Document Title	Specification of Operating System
Document Owner	AUTOSAR
Document Responsibility	AUTOSAR
Document Identification No	34

Document Status	published
Part of AUTOSAR Standard	Classic Platform
Part of Standard Release	R24-11

Document Change History

Date	Release	Changed by	Description
2024-11-27	R24-11	AUTOSAR Release Management	• Clarification on PRO_IGNORE, new PRO_PREVENT_ARRIVAL_RATE • Clarification of CallTrustedFunction, added new column to table 7.1 • Remove option to restart a OS-Application • Minor correction / clarification / editorial changes
2023-11-23	R23-11	AUTOSAR Release Management	• Renaming of restart symbols • Added new API isOsStarted, configuration change in OS-Application/EcuPartition/Core assignment • Memory mapping update • Minor correction / clarification / editorial changes

▽

△

2022-11-24	R22-11	AUTOSAR Release Management	• Several minor issues and clarifications (IOC error codes, applicability of multi-core, ARTI updates) • Additional memory allocation keywords • Added further uptraces to SRS requirements • Removal of `StartNonAutosarCore` API
2021-11-25	R21-11	AUTOSAR Release Management	• Further updates to ARTI sections • API changes and clarifications (SetScheduleTableAsync, GetNumberOfActivatedCores) • New configuration options for placement of callouts. • Update of RES_SCHEDULER handling. • Minor correction / clarification / editorial changes
2020-11-30	R20-11	AUTOSAR Release Management	• Updates to ARTI description and configuration • Ioc: correction regarding N:M communication • Minor correction / clarification / editorial changes
2019-11-28	R19-11	AUTOSAR Release Management	• Various updates for ARTI • Enhanced memory mapping for IOC • Some type improvements for multi-core • Minor correction / clarification / editorial changes • Changed Document Status from Final to published
2018-10-31	4.4.0	AUTOSAR Release Management	• New asynchronous services • ARTI support (DRAFT) • Editorial changes / clarifications

▽

△

2017-12-08	4.3.1	AUTOSAR Release Management	• minor corrections / clarifications / editorial changes; For details please refer to the ChangeDocumentation
2016-11-30	4.3.0	AUTOSAR Release Management	• Added new API for peripheral access • Added new API for interrupt handling • Minor updates/clarification of descriptions • Editorial changes
2015-07-31	4.2.2	AUTOSAR Release Management	• Allow calls to ControlIdle from all cores • Minor updates/clarification of descriptions • Editorial changes
2014-10-31	4.2.1	AUTOSAR Release Management	• Add support for AsilQmProtection • Minor updates/clarification of descriptions • Editorial changes
2014-03-31	4.1.3	AUTOSAR Release Management	• Changed multiplicity of attributes in IocSender/ReceiverProperties • Minor updates/clarification of descriptions • Editorial changes
2013-10-31	4.1.2	AUTOSAR Release Management	• Clarification on E_OS_NESTING_DEADLOCK • Update of table 2 • Corrected multiplicity of ECUC_Os_00393 • Minor updates/clarification of descriptions • Editorial changes • Removed chapter(s) on change documentation

▽

△

2013-03-15	4.1.1	AUTOSAR Administration	• Add support for ECU degradation • Changed service interface description to a formal format • Several minor changes and clarifications
2011-12-22	4.0.3	AUTOSAR Administration	• Included Multi-Core support from former "Specification of Multi-Core OS Architecture"
2010-09-30	3.1.5	AUTOSAR Administration	• Clarification in 7.8.1 (meaning of "do nothing") and 7.1.2.1 ("OSEK declarations") • Minor changes as typos and rewording
2010-02-02	3.1.4	AUTOSAR Administration	• Extension of services (Chapter 12) • States in OS- Applications • Active termination of other OS-Applications in possible (Chapter8) • Legal disclaimer revised • Chapter 10.4 revised
2009-02-04	3.1.2	AUTOSAR Administration	• Changes in OS configuration: • removed "OsAppModeId" Parameter from OsAppModeContainer • added optional references from OsAppModeContainer to OsAlarm, OsTask and OsScheduleTable
2008-08-13	3.1.1	AUTOSAR Administration	• Legal Disclaimer revised
2008-02-01	3.0.2	AUTOSAR Administration	• Added "OsScheduleTableDuration" parameter to configuration specification chapter
2007-12-21	3.0.1	AUTOSAR Administration	• Changed methods for timing protection • Moved configuration from OIL to AUTOSAR XML • Clarrified description for synchronization and `ScheduleTable`s • Document meta information extended • Small layout adaptations made

▽

△

2007-01-24	2.1.15	AUTOSAR Administration	• Added support for SoftwareFreeRunningTimer (SWFRT) incl. 2 new APIs • Added API to start a `ScheduleTable` synchron • Misc. Corrections, Clarification and further explanations • Legal disclaimer revised • Release Notes added • "Advice for users" revised • "Revision Information" added
2006-05-16	2.0	AUTOSAR Administration	• Document structure adapted to common Release 2.0 SWS Template. • Major changes in chapter 10 • Structure of document changed partly • Other changes see chapter 14
2005-05-31	1.0	AUTOSAR Administration	• Initial Release

Disclaimer

This work (specification and/or software implementation) and the material contained in it, as released by AUTOSAR, is for the purpose of information only. AUTOSAR and the companies that have contributed to it shall not be liable for any use of the work.

The material contained in this work is protected by copyright and other types of intellectual property rights. The commercial exploitation of the material contained in this work requires a license to such intellectual property rights.

This work may be utilized or reproduced without any modification, in any form or by any means, for informational purposes only. For any other purpose, no part of the work may be utilized or reproduced, in any form or by any means, without permission in writing from the publisher.

The work has been developed for automotive applications only. It has neither been developed, nor tested for non-automotive applications.

The word AUTOSAR and the AUTOSAR logo are registered trademarks.

Contents

1 Introduction and functional overview

This document describes the essential requirements on the AUTOSAR Operating System to satisfy the top-level requirements presented in the AUTOSAR SRS [1].

In general, operating systems can be split up in different groups according to their characteristics, e.g. statically configured vs. dynamically managed. To classify the AUTOSAR OS, here are the basic features of the OS

- is configured and scaled statically
- is amenable to reasoning of real-time performance
- provides a priority-based scheduling policy
- provides protective functions (memory, timing etc.) at run-time
- is hostable on low-end controllers and without external resources

This feature set defines the type of OS commonly used in the current generation of automotive ECUs, except for Telematic/Infotainment systems. It is assumed that Telematic/Infotainment systems will continue to use proprietary OSs under the AUTOSAR framework (e.g. Windows CE, VxWorks, QNX, etc.). In the case where AUTOSAR components are needed to run on these proprietary OSs, the interfaces defined in this document should be provided as an Operating System Abstraction Layer (OSAL).

This document uses the industry standard [2] (ISO 17356-3) as the basis for the AUTOSAR OS. The reader should be familiar with this standard before reading this document.

This document describes extensions to, and restrictions of [2].

2 Acronyms and Abbreviations

The glossary below includes acronyms and abbreviations relevant to the AUTOSAR Operating System module that are not included in the [3, AUTOSAR glossary].

Abbreviation	Description
API	Application Programming Interface
AR	AUTOSAR
ARTI	AUTOSAR Run-time interface
BSW	Basic Software
BSWMD	Basic Software Module Description
CDD	Complex Driver
COM	Communication
ECC	Extended Conformance Class
ECU	Electronic Control Unit
HW	Hardware
ID	Identifier
IOC	Inter OS-Application communicator
`ISR`	Interrupt Service Routine
LE	A locatable entity is a distinct piece of software that has the same effect regardless of which core it is located.
MC	Multi-Core
MCU	Microcontroller Unit
ME	Mutual exclusion
MPU	Memory Protection Unit
NMI	Non maskable interrupt
OIL	OSEK Implementation Language
OS	Operating System
OSEK/VDX	Offene Systeme und deren Schnittstellen für die Elektronik im Kraftfahrzeug
RTE	Run-Time Environment
RTOS	Real Time Operating System
SC	Single-Core
SLA	Software Layered Architecture
SW	Software
SWC	Software Component
SWFRT	Software FreeRunningTimer

2.1 Glossary of Terms

Term	Definition
Access Right	An indication that an object (e.g. `Task`, `ISR`, hook function) of an OS-Application has the permission of access or manipulation with respect to memory, OS services or (set of) OS objects.
Cardinality	The number of items in a set.
`Counter`	An operating system object that registers a count in ticks. There are two types of counters:

▽

△

Term	Definition	
	Hardware Counter	A Counter that is advanced by hardware (e.g. timer). The count value is maintained by the peripheral "in hardware".
	Software Counter	A Counter which is incremented by making the IncrementCounter API call (see [SWS_Os_00399]). The count value is maintained by the operating system "in software".
Deadline	The time at which a Task/Category 2 ISR must reach a certain point during its execution defined by system design relative to the stimulus that triggered activation. See figure 2.1	
Delay	The number of ticks between two adjacent expiry points on a ScheduleTable. A pair of expiry points X and Y are said to be adjacent when: • There is no expiry point Z such that X.Offset < Z.Offset < Y.Offset. In this case the Delay = Y.Offset-X.Offset • X and Y are the Final Expiry Point and the Initial Expiry Point respectively. In this case Delay = (Duration-X.Offset)+Y.Offset When used in the text, Delay is a relative number of ticks measured from a specified expiry point. For example: X.Delay is the delay from X to the next expiry point.	
Deviation	The minimum number of ticks between the current position on an explicitly synchronized ScheduleTable and the value of the synchronization count modulo the duration of the ScheduleTable.	
Duration	The number of ticks from a notional zero at which a ScheduleTable wraps.	
Execution Time	**Tasks:** The net time a Task spends in the RUNNING state without entering the SUSPENDED or WAITING state excluding all preemptions due to ISRs which preempt the Task. An extended Task executing the WaitEvent API call to wait on an Event which is already set notionally enters the WAITING state. For multiple activated basic Tasks the net time is per activation of a Task. **ISRs:** The net time from the first to the last instruction of the user provided Category 2 interrupt handler excluding all preemptions due to higher priority ISRs executing in preference. Execution time includes the time spent in the error, pretask and posttask hooks and the time spent making OS service calls.	
Execution Budget	Maximum permitted execution time for a Task/ISR.	
Expiry Point	The offset on a ScheduleTable, measured from zero, at which the OS activates Tasks and/or sets Events.	
	Initial Expiry Point	The expiry point with the smallest offset
	Final Expiry Point	The expiry point with the largest offset
Hook Function	A Hook function is implemented by the user and invoked by the operating system in the case of certain incidents. In order to react to these on system or application level, there are two kinds of hook functions	
	Application-specific	Hook functions within the scope of an individual OS-Application.
	System-specific	Hook functions within the scope of the complete system (in general provided by the integrator).
Initial Offset	The smallest expiry point offset on a ScheduleTable. This can be zero.	
Interarrival Time	**Basic Tasks:** The time between successively entering the READY state from the SUSPENDED state. Activation of a Task always represents a new arrival. This applies in the case of multiple activations, even if an existing instance of the Task is in the RUNNING or READY state. **Extended Tasks:** The time between successively entering the READY state from the SUSPENDED or WAITING states. Setting an Event for a Task in the WAITING state represents a new arrival if the Task is waiting on the Event. Waiting for an Event in the RUNNING state which is already set represents a new arrival. **ISRs:** The time between successive occurrences of an interrupt. See figure 2.1	
Interrupt Lock Time	The time for which a Task/ISR executes with Category 1 interrupts disabled/suspended and/or Category 2 interrupts disabled/suspended .	
Interrupt Source Enable	The switch which enables a specific interrupt source in the hardware.	

▽

△

Term	Definition	
Interrupt Vector Table	Conceptually, the interrupt vector table contains the mapping from hardware interrupt requests to (software) interrupt service routines. The real content of the Interrupt Vector Table is very hardware specific, e.g. it can contain the start addresses of the interrupt service routines.	
Final Delay	The difference between the Final Expiry Point offset and the duration on a `ScheduleTable` in ticks. This value defines the delay from the Final Expiry Point to the logical end of the `ScheduleTable` for single-shot and "nexted" `ScheduleTable`s.	
Forced OS-Application Termination	The operating system frees all system objects, e.g. forcibly terminates `Task`s, disables interrupts, etc., which are associated to the OS-Application. OS-Application and internal variables are potentially left in an undefined state.	
Forced Termination	The OS terminates the `Task`/Category 2 `ISR` and does "unlock" it's held resources. For details see [SWS_Os_00108] and [SWS_Os_00109].	
Linker File	File containing linking settings for the linker. The syntax of the linker file depends on the specific linker and, consequently, definitions are stored "linker-specific" in the linker file.	
Lock Budget	Maximum permitted Interrupt Lock Time or Resource Lock Time.	
Master core	A master core is a core from which the AUTOSAR system is bootstrapped.	
Memory Protection Unit	A Memory Protection Unit (MPU) enables memory partitioning with individual protection attributes. This is distinct from a Memory Management Unit (MMU) that provides a mapping between virtual addresses and physical memory locations at runtime. Note that some devices may realize the functionality of an MPU in an MMU.	
Mode	Describes the permissions available on a processor.	
	Privileged	In general, in "privileged mode" unrestricted access is available to memory as well as the underlying hardware.
	Non-privileged	In "non-privileged mode" access is restricted.
Modulus	The number of ticks required to complete a full wrap of an OSEK `Counter`. This is equal to `OsCounterMaxAllowedValue` +1 ticks of the `Counter`.	
OS-Application	A collection of OS objects	
	Trusted	An OS-Application that may be executed in privileged mode and may have unrestricted access to the API and hardware resources. Only trusted applications can provide trusted functions.
	Non-trusted	An OS-Application that is executed in non-privileged mode has restricted access to the API and hardware resources.
OS object	Object that belongs to a single OS-Application: `Task`, `ISR`, `Alarm`, `Event`, `ScheduleTable`, `Resource`, `Trustedfunction`, `Counter`, application-specific hook.	
OS Service	OS services are the API of the operating system.	
Protection Error	Systematic error in the software of an OS-Application.	
	Memory access violation	A protection error caused by access to an address in a manner for which no access right exists.
	Timing fault	A protection error that violates the timing protection.
	Illegal service	A protection error that violates the service protection, e.g. unauthorized call to OS service.
	Hardware exception	division by zero, illegal instruction etc.
Resource Lock Time	The time an OSEK `Resource` is held by a `Task`/`ISR` (excluding the preemptions of the `Task`/`ISR` by higher prior `Task`s/`ISR`s).	
Response Time	The time between a `Task`/`ISR` being made ready to execute and generating a specified response. The time includes all preemptions. See figure 2.1	
Scalability Class	The features of the OS (e.g. Memory Protection or Timing Protection), described by this document, can be grouped together to customize the operating system to the needs of the application. There are 4 defined groups of features which are named scalability classes. For details see Chapter 7.11	
`ScheduleTable`	Encapsulation of a statically defined set of expiry points.	

▽

△

<table>
<tr><th>Term</th><th colspan="2">Definition</th></tr>
<tr><td rowspan="3">Section</td><td colspan="2">Part of an object file in which instructions or data are combined to form a unit (contiguous address space in memory allocated for data or code). A section in an object file (object file format) has a name and a size.
From the linker perspective, two different sides can be distinguished:</td></tr>
<tr><td>Input section</td><td>memory section in an input object file of the linker.</td></tr>
<tr><td>Output section</td><td>memory section in an output object file of the linker.</td></tr>
<tr><td>Set (of OS objects)</td><td colspan="2">This document uses the term set, indicating a collection of the same type of OS objects, in the strict mathematical sense, i.e.:
- a set contains zero or more OS objects (this means a set can be empty)
- the OS objects in the set are unique (this means there cannot be duplicate OS objects in the set)</td></tr>
<tr><td>Spinlock</td><td colspan="2">A spinlock is a locking mechanism where the `Task` waits in a loop (*spins*) repeatedly checking for a shared variable to become a certain value.
The value indicates whether the lock is free or not. In Multi-Core systems the comparison and changing of the variable typically requires an atomic operation.
As the `Task` remains active but is not doing anything useful, a spinlock is a busy waiting mechanism</td></tr>
<tr><td>Spinlock variable</td><td colspan="2">A spinlock variable is a shared variable used by a spinlock to indicate whether a spinlock is free or occupied.</td></tr>
<tr><td rowspan="3">Symbol</td><td colspan="2">Address label that can be imported/used by software modules and resolved by the linker. The precise syntax of the labels is linker-specific. Here, these address labels are used to identify the start and end of memory sections.</td></tr>
<tr><td>Start symbol</td><td>Tags the start of a memory section</td></tr>
<tr><td>End symbol</td><td>Tags the end of a memory section</td></tr>
<tr><td>Synchronization of `ScheduleTable`s with a synchronization `Counter`</td><td colspan="2">Synchronization with a synchronization `Counter` is achieved, if the expiry points of the `Schedule Table` are processed within an absolute deviation from the synchronization `Counter` that is smaller than or equal to a precision threshold.</td></tr>
<tr><td>Synchronization `Counter`</td><td colspan="2">The "Synchronization `Counter`", distinct from an OS `Counter` object, is an external `Counter`, external to the OS, against which expiry points of a `ScheduleTable` are synchronized</td></tr>
<tr><td rowspan="3">`Task`</td><td colspan="2">A `Task` is the object which executes (user) code and which is managed by the OS. E.g. the OS switches between different `Task`s (*schedules*). There are 2 types of `Task`s; for more details see [2].</td></tr>
<tr><td>Basic `Task`</td><td>A `Task` which cannot block by itself. This means that it cannot wait for (OS) `Event`(s).</td></tr>
<tr><td>Extended `Task`</td><td>A `Task` which can block by itself and wait for (OS) `Event`(s).</td></tr>
<tr><td>Time Frame</td><td colspan="2">The minimum inter-arrival time for a `Task`/`ISR`.</td></tr>
<tr><td>`Trustedfunction`</td><td colspan="2">A service provided by a trusted OS-Application that can be used by other OS-Applications (trusted or non-trusted).</td></tr>
<tr><td>Worst case execution time (WCET)</td><td colspan="2">The longest possible execution time.</td></tr>
<tr><td>Write access</td><td colspan="2">Storing a value in a register or memory location. All memory accesses that have the consequence of writing (e.g. reads that have the side effect of writing to a memory location) are treated as write accesses.</td></tr>
</table>

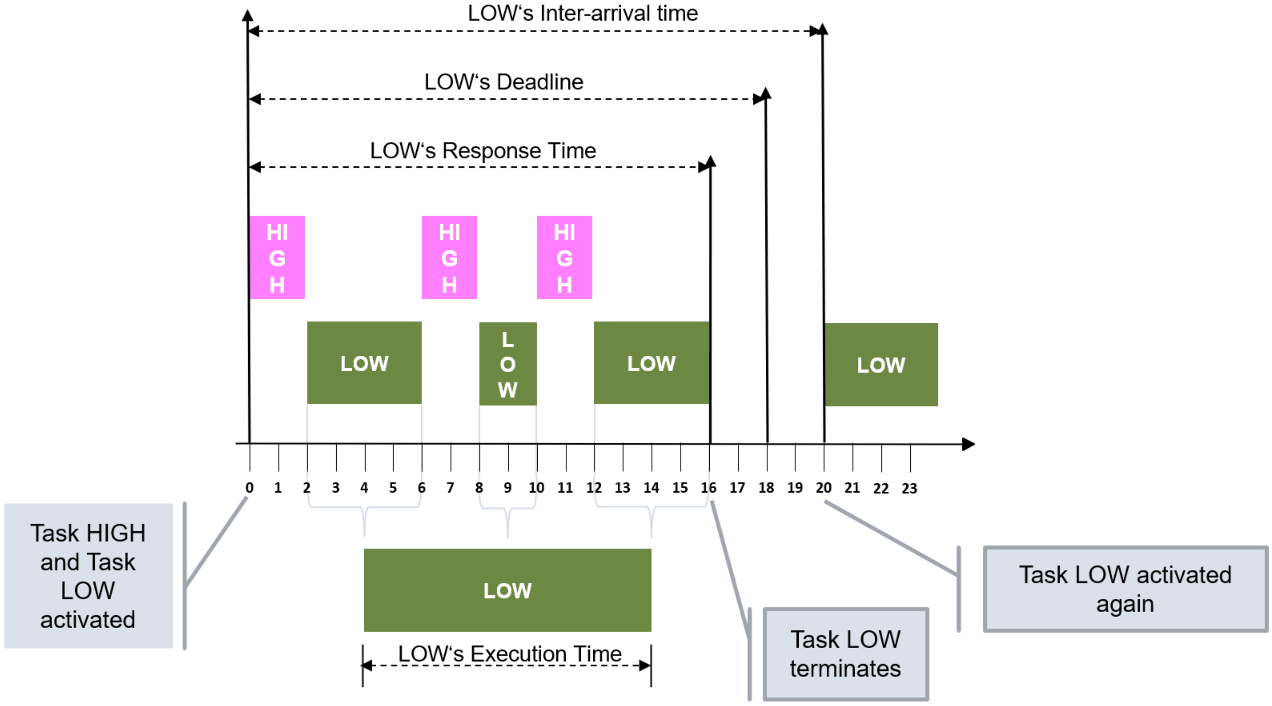

Figure 2.1: Definition of Timing Terminology

3 Related documentation

3.1 Input documents & related standards and norms

[1] Requirements on Operating System
AUTOSAR_CP_RS_OS

[2] ISO 17356-3: Road vehicles – Open interface for embedded automotive applications – Part 3: OSEK/VDX Operating System (OS)

[3] Glossary
AUTOSAR_FO_TR_Glossary

[4] General Specification of Basic Software Modules
AUTOSAR_CP_SWS_BSWGeneral

[5] Virtual Functional Bus
AUTOSAR_CP_EXP_VFB

[6] General Requirements on Basic Software Modules
AUTOSAR_CP_RS_BSWGeneral

[7] ISO 17356-6: Road vehicles – Open interface for embedded automotive applications – Part 6: OSEK/VDX Implementation Language (OIL)

[8] Specification of AUTOSAR Run-Time Interface
AUTOSAR_CP_SWS_ARTI

[9] Specification of RTE Software
AUTOSAR_CP_SWS_RTE

[10] Software Component Template
AUTOSAR_CP_TPS_SoftwareComponentTemplate

[11] Specification of Memory Mapping
AUTOSAR_CP_SWS_MemoryMapping

3.2 Related specification

AUTOSAR provides a *General Specification on Basic Software Modules* [4, SWS BSW General], which is also valid for AUTOSAR Operating System.

Thus, the specification [4, SWS BSW General] shall be considered as additional and required specification for AUTOSAR Operating System.

All OSEK OS related types, defines and functions can be found in [2]

.

4 Constraints and assumptions

4.1 Existing Standards

This document makes the following assumptions about the referenced related standards and norms:

- [2] provides a sufficiently flexible scheduling policy to schedule AUTOSAR systems.
- [2] is a mature specification and implementations are used in millions of ECUs worldwide.
- [2] does not provide enough support for isolating multi-source software components at runtime.
- [2] does not provide enough runtime support for demonstrating the absence of some classes of fault propagation in a safety-case.

