (e.g., PWM device)?
  - timer interrupts now need to be handled differently depending on which device’s alarm is going off
- Benefits of special-purpose output compare peripheral
  - output compare pins used exclusively for one device
  - output compare has a separate interrupt handling routine
- What if we don’t have output compare capability or run out of output compare units?

Sharing timers

- Create a new device driver for the timer unit
  - Allow other devices to ask for timer services
  - Manage timer independently so that it can service multiple requests
- Parameters:
  - Time to wait, address to call when timer reaches that value
  - API:
    - `set_timer(time_to_wait, call_back_address)`
      - Set call_back_address to correspond to time+time_to_wait
      - Compute next alarm to sound and set timer
      - Update in interrupt service routine for next alarm
- Internal state and functions:
  - How many alarms can the driver keep track of?
  - How are they organized? FIFO? priority queue?

Concurrency

- Multiple programs interleaved as if parallel
- Each program requests access to devices/services
  - e.g., timers, serial ports, etc.
- Exclusive or concurrent access to devices
  - allow only one program at a time to access a device (e.g., serial port)
  - arbitrate multiple accesses (e.g., timer)
- State and arbitration needed
  - keep track of state of devices and concurrent programs using resource
  - arbitrate their accesses (order, fairness, exclusivity)
  - monitors/locks (supported by primitive operations in ISA - test-and-set)
- Interrupts
  - disabling may affect timing of programs
  - keeping enabled may cause unwanted interactions

Handling concurrency

- Traditional operating system
  - multiple threads or processes
  - file system
  - virtual memory and paging
  - input/output (buffering between CPU, memory, and I/O devices)
  - interrupt handling (mostly with I/O devices)
  - resource allocation and arbitration
  - command interface (execution of programs)
- Embedded operating system
  - lightweight threads
  - input/output
  - interrupt handling
  - real-time guarantees

Embedded operating systems

- Lightweight threads
  - basic locks
  - fast context-switches
- Input/output
  - API for talking to devices
  - buffering
- Interrupt handling (with I/O devices and UI)
  - translate interrupts into events to be handled by user code
  - trigger new tasks to run (reactive)
- Real-time issues
  - guarantee task is called at a certain rate
  - guarantee an interrupt will be handled within a certain time
  - priority or deadline driven scheduling of tasks

Examples

- Palm OS
  - US Robotics Palm Pilot
  - Motorola microcontrollers (68328 – Dragonball, migrating to Xscale)
- simple OS for PDAs
  - only supports single threads
- Pocket PC
  - PDA operating system
  - spin-off of Windows NT
  - portable to a wide variety of processors (e.g., Xscale)
  - full-featured OS modularized to only include features as needed
- Wind River Systems VxWorks
  - one of the most popular embedded OS kernels
  - highly portable to an even wider variety of processors (tiny to huge)
  - modularized even further than the ones above (basic system under 50K)
TinyOS

- Open-source development environment
- Simple (and tiny) operating system – TinyOS
- Programming language and model – nesC
- Set of services

**Principal elements**
- Scheduler/event model of concurrency
- Software components for efficient modularity
- Software encapsulation for resources of sensor networks

TinyOS History – [www.tinyos.net](http://www.tinyos.net)

- Motivation – create Unix analog (circa 1969)
  - Uniform programming language: C
  - Uniform device abstractions
  - Open source: grow with different developers/needs
  - Support creation of many tools
- Created at UC Berkeley
  - 1st version written by Jason Hill in 2000
  - Large part of development moved to Intel Research Berkeley in 2001
    - [www.intel-research.net/berkeley](http://www.intel-research.net/berkeley)
- SmartDust, Inc. founded in 2002
- Large deployments
  - Great Duck Island (GDI)
    - [http://www.greatduckisland.net/](http://www.greatduckisland.net/)
  - Center for Embedded Network Sensing (CENS)
    - [http://www.cens.ucla.edu/](http://www.cens.ucla.edu/)

TinyOS Design Goals

- Support networked embedded systems
  - Asleep most of the time, but remain vigilant to stimuli
  - Bursts of events and operations
- Support UCB mote hardware
  - Power, sensing, computation, communication
  - Easy to port to evolving platforms
- Support technological advances
  - Keep scaling down
  - Smaller, cheaper, lower power

TinyOS Design Options

- Can’t use existing RTOS’s
  - Microkernel architecture
    - VxWorks, PocketPC, PalmOS
  - Execution similar to desktop systems
    - PDA’s, cell phones, embedded PC’s
  - More than a order of magnitude too heavyweight and slow
  - Energy hogs