4.2 Terminology

The specification uses the following operators when requirements specify multiple terms:

- **NOT** : negation of a single term e.g. NOT Weekend
- **AND** : conjunction of two terms e.g. Weekend AND Saturday
- **OR** : disjunction of two terms e.g. Monday OR Tuesday

A requirement comprising multiple terms is evaluated left to right. The precedence rules are:

- Highest Precedence **NOT**
- Lowest Precedence **AND OR**

The expression NOT X AND Y means (NOT X) AND (Y)

Where operators of the same precedence are used in the same sentence, commas are used to disambiguate. The expression X AND Y, OR Z means (X AND Y) OR Z.

4.3 Interaction with the RTE

The configuration of an AUTOSAR system [5] maps the *runnables* of a *software component* to (one or more) `Task`s that are scheduled by the operating system. All runnables in a `Task` share the same protection boundary. In AUTOSAR, a software component must not include an interrupt handler. A software component is therefore implemented as runnables executing within the body of a `Task`, or set of `Task`s, only.

Runnables get access to hardware-sourced data through the AUTOSAR RTE. The RTE provides the runtime interface between runnables and the basic software modules. The basic software modules also comprise a number of `Task`s and `ISR`s that are scheduled by the operating system.

It is assumed that the software component templates and the description of the basic software modules provide sufficient information about the required runtime behavior to be able to specify the attributes of `Task`s required to configure the OS.

4.4 Operating System Abstraction Layer (OSAL)

Systems that do not use the OS defined in AUTOSAR can provide a platform for the execution of AUTOSAR software components using an Operating System Abstraction Layer. The interface to the OSAL is exactly that defined for the AUTOSAR OS.

4.5 Multi-Core Hardware assumptions

There are currently several existing and suggested HW-architectures[1] for Multi-Core microprocessors. There is considerable variation in the features offered by these architectures. Therefore this section attempts to capture a common set of architectural features required for Multi-Core.

Hardware assumptions shall remain assumptions and shall not become official AUTOSAR requirements.

4.5.1 CPU Core features

1. More than one core on the same piece of silicon.
2. The HW offers a method that can be used by the SW to identify a core.
3. The hardware supports atomic read and atomic write operations for a fixed word length depending on the hardware.
4. The hardware supports some atomic Test-And-Set functionality or similar functionalities that can be used to build a critical section shared between cores. Additional atomic operations may exist.

[1] In this context "architecture" encompasses: the connections between cores and memory, and to peripherals and how interrupts work.

5. The cores may have the same instruction set; at least a common basic instruction set is available on all cores. Core specific add-ons may exist, but they are not considered.
6. The cores have the same data representation. For example, the same size of integer, same byte and bit order, etc.
7. If per-core caches exist, AUTOSAR requires support for RAM - cache coherency in HW or in SW. In software means that the cache-controller can be programmed by the SW in a way that it invalidates cache lines or excludes certain memory regions from caching.
8. In case of an exception (such as an illegal memory reference or divide by zero) the exception occurs on the core that introduced the exception.
9. For notification purposes, it is possible to trigger an interrupt/trap on any core.

4.5.2 Memory features

- Shared RAM is available to all cores; at least all cores can share a substantial part of the memory.
- Flash shall be shared between all cores at least. However, performance can be improved if Flash/RAM can be partitioned so that there are separate pathways from cores to Flash.
- A single address space is assumed, at least in the shared parts of the memory address space.
- The AUTOSAR Multi-Core architecture shall be capable to run on systems that do and do not support memory protection. If memory protection exists, all cores are covered by a hardware-based memory protection.

4.5.3 Multi-Core Limitations

- In AUTOSAR R4.0, it is not supported to activate additional cores under control of AUTOSAR after the Operating System was started.
- The scheduling algorithm does not assign `Task`s dynamically to cores.
- The AUTOSAR OS `Resource` algorithm is not supported across cores. `Resource`s can be used locally, between `Task`s that are bound to the same core but not between `Task`s/`ISR`s which are bound to different cores.

4.6 Limitations

4.6.1 Hardware

The core AUTOSAR operating system assumes free access to hardware resources, which are managed by the OS itself. This includes, but is not limited to, the following hardware:

- interrupt control registers
- processor status words
- stack pointer(s)

Specific (extended) features of the core operating system extend the requirements on hardware resource. The following list outlines the features that have requirements on the hardware. Systems that do not use these OS features do not have these hardware requirements.

- Memory Protection: A hardware memory protection unit is required. All memory accesses that have the consequence of writing (e.g. reads that have the side effect of writing to a memory location) shall be treated as writes.
- Time Protection: Timer Hardware for monitoring execution times and arrival rates.
- *Privileged* and *non-privileged* modes on the MCU: to protect the OS against internal corruption caused by writes to OS controlled registers. This mode must not allow OS-Applications to circumvent protection (e.g. write registers which govern memory protection, write to processor status word etc.). The privileged mode must be under full control of the protected OS which uses the mode internally and to transfer control back and forth from a non-trusted OS-Application to a trusted OS-Application. The microprocessor must support a controlled means which moves a processor into this privileged mode.
- Local/Global Time Synchronization: A global time source is needed.

In general hardware failures in the processor are not detected by the operating system. In the event of hardware failure, correct operation of the OS cannot be guaranteed.

The resources managed by a specific OS implementation have to be defined within the appropriate configuration file of the OS.

4.6.2 Programming Language

The API of the operating system is defined as C function calls or macros. If other languages are used, they must adapt to the C interface.

4.6.3 Miscellaneous

The operating system does not provide services for dynamic memory management.

4.7 Applicability to car domains

The operating system has the same design constraints regarding size and scalability under which [2] was designed. The immediate domain of applicability is therefore currently body, chassis and power train ECUs. However, there is no reason that the OS cannot be used to implement ECUs for infotainment applications.

5 Dependencies to other modules

- It is assumed that the operating system may use timer units directly to drive counters.
- If the user needs to drive scheduling directly from global time, then a global time interrupt is required.
- If the user needs to synchronize the processing of a `ScheduleTable` to a global time, the operating system needs to be told the global time using the `SyncScheduleTable` service.
- The IOC described in this document provides communication between OS-Applications. The IOC generation is based on configuration information which is generated by the RTE generator. On the other hand the RTE uses functions generated by the IOC to transmit data.
- The Operating System depends on the definition of partitions and cores in the virtual module EcuC if OS-Applications are used.

5.1 File structure

5.1.1 Code file structure

The code file structure of the Operating System module is not fixed, besides the requirements in the [6, General SRS].

5.1.2 Header file structure

The IOC generator generates an additional header file Ioc.h. Users of the Ioc.h shall include the Ioc.h file. If an implementation of the IOC requires additional header files, it is free to include them. The header files are self-contained, that means they will include all other header files, which they require.

5.1.3 ARTI File Structure

To support ARTI based debugging and tracing, all source files of the OS module with ARTI hook macros shall include an "Os_Arti.h" file. This file (along with the corresponding Arti.h and Arti.c file) will be provided by the ARTI hook implementer, i.e. the tracing tool. When building the final executable, the linker will pull in the compiled Arti.c file, too.

The usage of the ARTI hook macros is configurable. If the OS is configured to not use ARTI, the inclusion of "Os_Arti.h" may be omitted, and the ARTI hooks macros may be expanded to empty macros (*nothing*).

6 Requirements Tracing

The following tables reference the requirements specified in [6, SRS BSW General] and [1, SRS OS] and links to the fulfillment of these. Please note that if column "Satisfied by" is empty for a specific requirement this means that this requirement is not fulfilled by this document.

Requirement	Description	Satisfied by
[RS_ARTIFO_00014]	ARTI Hooks shall be implemented with minimal intrusion	[SWS_Os_00836] [SWS_Os_00837]
[RS_ARTIFO_00015]	ARTI Hooks shall follow a fixed format	[SWS_Os_00839] [SWS_Os_00841] [SWS_Os_00842] [SWS_Os_00844] [SWS_Os_00846] [SWS_Os_00857]
[RS_Arti_00001]	The ARTI template shall support core specific ARTI additions	[SWS_Os_00859]
[RS_Arti_00002]	The ARTI template shall support a parameter for the current application	[SWS_Os_00859]
[RS_Arti_00003]	The ARTI template shall support a parameter for the current task	[SWS_Os_00859]
[RS_Arti_00004]	The ARTI template shall support a parameter for the last error	[SWS_Os_00859]
[RS_Arti_00005]	The ARTI template shall support OS specific ARTI additions	[SWS_Os_00859]
[RS_Arti_00007]	The ARTI template shall support task specific ARTI additions	[SWS_Os_00859]
[RS_Arti_00009]	The ARTI description shall include a core class definition.	[SWS_Os_00859]
[RS_Arti_00011]	The ARTI description for a core class shall include a "current task" reference to the interpret the parameter value	[SWS_Os_00859]
[RS_Arti_00012]	The ARTI description shall include instance definitions for all cores of the ECU.	[SWS_Os_00859]
[RS_Arti_00014]	The ARTI description for a core instance shall include a "current task" reference to evaluate the parameter value	[SWS_Os_00859]
[RS_Arti_00016]	The ARTI description shall include an OS class definition.	[SWS_Os_00859]
[RS_Arti_00018]	The ARTI description shall include an instance definition for the OS of the ECU.	[SWS_Os_00859]
[RS_Arti_00022]	The ARTI description shall include a task class definition.	[SWS_Os_00859]
[RS_Arti_00023]	The ARTI description shall include instance definitions for all tasks of the ECU.	[SWS_Os_00859]
[RS_Arti_00029]	AUTOSAR shall support recording timing events of application states	[SWS_Os_00838]
[RS_Arti_00030]	AUTOSAR shall support recording timing events of tasks	[SWS_Os_00840]
[RS_Arti_00031]	AUTOSAR shall support recording timing events of category 2 interrupt states	[SWS_Os_00849]

▽

△

Requirement	Description	Satisfied by
[RS_Arti_00032]	AUTOSAR shall support recording timing events of service calls	[SWS_Os_00843]
[RS_Arti_00033]	AUTOSAR shall support recording timing events of spinlock states	[SWS_Os_00845]
[RS_Arti_00034]	AUTOSAR shall support recording timing events of protection hooks	[SWS_Os_00856] [SWS_Os_00857]
[SRS_BSW_00336]	Basic SW module shall be able to shutdown	[SWS_Os_00001] [SWS_Os_00713]
[SRS_BSW_00345]	BSW Modules shall support pre-compile configuration	[SWS_Os_00001]
[SRS_BSW_00351]	Encapsulation of compiler specific methods to map objects	[SWS_Os_00815]
[SRS_BSW_00459]	It shall be possible to concurrently execute a service offered by a BSW module in different partitions	[SWS_Os_00589]
[SRS_BSW_00480]	Null pointer errors shall follow a naming rule	[SWS_Os_91025]
[SRS_Os_00097]	The OS shall provide an API that is backward compatible to the API of OSEK OS	[SWS_Os_00001]
[SRS_Os_00098]	The Operating System shall provide statically configurable schedule tables based on time tables as an optional service	[SWS_Os_00002] [SWS_Os_00007]
[SRS_Os_00099]	The Operating System shall provide a mechanism which allows switching between different schedule tables	[SWS_Os_00191]
[SRS_Os_11000]	The OS may offer support to protect the memory sections of an OS-Application against read accesses by all other OS-Applications	[SWS_Os_00026]
[SRS_Os_11001]	The OS shall provide partitions which allow for fault isolation capabilities	[SWS_Os_00056]
[SRS_Os_11002]	The operating system shall provide the ability to synchronize the processing of schedule tables with a global system time base	[SWS_Os_00013] [SWS_Os_00199] [SWS_Os_00201] [SWS_Os_00206] [SWS_Os_00227]
[SRS_Os_11003]	The operating system shall be able to monitor stack usage and check for a stack overflow on a per executable object basis	[SWS_Os_00067] [SWS_Os_00068]
[SRS_Os_11005]	The operating system shall prevent an OS-Application from modifying the memory of other OS-Applications	[SWS_Os_00195] [SWS_Os_00207] [SWS_Os_00208] [SWS_Os_00795] [SWS_Os_00806] [SWS_Os_00807] [SWS_Os_91010] [SWS_Os_91011] [SWS_Os_91012] [SWS_Os_91013] [SWS_Os_91014] [SWS_Os_91015] [SWS_Os_91016] [SWS_Os_91017] [SWS_Os_91018]
[SRS_Os_11006]	The operating system shall allow tasks and ISRs within an OS-Application to exchange data	[SWS_Os_00086] [SWS_Os_00087] [SWS_Os_00196]
[SRS_Os_11007]	The operating system shall allow OS-Applications to execute shared code	[SWS_Os_00081]

▽

△

Requirement	Description	Satisfied by
[SRS_Os_11008]	Timing Fault Detection and Prevention of Propagation	[SWS_Os_00028] [SWS_Os_00033] [SWS_Os_00037] [SWS_Os_00048] [SWS_Os_00064] [SWS_Os_00089] [SWS_Os_00465] [SWS_Os_00469] [SWS_Os_00470] [SWS_Os_00471] [SWS_Os_00472] [SWS_Os_00473] [SWS_Os_00474] [SWS_Os_00863]
[SRS_Os_11009]	The operating system shall prevent the corruption of the OS by any call of a system service	[SWS_Os_00051] [SWS_Os_00052] [SWS_Os_00069] [SWS_Os_00070] [SWS_Os_00088] [SWS_Os_00092] [SWS_Os_00093]
[SRS_Os_11010]	The operating system shall prevent an OS-Application modifying OS objects that are not owned by that OS-Application	[SWS_Os_00056]
[SRS_Os_11011]	The OS shall protect itself against OS-Applications attempting to modify control registers directly which are managed by the OS	[SWS_Os_00096] [SWS_Os_00245] [SWS_Os_00808] [SWS_Os_00809] [SWS_Os_00810] [SWS_Os_00811] [SWS_Os_00812] [SWS_Os_00813] [SWS_Os_00814] [SWS_Os_91019] [SWS_Os_91020] [SWS_Os_91021]
[SRS_Os_11012]	The OS shall provide scalability for its protection features	[SWS_Os_00240] [SWS_Os_00241]
[SRS_Os_11013]	The OS shall be capable of notifying the occurrence of a protection error at runtime	[SWS_Os_00033] [SWS_Os_00037] [SWS_Os_00044] [SWS_Os_00051] [SWS_Os_00056] [SWS_Os_00064] [SWS_Os_00068] [SWS_Os_00070] [SWS_Os_00088] [SWS_Os_00093] [SWS_Os_00210] [SWS_Os_00246] [SWS_Os_00860]
[SRS_Os_11014]	In case of a protection error, the OS shall provide an error reaction on OS-, OS-Application and task/ ISR-level	[SWS_Os_00033] [SWS_Os_00037] [SWS_Os_00106] [SWS_Os_00107] [SWS_Os_00108] [SWS_Os_00109] [SWS_Os_00110] [SWS_Os_00243] [SWS_Os_00244] [SWS_Os_00863]
[SRS_Os_11016]	The OS implementation shall offer scalability which is configurable by a generation tool	[SWS_Os_00240] [SWS_Os_00241]
[SRS_Os_11018]	The OS shall provide interrupt mask functions	[SWS_Os_00299]
[SRS_Os_11019]	The AUTOSAR OS generation tool shall create the interrupt vector table	[SWS_Os_00336]
[SRS_Os_11020]	The OS shall provide a standard interface to tick a software counter	[SWS_Os_00286]
[SRS_Os_11021]	The OS shall provide a mechanism to cascade multiple software counters from a single hardware counter.	[SWS_Os_00301]
[SRS_Os_11022]	The OS shall provide a mechanism to terminate OS-Application	[SWS_Os_00258] [SWS_Os_00447]
[SRS_Os_12001]	The OS shall create an ARTI module description file	[SWS_Os_00858]
[SRS_Os_12002]	The OS code shall incorporate ARTI hooks	[SWS_Os_00836] [SWS_Os_00837]
[SRS_Os_12003]	ARTI module description file shall support all ORTI containers	[SWS_Os_00829]

▽

△

Requirement	Description	Satisfied by
[SRS_Os_80001]	The OS shall be able to manage multiple closely coupled CPU Cores	[SWS_Os_00568] [SWS_Os_00569] [SWS_Os_00579] [SWS_Os_00583] [SWS_Os_00596] [SWS_Os_00600] [SWS_Os_00606] [SWS_Os_00616] [SWS_Os_00627] [SWS_Os_00628] [SWS_Os_00672] [SWS_Os_00673] [SWS_Os_00674] [SWS_Os_00675]
[SRS_Os_80003]	The multi core extension shall provide the same degree of predictability as the single core	[SWS_Os_00570] [SWS_Os_00571] [SWS_Os_00573]
[SRS_Os_80005]	OsApplications and as a result TASKS and OsISRs shall be assigned statically to cores	[SWS_Os_00570] [SWS_Os_00571] [SWS_Os_00572] [SWS_Os_00573] [SWS_Os_00667] [SWS_Os_00826] [SWS_Os_CONSTR_00001] [SWS_Os_CONSTR_00002]
[SRS_Os_80006]	Initialization/Start-up of the system shall be synchronized	[SWS_Os_00572] [SWS_Os_00574] [SWS_Os_00575] [SWS_Os_00576] [SWS_Os_00577] [SWS_Os_00578] [SWS_Os_00579] [SWS_Os_00580] [SWS_Os_00581] [SWS_Os_00582] [SWS_Os_00607] [SWS_Os_00608] [SWS_Os_00609] [SWS_Os_00610] [SWS_Os_00625] [SWS_Os_00668] [SWS_Os_00669] [SWS_Os_00670] [SWS_Os_00676] [SWS_Os_00677] [SWS_Os_00678] [SWS_Os_00679] [SWS_Os_00681]
[SRS_Os_80007]	Shutdown procedure shall be triggered by any core	[SWS_Os_00586] [SWS_Os_00587] [SWS_Os_00588] [SWS_Os_00616] [SWS_Os_00617] [SWS_Os_00621] [SWS_Os_00713] [SWS_Os_00714] [SWS_Os_00715] [SWS_Os_00716]
[SRS_Os_80008]	It shall be a common OS configuration across multiple cores	[SWS_Os_00567] [SWS_Os_00582]
[SRS_Os_80011]	The number of cores that the operating system manages shall be configurable offline	[SWS_Os_00583] [SWS_Os_00825]
[SRS_Os_80013]	The behaviour of services shall be identical to single core systems	[SWS_Os_00569] [SWS_Os_00589] [SWS_Os_00590] [SWS_Os_00591] [SWS_Os_00592] [SWS_Os_00593] [SWS_Os_00594] [SWS_Os_00595] [SWS_Os_00607] [SWS_Os_00618] [SWS_Os_00619] [SWS_Os_00623] [SWS_Os_00629] [SWS_Os_00630] [SWS_Os_00631] [SWS_Os_00635] [SWS_Os_00636] [SWS_Os_00637] [SWS_Os_00638] [SWS_Os_00639] [SWS_Os_00640] [SWS_Os_00643] [SWS_Os_00645] [SWS_Os_00646] [SWS_Os_00647] [SWS_Os_00663] [SWS_Os_00664] [SWS_Os_00665]
[SRS_Os_80015]	The MC extensions shall provide a mechanism to activate tasks on different cores	[SWS_Os_00596] [SWS_Os_00598] [SWS_Os_00599] [SWS_Os_00600] [SWS_Os_00816] [SWS_Os_00818] [SWS_Os_00819] [SWS_Os_91022] [SWS_Os_91023]
[SRS_Os_80016]	Event mechanism shall work across cores	[SWS_Os_00602] [SWS_Os_00604] [SWS_Os_00605] [SWS_Os_00817]

▽

△

Requirement	Description	Satisfied by
[SRS_Os_80018]	A method to synchronize tasks on more than one core shall be provided	[SWS_Os_00632] [SWS_Os_00633] [SWS_Os_00634] [SWS_Os_00641] [SWS_Os_00642] [SWS_Os_00644] [SWS_Os_00648] [SWS_Os_00649] [SWS_Os_00650] [SWS_Os_00652] [SWS_Os_00653] [SWS_Os_00654] [SWS_Os_00655] [SWS_Os_00656] [SWS_Os_00657] [SWS_Os_00658] [SWS_Os_00659] [SWS_Os_00660] [SWS_Os_00661]
[SRS_Os_80020]	A data exchange mechanism shall be provided	[SWS_Os_00611] [SWS_Os_00671] [SWS_Os_00718] [SWS_Os_00719] [SWS_Os_00720] [SWS_Os_00721] [SWS_Os_00722] [SWS_Os_00723] [SWS_Os_00724] [SWS_Os_00725] [SWS_Os_00726] [SWS_Os_00727] [SWS_Os_00728] [SWS_Os_00729] [SWS_Os_00730] [SWS_Os_00731] [SWS_Os_00732] [SWS_Os_00733] [SWS_Os_00734] [SWS_Os_00735] [SWS_Os_00736] [SWS_Os_00737] [SWS_Os_00738] [SWS_Os_00739] [SWS_Os_00740] [SWS_Os_00741] [SWS_Os_00742] [SWS_Os_00743] [SWS_Os_00744] [SWS_Os_00745] [SWS_Os_00746] [SWS_Os_00747] [SWS_Os_00748] [SWS_Os_00749] [SWS_Os_00750] [SWS_Os_00751] [SWS_Os_00752] [SWS_Os_00753] [SWS_Os_00754] [SWS_Os_00755] [SWS_Os_00756] [SWS_Os_00757] [SWS_Os_00758] [SWS_Os_00759] [SWS_Os_00760] [SWS_Os_00761] [SWS_Os_00803] [SWS_Os_00805] [SWS_Os_00827] [SWS_Os_00828] [SWS_Os_00830] [SWS_Os_00831] [SWS_Os_00832] [SWS_Os_00833] [SWS_Os_00834] [SWS_Os_00835]
[SRS_Os_80021]	The MC extension of the AUTOSAR environment shall support a mutual exclusion mechanism between cores that shall not cause deadlocks	[SWS_Os_00612] [SWS_Os_00613] [SWS_Os_00614] [SWS_Os_00615] [SWS_Os_00620] [SWS_Os_00622] [SWS_Os_00624] [SWS_Os_00648] [SWS_Os_00649] [SWS_Os_00650] [SWS_Os_00651] [SWS_Os_00652] [SWS_Os_00653] [SWS_Os_00654] [SWS_Os_00655] [SWS_Os_00656] [SWS_Os_00657] [SWS_Os_00658] [SWS_Os_00659] [SWS_Os_00660] [SWS_Os_00661] [SWS_Os_00662] [SWS_Os_00666] [SWS_Os_00686] [SWS_Os_00687] [SWS_Os_00688] [SWS_Os_00689] [SWS_Os_00690] [SWS_Os_00691] [SWS_Os_00692] [SWS_Os_00693] [SWS_Os_00694] [SWS_Os_00695] [SWS_Os_00696] [SWS_Os_00697] [SWS_Os_00698] [SWS_Os_00699] [SWS_Os_00700] [SWS_Os_00701] [SWS_Os_00703] [SWS_Os_00704] [SWS_Os_00705] [SWS_Os_00706] [SWS_Os_00707] ▽

▽

△

Requirement	Description	Satisfied by
		△ [SWS_Os_00708] [SWS_Os_00709] [SWS_Os_00710] [SWS_Os_00711] [SWS_Os_00712] [SWS_Os_00792] [SWS_Os_00801]
[SRS_Os_80022]	In case no task is going to be scheduled on a specific core, the OS shall execute a user selectable operation	[SWS_Os_00769]
[SRS_Os_80023]	The OS shall execute an operation which can be selected at runtime, in case no task is going to be scheduled on a specific core	[SWS_Os_00770] [SWS_Os_00771] [SWS_Os_00802]

Table 6.1: Requirements Tracing

7 Functional specification

7.1 Core OS

7.1.1 Background & Rationale

The OSEK/VDX Operating System [2] is widely used in the automotive industry and has been proven in use in all classes of ECUs found in modern vehicles. The concepts that OSEK OS has introduced are widely understood and the automotive industry has many years of collective experience in engineering OSEK OS based systems.

OSEK OS is an event-triggered operating system. This provides high flexibility in the design and maintenance of AUTOSAR based systems. Event triggering gives freedom for the selection of the events to drive scheduling at runtime, for example angular rotation, local time source, global time source, error occurrence etc.

For these reasons the core functionality of the AUTOSAR OS shall be based upon the OSEK OS. In particular OSEK OS provides the following features to support concepts in AUTOSAR:

- fixed priority-based scheduling
- facilities for handling interrupts
- only interrupts with higher priority than `Task`s
- some protection against incorrect use of OS services
- a startup interface through `StartOS` and the `StartupHook`
- a shutdown interface through `ShutdownOS` and the `ShutdownHook`

OSEK OS provides many features in addition to these. Readers should consult the specification [2] for details.

Basing AUTOSAR OS on OSEK OS means that legacy applications will be backward compatible - i.e. applications written for OSEK OS will run on AUTOSAR OS. However, some of the features introduced by AUTOSAR OS require restrictions on the use of existing OSEK OS features or extend existing OSEK OS features.

7.1.2 Requirements

[SWS_Os_00001]

Upstream requirements: SRS_Os_00097, SRS_BSW_00336, SRS_BSW_00345

⌈The Operating System module shall provide an API that is backward compatible with the OSEK OS API [2].⌋

7.1.2.1 Restrictions on OSEK OS

It is too inefficient to achieve timing and memory protection for alarm callbacks. They are therefore not allowed in specific scalability classes ([SWS_Os_00242])

[SWS_Os_00242] ⌈The Operating System module shall only allow `Alarm` Callbacks in Scalability Class 1.⌋

OSEK OS is required to provide functionality to handle inter-task (internal) communication according to the OSEK COM specification when internal communication only is required in the system. In AUTOSAR, internal communication is provided by the AUTOSAR RTE or by AUTOSAR COM at least one of which will be present for all AUTOSAR ECUs.

AUTOSAR OS, when used in an AUTOSAR system, therefore does not need to support internal communication.

An OSEK OS must implement internal communication if the symbol `LOCALMESSAGESONLY` is defined. AUTOSAR OS can deprecate the need to implement OSEK COM functionality and maintain compatibility with OSEK suite of specifications by ensuring that AUTOSAR OS always exists in an environment where `LOCALMESSAGESONLY` is undefined.

OSEK OS has one special `Resource` called `RES_SCHEDULER`. This `Resource` has 2 specific aspects:

1. It is always present in the system, even if it is not configured. This means that the `RES_SCHEDULER` is always known by the OS.
2. It has always the highest `Task` priority. This means a `Task` which allocates this `Resource` cannot be preempted by other `Task`s.

Since special cases are always hard to handle (e.g. in this case with respect to timing protection) AUTOSAR OS handles `RES_SCHEDULER` as any other `Resource`. This means that the `RES_SCHEDULER` is not automatically created.

Note that on multi-core systems the scheduling happens per core. Chapter 7.9.21 contains more information regarding handling of `Resource`s in such systems.

In OSEK OS users must declare Operating System objects with specific macros (e.g. `DeclareTask(), ...`) An AUTOSAR OS implementation shall not depend on such declarations and shall (for backwards compatibility) supply macros without functionality.

7.1.2.2 Undefined Behaviour in OSEK OS

There are a number of cases where the behaviour of OSEK OS is undefined. These cases represent a barrier to portability. AUTOSAR OS tightens the OSEK OS specification by defining the required behaviour.

[SWS_Os_00304] ⌈If in a call to SetRelAlarm the parameter "increment" is set to zero, the service shall return E_OS_VALUE in standard and extended status .⌋

[SWS_Os_00424] ⌈The first call to StartOS (for starting the Operating System) shall not return.⌋

[SWS_Os_00425] ⌈If ShutdownOS is called and ShutdownHook returns then the Operating System module shall disable all interrupts and enter an endless loop.⌋

7.1.2.3 Extensions to OSEK OS

[SWS_Os_00299]

Upstream requirements: SRS_Os_11018

⌈The Operating System module shall provide the services DisableAllInterrupts, EnableAllInterrupts, SuspendAllInterrupts, ResumeAllInterrupts prior to calling StartOS and after calling ShutdownOS.⌋

It is assumed that the static variables of the functions mentioned in [SWS_Os_00299] are initialized.

[SWS_Os_00301]

Upstream requirements: SRS_Os_11021

⌈The Operating System module shall provide the ability to increment a software Counter as an alternative action on alarm expiry.⌋

The Operating System module provides API service IncrementCounter (see [SWS_Os_00399]) to increment a software Counter.

[SWS_Os_00476] ⌈The Operating System module shall allow to automatically start preconfigured absolute alarms during the start of the Operating System.⌋

[SWS_Os_00476] is an extension to OSEK OS which allows this only for relative alarms.

[SWS_Os_00566] ⌈The Operating System API shall check in extended mode all pointer arguments for a NULL_PTR and return E_OS_ILLEGAL_ADDRESS in this case unless NULL_PTR is explicitly allowed as a valid pointer address value in the API parameter specification.⌋

7.2 Software Free Running Timer

Due to the fact that the number of timers is often very limited, some functionality and configuration is added to extend the reuse of timers. E.g. this allows timer measurements.

[SWS_Os_00374] ⌈The Operating System module shall handle all the initialization and configuration of timers used directly by the Operating System module and not handled by the GPT driver.⌋

The Operating System module provides API service `GetCounterValue` (see [SWS_Os_00383]) to read the current count value of a `Counter` (returning either the hardware timer ticks if `Counter` is driven by hardware or the software ticks when user drives `Counter`).

The Operating System module provides API service `GetElapsedValue` (see [SWS_Os_00392]) to get the number of ticks between the current tick value and a previously read tick value.

[SWS_Os_00384] ⌈The Operating System module shall adjust the read out values of hardware timers (which drive counters) in such that the lowest value is zero and consecutive reads return an increasing count value until the timer wraps at its modulus.⌋

7.3 `ScheduleTable`s

7.3.1 Background & Rationale

It is possible to implement a statically defined `Task` activation mechanism using an OSEK `Counter` and a series of auto started alarms. In the simple case, this can be achieved by specifying that the `Alarm`s are not modified once started. Run-time modifications can only be made if relative synchronization between alarms can be guaranteed. This typically means modifying the alarms while associated `Counter` tick interrupts are disabled.

`ScheduleTable`s address the synchronization issue by providing an encapsulation of a statically defined set of expiry points. Each expiry point defines:

- one or more actions that must occur when it is processed where an action is the activation of a `Task` or the setting of an event.
- An offset in ticks from the start of the `ScheduleTable`

Each `ScheduleTable` has a duration in ticks. The duration is measured from zero and defines the modulus of the `ScheduleTable`.

At runtime, the Operating System module will iterate over the `ScheduleTable`, processing each expiry point in turn. The iteration is driven by an OSEK `Counter`. It therefore follows that the properties of the `Counter` have an impact on what is possible to configure on the `ScheduleTable`.

7.3.2 Requirements

7.3.2.1 Structure of a `ScheduleTable`

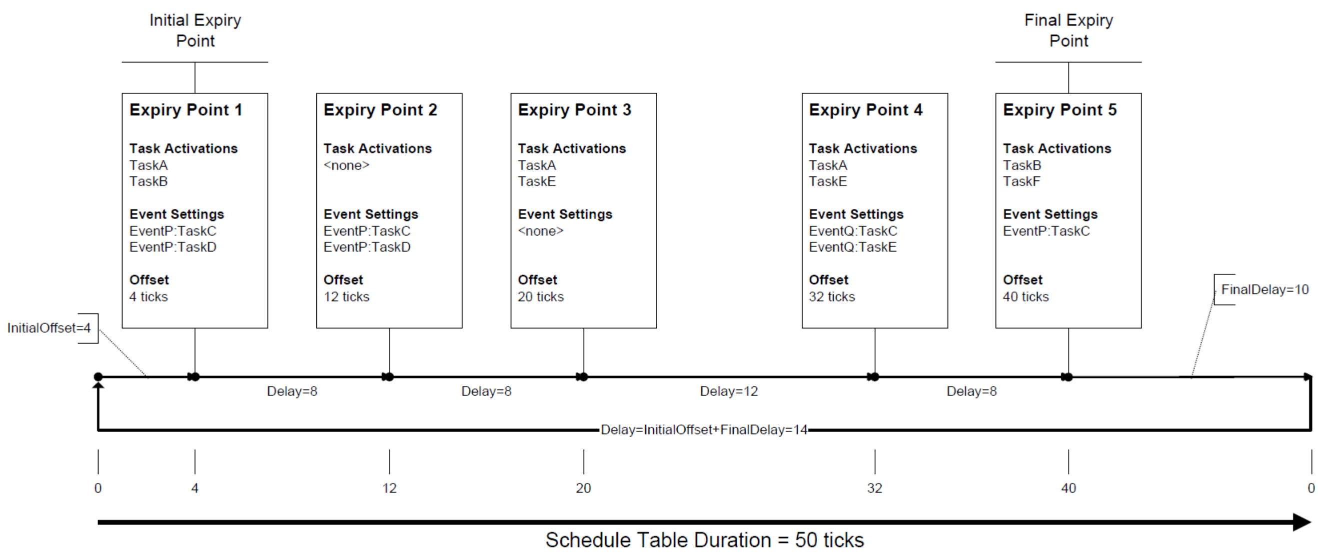

Figure 7.1: Anatomy of a `ScheduleTable`

[SWS_Os_00401] ⌈A `ScheduleTable` shall have at least one expiry point.⌋

[SWS_Os_00402] ⌈An expiry point shall contain a (possibly empty) set of `Task`s to activate.⌋

[SWS_Os_00403] ⌈An expiry point shall contain a (possibly empty) set of `Event`s to set.⌋

[SWS_Os_00404] ⌈An expiry point shall contain an offset in ticks from the start of the `ScheduleTable`.⌋

7.3.2.2 Constraints on Expiry Points

There is no use case for an empty expiry point, so each one must define at least one action.

[SWS_Os_00407] ⌈An expiry point shall activate at least one Task OR set at least one event.⌋

The OS needs to know the order in which expiry points are processed. It is therefore necessary to ensure that the expiry points on a ScheduleTable can be totally ordered. This is guaranteed by forcing each expiry point on a ScheduleTable to have a unique offset.

[SWS_Os_00442] ⌈Each expiry point on a given ScheduleTable shall have a unique offset.⌋

Iteration over expiry points on a ScheduleTable is driven by an OSEK Counter. The characteristics of the Counter - OsCounterMinCycle and OsCounterMaxAllowedValue - place constraints on expiry point offsets.

[SWS_Os_00443] ⌈The Initial Offset shall be zero OR in the range OsCounterMinCycle .. OsCounterMaxAllowedValue of the underlying Counter.⌋

Similarly, constraints apply to the delays between of adjacent expiry points and the delay to the logical end of the ScheduleTable.

[SWS_Os_00408] ⌈The delay between adjacent expiry points shall be in the range OsCounterMinCycle .. OsCounterMaxAllowedValue of the underlying Counter.⌋

7.3.2.3 Processing ScheduleTables

[SWS_Os_00002]

Upstream requirements: SRS_Os_00098

⌈The Operating System module shall process each expiry point on a ScheduleTable from the Initial Expiry Point to the Final Expiry Point in order of increasing offset.⌋

[SWS_Os_00007]

Upstream requirements: SRS_Os_00098

⌈The Operating System module shall permit multiple ScheduleTables to be processed concurrently.⌋

[SWS_Os_00409] ⌈A ScheduleTable of the Operating System module shall be driven by exactly one Counter.⌋

[SWS_Os_00410] ⌈The Operating System module shall be able to process at least one `ScheduleTable` per `Counter` at any given time.⌋

[SWS_Os_00411] ⌈The Operating System module shall make use of ticks so that one tick on the `Counter` corresponds to one tick on the `ScheduleTable`.⌋

It is possible to activate a `Task` and set (one or more unique) `Event`s for the same `Task` at the same expiry point. The ordering of `Task` activations and event settings performed from the expiry point could lead to different implementations exhibiting different behaviour (for example, activating a suspended `Task` and then setting and event on the `Task` would succeed but if the ordering was reversed then the event setting would fail). To prevent such non-determinism, it is necessary to enforce a strict ordering of actions on the expiry point.

[SWS_Os_00412] ⌈If an expiry point contains actions to activate a `Task` and to set one or several `Event`(s) of the same `Task`, then the Operating System module shall process this `Task` activation before the related `Event`(s) are set. No further assumptions about the order for the processing of expiry points can be made.⌋

A `ScheduleTable` always has a defined state and the following figure illustrates the different states (for a non-synchronized `ScheduleTable`) and the transitions between them.

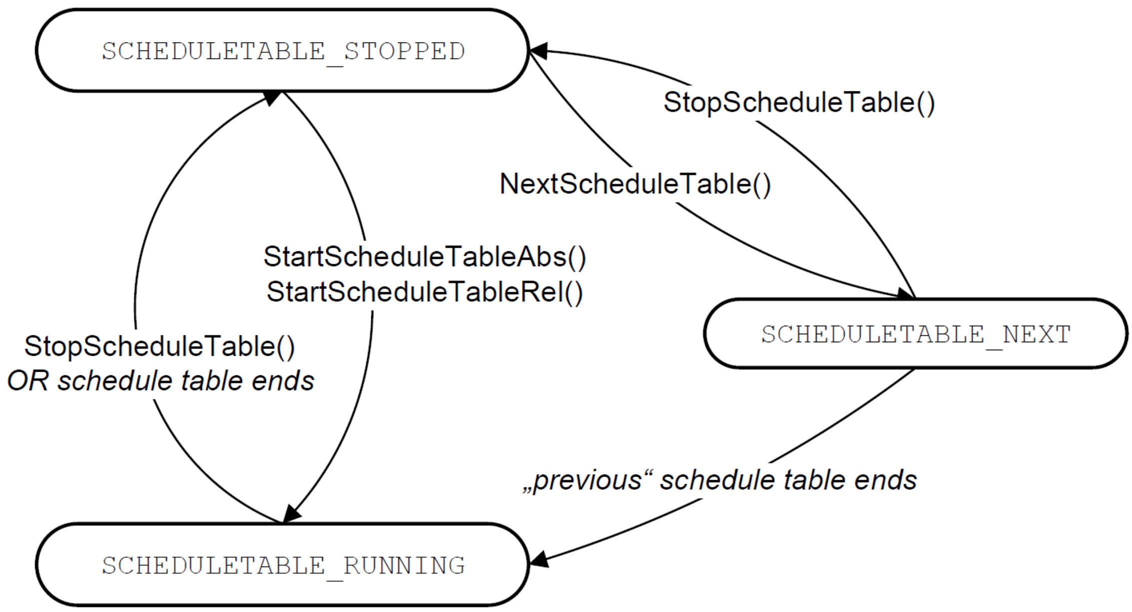

Figure 7.2: States of a `ScheduleTable`

If a `ScheduleTable` is not active - this means that is not processed by the Operating System - the state is `SCHEDULETABLE_STOPPED`. After starting a `ScheduleTables` enters the `SCHEDULETABLE_RUNNING` state where the OS processes the expiry points. If the service to switch a ScheduleTable is called a ScheduleTable enters the SCHEDULETABLE_NEXT state and waits until the "current" ScheduleTable ends.

7.3.2.4 Repeated ScheduleTable Processing

A ScheduleTable may or may not repeat after the final expiry point is processed. This allows two types of behaviour:

1. single-shot - the ScheduleTable processes each expiry point in sequence and then stops at the end. This is useful for triggering a phased sequence of actions in response to some trigger
2. repeating - the ScheduleTable processes each expiry point in turn, after processing the final expiry point, it loops back to the initial expire point. This is useful for building applications that perform repeated processing or system which need to synchronize processing to a driver source.

A repeating ScheduleTable means that each expiry point is repeated at a period equal to the ScheduleTable duration.

[SWS_Os_00413] ⌈The ScheduleTable shall be configurable as either single-shot or repeating.⌋

[SWS_Os_00009] ⌈If the ScheduleTable is single-shot, the Operating System module shall stop the processing of the ScheduleTable Final Delay ticks after the Final Expiry Point is processed.⌋

[SWS_Os_00427] ⌈If the ScheduleTable is single-shot, the Operating System module shall allow a Final Delay between 0 .. OsCounterMaxAllowedValue of the underlying Counter.⌋

[SWS_Os_00444] ⌈For periodic ScheduleTables the value of Final Delay shall be in the range OsCounterMinCycle .. OsCounterMaxAllowedValue of the underlying Counter.⌋

[SWS_Os_00194] ⌈After processing the Final Expiry Point, and if the ScheduleTable is repeating, the Operating System shall process the next Initial Expiry Point, after Final Delay plus Initial Offset ticks have elapsed.⌋

7.3.2.5 Controlling ScheduleTable Processing

The application is responsible for starting and stopping the processing of a ScheduleTable.

The Operating System module provides the service StartScheduleTableAbs (see [SWS_Os_00358]) to start the processing of a ScheduleTable at an absolute value "Start" on the underlying Counter. (The Initial Expiry Point has to be processed when the value of the underlying Counter equals Start + InitialOffset).

The Operating System module provides the service StartScheduleTableRel (see [SWS_Os_00347]) to start the processing of a ScheduleTable at "Offset" relative to the "Now" value on the underlying Counter (The Initial Expiry Point shall be processed when the value of the underlying Counter equals Now + Offset + InitialOffset).

The figure below illustrates the two different methods for a ScheduleTable driven by a Counter with a modulus of 65536 (i.e. an OsCounterMaxAllowedValue = 65535).

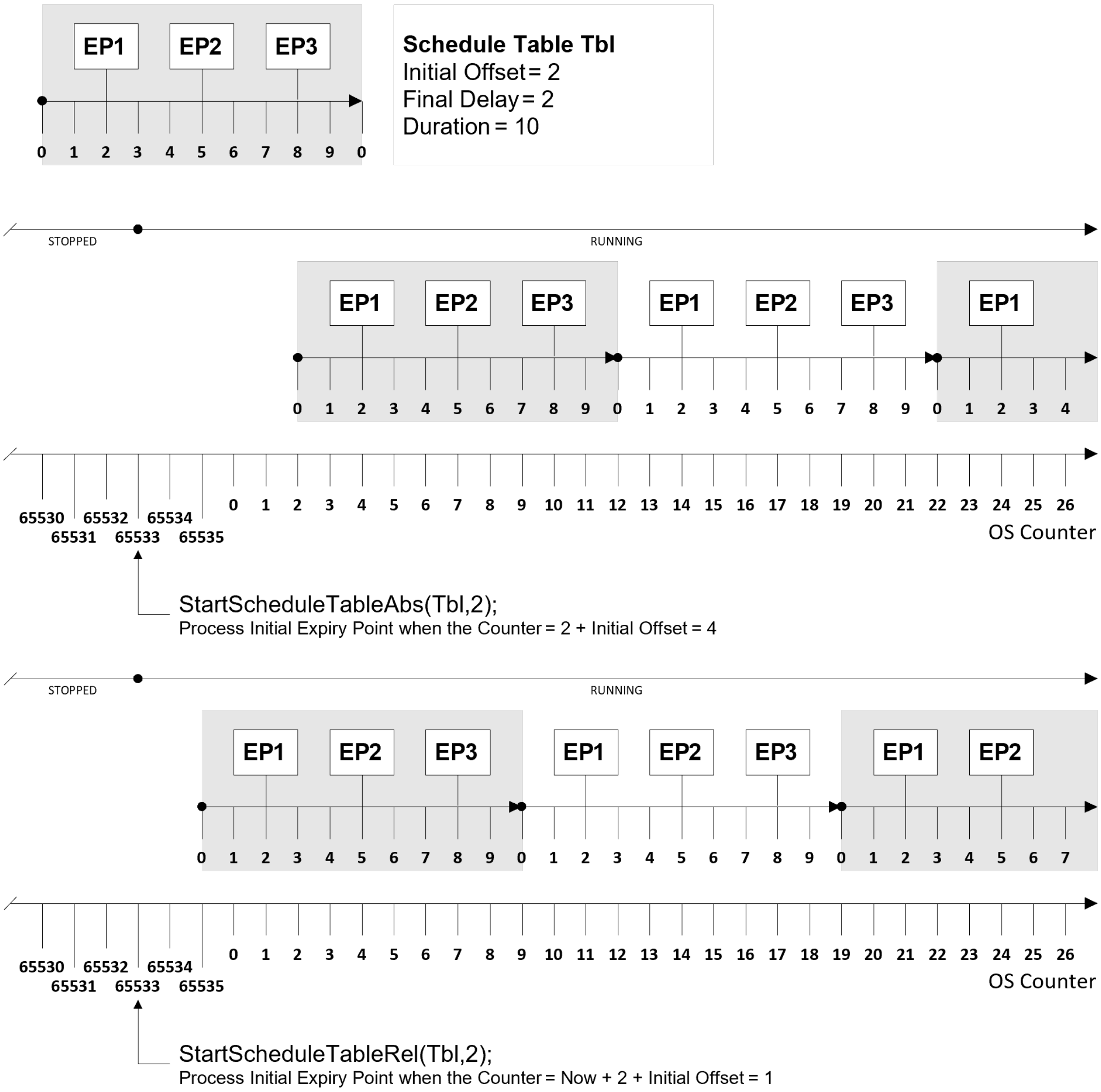

Figure 7.3: Starting a `ScheduleTable` at an Absolute and a Relative Count

The Operating System module provides the service `StopScheduleTable` (see [SWS_Os_00006]) to cancel the processing of a `ScheduleTable` immediately at any point while the `ScheduleTable` is running.

[SWS_Os_00428] ⌈If `ScheduleTable` processing has been cancelled before reaching the Final Expiry Point and is subsequently restarted then [SWS_Os_00358]/[SWS_Os_00347] means that the re-start occurs from the start of the `ScheduleTable`.⌋

The Operating System module provides the service `NextScheduleTable` (see [SWS_Os_00191]) to switch the processing from one `ScheduleTable` to another `ScheduleTable`.

[SWS_Os_00414] ⌈When a ScheduleTable switch is requested, the OS shall continue to process expiry points on the current ScheduleTable. After the Final Expiry Point there will be a delay equivalent to Final Delay ticks before processing the switched-to ScheduleTable. The initial expiry point will be processed after initial offset.⌋

The Operating System module provides the service GetScheduleTableStatus (see [SWS_Os_00227]) to query the state of a ScheduleTable.

ScheduleTables can be configured (see chapter 10) to start automatically during start of the Operating System module (like Tasks and Alarms in OSEK OS). OSEK OS defines a specific order: Autostart of Tasks is performed before autostart of alarms. AUTOSAR OS extends this with ScheduleTables.

[SWS_Os_00510] ⌈The Operating System module shall perform the autostart of ScheduleTables during startup after the autostart of Tasks and Alarms.⌋

7.4 ScheduleTable Synchronization

7.4.1 Background & Rationale

The absolute time at which the Initial Expiry Point on a ScheduleTable is processed is under user control. However, if the ScheduleTable repeats then it is not guaranteed that the absolute count value at which the initial expiry point was first processed is the same count value at which it is subsequently processed. This is because the duration of the ScheduleTable need not be equal to the Counter modulus.