TinyOS Design Conclusion

- Similar to building networking interfaces
  - Data driven execution
  - Manage large # of concurrent data flows
  - Manage large # of outstanding events
- Add: managing application data processing
- Conclusion: need a multi-threading engine
  - Extremely efficient
  - Extremely simple

TinyOS Kernel Design

- Two-level scheduling structure
  - Events
    - Small amount of processing to be done in a timely manner
    - E.g. timer, ADC interrupts
    - Can interrupt longer running tasks
  - Tasks
    - Not time critical
    - Larger amount of processing
    - E.g. computing the average of a set of readings in an array
    - Run to completion with respect to other tasks
    - Only need a single stack
TinyOS Concurrency Model

Tasks

FIFO queue

Interrupts

Two-level of concurrency: tasks and interrupts

TinyOS Concurrency Model (cont’d)

- Tasks
  - FIFO queue
  - Placed on queue by:
    - Application
    - Other tasks
    - Self-queued
    - Interrupt service routine
  - Run-to-completion
    - No other tasks can run until completed
    - Interruptable, but any new tasks go to end of queue
- Interrupts
  - Stop running task
  - Post new tasks to queue

TinyOS Concurrency Model (cont’d)

- Two-levels of concurrency
  - Possible conflicts between interrupts and tasks
- Atomic statements
  ```
  atomic {
  ...
  }
  ```
- Asynchronous service routines (as opposed to synchronous tasks)
  ```
  async result_t interface_name.cmd_or_event_name {
  ...
  }
  ```
- Race conditions detected by compiler
  - Can generated false positives – `norace` keyword to stop warnings, but be careful

TinyOS Programming Model

- Separation of construction and composition
  - Programs are built out of `components`
  - Specification of component behavior in terms of a set of `interfaces`
  - Components specify interfaces they `use` and `provide`
  - Components are statically `wired` to each other via their interfaces
  - This increases runtime efficiency by enabling compiler optimizations
- Finite-state-machine-like specifications
- Thread of control passes into a component through its interfaces to another component

TinyOS Basic Constructs

- Commands
  - Cause action to be initiated
- Events
  - Notify action has occurred
  - Generated by external interrupts
  - Call back to provide results from previous command
- Tasks
  - Background computation
  - Not time critical

Flow of Events and Commands

- Fountain of events leading to commands and tasks (which in turn issue may issue other commands that may cause other events, …)
**TinyOS File Types**

- **Interfaces** (xxx.nc)
  - Specifies functionality to outside world
  - what commands can be called
  - what events need handling
- **Module** (xxxM.nc)
  - Code implementation
  - Code for Interface functions
  - Wiring of components
  - When top level app, drop C from filename xxx.nc

**Configuration** (xxxC.nc)
- When top level app, drop C from filename xxx.nc

**Commands**

- Commands are issued with "call"
  
  ```
  call Timer.start(TIMER_REPEAT, 1000);
  ```

  - Cause action to be initiated
  - Bounded amount of work
    - Does not block
  - Act similarly to a function call
    - Execution of a command is immediate

**Events**

- Events are called with "signal"
  
  ```
  signal ByteComm.txByteReady(SUCCESS);
  ```

  - Used to notify a component an action has occurred
  - Lowest-level events triggered by hardware interrupts
  - Bounded amount of work
    - Do not block
  - Act similarly to a function call
    - Execution of an event is immediate

**Tasks**

- Tasks are queued with "post"
  
  ```
  post radioEncodeThread();
  ```

  - Used for longer running operations
  - Pre-empted by events
  - Not pre-empted by other tasks
  - Example tasks
    - High level – calculate aggregate of sensor readings
    - Low level – encode radio packet for transmission, calculate CRC

**Components**

- Two types of components in nesC:
  - Module
  - Configuration

  A component provides and uses Interfaces
Module

- Provides application code
  - Contains C-like code
- Must implement the 'provides' interfaces
  - Implement the "commands" it provides
  - Make sure to actually "signal"
- Must implement the 'uses' interfaces
  - Implement the "events" that need to be handled
  - "call" commands as needed

Configuration

- A configuration is a component that "wires" other components together.
- Configurations are used to assemble other components together
- Connects interfaces used by components to interfaces provided by others.