In many cases it may be important that ScheduleTable expiry points are processed at specific absolute values of the underlying Counter. This is called synchronization. Typical use-cases include:

- Synchronization of expiry points to degrees of angular rotation for motor management
- Synchronizing the computation to a global (network) time base. Note that in AUTOSAR, the Operating System does not provide a global (network) time source because
    1. a global time may not be needed in many cases
    2. other AUTOSAR modules, most notably FlexRay, provide this independently to the Operating System

3. if the Operating System is required to synchronize to multiple global (network) time sources (for example when building a gateway between two time-triggered networks) the Operating System cannot be the source of a unique global time.

AUTOSAR OS provides support for synchronization in two ways:

- implicit synchronization - the `Counter` driving the `ScheduleTable` is the `Counter` with which synchronization is required. This is typically how synchronization with time-triggered networking technologies (e.g. FlexRay, TTP) is achieved - the underlying hardware manages network time synchronization and simply presents time as an output/compare timer interface to the Operating System. The following figure shows the possible states for `ScheduleTable`s with implicit synchronization.

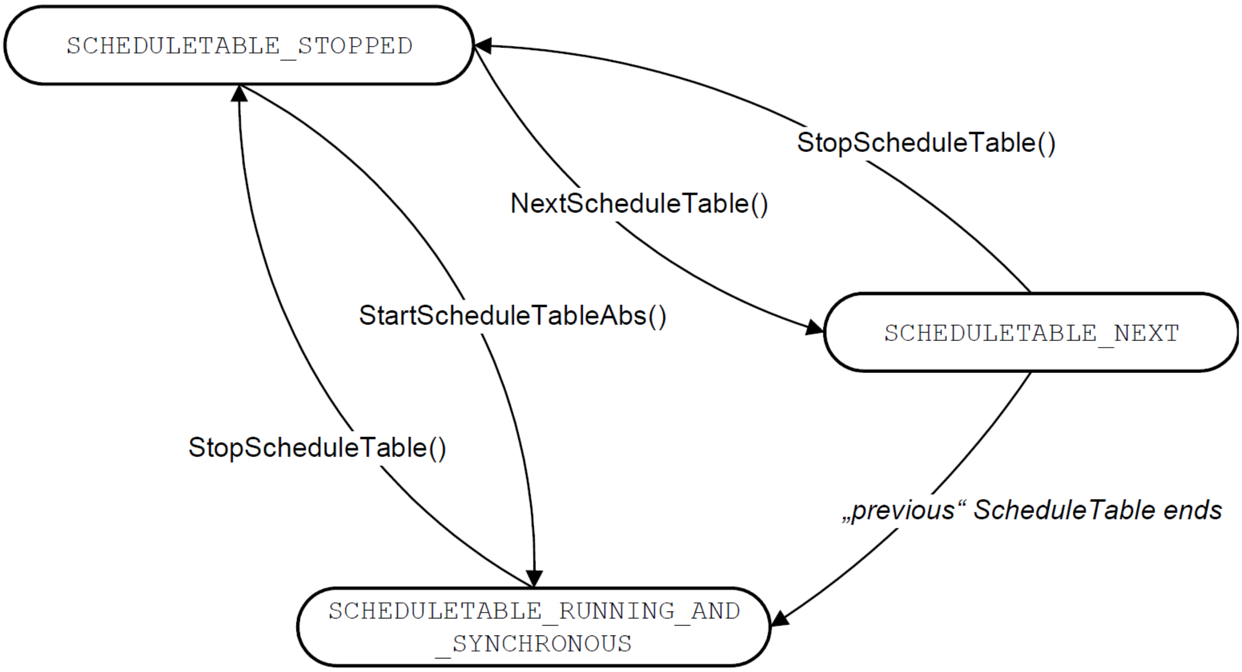

Figure 7.4: States of an implicit synchronized `ScheduleTable`

- explicit synchronization - the `ScheduleTable` is driven by an Operating System `Counter` which is not the `Counter` with which synchronization is required. The Operating System provides additional functionality to keep `ScheduleTable` processing driven by the Operating System `Counter` synchronized with the synchronization `Counter`. This is typically how synchronization with periodically broadcast global times works. The next figure shows the states of such `ScheduleTable`s.

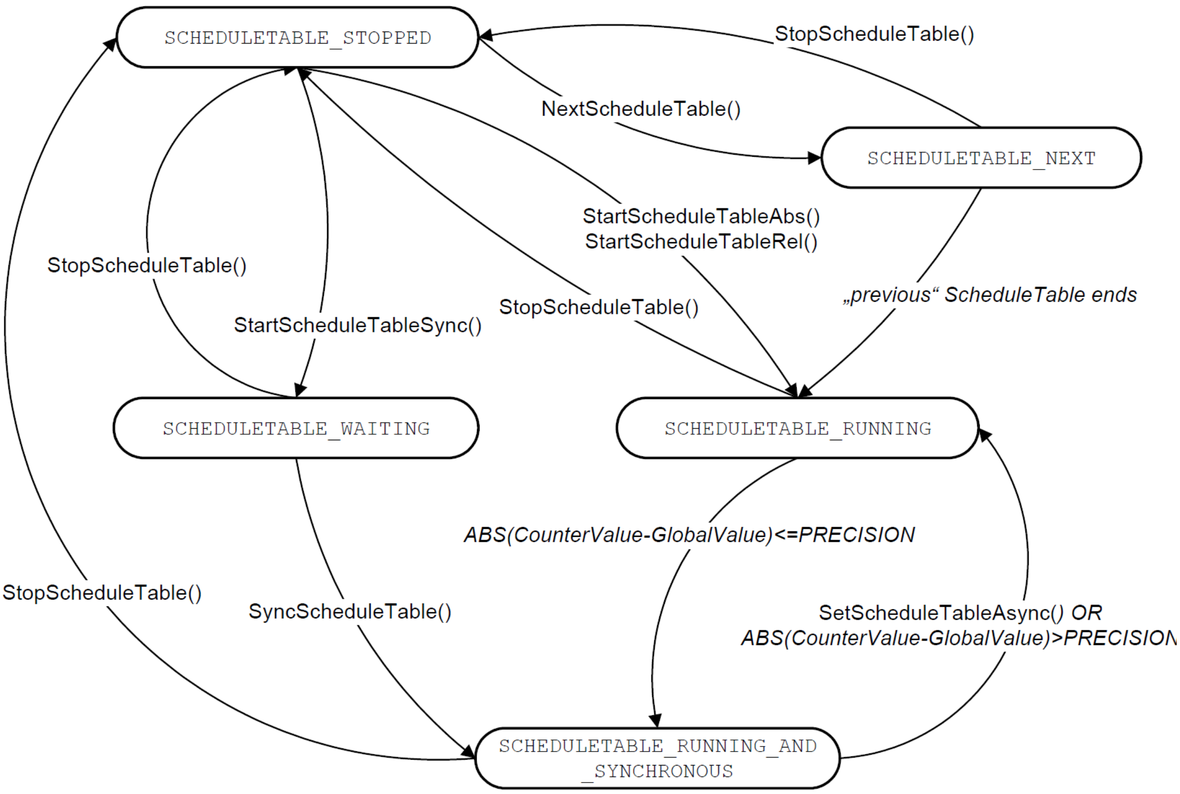

Figure 7.5: States of an explicit synchronized `ScheduleTable` (not all conditions for transitions are shown in the picture)

7.4.2 Requirements

[SWS_Os_00013]

Upstream requirements: SRS_Os_11002

⌈The Operating System module shall provide the ability to synchronize the processing of `ScheduleTable` to known `Counter` values.⌋

7.4.2.1 Implicit Synchronization

The Operating System module does not need to provide any additional support for implicit synchronization of `ScheduleTable`s. However, it is necessary to constrain configuration and runtime control of the `ScheduleTable` so that ticks on the configured `ScheduleTable` can be aligned with ticks on the `Counter`. This requires the range of the `ScheduleTable` to be identical to the range of the `Counter` (the equality of tick resolution of each is guaranteed by the requirements on the `ScheduleTable` / `Counter` interaction):

[SWS_Os_00429] ⌈A ScheduleTable of the Operating System module that is implicitly synchronized shall have a Duration equal to OsCounterMaxAllowedValue + 1 of its associated OSEK OS Counter.⌋

To synchronize the processing of the ScheduleTable it must be started at a known counter value. The implication of this is that a ScheduleTable requiring implicit synchronization must only be started at an absolute counter value and cannot be started at a relative count value.

[SWS_Os_00430] ⌈The Operating System module shall prevent a ScheduleTable that is implicitly synchronized from being started at a relative count value.⌋

When the ScheduleTable is started at an absolute counter value each expiry point will be processed when the counter equals the value specified in the service call plus expiry point's offset. The common use-case is to ensure that the offsets specified in the ScheduleTable configuration correspond to absolute values of the underlying Counter. This is achieved trivially using StartScheduleTableAbs(Tbl,0) as shown below.

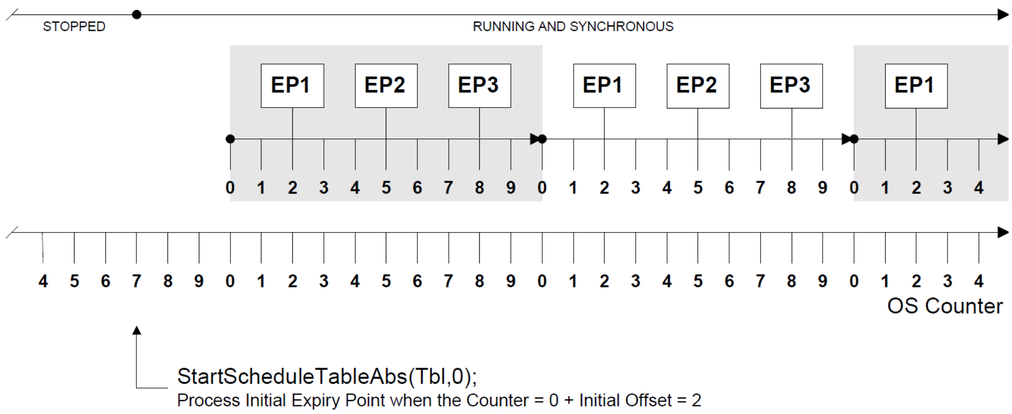

Figure 7.6: Example for implicit synchronized ScheduleTable

7.4.2.2 Explicit Synchronization

An explicitly synchronized ScheduleTable requires additional support from the Operating System module. The ScheduleTable is driven by an Operating System module's Counter as normal (termed the "drive Counter") but processing needs to be synchronized with a different Counter (termed the "synchronization Counter") which is not an Operating System module's Counter object.

The following constraints must be enforced between the ScheduleTable, the Operating System module's Counter and the synchronization Counter:

Constraint1:

[SWS_Os_00431] ⌈A ScheduleTable that is explicitly synchronized shall have a duration no greater than modulus of the drive Counter.⌋

Constraint2:

[SWS_Os_00462] ⌈A ScheduleTable that is explicitly synchronized shall have a duration equal to the modulus of the synchronization Counter.⌋

Constraint3:

[SWS_Os_00463] ⌈The synchronization Counter shall have the same resolution as the drive Counter associated with the ScheduleTable. This means that a tick on the ScheduleTable has the same duration as a tick on the synchronization Counter.⌋

Note that it is in the responsibility of the Operating System module user to verify that Constraints 2 and 3 are satisfied by their system.

The function of explicit synchronization is for the Operating System module to keep processing each expiry point at absolute value of the synchronization Counter equal to the expiry point's offset. This means that explicit synchronization always assumes that the notional zero of the ScheduleTable has to be synchronized with absolute value zero on the synchronization Counter.

To achieve this, the Operating System module must be told the value of the synchronization Counter by the user. As the modulus of the synchronization Counter and the ScheduleTable are identical, the Operating System module can use this information to calculate drift. The Operating System module then automatically adjusts the delay between specially configured expiry points, retarding them or advancing them as appropriate, to ensure that synchronization is maintained.

7.4.2.2.1 Startup

There are two options for starting an explicitly synchronized ScheduleTable:

1. Asynchronous start: Start the ScheduleTable at an arbitrary value of the synchronization Counter.
2. Synchronous start: Start the ScheduleTable at absolute value zero of the synchronization Counter only after a synchronization count has been provided. This may mean waiting for first synchronization indefinitely.

Asynchronous start is provided by the existing absolute and relative ScheduleTable start services. Both of these services set the point at which the initial expiry point is processed with respect to the driver Counter not the synchronization Counter. This allows the ScheduleTable to start running before the value of the synchronization Counter is known.

Synchronous start requires an additional service that starts the ScheduleTable only after the Operating System module is told the value of the synchronization Counter.

The Operating System module provides the service StartScheduleTableSynchron (see [SWS_Os_00201]) to start an explicitly synchronized ScheduleTable synchronously. The Initial Expiry Point will be processed after (Duration - Value) + Initial Offset ticks of the driver Counter have elapsed where Value is the absolute value of the synchronization Counter provided to the ScheduleTable.

[SWS_Os_00435] ⌈If an explicitly synchronized ScheduleTable was started synchronously, then the Operating System module shall guarantee that it has state "waiting" when the call of service StartScheduleTableSynchron returns.⌋

7.4.2.2.2 Providing a Synchronization Count

The Operating System module must be told the value of the synchronization Counter. Since the ScheduleTable duration is equal to the modulus of the synchronization Counter, the Operating System module can use this to determine the drift between the current count value on the ScheduleTable time and the synchronization count and decide whether (or not) any action to achieve synchronization is required.

The Operating System module provides the service SyncScheduleTable (see [SWS_Os_00199]) to provide the ScheduleTable with a synchronization count and start synchronization.

7.4.2.2.3 Specifying Synchronization Bounds

A ScheduleTable defaults to denying adjustment at all expiry points. Adjustment is allowed only when explicitly configured. The range of adjustment that the Operating System module can make at an adjustable expiry point is controlled by specifying:

- OsScheduleTableMaxShorten : the maximum value that can be subtracted from the expiry offset
- OsScheduleTableMaxLengthen: the maximum value that can be added to the expiry point offset

The following figure illustrates the behaviour depending on OsScheduleTableMaxShorten and OsScheduleTableMaxLengthen:

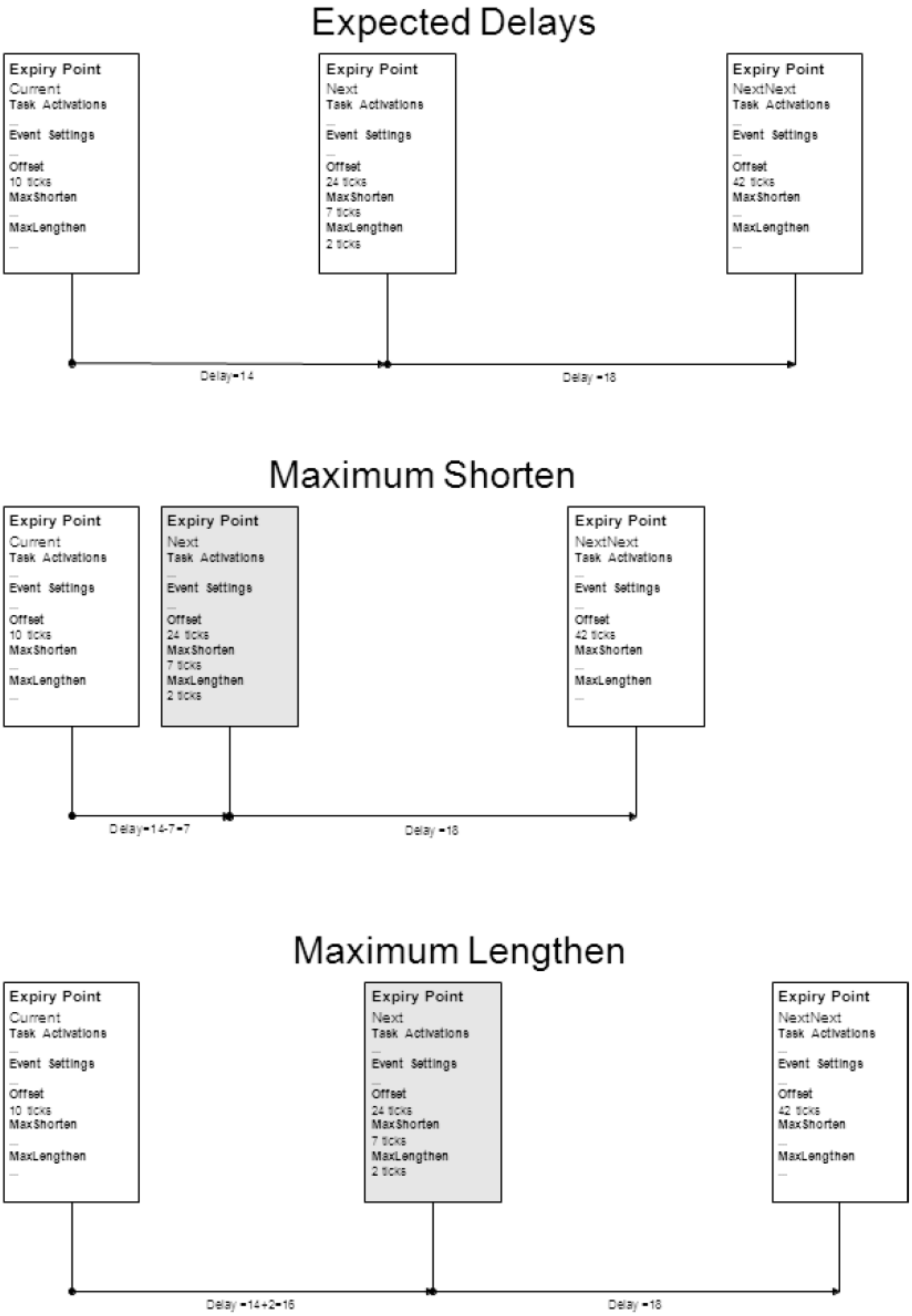

Figure 7.7: Adjustment of Expiry Points

[SWS_Os_00415] ⌈An expiry point shall permit the configuration of an `OsScheduleTableMaxShorten` that defines the maximum number of ticks that can be subtracted from expiry point offset.⌋

[SWS_Os_00416] ⌈An expiry point shall permit the configuration of an OsScheduleTableMaxLengthen that defines the maximum number of ticks that can be added to expiry point offset.⌋

When performing synchronization it is important that the expiry points on the ScheduleTable are processed according to the total ordering defined by their offsets. This means that the range of permitted values for OsScheduleTableMaxShorten and OsScheduleTableMaxLengthen must ensure that the next expiry point is not retarded into the past or advanced beyond more than one iteration of the Schedule Table.

[SWS_Os_00436] ⌈The value of (Offset - OsScheduleTableMaxShorten) of an expiry point shall be greater than (Offset + OsCounterMinCycle) of the pervious expiry point.⌋

[SWS_Os_00559] ⌈The value of OsScheduleTableMaxLengthen shall be smaller than the duration of the ScheduleTable.⌋

[SWS_Os_00437] ⌈The value of (OsScheduleTableMaxLengthen + delay_from_previous_EP) of an expiry point shall be less than the OsCounterMaxAllowedValue of the underlying Counter.⌋

Explicitly synchronized ScheduleTables allow the tolerance of some drift between the ScheduleTable value and the synchronization counter value. This tolerance can be zero, indicating that the ScheduleTable is not considered synchronized unless the values are identical.

[SWS_Os_00438] ⌈A ScheduleTable shall define a precision bound with a value in the range 0 to duration.⌋

7.4.2.3 Performing Synchronization

The Operating System module uses the synchronization count to support (re-)synchronization of a ScheduleTable at each expiry point by calculating an adjustment to the delay to the next expiry point. This provides faster re-synchronization of the ScheduleTable than doing the action on the final expiry point.

[SWS_Os_00206]

Upstream requirements: SRS_Os_11002

⌈When a new synchronization count is provided, the Operating System module shall calculate the current deviation between the explicitly synchronized scheduled table and the synchronization count.⌋

It is meaningless to try and synchronize an explicitly synchronized ScheduleTable before a synchronization count is provided.

[SWS_Os_00417] ⌈The Operating System module shall start to synchronize an explicitly synchronized ScheduleTable after a synchronization count is provided AND shall continue to adjust expiry points until synchronized.⌋

[SWS_Os_00418] ⌈The Operating System module shall set the state of an explicitly synchronized ScheduleTable to "running and synchronous" if the deviation is less than or equal to the configured OsScheduleTblExplicitPrecision threshold.⌋

[SWS_Os_00419] ⌈The Operating System module shall set the state of an explicitly synchronized ScheduleTable to "running" if the deviation is greater than the configured OsScheduleTblExplicitPrecision threshold.⌋

[SWS_Os_00420] ⌈IF the deviation is non-zero AND the next expiry point is adjustable AND the table is behind the sync Counter (TableTicksAheadOfSyncCounter <= TableTicksBehindOfSyncCounter) THEN the OS shall set the next EP to expire delay - min(MaxShorten, Deviation) ticks from the current expiry.⌋

[SWS_Os_00421] ⌈IF the deviation is non-zero AND the next expiry point is adjustable AND the table is ahead of the sync Counter (TableTicksAheadOfSyncCounter > TableTicksBehindOfSyncCounter) THEN the OS shall set the next EP to expire delay + min(MaxLengthen, Deviation) ticks from the current expiry.⌋

Figure 7.8 shows explicit synchronization of a ScheduleTable. It assumes the following:

- EP1-3 have OsScheduleTableMaxLengthen=2
- EP1-3 have OsScheduleTableMaxShorten =1

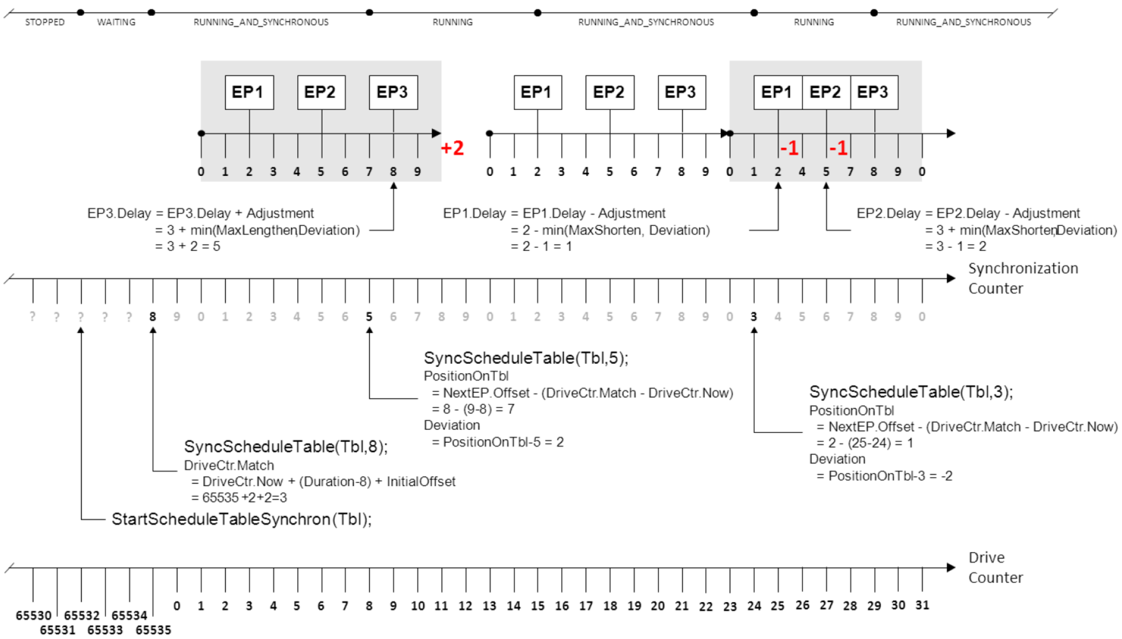

Figure 7.8: Explicit `ScheduleTable` Synchronization

The Operating System module provides the service `SetScheduleTableAsync` (see [SWS_Os_00422]) to cancel synchronization being performed at adjustable expiry points on a `ScheduleTable`.