Interfaces

- Bi-directional multi-function interaction channel between two components
- Allows a single interface to represent a complex event
  - E.g., a registration of some event, followed by a callback
  - Critical for non-blocking operation
- "provides" interfaces:
  - Represent the functionality that the component provides to its user
  - Service "commands" – implemented command functions
  - Issue "events" – signal to user for passing data or signalling done
- "uses" interfaces:
  - Represent the functionality that the component needs from a provider
  - Service "events" – implement event handling
  - Issue "commands" – ask provider to do something

Application

- Consists of one or more components, wired together to form a runnable program
- Single top-level configuration that specifies the set of components in the application and how they connect to one another
- Connection (wire) to main component to start execution
  - Must implement init, start, and stop commands

Components/Wiring

- Directed wire (an arrow: '->') connects components
  - Only 2 components at a time – point-to-point
  - Connection is across compatible interfaces
  - 'A <- B' is equivalent to 'B -> A'
- [component using interface] -> [component providing interface]
  - [interface] -> [implementation]
- '=' can be used to wire a component directly to the top-level object's interfaces
  - Typically used in a configuration file to use a sub-component directly
  - Unused system components excluded from compilation

Blink Application

What the executable does:
1. Main initializes and starts the application
2. BlinkM initializes ClockC's rate at 1Hz
3. ClockC continuously signals BlinkM at a rate of 1 Hz
4. BlinkM commands LedsC red led to toggle each time it receives a signal from ClockC

Note: The StdControl interface is similar to state machines (init, start, stop), used extensively throughout TinyOS apps & libs
Blink.nc

configuration Blink {
}
implementation {
    components Main, BlinkM, SingleTimer, LedsC;
    Main.StdControl -> SingleTimer.StdControl;
    Main.StdControl -> BlinkM.StdControl;
    BlinkM.Timer -> SingleTimer.Timer;
    BlinkM.Leds -> LedsC.Leds;
}

StdControl.nc

interface StdControl {
    command result_t init();
    command result_t start();
    command result_t stop();
}

BlinkM.nc

BlinkM.nc module BlinkM {
    provides {
        interface StdControl;
    }
    uses {
        interface Timer;
        interface Leds;
    }
    implementation {
        command result_t StdControl.init() {
            call Leds.init();
            return SUCCESS;
        }
        command result_t StdControl.start() {
            return call Timer.start(TIMER_REPEAT, 1000);
        }
        command result_t StdControl.stop() {
            return call Timer.stop();
        }
        event result_t Timer.fired() {
            call Leds.redToggle();
            return SUCCESS;
        }
    }
}

SingleTimer.nc (should have been SingleTimerC.nc)

- Parameterized interfaces
  - allows a component to provide multiple instances of an interface that are parameterized by a value
- Timer module supports many interfaces
  - This module simply creates one unique timer interface and wires it up
  - By wiring Timer to a separate instance of the Timer interface provided by TimerC, each component can effectively get its own "private" timer
  - Uses a compile-time constant function unique() to ensure index is unique

configuration SingleTimer {
    provides interface Timer;
    provides interface StdControl;
}
implementation {
    components TimerC;
    Timer = TimerC.Timer[unique("Timer")];
    StdControl = TimerC.StdControl;
}

Timer.nc

interface Timer {
    command result_t start(char type, uint32_t interval);
    command result_t stop();
    event result_t fired();
}
TimerC.nc

- Implementation of multiple timer interfaces to a single shared timer
- Each interface is named
- Each interface connects to one other module

Leds.nc (partial)

```c
interface leds |
/**
 * Initialize the LEDs; among other things, initialization turns them all off.
 * async command result_t init();
 */
* Turn the red LED on.
 async command result_t redOn();
* Turn the red LED off.
 async command result_t redOff();
/**
 * Toggle the red LED. If it was on, turn it off. If it was off, turn it on.
 * async command result_t redToggle();
 ...
```

Leds.nc (partial)

```c
module LedsC {
{
{
inline static result_t BlinkM$Leds$redToggle(void)

# rval;
BlinkM$Leds$redToggle();
YYYY_BIT = 4
TOSH_MAKE_YELLOW_LED_OUTPUT();
```

Blink – Compiled

```c
unsigned char result = rcombine(result, BlinkM$StdControl$init());
unsigned char result = rcombine(result, BlinkM$StdControl$start());
return SUCCESS;
```

Blink – Compiled – a small piece

```c
static inline result_t BlinkM$StdControl$init(void);
static inline result_t BlinkM$StdControl$start(void);
```

Concurrency Model

- Asynchronous Code (AC)
  - Any code that is reachable from an interrupt handler
- Synchronous Code (SC)
  - Any code that is ONLY reachable from a task
- Boot sequence
- Potential race conditions
  - Asynchronous Code and Synchronous Code
  - Asynchronous Code and Asynchronous Code
- Non-preemption eliminates data races among tasks
- resC reports potential data races to the programmer at compile time (new with version 1.1)
- Use atomic statement when needed
- async keyword is used to declare asynchronous code to compiler
Commands, Events, and Tasks

```
... status = call CmdName(args);
...
... status = signal EvtName(args);
...
... post TskName();
...
```

The command `CmdName` either posts a task to do real work or signals busy and to try again later.