The Operating System module provides the service `GetScheduleTableStatus` (see [SWS_Os_00227]) to query the state of a `ScheduleTable` also with respect to synchronization.

7.5 Stack Monitoring Facilities

7.5.1 Background & Rationale

On processors that do not provide any memory protection hardware it may still be necessary to provide a "best effort with available resources" scheme for detectable classes of memory faults. Stack monitoring will identify where a `Task` or `ISR` has exceeded a specified stack usage at context switch time. This may mean that there is considerable time between the system being in error and that fault being detected. Similarly, the error may have been cleared at the point the fault is notified (the stack may be less than the specified size when the context switch occurs).

It is not usually sufficient to simply monitor the entire stack space for the system because it is not necessarily the `Task`/`ISR` that was executing that used more than stack space than required - it could be a lower priority object that was pre-empted.

Significant debugging time can be saved by letting the Operating System correctly identify the `Task`/Category 2 `ISR` in error.

Note that for systems using an MPU and scalability class 3 or 4 a stack overflow may cause a memory exception before the stack monitoring is able to detect the fault.

7.5.2 Requirements

[SWS_Os_00067]

Upstream requirements: SRS_Os_11003

⌈The Operating System module shall provide a stack monitoring which detects possible stack faults of `Task`(s)/Category 2 `ISR`(s).⌋

[SWS_Os_00068]

Upstream requirements: SRS_Os_11003, SRS_Os_11013

⌈If a stack fault is detected by stack monitoring AND no `ProtectionHook` is configured, the Operating System module shall call the `ShutdownOS` service with the status `E_OS_STACKFAULT`.⌋

[SWS_Os_00396] ⌈If a stack fault is detected by stack monitoring AND a `ProtectionHook` is configured the Operating System module shall call the `ProtectionHook` with the status `E_OS_STACKFAULT`.⌋

7.6 OS-Application

7.6.1 Background & Rationale

An AUTOSAR OS must be capable of supporting a collection of Operating System objects (`Task`s, `ISR`s, `Alarm`s, `ScheduleTable`s, `Counter`s) that form a cohesive functional unit. This collection of objects is termed an OS-Application.

The Operating System module is responsible for scheduling the available processing resource between the OS-Applications that share the processor. If OS-Application(s) are used, all `Task`s, `ISR`s, `Counter`s, `Alarm`s and `ScheduleTable`s must belong to an OS-Application. All objects which belong to the same OS-Application have access to each other. The right to access objects from other OS-Applications may be granted during configuration. An `Event` is accessible if the `Task` for which the event can be set is accessible. Access means that these Operating System objects are allowed as parameters to API services.

There are two classes of OS-Application:

1. **Trusted** OS-Applications are allowed to run with monitoring or protection features disabled at runtime. They may have unrestricted access to memory, the Operating System module's API, and need not have their timing behaviour enforced at runtime. They are allowed to run in privileged mode when supported by the processor. The Operating System module assumes that trusted OS-Applications (and trusted functions) do not cause a memory related protection fault. If such a fault happens the system stability is likely gone and a shutdown may be the only option.

2. **Non-Trusted** OS-Applications are not allowed to run with monitoring or protection features disabled at runtime. They have restricted access to memory, restricted access to the Operating System module's API and have their timing behaviour enforced at runtime. They are not allowed to run in privileged mode when supported by the processor.

It is assumed that the Operating System module itself is trusted.

There are services offered by the AUTOSAR OS which give the caller information about the access rights and the membership of objects. These services are intended to be used in case of an inter-OS-Application call for checking access rights and arguments.

Note that `Resource` objects do not belong to any OS-Application, but access to them must be explicitly granted. (The same principle applies to spinlocks in Multi-Core systems)

The running OS-Application is defined as the OS-Application to which the currently running `Task` or `ISR` belongs. In case of a hook routine the `Task` or `ISR` which caused the call of the hook routine defines the running OS-Application.

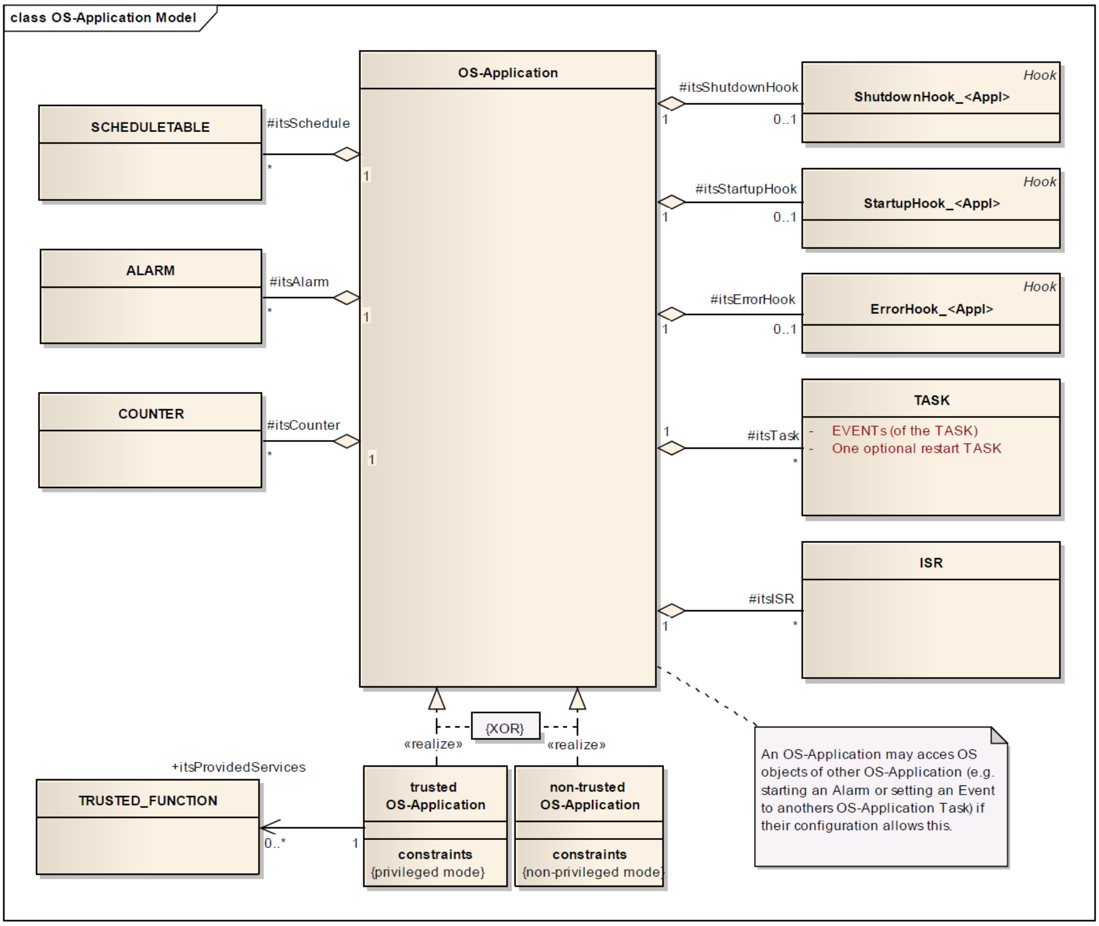

Figure 7.9: UML-model of OS-Application

OS-Applications have a state which defines the scope of accessibility of its Operating System objects from other OS-Applications. Each OS-Application is always in one of the following states:

- Active and accessible (`APPLICATION_ACCESSIBLE`): Operating System objects may be accessed from other OS-Applications. This is the default state at startup.
- Terminated and not accessible (`APPLICATION_TERMINATED`): Operating System objects cannot be accessed from other OS-Applications. State will not change.

The following figure shows the states and the possible transitions:

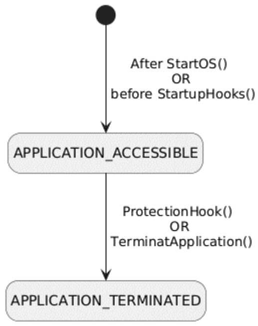

Figure 7.10: States of OS-Applications

7.6.2 Requirements

[SWS_Os_00445] ⌈The Operating System module shall support OS-Applications which are a configurable selection of Trusted Functions, Tasks, ISRs, Alarms, ScheduleTables, Counters, hooks (for startup, error and shutdown).⌋

[SWS_Os_00446] ⌈The Operating System module shall support the notion of trusted and non-trusted OS-Applications.⌋

[SWS_Os_00464] ⌈Trusted OS-Applications may offer services ("trusted services") to other (even non-trusted) OS-Applications.⌋

The Operating System module provides the services GetApplicationID and GetCurrentApplicationID (see [SWS_Os_00016]) to determine the configured resp. currently executing OS-Application (a unique identifier shall be allocated to each application).

The Operating System module provides the service CheckObjectOwnership (see [SWS_Os_00017]) to determine to which OS-Application a given Task, ISR, Counter, Alarm or ScheduleTable belongs.

The Operating System module provides the service CheckObjectAccess (see [SWS_Os_00256]) to determine which OS-Applications are allowed to use the IDs of a Task, Resource, Counter, Alarm or ScheduleTable in API calls.

The Operating System module provides the service TerminateApplication (see [SWS_Os_00258]) to terminate the OS-Application to which the calling Task/Category 2 ISR/application specific error hook belongs. (This is an OS-Application level variant of the TerminateTask service)

The Operating System provides the service TerminateApplication (see [SWS_Os_00258]) to terminate another OS-Application AND calls to this service shall be ignored if the caller does not belong to a trusted OS-Application.

[SWS_Os_00447]

Upstream requirements: SRS_Os_11022

⌈If the Operating System module terminates an OS-Application, then it shall:

- terminate all running, ready and waiting Tasks/ISRs of the OS-Application AND
- disable all interrupts of the OS-Application AND
- stop all active alarms of the OS-Applications AND
- stop all ScheduleTables of the OS-Application.

⌋

[SWS_Os_00448] ⌈The Operating System module shall prevent access of OS-Applications, trusted or non-trusted, to objects not belonging to this OS-Application, except access rights for such objects are explicitly granted by configuration.⌋

The Operating System provides the service GetApplicationState (see [SWS_Os_00499]) to request the current state of an OS-Application.

[SWS_Os_00500] ⌈The Operating System module shall set the state of all OS-Applications after the call of StartOS and before any StartupHook is called to APPLICATION_ACCESSIBLE.⌋

[SWS_Os_00502] ⌈If an OS-Application is terminated (e.g. through a service call or via protection hook) then the Operating System module shall set the state of this OS-Application to APPLICATION_TERMINATED.⌋

[SWS_Os_00504] ⌈The Operating System module shall deny access to Operating System objects from other OS-Applications to an OS-Application which is not in state APPLICATION_ACCESSIBLE.⌋

[SWS_Os_00509] ⌈If a service call is made on an Operating System object that is owned by another OS-Application without state APPLICATION_ACCESSIBLE, then the Operating System module shall return E_OS_ACCESS.⌋

An example for [SWS_Os_00509] is a call to ActivateTask for a Task in an OS-Application that already terminated.

7.7 Protection Facilities

Protection is only possible for Operating System managed objects. This means that:

- It is not possible to provide protection during runtime of Category 1 ISRs, because the operating system is not aware of any Category 1 ISRs being invoked. Therefore, if any protection is required, Category 1 ISRs have to be avoided. If Category 1 interrupts AND OS-Applications are used together then all Category 1 ISR must belong to a trusted OS-Application.
- It is not possible to provide protection between functions called from the body of the same Task/Category 2 ISR.

7.7.1 Memory Protection

7.7.1.1 Background & Rationale

Memory protection will only be possible on processors that provide hardware support for memory protection.

The memory protection scheme is based on the (data, code and stack) sections of the executable program.

Stack: An OS-Application comprises a number of Tasks and ISRs. The stack for these objects, by definition, belongs only to the owner object and there is therefore no need to share stack data between objects, even if those objects belong to the same OS-Application.

Memory protection for the stacks of Tasks and ISRs is useful mainly for two reasons:

1. Provide a more immediate detection of stack overflow and underflow for the Task or ISR than can be achieved with stack monitoring
2. Provide protection between constituent parts of and OS-Application, for example to satisfy some safety constraints.

Data: OS-Applications can have private data sections and Tasks/ISRs can have private data sections. OS-Application's private data sections are shared by all Tasks/ISRs belonging to that OS-Application.

Code: Code sections are either private to an OS-Application or can be shared between all OS-Applications (to use shared libraries). In the case where code protection is not used, executing incorrect code will eventually result in a memory, timing or service violation.

7.7.1.2 Requirements

Data Sections and Stack

[SWS_Os_00198] ⌈The Operating System module shall prevent write access to its own data sections and its own stack from non-trusted OS-Applications.⌋

[SWS_Os_00795]

Upstream requirements: SRS_Os_11005

⌈The OS shall offer the possibility to restrict write access of trusted OS-Applications in the same way as it is done for non-trusted OS-Applications.⌋

This can be configured with the `OsTrustedApplicationWithProtection`.

Private data of an OS-Application

[SWS_Os_00026]

Upstream requirements: SRS_Os_11000

⌈The Operating System module may prevent read access to an OS-Application's data section attempted by other non-trusted OS-Applications.⌋

[SWS_Os_00086]

Upstream requirements: SRS_Os_11006

⌈The Operating System module shall permit an OS-Application read and write access to that OS-Application's own private data sections.⌋

[SWS_Os_00207]

Upstream requirements: SRS_Os_11005

⌈The Operating System module shall prevent write access to the OS-Application's private data sections from other non-trusted OS-Applications.⌋

Private Stack of `Task`/`ISR`

[SWS_Os_00196]

Upstream requirements: SRS_Os_11006

⌈The Operating System module shall permit a `Task`/Category 2 `ISR` read and write access to that `Task`'s/Category 2 `ISR`'s own private stack.⌋

[SWS_Os_00208]

Upstream requirements: SRS_Os_11005

⌈The Operating System module may prevent write access to the private stack of `Task`s/Category 2 `ISR`s of a non-trusted application from all other `Task`s/`ISR`s in the same OS-Application.⌋

[SWS_Os_00355] ⌈The Operating System module shall prevent write access to all private stacks of `Task`s/Category 2 `ISR`s of an OS-Application from other non-trusted OS-Applications.⌋

Private data of a Task/ISR

[SWS_Os_00087]

Upstream requirements: SRS_Os_11006

⌈The Operating System module shall permit a Task/Category 2 ISR read and write access to that Task's/Category 2 ISR's own private data sections.⌋

[SWS_Os_00195]

Upstream requirements: SRS_Os_11005

⌈The Operating System module may prevent write access to the private data sections of a Task/Category 2 ISR of a non-trusted application from all other Tasks/ISRs in the same OS-Application.⌋

[SWS_Os_00356] ⌈The Operating System module shall prevent write access to all private data sections of a Task/Category 2 ISR of an OS-Application from other non-trusted OS-Applications.⌋

Code Sections

[SWS_Os_00027] ⌈The Operating System module may provide an OS-Application the ability to protect its code sections against executing by non-trusted OS-Applications.⌋

[SWS_Os_00081]

Upstream requirements: SRS_Os_11007

⌈The Operating System module shall provide the ability to provide shared library code in sections that are executable by all OS-Applications.⌋

Peripherals

[SWS_Os_00209] ⌈If OsTrustedApplicationWithProtection == FALSE then the Operating System module shall permit trusted OS-Applications read and write access to peripherals.⌋

[SWS_Os_00083] ⌈The Operating System module shall allow non-trusted OS-Applications to write to their assigned peripherals only (incl. reads that have the side effect of writing to a memory location).⌋

Memory Access Violation

[SWS_Os_00044]

Upstream requirements: SRS_Os_11013

⌈If a memory access violation is detected, the Operating System module shall call the ProtectionHook with status code E_OS_PROTECTION_MEMORY.⌋

7.7.2 Timing Protection

7.7.2.1 Background & Rationale

A timing fault in a real-time system occurs when a Task or interrupt misses its deadline at runtime.

AUTOSAR OS does not offer deadline monitoring for timing protection. Deadline monitoring is insufficient to correctly identify the Task/ISR causing a timing fault in an AUTOSAR system. When a deadline is violated this may be due to a timing fault introduced by an unrelated Task/ISR that interferes/blocks for too long. The fault in this case lies with the unrelated Task/ISR and this will propagate through the system until a Task/ISR misses its deadline. The Task/ISR that misses a deadline is therefore not necessarily the Task/ISR that has failed at runtime, it is simply the earliest point that a timing fault is detected.

If action is taken based on a missed deadline identified with deadline monitoring this would potentially use false evidence of error to terminate a correct OS-Application in favor of allowing an incorrect OS-Application to continue running. The problem is best illustrated by example. Consider a system with the following configuration:

TaskID	Priority	Execution Time	Deadline (=Period)
A	High	1	5
B	Medium	3	10
C	Low	5	15

Assuming that all Tasks are ready to run at time zero, the following execution trace would be expected and all Tasks would meet their respective deadlines.

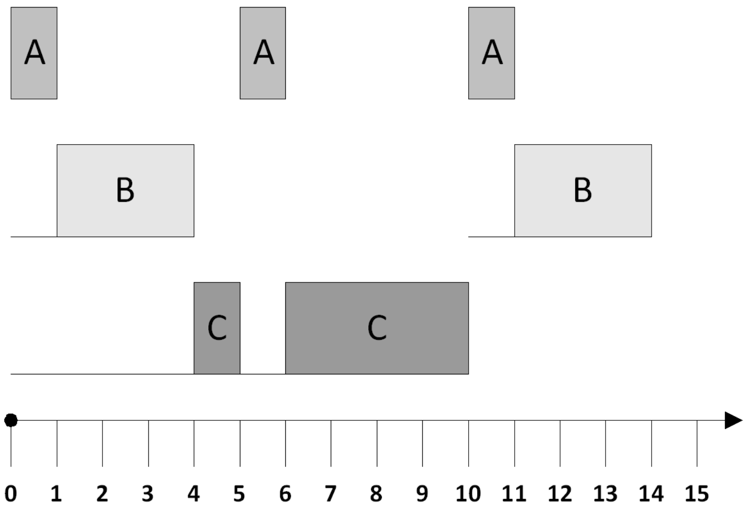

Figure 7.11: Example execution trace

Now consider the case when `Task`s A and B behave incorrectly. The figure below shows both `Task` A and `Task` B executing for longer than specified and `Task` B arriving 2 ticks earlier than specified. Both `Task`s A and B meet their deadlines. `Task` C however, behaves correctly but it fails to meet its deadline because of the incorrect execution of `Task`s A and B. This is fault propagation - a fault in an unrelated part of the system is causing a correctly functioning part of the system to fail.

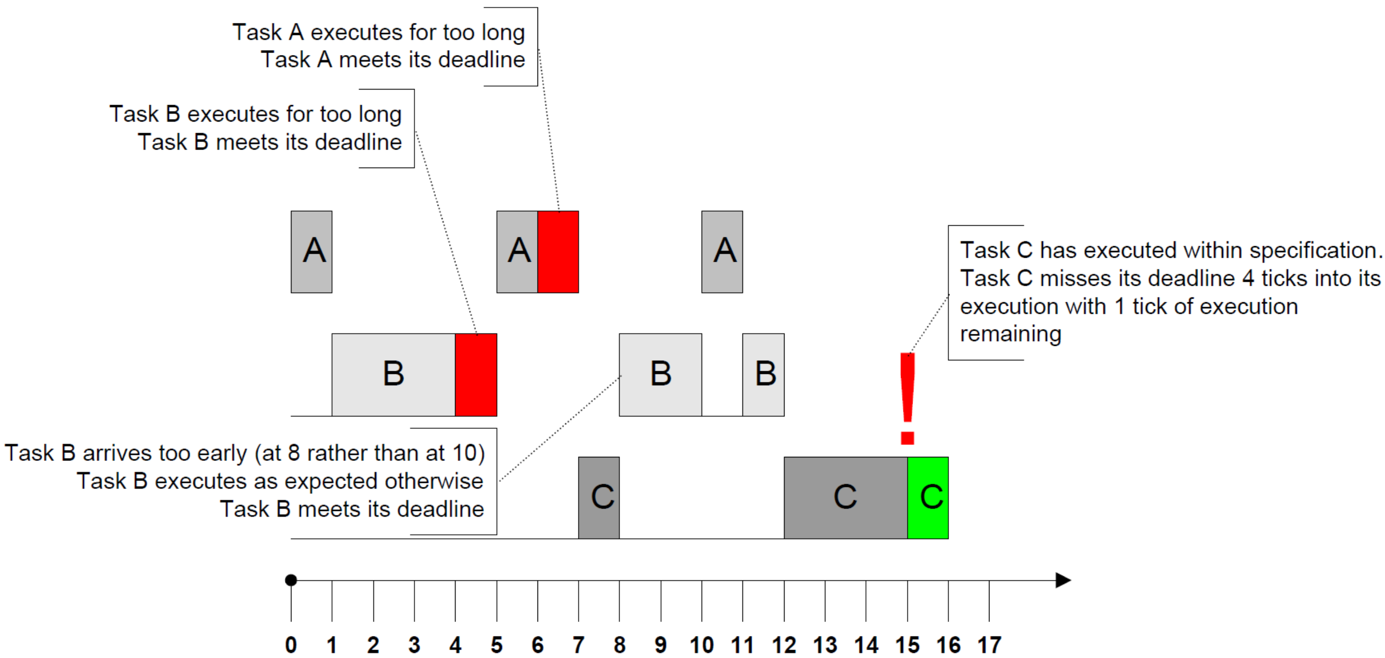

Figure 7.12: Insufficiency of Deadline Monitoring

Whether a `Task` or `ISR` meets its deadline in a fixed priority preemptive operating system like AUTOSAR OS is determined by the following factors:

- the execution time of Task/ISRs in the system
- the blocking time that Task/ISRs suffers from lower priority Tasks/ISRs locking shared resources or disabling interrupts
- the interarrival rate of Task/ISRs in the system

For safe and accurate timing protection it is necessary for the operating system to control these factors at runtime to ensure that Tasks/ISRs can meet their respective deadlines.

AUTOSAR OS prevents timing errors from (1) by using *execution time protection* to guarantee a statically configured upper bound, called the Execution Budget, on the execution time of:

- Tasks
- Category 2 ISRs

AUTOSAR OS prevents timing errors from (2) by using *locking time protection* to guarantee a statically configured upper bound, called the Lock Budget, on the time that:

- Resources are held by Tasks/Category 2 ISRs
- OS interrupts are suspended by Tasks/Category 2 ISRs
- ALL interrupts are suspended/disabled by Tasks/Category 2 ISRs

AUTOSAR OS prevents timing errors from (3) by using *inter-arrival time protection* to guarantee a statically configured lower bound, called the Time Frame, on the time between:

- A Task being permitted to transition into the READY state due to:
  - Activation (the transition from the SUSPENDED to the READY state)
  - Release (the transition from the WAITING to the READY state)
- A Category 2 ISR arriving. An arrival occurs when the Category 2 ISR is recognized by the OS

Inter-arrival time protection for basic Tasks controls the time between successive activations, irrespective of whether activations are queued or not. In the case of queued activations, activating a basic Task which is in the READY or RUNNING state is a new activation because it represents the activation of a new instance of the Task. Inter-arrival time protection therefore interacts with queued activation to control the rate at which the queue is filled.

Inter-arrival time protection for extended Tasks controls the time between successive activations and releases. When a Task is in the WAITING state and multiple Events are set with a single call to SetEvent this represents a single release. When a Task waits for one or more Events which are already set this represents a notional Wait/Release/Start transition and therefore is considered as a new release.

The following figure shows how execution time protection and inter-arrival time protection interact with the task state transition model for AUTOSAR OS.

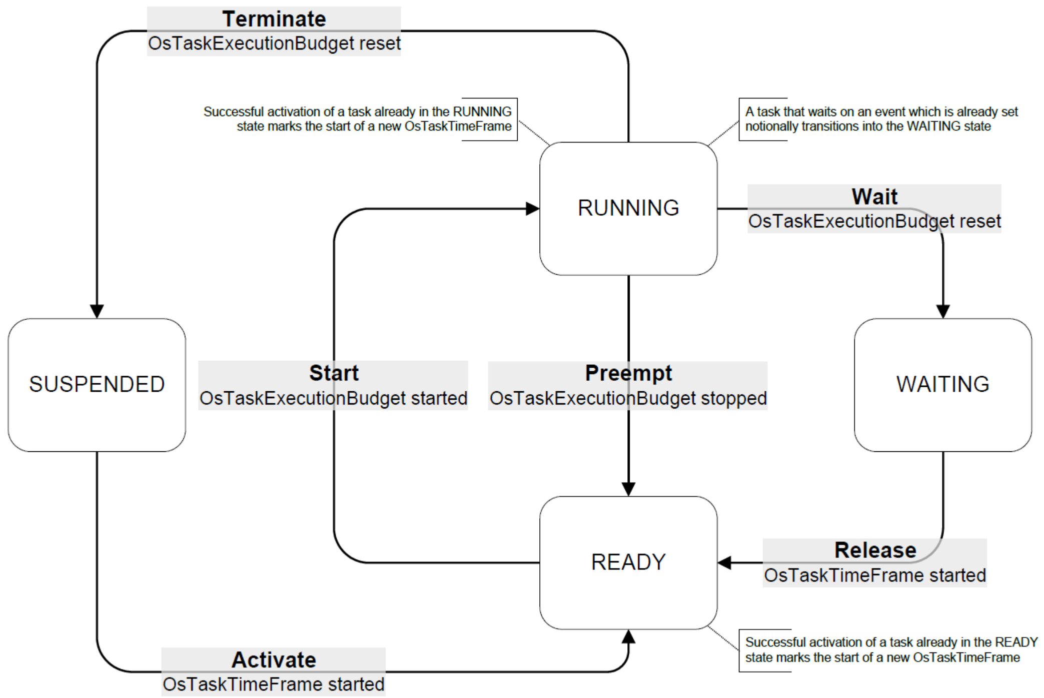

Figure 7.13: Time protection interaction with the task state transition model

Notes:

1. Inter-arrival time enforcement on Category 2 `ISR`s can be used to protect an ECU from a "babbling idiot" source of interrupts (e.g. a CAN controller taking an interrupt each time a frame is received from another ECU on the network).
2. Timing protection only applies to `Task`s or Category 2 `ISR`s. There is no protection for Category 1 `ISR`s. If timing protection error occurs during a category 1 `ISR`, consistency of the Operating System module cannot be guaranteed. Therefore we discourage timing protection in systems with category 1 interrupts.
3. Timing protection does not apply before the Operating System module is started.
4. In the case of trusted OS-Applications it is essential that all timing information is correct, otherwise the system may fail at run-time. For a non-trusted OS-Application, timing protection can be used to enforce timing boundaries between executable objects.

7.7.2.2 Requirements

[SWS_Os_00028]

Upstream requirements: SRS_Os_11008

⌈In a non-trusted OS-Application, the Operating System module shall apply timing protection to every Task/Category 2 ISR of this non-trusted OS-Application.⌋

[SWS_Os_00089]

Upstream requirements: SRS_Os_11008

⌈In a trusted OS-Application, the Operating System module shall provide the ability to apply timing protection to Tasks/Category 2 ISRs of this OS-Application.⌋

[SWS_Os_00397] ⌈If no OS-Application is configured, the Operating System module shall be able to apply timing protection to Tasks/Category 2 ISRs.⌋

Timing Protection: Tasks

[SWS_Os_00064]

Upstream requirements: SRS_Os_11008, SRS_Os_11013

⌈If a Task's OsTaskExecutionBudget is reached then the Operating System module shall call the ProtectionHook with E_OS_PROTECTION_TIME.⌋

[SWS_Os_00473]

Upstream requirements: SRS_Os_11008

⌈The Operating System module shall reset a Task's OsTaskExecutionBudget on a transition to the SUSPENDED or WAITING states.⌋

[SWS_Os_00465]

Upstream requirements: SRS_Os_11008

⌈The Operating System module shall limit the inter-arrival time of Tasks to one per OsTaskTimeFrame.⌋

[SWS_Os_00469]

Upstream requirements: SRS_Os_11008

⌈The Operating System module shall start an OsTaskTimeFrame when a Task is activated successfully.⌋

[SWS_Os_00472]

Upstream requirements: SRS_Os_11008

⌈The Operating System module shall start an OsTaskTimeFrame when a Task is released successfully.⌋

[SWS_Os_00466] ⌈If an attempt is made to activate a Task before the end of an OsTaskTimeFrame then the Operating System module shall not perform the activation AND shall call the ProtectionHook with E_OS_PROTECTION_ARRIVAL.⌋

[SWS_Os_00467] ⌈If an attempt is made to release a Task before the end of an OsTaskTimeFrame then the Operating System module shall not perform the release AND shall call the ProtectionHook with E_OS_PROTECTION_ARRIVAL.⌋

Timing Protection: ISRs

[SWS_Os_00210]

Upstream requirements: SRS_Os_11013

⌈If a Category 2 ISR's OsIsrExecutionBudget is reached then the Operating System module shall call the ProtectionHook with E_OS_PROTECTION_TIME.⌋

[SWS_Os_00474]

Upstream requirements: SRS_Os_11008

⌈The Operating System module shall reset an ISR's OsIsrExecutionBudget when the ISR returns control to the OS or terminates.⌋

[SWS_Os_00470]

Upstream requirements: SRS_Os_11008

⌈The Operating System module shall limit the inter-arrival time of Category 2 ISRs to one per OsIsrTimeFrame.⌋

[SWS_Os_00471]

Upstream requirements: SRS_Os_11008

⌈The Operating System module shall measure the start of an OsIsrTimeFrame from the point at which it recognizes the interrupt (i.e. in the Operating System interrupt wrapper).⌋

[SWS_Os_00048]

Upstream requirements: SRS_Os_11008

⌈If Category 2 interrupt occurs before the end of the OsIsrTimeFrame then the Operating System module shall not execute the user provided ISR AND shall call the ProtectionHook with E_OS_PROTECTION_ARRIVAL.⌋

Timing Protection: Resource Locking and Interrupt Disabling

[SWS_Os_00033]

Upstream requirements: SRS_Os_11008, SRS_Os_11013, SRS_Os_11014

⌈If a Task/Category 2 ISR holds an OSEK Resource and exceeds the OsTaskResourceLockBudget (or OsIsrResourceLockBudget) , the Operating System module shall call the ProtectionHook with E_OS_PROTECTION_LOCKED.⌋

[SWS_Os_00037]

Upstream requirements: SRS_Os_11008, SRS_Os_11013, SRS_Os_11014

⌈If a Task/Category 2 ISR disables interrupts (via Suspend/Disable|All/OS|Interrupts()) and exceeds the configured OsIsrAllInterruptLockBudget (or OsIsrOsInterruptLockBudget or OsTaskAllInterruptLockBudget or OsTaskOsInterruptLockBudget) the Operating System module shall call the ProtectionHook with E_OS_PROTECTION_LOCKED.⌋

7.7.2.3 Implementation Notes

Execution time enforcement requires hardware support, e.g. a timing enforcement interrupt. If an interrupt is used to implement the time enforcement, the priority of this interrupt has to be high enough to "interrupt" the supervised Tasks or ISRs.

Depending on the real hardware support this could mean that DisableAllInterrupts and SuspendAllInterrupts disable not all interrupts (e.g. all interrupts except of the interrupt used for timing protection) or that the usage of Category 1 ISRs - which bypass the Operating System (and also the timing protection) - is limited somehow.

The implementation has to document such implementation specific behaviour (e.g. the limitations when timing protection is used).

7.7.3 Service Protection

7.7.3.1 Background & Rationale

As OS-Applications can interact with the Operating System module through services, it is essential that the service calls will not corrupt the Operating System module itself. Service Protection guards against such corruption at runtime.

There are a number of cases to consider with Service Protection: An OS-Application makes an API call

1. with an invalid handle or out of range value.
2. in the wrong context, e.g. calling `ActivateTask` in the `StartupHook`.
3. or fails to make an API call that results in the OSEK OS being left in an undefined state, e.g. it terminates without a `ReleaseResource` call
4. that impacts on the behaviour of every other OS-Application in the system, e.g. `ShutdownOS`
5. to manipulate Operating System objects that belong to another OS-Application (to which it does not have the necessary permissions), e.g. an OS-Application tries to execute `ActivateTask` on a `Task` it does not own.

The OSEK OS already provides some service protection through the status codes returned from service calls and this will provide the basis for service protection. This means that service protection will only apply for the extended status of OSEK OS.

However, OSEK OS does not cover all the cases outlined above. The following sections describe - besides the mandatory extended status - the additional protection requirements to be applied in each of these cases.

7.7.3.2 Invalid Object Parameter or Out of Range Value

7.7.3.2.1 Background & Rationale

The current OSEK OS service calls already return `E_OS_ID` on invalid objects (i.e. objects not defined in the OIL file) and `E_OS_VALUE` for out of range values (e.g. setting an alarm cycle time less than `OsCounterMinCycle`).

7.7.3.2.2 Requirements

[SWS_Os_00051]

Upstream requirements: SRS_Os_11009, SRS_Os_11013

⌈If an invalid address (address is not writable by this OS-Application) is passed as an out-parameter to an Operating System service, the Operating System module shall return the status code `E_OS_ILLEGAL_ADDRESS`.⌋

7.7.3.3 Service Calls Made from Wrong Context

7.7.3.3.1 Background & Rationale

The current OSEK OS defines the valid calling context for service calls (see [2]), however protects against only a small set of these invalid calls, e.g. calling `TerminateTask` from a Category 2 `ISR`.

Service	`Task`	Cat1 `ISR`	Cat2 `ISR`	ErrorHook	Pre/PostTaskHook	StartupHook	ShutdownHook	`Alarm` Callback	ProtectionHook	inside trusted function
ActivateTask	OK		OK							OK
ActivateTaskAsyn	OK		OK							OK
TerminateTask	OK		C							
ChainTask	OK		C							
Schedule	OK		C							
GetTaskID	OK		OK	OK	OK				OK	OK
GetTaskState	OK		OK	OK	OK					OK
DisableAllInterrupts	OK	OK	OK	OK	OK	OK	OK	OK	OK	OK
EnableAllInterrupts	OK	OK	OK	OK	OK	OK	OK	OK	OK	OK
SuspendAllInterrupts	OK	OK	OK	OK	OK	OK	OK	OK	OK	OK
ResumeAllInterrupts	OK	OK	OK	OK	OK	OK	OK	OK	OK	OK
SuspendOSInterrupts	OK	OK	OK	OK	OK	OK	OK	OK	OK	OK
ResumeOSInterrupts	OK	OK	OK	OK	OK	OK	OK	OK	OK	OK
GetResource	OK		OK							OK
ReleaseResource	OK		OK							OK
SetEvent	OK		OK							OK
SetEventAsyn	OK		OK							OK
ClearEvent	OK		C							
GetEvent	OK		OK	OK	OK					OK
WaitEvent	OK		C							
GetAlarmBase	OK		OK	OK	OK					OK
GetAlarm	OK		OK	OK	OK					OK

▽

△

SetRelAlarm	OK		OK							OK
SetAbsAlarm	OK		OK							OK
CancelAlarm	OK		OK							OK
GetActiveApplicationMode	OK		OK	OK	OK	OK	OK			OK
StartOS										
ShutdownOS	OK		OK	OK		OK				OK
GetApplicationID	OK		OK	OK	OK	OK	OK		OK	OK
GetISRID	OK		OK	OK					OK	OK
CallTrustedFunction	OK		OK							OK
CheckISRMemoryAccess	OK		OK	OK					OK	OK
CheckTaskMemoryAccess	OK		OK	OK					OK	OK
CheckObjectAccess	OK		OK	OK					OK	OK
CheckObjectOwnership	OK		OK	OK					OK	OK
StartScheduleTableRel	OK		OK							OK
StartScheduleTableAbs	OK		OK							OK
StopScheduleTable	OK		OK							OK
NextScheduleTable	OK		OK							OK
StartScheduleTableSynchron	OK		OK							OK
SyncScheduleTable	OK		OK							OK
GetScheduleTableStatus	OK		OK							OK
SetScheduleTableAsync	OK		OK							OK
IncrementCounter	OK		OK							OK
GetCounterValue	OK		OK							OK
GetElapsedValue	OK		OK							OK
TerminateApplication	OK		OK	OK[1]						
GetApplicationState	OK		OK	OK	OK	OK	OK		OK	OK
ControlIdle	OK		OK							OK
GetCurrentApplicationID	OK		OK	OK	OK	OK	OK		OK	OK
ReadPeripheral8	OK		OK							OK
ReadPeripheral16	OK		OK							OK
ReadPeripheral32	OK		OK							OK
WritePeripheral8	OK		OK							OK
WritePeripheral16	OK		OK							OK
WritePeripheral32	OK		OK							OK
ModifyPeripheral8	OK		OK							OK
ModifyPeripheral16	OK		OK							OK
ModifyPeripheral32	OK		OK							OK
DisableInterruptSource	OK		OK							OK
EnableInterruptSource	OK		OK							OK
ClearPendingInterrupt	OK		OK							
isOsStarted	OK	OK	OK	OK	OK	OK	OK	OK	OK	OK

Table 7.1: Allowed Calling Context for OS Service Calls

In the table above "C" indicates that validity is only "Checked in Extended status by `E_OS_CALLEVEL`".

[1] Only in case of self termination.

7.7.3.3.2 Requirements

[SWS_Os_00088]

Upstream requirements: SRS_Os_11009, SRS_Os_11013

⌈If an OS-Application makes a service call from the wrong context AND is currently not inside a Category 1 ISR the Operating System module shall not perform the requested action (the service call shall have no effect) and return E_OS_CALLEVEL or the "invalid value" of the service.⌋

7.7.3.4 Services with Undefined Behaviour

7.7.3.4.1 Background & Rationale

There are a number of situations where the behaviour of OSEK OS is undefined in extended status. This is unacceptable when protection is required as it would allow the Operating System module to be corrupted through its own service calls. The implementation of service protection for the Operating System module must therefore describe and implement a behaviour that does not jeopardize the integrity of the system or of any OS-Application which did not cause the specific error.

7.7.3.4.2 Requirements

Tasks ends without calling a TerminateTask or ChainTask

[SWS_Os_00052]

Upstream requirements: SRS_Os_11009

⌈If a Task returns from its entry function without making a TerminateTask or ChainTask call, the Operating System module shall terminate the Task (and call the OsPostTaskHook if configured).⌋

[SWS_Os_00069]

Upstream requirements: SRS_Os_11009

⌈If a Task returns from its entry function without making a TerminateTask or ChainTask call AND the error hook is configured, the Operating System module shall call the ErrorHook (this is done regardless of whether the Task causes other errors, e.g. E_OS_RESOURCE) with status E_OS_MISSINGEND before the Task leaves the RUNNING state.⌋

[SWS_Os_00070]

Upstream requirements: SRS_Os_11009, SRS_Os_11013

⌈If a Task returns from the entry function without making a TerminateTask or ChainTask call and still holds OSEK Resources, the Operating System module shall release them.⌋

[SWS_Os_00239] ⌈If a Task returns from the entry function without making a TerminateTask or ChainTask call and interrupts are still disabled, the Operating System module shall enable them.⌋

Category 2 ISR ends with locked interrupts or allocated resources

[SWS_Os_00368] ⌈If a Category 2 ISR calls DisableAllInterrupts / SuspendAllInterrupts / SuspendOSInterrupts and ends (returns) without calling the corresponding EnableAllInterrupts / ResumeAllInterrupts / ResumeOSInterrupts, the Operating System module shall perform the missing service and shall call the ErrorHook (if configured) with the status E_OS_DISABLEDINT.⌋

[SWS_Os_00369] ⌈If a Category 2 ISR calls GetResource and ends (returns) without calling the corresponding ReleaseResource, the Operating System module shall perform the ReleaseResource call and shall call the ErrorHook (if configured) with the status E_OS_RESOURCE (see [12], section 13.1).⌋

PostTaskHook called during ShutdownOS

[SWS_Os_00071] ⌈If the PostTaskHook is configured, the Operating System module shall not call the hook if ShutdownOS is called.⌋

Tasks/ISRs calls EnableAllInterrupts/ResumeAllInterrupts/ResumeOSInterrupts without a corresponding disable

[SWS_Os_00092]

Upstream requirements: SRS_Os_11009

⌈If EnableAllInterrupts / ResumeAllInterrupts / ResumeOSInterrupts are called and no corresponding DisableAllInterrupts / SuspendAllInterrupts / SuspendOSInterrupts was done before, the Operating System module shall not perform this Operating System service.⌋

Tasks/ISRs calling OS services when DisableAllInterupts/SuspendAllInterrupts/SuspendOSInterrupts called

[SWS_Os_00093]

Upstream requirements: SRS_Os_11009, SRS_Os_11013

⌈If interrupts are disabled/suspended by a Task/ISR/Hook and the Task/ISR/Hook calls any Operating System service (excluding the interrupt services) then the Operating System module shall ignore the service AND shall return E_OS_DISABLEDINT if the service returns a StatusType value.⌋

7.7.3.5 Service Restrictions for Non-Trusted OS-Applications

7.7.3.5.1 Background & Rationale

The Operating System service calls available are restricted according to the calling context (see 7.7.3.3). In a protected system, additional constraints need to be placed to prevent non-trusted OS-Applications executing API calls that can have a global effect on the system. Each level of restriction is a proper subset of the previous level as shown in the figure below.

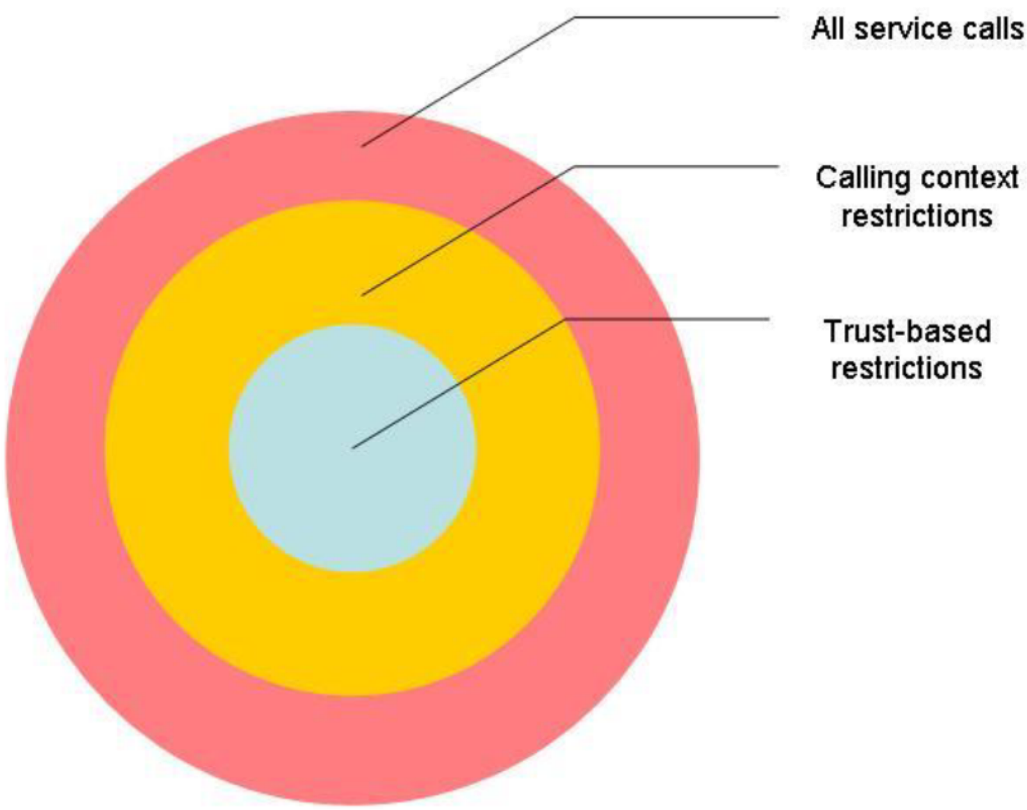

Figure 7.14: API Restrictions

There are two defined integrity levels:

1. Trusted
2. Non-Trusted

that correspond exactly with trusted and non-trusted OS-Applications.

7.7.3.5.2 Requirements

[SWS_Os_00054] ⌈The Operating System module shall ignore calls to ShutdownOS from non-trusted OS-Applications.⌋

7.7.3.6 Service Calls on Objects in Different OS-Applications

7.7.3.6.1 Background

Section 7.7.3.2 stated that E_OS_ID is returned by OSEK OS service calls when the object is invalid. Under the protection scheme a service call can be invalid because the caller does not have valid permissions for the object (a new meaning for multi-OS-Application systems).

This is a similar case to an object not being accessible in OSEK OS (for example, when a Task tries to get a Resource which exists in the system but has not been configured as used by the Task).

7.7.3.6.2 Requirements

[SWS_Os_00056]

Upstream requirements: SRS_Os_11001, SRS_Os_11010, SRS_Os_11013

⌈If an OS-object identifier is the parameter of an Operating System module's system service, and no sufficient access rights have been assigned to this OS-object at configuration time (parameter Os[...]AccessingApplication, e.g. OsTaskAccessingApplication) to the calling Task/Category 2 ISR, the Operating System module's system service shall return E_OS_ACCESS.⌋

[SWS_Os_00449] ⌈CheckTaskMemoryAccess and CheckISRMemoryAccess check the memory access. Memory access checking is possible for all OS-Applications and from all OS-Applications and does not need granted rights.⌋

[SWS_Os_00449] is an exception to [SWS_Os_00056].

[SWS_Os_00450] ⌈CheckObjectAccess checks the access rights for Operating System objects. Checking object access is possible for all OS-Applications and from all OS-Applications and does not need granted rights.⌋

[SWS_Os_00450] is an exception to [SWS_Os_00056].