The event `EvtName` either checks success flag (OK, failed, etc.) or returns OK, or returns busy.

The task `TskName` executes and signals completion with event.

Naming Convention

- Use mixed case with the first letter of word capitalized
  - Interfaces (Xxx.nc)
  - Components
  - Configuration (XxxC.nc)
  - Module (XxxM.nc)
  - Application – top level component (Xxx.nc)
- Commands, Events, & Tasks
  - First letter lowercase
  - Task names should start with the word “task”, commands with “cmd”, events with “evt” or “event”
  - If a command/event pair form a split-phase operation, event name should be same as command name with the suffix “Done” or “Complete”
  - Commands with “TOSH_” prefix indicate that they touch hardware directly
- Variables – first letter lowercase, caps on first letter of all sub-words
- Constants – all caps

Interases can fan-out and fan-in

- nesC allows interfaces to fan-out to and fan-in from multiple components
- One “provides” can be connected to many “uses” and vice versa
- Wiring fans-out, fan-in is done by a combine function that merges results

```
implementation {
  components Main, Counter, IntToLeds, TimerC;
  Main.StdControl -> IntToLeds.StdControl;
  Main.StdControl -> Counter.StdControl;
  Main.StdControl -> TimerC.StdControl;
  Counter.Timer -> TimerC.Timer[unique("Timer")];
  Counter.IntOutput -> IntToLeds.IntOutput;
}
```

Exercise

- Which of the following goes inside the module you are implementing if we assume you are the “user” of the interface?
  - post taskA()
  - call commandB(args);
  - signal eventC(args);
  - taskA implementation
  - commandB implementation
  - eventC implementation
### Sense Application

#### SenseM.nc

```plaintext
configuration SenseM {
  provides interface StdControl;
  provides interface ADC;
  implementation {
    components Main, SenseM, LedsC, TimerC, DemoSensorC as Sensor;
    Main.StdControl -> Sensor.StdControl;
    Main.StdControl -> TimerC.StdControl;
    Main.StdControl -> SenseM.StdControl;
    SenseM.ADC -> Sensor.ADC;
    SenseM.ADCControl -> Sensor.StdControl;
    SenseM.Leds -> LedsC.Leds;
    SenseM.Timer -> TimerC.Timer[unique("Timer")];
  }
}
```

#### DemoSensorC.nc

```plaintext
configuration DemoSensorC {
  provides interface ADC;
  provides interface StdControl;
  implementation {
    components Photo as Sensor;
    StdControl = Sensor;
    ADC = Sensor;
  }
}
```

### Sense Application Using Task

#### SenseTaskM.nc

```plaintext
configuration SenseTask {
  implementation {
    components Main, SenseTaskM, LedsC, TimerC, DemoSensorC as Sensor;
    Main.StdControl -> TimerC;
    Main.StdControl -> Sensor;
    Main.StdControl -> SenseTaskM;
    SenseTaskM.Timer -> TimerC.Timer[unique("Timer")];
    SenseTaskM.ADC -> Sensor;
    SenseTaskM.Leds -> LedsC;
  }
}
```

### A More Extensive Application

#### Tips

- Make liberal use of "grep" or "find in files"
- Look at example applications in the /apps directory
- All interfaces are in /interfaces directory
- Utilities are in /system, /lib, /platform, or /sensorboards
- Try to keep commands and events very short
  - Avoid loops, use queues and callbacks

NOTE: This is NOT the radio stack we will be using.
Debugging

- Cover in more detail in later lectures
- Applications can be built to run on the PC (TOSSIM)
  - Good to debug
  - Does not perfectly simulate the hardware
- Toggling LEDs
  - Can only get so much information from 1 LED
  - Useful for indicating specific events (will LED be on long enough?):
    - Radio packet transmit/receive
    - Timer fired
    - Sensor activation