7.7.4 Protecting the Hardware used by the OS

7.7.4.1 Background & Rationale

Where a processor supports privileged and non-privileged mode it is usually the case that certain registers, and the instructions to modify those registers, are inaccessible outside the privileged mode.

On such hardware, executing the Operating System module in privileged mode and Tasks/ISRs in non-privileged mode protects the registers fundamental to Operating System module operation from inadvertent corruption by the objects executing in non-privileged mode. The Operating System module's services will need to execute in privileged mode as they will need to modify the registers that are protected outside this mode.

The Operating System module can use the control registers of the MPU, timer unit(s), interrupt controller, etc. and therefore it is necessary to protect those registers against non-trusted OS-Applications.

7.7.4.2 Requirements

[SWS_Os_00058] ⌈If supported by hardware, the Operating System module shall execute non-trusted OS-Applications in non-privileged mode.⌋

[SWS_Os_00096]

Upstream requirements: SRS_Os_11011

⌈As far as supported by hardware, the Operating System module shall not allow non-trusted OS-Applications to access control registers managed by the Operating System module.⌋

[SWS_Os_00245]

Upstream requirements: SRS_Os_11011

⌈If an instruction exception occurs (e.g. division by zero) the Operating System module shall call the protection hook with E_OS_PROTECTION_EXCEPTION.⌋

7.7.4.3 Implementation Notes

When the Operating System module is running non-trusted OS-Applications, the Operating System module's treatment of interrupt entry and hook routines must be carefully managed.

Interrupt handling: Where the MCU supports different modes (as discussed in this section) `ISR`s will require the Operating System module to do extra work in the `ISR()` wrapper. `ISR`s will typically be entered in privileged mode. If the handler is part of a non-trusted OS-Application then the `ISR()` wrapper must make sure that a switch to non-privileged mode occurs before the handler executes.

7.7.5 Providing `Trustedfunctions`

7.7.5.1 Background & Rationale

An OS-Application can invoke a `Trustedfunction` provided by (another) trusted OS-Application. That can require a switch from non-privileged to privileged mode. This is typically achieved by these operations:

- Each trusted OS-Application may export services which are callable from other OS-Applications.
- During configuration these trusted services must be configured to be called from a non-trusted OS-Application.
- The call from the non-trusted OS-Application to the trusted service is using a mechanism (e.g. trap/software interrupt) provided by the Operating System. The service is passed as an identifier that is used to determine, in the trusted environment, if the service can be called.
- The Operating System offers services to check if a memory region is write/read/execute accessible from an OS-Application. It also returns information if the memory region is part of the stack space.

The Operating System software specification does not provide support for *non-trusted services*.

Please note: During the execution of a trusted function a protection violation or the self-termination of the calling OS-Application can be fatal. In such cases the fault reaction (e.g. restart or terminate OS-Application) impacts also the ongoing trusted function call. It is assumed that the code of the trusted function itself is free of such direct violations, but there are some cases where a violation nevertheless may occur. These are:

- **(A) Timing violation inside the trusted function:** It might happen that during the execution of a trusted function a timing violation happens. E.g. the configured execution budget of the caller is exhausted inside the trusted function. In such cases the violation can be delayed until the function returns to the non-trusted caller (see also [SWS_Os_00565].

- **(B) Parallel violations within the OS-Application which called the trusted function:** It might happen that a Task which executes the trusted function is preempted by another Task (or Category 2 ISR) of the same OS-Application. Then this other Task (or Category 2 ISR) is causing a violation, e.g. via a memory fault or a timing violation.
- **(C) Self termination of the OS-Application:** Each application can perform a self-termination, e.g. initated by another Task of the same OS-Application. In case of an ongoing trusted function call of the OS-Application this may also impact the (trusted) OS-Application which offers the trusted function.
- **(D) Foreign termination of the OS-Application:** Each trusted OS-Application can request a termination of another OS-Application. If the to be terminated OS-Application is currently executing a trusted function it may have also impact on this trusted OS-Application. It is assumed that a (trusted) OS-Application never terminates another OS-Application with an on-going trusted function call.

Situations like (B) or (C) can be solved by avoiding preemptions in the OS-Application when a trusted function is ongoing. This can be reached by using locks which are preventing the scheduling (on the same core). The disadvantage of this approach is that it impacts the overall timing (i.e. also of other OS-Applications which use the same core). So a violation caused by another entity is avoided, but maybe at the cost of a timing violation which then may also require a restart or reset. On the other hand a careful design could solve the issue without locking, e.g. by only perfoming calls to trusted function from tasks with the highest priority of the OS-Application. Therefore the OS offers a (global) switch (see `OsLockTrustedFunctionCall`) to allow adaption of the required behaviour.

For `OsLockTrustedFunctionCall` == `TRUE` the OS will lock parallel activities of the OS-Application to avoid situations like (B) or (C).

For `OsLockTrustedFunctionCall` == `FALSE` no locks are perfomed by the OS and parallel activities may happen in the OS-Application.

7.7.5.2 Requirements

[SWS_Os_00451] ⌈The Operating System module shall allow exporting services from trusted OS-Applications.⌋

The Operating System module provides the service `CallTrustedFunction` (see [SWS_Os_00097]) to call a trusted function from a (trusted or non-trusted) OS-Application.

[SWS_Os_00100] ⌈If CallTrustedFunction is called and the called trusted function is not configured the Operating System module shall call the ErrorHook with E_OS_SERVICEID.⌋

The Operating System module provides the services CheckISRMemoryAccess and CheckTaskMemoryAccess (see [SWS_Os_00512] and [SWS_Os_00513]) for OS-Applications to check if a memory region is write/read/execute accessible from a Task/Category 2 ISR and also return information if the memory region is part of the stack space.

7.8 Protection Error Handling

7.8.1 Background & Rationale

The Operating System can detect protection errors based on statically configured information on what the constituent parts of an OS-Application can do at runtime. See section 7.7.

Unlike monitoring, protection facilities will trap the erroneous state at the point the error occurs, resulting in the shortest possible time between transition into an erroneous state and detection of the fault. The different kinds of protection errors are described in the glossary. If a protection error occurs before the Operating System module is started the behaviour is not defined. If a protection error happens during shutdown, e.g. in the application-specific shutdown hook, an endless loop between the shutdown service and the protection hook may occur.

In the case of a protection error, the Operating System module calls a user provided ProtectionHook for the notification of protection errors at runtime. The ProtectionHook runs in the context of the Operating System module and must therefore be trusted code.

The Operating System module itself needs only to detect an error and provide the ability to act. The ProtectionHook can select the right action, which will be performed after returning from the ProtectionHook, depending on the return value of the ProtectionHook. The options are:

1. do nothing
2. for arrival rate errors: do not perform the requested action (task activation / ISR 2 call / event setting)
3. forcibly terminate the faulty Task/Category 2 ISR
4. forcibly terminate all Tasks and ISRs in the faulty OS-Application
5. shutdown the Operating System module.

Requirements [SWS_Os_00243] and [SWS_Os_00244] define the order of the default reaction if no faulty Task/Category 2 ISR or OS-Application can be found, e.g. in the system specific hook routines. Also OS-Applications are only mandatory in Scalability Classes 3 and 4, therefore in other Scalability Classes OS-Applications need not be defined.

Note that forcibly terminating interrupts is handled differently in "forcibly terminate the faulty ISR" and "forcibly terminate the OS-Application". If a faulty ISR is forcibly terminated, the current invocation of the ISR is terminated. A subsequent invocation is allowed. If the OS-Application is forcibly terminated, then the interrupt source is also disabled, preventing subsequent interrupts.

Notes regarding the return value PRO_IGNORE:

The meaning of "do nothing" (PRO_IGNORE) means that the error reaction is ignored. The PRO_IGNORE is only allowed in specific situations (currently: arrival rate errors). After the error is detected (e.g. as specified in [SWS_Os_00466] or [SWS_Os_00467]) the protection hook is called. If the hook returns with PRO_IGNORE the OS does continue its normal operation. If a service call was the root cause of the violation (e.g. an ActivateTask) and protection hook returns PRO_IGNORE the service call shall continue its operation (e.g. to activate a Task) and return E_OK (if successful and possible).

Example 1: A Task calls ActivateTask(B) and causes an arrival rate violation. The activation is not performed ([SWS_Os_00466]) and protection hook is called. When returning PRO_IGNORE the OS continues and the ActivateTask service activates B and returns E_OK.

Example 2: A Task A calls SetEvent for Task B (which currently waits for the event). The OS detects ([SWS_Os_00467]) an arrival rate violation and performs a call of the protection hook. When the call returns with PRO_IGNORE, the SetEvent service continues and sets the event. Task B changes to READY state and a rescheduling might happen. The SetEvent service call will return E_OK to Task A.

Notes regarding the return value PRO_PREVENT_ARRIVAL_RATE:

The PRO_PREVENT_ARRIVAL_RATE is used to prevent arrival rate errors.

Example 1 : A Task calls ActivateTask(B) and causes an arrival rate violation. The activation is not performed ([SWS_Os_00466]) and protection hook is called. When returning PRO_PREVENT_ARRIVAL_RATE the OS will not perform the task activation (it prevents the arrival rate error). The ActivateTask service will return in such cases E_OK, so no error hooks are called.

Example 2: A Task A calls SetEvent for Task B (which currently waits for the event). The OS detects ([SWS_Os_00467]) an arrival rate violation and performs a call of the protection hook. When the call returns with PRO_PREVENT_ARRIVAL_RATE, the event setting will not be performed and the SetEvent service call will return E_OK. Also here no additional error hooks will be called.

7.8.2 Requirements

[SWS_Os_00211] ⌈The Operating System module shall execute the ProtectionHook with the same permissions as the Operating System module.⌋

[SWS_Os_00107]

Upstream requirements: SRS_Os_11014

⌈If no ProtectionHook is configured and a protection error occurs, the Operating System module shall call ShutdownOS.⌋

[SWS_Os_00106]

Upstream requirements: SRS_Os_11014

⌈If the ProtectionHook returns PRO_IGNORE and was called with E_OS_PROTECTION_ARRIVAL the Operating System module shall perfom the requested action.⌋

[SWS_Os_00863] Prevent arrival rate errors

Upstream requirements: SRS_Os_11014, SRS_Os_11008

⌈If the ProtectionHook returns PRO_PREVENT_ARRIVAL_RATE and was called with E_OS_PROTECTION_ARRIVAL the Operating System module shall not perform the action which caused the arrival rate error.⌋

[SWS_Os_00553] ⌈If the ProtectionHook returns PRO_TERMINATETASKISR the Operating System module shall forcibly terminate the faulty Task/Category 2 ISR.⌋

[SWS_Os_00554] ⌈If the ProtectionHook returns PRO_TERMINATEAPPL the Operating System module shall forcibly terminate the faulty OS-Application.⌋

[SWS_Os_00556] ⌈If the ProtectionHook returns PRO_SHUTDOWN the Operating System module shall call the ShutdownOS.⌋

[SWS_Os_00506] ⌈If the ProtectionHook is called with E_OS_PROTECTION_ARRIVAL the only valid return values are PRO_IGNORE or PRO_PREVENT_ARRIVAL_RATE or

PRO_SHUTDOWN[2]. Returning other values will result in a call to ShutdownOS.⌋

[2] The reason for this case is that the Task which is supervised is not necessary active (and can not be e.g. terminated) and it can be that the caller of the activation is the real problem.

[SWS_Os_00475] ⌈If the ProtectionHook returns PRO_IGNORE and the ProtectionHook was not called with E_OS_PROTECTION_ARRIVAL then the Operating System module shall call ShutdownOS.⌋

[SWS_Os_00243]

Upstream requirements: SRS_Os_11014

⌈If the ProtectionHook returns PRO_TERMINATETASKISR and no Task or ISR can be associated with the error, the running OS-Application is forcibly terminated by the Operating System module. If even no OS-Application can be assigned, ShutdownOS is called.⌋

[SWS_Os_00244]

Upstream requirements: SRS_Os_11014

⌈If the ProtectionHook returns PRO_TERMINATEAPPL and no OS-Application can be assigned, ShutdownOS is called.⌋

[SWS_Os_00108]

Upstream requirements: SRS_Os_11014

⌈If the Operating System module forcibly terminates a Task, it terminates the Task, releases all allocated OSEK resources and calls EnableAllInterrupts/ ResumeOSInterrupts / ResumeAllInterrupts if the Task called DisableAllInterrupts / SuspendOSInterrupts / SuspendAllInterrupts before without the corresponding EnableAllInterrupts/ ResumeOSInterrupts / ResumeAllInterrupts call.⌋

[SWS_Os_00109]

Upstream requirements: SRS_Os_11014

⌈If the Operating System module forcibly terminates an interrupt service routine, it clears the interrupt request, aborts the interrupt service routine (The interrupt source stays in the current state.) and releases all OSEK resources the interrupt service routine has allocated and calls EnableAllInterrupts / ResumeOSInterrupts / ResumeAllInterrupts if the interrupt called DisableAllInterrupts / SuspendOSInterrupts / SuspendAllInterrupts before without the corresponding EnableAllInterrupts/ ResumeOSInterrupts / ResumeAllInterrupts call.⌋

[SWS_Os_00110]

Upstream requirements: SRS_Os_11014

⌈If the Operating System module shall forcibly terminate an OS-Application, it: shall

- forcibly terminate all Tasks/ISRs of the OS-Application AND
- cancel all alarms of the OS-Application AND

- stop ScheduleTables of the OS-Application AND
- disable interrupt sources of Category 2 ISRs belonging to the OS-Application

⌋

[SWS_Os_00860]

Upstream requirements: SRS_Os_11013

⌈If the call to the ProtectionHook is caused by a trusted function which causes a E_OS_PROTECTION_EXCEPTION or E_OS_PROTECTION_MEMORY, the only valid return value shall be PRO_SHUTDOWN. Returning other values shall also result in a shutdown of the OS.⌋

7.9 Operating System for Multi-Core

This chapter specifies some extensions that allow to use an AUTOSAR system on Multi-Core micro-processors. It describes the main philosophy as well as additional extensions to the existing OS functionality regarding Multi-Core. The following chapter contains a specification of a new mechanism within the OS called IOC (Inter OS-Application Communicator) that supports the communication between OS-Applications located on the same or on different cores

7.9.1 Background & Rationale

The existing AUTOSAR-OS is based on the OSEK/VDX Operating System which is widely used in the automotive industry. The AUTOSAR Multi-Core OS is derived from the existing AUTOSAR OS.

The Multi-Core OS in AUTOSAR is not a virtual ECU concept, instead it shall be understood as an OS that shares the same configuration and most of the code but operates on different data structures for each core.

To reduce the memory footprint all cores should use the same code base. Sometimes it can be beneficial to spend some more ROM/Flash, e.g. to use a local ROM, and "double" parts of the code to get faster ROM/Flash access.

7.9.1.1 Requirements

[SWS_Os_00567]

Upstream requirements: SRS_Os_80008

⌈The generated part of the OS is derived from a single configuration that contains the relevant information for all cores. This implies, that IDs (e.g. `TaskID`, `ResourceID`, `...`) are unique across cores. Every ID shall refer exactly to one entity independent from the core on which the entity is accessed. This applies also to objects that cannot be shared between cores.⌋

7.9.2 Scheduling

The priority of the `Task`s drives the scheduling. Since multiple cores run truly parallel, several `Task`s can execute at the same time.

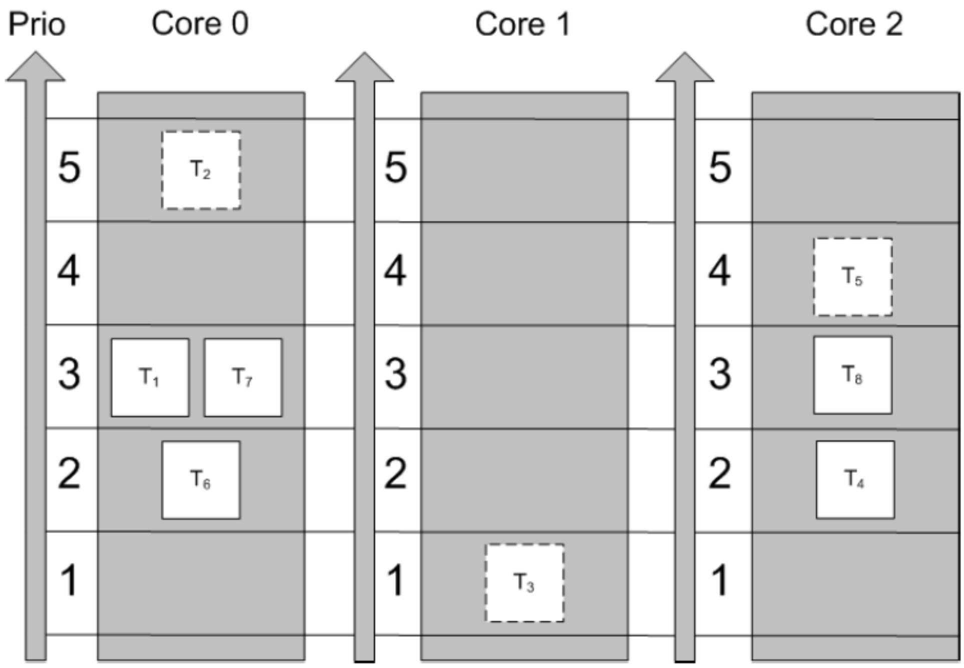

Figure 7.15: Priorities are assigned to `Tasks`. The cores schedule independently from each other. The `Tasks` T2, T3 and T5 are executed in true parallelism. `Tasks` with the same priority on the same core will be executed in order of activation; `Tasks` with the same priority on different cores may not be executed in the order of activation, since the cores schedule independent from each other.

The OS can be entered on each core in parallel. This optimizes scalability towards multiple cores. The cores schedule independently. This implies that the schedule on one core does not consider the scheduling on the other cores[3]. A low priority `Task` on one core may run in parallel with a high priority `Task` on another core.

`Task`s and `ISR`s cannot dynamically change cores by means of the scheduling algorithm.

7.9.2.1 Requirements

[SWS_Os_00568]

Upstream requirements: SRS_Os_80001

⌈Implementations shall be able to independently execute a `Task` or an `ISR` on each started AUTOSAR OS core in parallel.⌋

[SWS_Os_00569]

Upstream requirements: SRS_Os_80001, SRS_Os_80013

⌈The scheduling strategy as defined in AUTOSAR OS shall apply for each individual core in a Multi-Core system, for the `Task`s and `ISR` assigned to the core.⌋

7.9.3 Locatable entities (LE)

A locatable entity is an entity that has to be located entirely on one core. The assignment of LEs to cores is defined at configuration time (`OsAppEcucPartitionRef`).

In this release of the AUTOSAR standard OS-Applications shall be the LEs. Because every `Task` has to run on some core, the usage of OS-Applications becomes obligatory in AUTOSAR R4.0 for Multi-Core systems. BSW modules are not allowed to ignore OS-Applications, even if they do not use any protection mechanisms. This is independent from the SC class.

As is stated in the AUTOSAR Specification of the Operating System, if OS-Applications are used, all `Task`s, `ISR` etc. must belong to an OS-Application. This implies, that no AUTOSAR software exists outside of an OS-Application in Multi-Core systems.

On single-core systems OS-Applications are available only for SC3 and SC4 because the mechanism is used to support memory protection and implies the usage of extended mode. In Multi-core systems OS-Applications are always available independent of memory protection and on SC1 standard mode shall be possible.

[3] This also applies to `Task`s with the same priority, bound to different cores. It also means that non-preemptive `Task`s cannot be preempted on the core they are running, but `Task`s on other cores can run in parallel.

7.9.3.1 Requirements

[SWS_Os_00570]

Upstream requirements: SRS_Os_80003, SRS_Os_80005

⌈All Tasks that are assigned to the same OS-Application shall execute on the same core.⌋

[SWS_Os_00571]

Upstream requirements: SRS_Os_80003, SRS_Os_80005

⌈All ISRs that are assigned to the same OS-Application shall execute on the same core.⌋

[SWS_Os_00572]

Upstream requirements: SRS_Os_80005, SRS_Os_80006

⌈ISR balancing (if supported by the HW) shall be switched off at boot time by the OS.⌋

[SWS_Os_00764] ⌈The OS module shall support OS-Applications in case of Multi-Core also for SC1 and SC2.⌋

[SWS_Os_00763] ⌈In an SC1 system standard mode shall be possible.⌋

[SWS_Os_00573]

Upstream requirements: SRS_Os_80003, SRS_Os_80005

⌈The binding of OS-Applications to cores shall be derived from the referenced Ecuc-Partition.⌋

The configuration item OsAppEcucPartitionRef within the OS-Application container shall be used to define the core to which the EcucPartition and hence the OS-Application is bound. The OS generator will map the configuration parameter "CORE" to a certain core, so that all OS-Applications with the same configuration parameter reside on the same core.

7.9.4 Multi-Core start-up concept

The way cores are started depends heavily on the hardware. Typically the hardware only starts one core, referred as the master core, while the other cores (slaves) remain in halt state until they are activated by the software.

In contrast to such a master-slave system other boot concepts with cores that start independently from each other are conceivable. However it is possible to emulate master-slave behavior on such systems by software.

The AUTOSAR Multi-Core OS specification requires a system with master-slave start-up behavior, either supported directly by the hardware or emulated in software. The master core is defined to be the core that requires no software activation, whereas a slave core requires activation by software.

In Multi-Core configurations, each slave core that is used by AUTOSAR must be activated before `StartOS` is entered on the core. Depending on the hardware, it may be possible to only activate a subset of the available cores from the master. The slave cores might activate additional cores before calling `StartOS`. All cores that belong to the AUTOSAR system have to be activated by the designated AUTOSAR API function. Additionally, the `StartOS` function has to be called on all these cores.

If a core is activated it executes some HW and compiler specific operations, before the "main" function is called. In case the same "main" function is executed on each core, the cores have to be differentiated by their specific core Id within the function.

Example:

```
void main ()
{
    StatusType rv;

    /* ... */

    switch (GetCoreID())
  {

    case OS_CORE_ID_MASTER:
         /* ... */

        StartCore(OS_CORE_ID_0, &rv);
        StartOS(OSDEFAULTAPPMODE);
        break;

    case OS_CORE_ID_0:
        /* ... */

        StartCore(OS_CORE_ID_1, &rv);
        StartOS(DONOTCARE);
        break;

    otherwise:

        StartOS(DONOTCARE);

    }
}
```

StartOS synchronizes all cores twice. The first synchronization point is located before the StartupHooks are executed, the second after the OS-Application specific StartupHooks have finished and before the scheduler is started. The exact point where the second synchronization occurs depends on the implementation, but it shall be before the scheduling is started. This release of the AUTOSAR specification does not support timeouts during the synchronization phase. Cores that are activated with StartCore but do not call StartOS may cause the system to hang. It is in the responsibility of the integrator to avoid such behavior.

As shown in figure 7.16, the StartupHook is called on every core right after the first synchronization. However, there is only one StartupHook in the system. If, for example, core-individual functionality must be executed during StartupHook the GetCoreID function can be used to discriminate the individual cores. After the global StartupHook has finished each core performs the StartupHooks of its OS-Applications . Since OS-Applications are bound to cores the OS-Application specific StartupHooks are executed only on the core to which the corresponding OS-Application is bound.

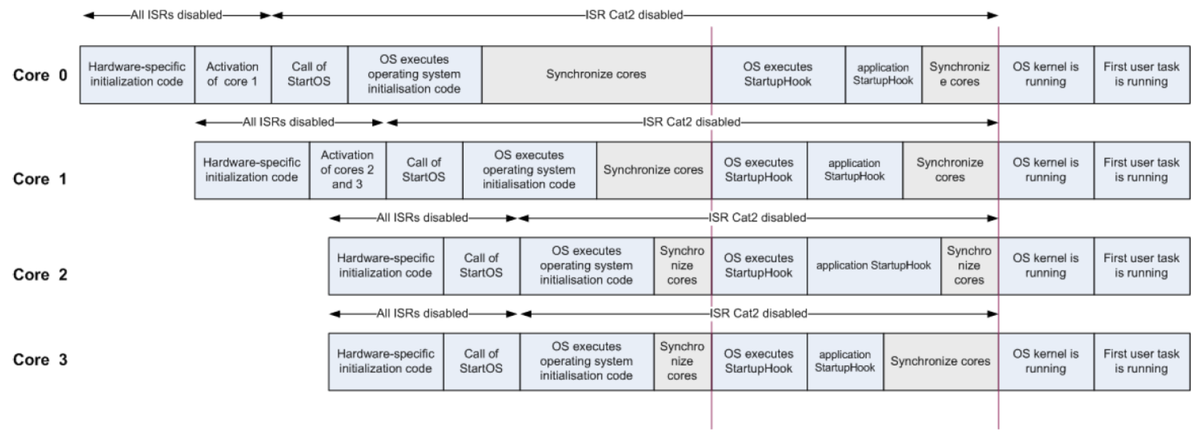

Figure 7.16: This figure shows an example of an initialization process with 4 cores

7.9.4.1 Requirements

[SWS_Os_00574]

Upstream requirements: SRS_Os_80006

⌈The master core shall be able to activate cores.⌋

[SWS_Os_00575]

Upstream requirements: SRS_Os_80006

⌈Any slave core shall be able to activate cores.⌋

[SWS_Os_00576]

Upstream requirements: SRS_Os_80006

⌈It shall be allowed to use only a subset of the cores available on a μC for the AUTOSAR system.⌋

[SWS_Os_00577]

Upstream requirements: SRS_Os_80006

⌈The cores shall boot in master-slave mode. If this is not supported by the hardware, it shall be that the cores boot in parallel and emulate the behavior of a master-slave system.⌋

[SWS_Os_00578]

Upstream requirements: SRS_Os_80006

⌈In case of an emulation a slave core (CoreS), which is controlled by the AUTOSAR OS (AUTOSAR core), shall not enter the main function before another core has activated the slave core by means of `StartCore`(CoreS).⌋

[SWS_Os_00579]

Upstream requirements: SRS_Os_80001, SRS_Os_80006

⌈All cores that belong to the AUTOSAR system shall be synchronized within the `StartOS` function before the scheduling is started and after the global `StartupHook` is called.⌋

[SWS_Os_00580]

Upstream requirements: SRS_Os_80006

⌈All cores that belong to the AUTOSAR system shall be synchronized within the `StartOS` before the global `StartupHook` is called.⌋

[SWS_Os_00581]

Upstream requirements: SRS_Os_80006

⌈The global `StartupHook` shall be called on all cores immediately after the first synchronization point.⌋

[SWS_Os_00582]

Upstream requirements: SRS_Os_80006, SRS_Os_80008

⌈The OS-Application-specific `StartupHook`s shall be called after the global `StartupHook` but only on the cores to which the OS-Application is bound.⌋

7.9.5 Cores under control of the AUTOSAR OS

The AUTOSAR OS controls several cores as stated above. It need not control all cores of a μC, however. The maximum number of controlled cores shall be configured within the OsOS section of the configuration.

The AUTOSAR OS API provides a StartCore function to start the cores under its control. The StartCore function takes a scalar value parameter of type CoreIdType, specifying the core that shall be started. StartCore can be called more than once on the master core and also on slave cores. Each core can only be started once, however. For example:

```
StartusType rv1, rv2;
StartCore(OS_CORE_ID_1, &rv1);
StartCore(OS_CORE_ID_2, &rv2);
if (rv1 != E_OK) ||  (rv2 != E_OK)
    EnterPanicMode();
StartOS(OSDEFAULTAPPMODE);
```

The StartOS function shall be called on all cores that have been activated by StartCore. It is not allowed to call StartCore from a core that has already called StartOS.

Cores that belong to the AUTOSAR system shall be started by the designated AUTOSAR OS API service StartCore.

7.9.5.1 Requirements

[SWS_Os_00583]

Upstream requirements: SRS_Os_80001, SRS_Os_80011

⌈The number of cores that can be controlled by the AUTOSAR OS shall be configured offline.

A new configuration item (OsNumberOfCores) within the OsOS container is used to specify the maximum number of cores that are controlled by the AUTOSAR OS. If no value for OsNumberOfCores has been specified the number of cores shall be one.⌋

7.9.6 Multi-Core shutdown concept

AUTOSAR supports two shutdown concepts, the synchronized shutdown and the individual shutdown concept. While the synchronized shutdown is triggered by the new API function ShutdownAllCores, the individual shutdown is invoked by the existing API function ShutdownOS.

7.9.6.1 Synchronized shutdown concept

If a Task with the proper rights calls ShutdownAllCores, a signal is sent to all other cores to induce the shutdown procedure. Once the shutdown procedure has started on a core, interrupts and Tasks are not further processed, and no scheduling will take place, therefore it makes no sense to activate any Task, however no error will be generated. It is in the responsibility of the application developer/system integrator to make sure that any preparations for shutdown on application and basic software level are completed before calling ShutdownAllCores (e.g. by means of the ECU state manager).

During the shutdown procedure every core executes its OS-Application specific ShutdownHook functions, followed by a synchronization point. After all cores have reached the synchronization point the global ShutdownHook function is executed by all cores in parallel.

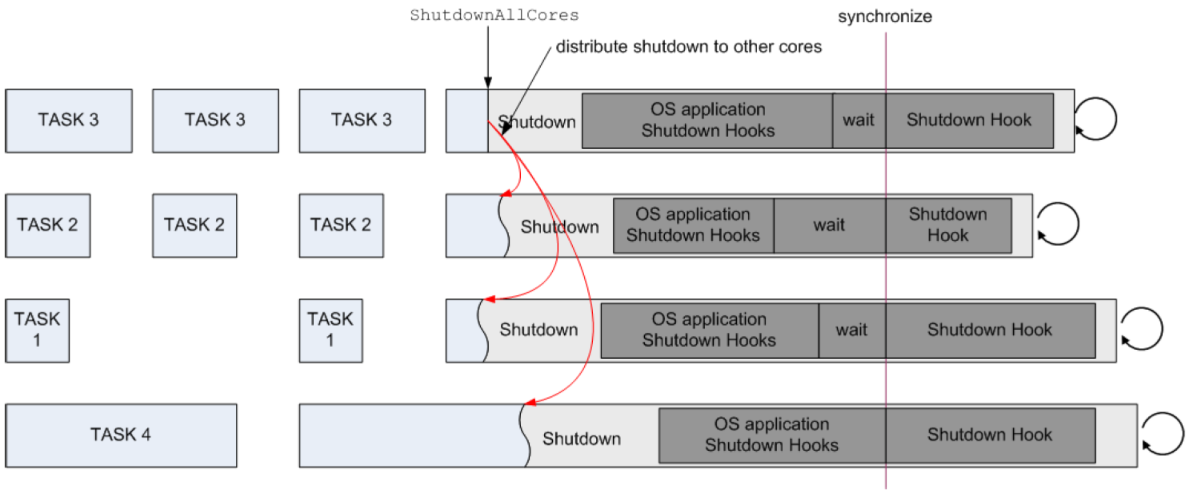

Figure 7.17: Example of a shutdown procedure

[SWS_Os_00586]

Upstream requirements: SRS_Os_80007

⌈During the shutdown, the OS-Application specific ShutdownHook shall be called on the core on which the corresponding OS-Application is bound.⌋

[SWS_Os_00587]

Upstream requirements: SRS_Os_80007

⌈Before calling the global ShutdownHook, all cores shall be synchronized.⌋

[SWS_Os_00588]

Upstream requirements: SRS_Os_80007

⌈The global ShutdownHook shall be called on all cores.⌋

7.9.6.2 Individual shutdown concept

If a `Task` calls `ShutdownOS` the OS will be shut down on the core on which `ShutdownOS` has been called. Every core shall be able to invoke `ShutdownOS` . Similar to `StartOS` this function will shutdown the individual core. To shutdown the whole ECU `ShutdownOS` has to be called on every core. The function will not return.

Individual shutdown is not supported in AUTOSAR R4.x (AUTOSAR mode management will not use it).

7.9.6.3 Shutdown in case of fatal internal errors

In multicore systems it can happen that a fatal internal OS error is detected only on one core. In such cases a local shutdown of that core does not make sense.

[SWS_Os_00762] ⌈In cases where the OS detects a fatal internal error all cores shall be shut down.⌋

7.9.7 OS service functionality (overview)

Within this chapter we describe which existing single core AUTOSAR OS functionality has been extended. The following table gives an overview of all standard OS API functions. The column "Multi-Core support" contains one of the following values:

- **Extended**: The function that has been extended substantially to support special Multi-Core functionality.
- **Adapted**: the function required some minor changes but basically remains unchanged.
- **Unchanged**: the behavior of the function has not changed.
- **New**: the function is a new AUTOSAR OS API-function.

Service	Multi-Core support	Annotation
ActivateTask	Extended	Cross core use shall be supported.
CallTrustedFunction	Adapted	Function must be bound to the same core.
CancelAlarm	Extended	Cross core use shall be supported.
ChainTask	Extended	Cross core use shall be supported.
CheckISRMemoryAccess	Unchanged	
CheckObjectAccess	Unchanged	
CheckObjectOwnership	Unchanged	
CheckTASKMemoryAccess	Unchanged	
ClearEvent	Unchanged	

▽

△

Service	Multi-Core support	Annotation
ControlIdle	Unchanged	Is allowed to be called from any core.
DisableAllInterrupts	Unchanged	Works only on the same core.
EnableAllInterrupts	Unchanged	Works only on the same core.
GetActiveApplicationMode	Unchanged	
GetAlarm	Extended	Cross core use shall be supported.
GetAlarmBase	Extended	Cross core use shall be supported.
GetApplicationID	Unchanged	
GetApplicationState	Extended	Cross core use shall be supported.
GetCoreID	New	ID of the current core.
GetCounterValue	Adapted	Cross core is not allowed.
GetElapsedValue	Adapted	Cross core is not allowed.
GetEvent	Unchanged	
GetISRID	Unchanged	
GetNumberOfActivatedCores	New	Number of cores running the AUTOSAR OS.
GetResource	Adapted	Nestable with spinlocks.
GetScheduleTableStatus	Extended	Cross core use shall be supported.
GetSpinlock	New	Occupy a spinlock.
GetTaskID	Unchanged	Works only on the same core.
GetTaskState	Extended	Cross core use shall be supported.
IncrementCounter	Adapted	Cross core is not allowed.
NextScheduleTable	Unchanged	
ReleaseResource	Adapted	Nestable with spinlocks.
ReleaseSpinlock	New	Release a spinlock.
ResumeAllInterrupts	Unchanged	Works only on the same core.
ResumeOSInterrupts	Unchanged	Works only on the same core.
Schedule	Adapted	Check for unreleased spinlocks
SetAbsAlarm	Extended	Cross core use shall be supported
SetEvent	Extended	Cross core use shall be supported.
SetRelAlarm	Extended	Cross core use shall be supported
SetScheduleTableAsync	Unchanged	
ShutdownAllCores	New	Synchronized shutdown.
ShutdownOS	Extended	Support for MC systems
StartCore	New	Start additional core
StartOS	Extended	Support for MC systems
StartScheduleTableAbs	Extended	Cross core use shall be supported.
StartScheduleTableRel	Extended	Cross core use shall be supported.
StartScheduleTableSynchron	Unchanged	
StopScheduleTable	Extended	Cross core use shall be supported.
SuspendAllInterrupts	Unchanged	Works only on the same core
SuspendOSInterrupts	Unchanged	Works only on the same core
SyncScheduleTable	Unchanged	
TerminateApplication	Extended	Check for unreleased spinlocks. Cross core use shall be supported.
TerminateTask	Adapted	Check for unreleased spinlocks
TryToGetSpinlock	New	Try to occupy a spinlock

▽

△

Service	Multi-Core support	Annotation
WaitEvent	Adapted	Check for unreleased spinlocks
isOsStarted	Adapted	In case of multi-core it returns just the value for the core which called the service

Table 7.2: Gives an overview of changes to the OS Service Calles

Service	Task	Cat1 ISR	Cat2 ISR	Error Hook	Pre/-Post-TaskHook	Startup Hook	Shut-down Hook	Alarm Call-back	Pro-tec-tion-Hook	inside trusted func-tion
GetNumberOfActivated-Cores	Ok		Ok							Ok
GetCoreID	Ok	Ok	Ok	Ok	Ok	Ok	Ok	Ok	Ok	Ok
StartCore										
GetSpinlock	Ok		Ok							Ok
ReleaseSpinlock	Ok		Ok							Ok
TryToGetSpinlock	Ok		Ok							Ok
GetNumberOfActivated-Cores	Ok		Ok							Ok
ShutdownAllCores	Ok		Ok	Ok		Ok				Ok

Table 7.3: Allowed Calling Context for OS Service Calls

[SWS_Os_00589]

Upstream requirements: SRS_Os_80013, SRS_BSW_00459

⌈All functions that are not allowed to operate cross core shall return E_OS_CORE in extended status if called with parameters that require a cross core operation.⌋

7.9.8 GetTaskID

GetTaskID can be called both from Task and Category 2 ISR level. When called from an interrupt routine, on Single-Core systems, GetTaskID returns either the interrupted Task or indicates that no Task is running. On Multi-Core systems it

- indicates that no Task is running on the core or,
- returns the ID of the interrupted Task on the core.

7.9.9 Interrupt disabling

Note: All types of interrupts can only be disabled on the local core. This implies that the interrupt flags on other cores remain in their current state. Scheduling continues on the other cores. Running ISRs on other cores continue executing.

7.9.9.1 Requirements

[SWS_Os_00590]

Upstream requirements: SRS_Os_80013

⌈The OS service `DisableAllInterrupts` shall only affect the core on which it is called.⌋

[SWS_Os_00591]

Upstream requirements: SRS_Os_80013

⌈The OS service `EnableAllInterrupts` shall only affect the core on which it is called.⌋

[SWS_Os_00592]

Upstream requirements: SRS_Os_80013

⌈The OS service `SuspendAllInterrupts` shall only affect the core on which it is called.⌋

[SWS_Os_00593]

Upstream requirements: SRS_Os_80013

⌈The OS service `ResumeAllInterrupts` shall only affect the core on which it is called.⌋

[SWS_Os_00594]

Upstream requirements: SRS_Os_80013

⌈The OS service `SuspendOSInterrupts` shall only affect the core on which it is called.⌋

[SWS_Os_00595]

Upstream requirements: SRS_Os_80013

⌈The OS service `ResumeOSInterrupts` shall only affect the core on which it is called.⌋

7.9.10 `Task` activation

`Task` activation shall be extended to work across cores. This document will not specify any implementation details. This functions timing behavior can be slower when working across cores. If a `Task` has to be activated on another core, a scheduling decision is necessary on that core. If the core has not been started an error is generated.

7.9.10.1 Requirements

[SWS_Os_00596]

Upstream requirements: SRS_Os_80001, SRS_Os_80015

⌈It shall be possible to activate a Task that is part of an OS-Application located on another core, as long as the assigned access rights allow it.⌋

[SWS_Os_00598]

Upstream requirements: SRS_Os_80015

⌈The call of ActivateTask across cores shall behave synchronously, i.e. a call returns after the Task has been activated or an error has been detected. It shall not be possible to continue execution on the calling core before ActivateTask is accomplished on the remote core.⌋

[SWS_Os_00599]

Upstream requirements: SRS_Os_80015

⌈In case of an error when calling ActivateTask across cores, the error handler shall be called on the core on which ActivateTask was originally called.⌋

[SWS_Os_00816]

Upstream requirements: SRS_Os_80015

⌈The operating system shall provide an asynchronous version of ActivateTask which does not return errors to the caller, but only calls the (global) error hook (if configured). The function name shall be ActivateTaskAsyn.⌋

7.9.11 Task Chaining

Task chaining shall be extended to work across cores. This document will not specify any implementation details. This function's timing behavior can be slower when working across cores. If a Task has to be activated on another core, a scheduling decision is necessary on that core. If the core has not been activated, an error is generated.

7.9.11.1 Requirements

[SWS_Os_00600]

Upstream requirements: SRS_Os_80001, SRS_Os_80015

⌈It shall be possible to chain a Task that is part of an OS-Application located on another core, as long as the assigned access rights allow it.⌋

7.9.12 Event setting

SetEvent shall be extended to work across cores. This document will not specify any implementation details. This function's timing behavior can be slower when working across cores. If the core has not been activated, an error is generated.

7.9.12.1 Requirements

[SWS_Os_00602]

Upstream requirements: SRS_Os_80016

⌈It shall be possible to set an Event that is part of an OS-Application located on another core, as long as the assigned access rights allow it.⌋

[SWS_Os_00604]

Upstream requirements: SRS_Os_80016

⌈The call of SetEvent across cores shall behave synchronously, i.e. a call returns after the Event has been set or an error has been detected. It shall not be possible to continue execution on the calling core before SetEvent is accomplished on the remote core.⌋

[SWS_Os_00605]

Upstream requirements: SRS_Os_80016

⌈In case of an error when calling SetEvent across cores, the error handler shall be called on the core on which SetEvent was originally called.⌋

[SWS_Os_00817]

Upstream requirements: SRS_Os_80016

⌈The operating system shall provide an asynchronous version of SetEvent which does not return errors to the caller, but only calls the (global) error hook (if configured). The function name shall be SetEventAsyn.⌋

7.9.13 Activating additional cores

The mechanism by which additional cores can be activated as described in section 7.9.5

7.9.14 Start of the OS

It is necessary to extend the functionality of StartOS. This is because StartOS is called once on each core. The user provides the so called application mode [4] to the Operating System through the call parameter of StartOS(AppMode).The application mode defines which of the configured (startup) objects (Tasks, Alarms, Schedule Tables) the OS automatically starts.

On a Multi-Core system all cores shall run in the same application mode. If StartOS is called with the Appmode DONOTCARE, the AppMode of the other cores is used. At least one core has to define an AppMode other than DONOTCARE.

If the application mode is the same on all cores, StartOS will proceed its task. More details can be found in chapter 7.9.4.

7.9.14.1 Requirements

[SWS_Os_00606]

Upstream requirements: SRS_Os_80001

⌈The AUTOSAR specification does not support the activation of AUTOSAR cores after calling StartOS on that core. If StartCore is called after StartOS it shall return with E_OS_ACCESS in extended status.⌋

[SWS_Os_00607]

Upstream requirements: SRS_Os_80006, SRS_Os_80013

⌈StartOS shall start the OS on the core on which it is called.⌋

[SWS_Os_00608]

Upstream requirements: SRS_Os_80006

⌈If more than one core calls StartOS with an AppMode other than DONOTCARE, the AppModes shall be the same. StartOS shall check this at the first synchronization point. In case of violation, StartOS shall not start the scheduling, shall not call any StartupHooks, and shall enter an endless loop on every core.⌋

[4] This is the application mode of the Operating System and shall not be confused by other application modes defined in the AUTOSAR mode management.

[SWS_Os_00609]

Upstream requirements: SRS_Os_80006

⌈If StartOS is called with the AppMode DONOTCARE the application mode of the other core(s) (differing from DONOTCARE) shall be used.⌋

[SWS_Os_00610]

Upstream requirements: SRS_Os_80006

⌈At least one core shall define an AppMode other than DONOTCARE.⌋

[SWS_Os_00611]

Upstream requirements: SRS_Os_80020

⌈If the IOC is configured, StartOS shall initialize the data structures of the IOC.⌋

[SWS_Os_00830] DRAFT

Upstream requirements: SRS_Os_80020

⌈If the IOC is configured and the OS Generator is invoked in "Default mode", StartOS shall invoke the IocInit (See [SWS_Os_00835]) to initialize the data structures of the IOC.⌋

7.9.15 Task termination

The termination of Tasks requires an additional check: It is not allowed to terminate a Task while a spinlock is occupied. If TerminateTask / ChainTask is called with an occupied spinlock an error is returned.

7.9.15.1 Requirements

If TerminateTask (or ChainTask) is called while the calling Task holds a spinlock, the behavior is undefined in standard status.

[SWS_Os_00612]

Upstream requirements: SRS_Os_80021

⌈In extended status TerminateTask / ChainTask shall return with an error (E_OS_SPINLOCK), which can be evaluated in the application.⌋

[SWS_Os_00613]

Upstream requirements: SRS_Os_80021

⌈Spinlocks occupied by Tasks that are terminated in response to a protection hook shall be automatically released. This applies also to the case in which an OS-Application is terminated.⌋

7.9.16 Termination of OS-Applications

Similar to Tasks an OS-Application cannot be terminated while any of its Tasks occupy a spinlock. In such cases, the lock is automatically released. To avoid an avalanche of error handling, no calls to the ErrorHook are made.

It might be possible that TerminateApplication(A) is called in parallel from different cores. The implementation has to support such a call pattern by executing the first arriving call of TerminateApplication(A)and ignoring any subsequent calls until the termination is completed.

7.9.16.1 Requirements

[SWS_Os_00614]

Upstream requirements: SRS_Os_80021

⌈TerminateApplication shall check if any of the Tasks in the OS-Application have occupied a spinlock. If so, the spinlocks shall be released.⌋

[SWS_Os_00615]

Upstream requirements: SRS_Os_80021

⌈If TerminateApplication(A) is called in parallel from different cores, the OsApplication A is terminated by the first call, any subsequent calls will return with E_OK in standard and extended status without doing anything, until the termination is completed.⌋

7.9.17 Shutdown of the OS

Every core shall be able to invoke shutdown by using the ShutdownOS function. By calling ShutdownOS only the calling core will enter the shutdown procedure.

If the user wants to shutdown all cores (more or less in parallel) ShutdownAllCores shall be used. ShutdownOS and ShutdownAllCores will not return.

The OS service ShutdownOS is not used by the AUTOSAR mode management in AUTOSAR R4.0. The function is offered for users that run the OS on cores without RTE and without mode management.

7.9.17.1 Requirements

[SWS_Os_00616]

Upstream requirements: SRS_Os_80001, SRS_Os_80007

⌈ShutdownOS shall be callable from each core running an AUTOSAR OS.⌋

[SWS_Os_00617]

Upstream requirements: SRS_Os_80007

⌈ShutdownOS shall shutdown the core on which it was called.⌋

[SWS_Os_00618]

Upstream requirements: SRS_Os_80013

⌈The OS shall not start Tasks of an OS-Application once the shutdown procedure has been entered on a particular core.⌋

[SWS_Os_00619]

Upstream requirements: SRS_Os_80013

⌈The AUTOSAR OS function ShutdownOS shall be callable in parallel on multiple cores.⌋

[SWS_Os_00620]

Upstream requirements: SRS_Os_80021

⌈ShutdownOS shall release all spinlocks which are occupied by the calling core.⌋

[SWS_Os_00621]

Upstream requirements: SRS_Os_80007

⌈ShutdownAllCores shall be callable from each core running an AUTOSAR OS.⌋

7.9.18 Waiting for Events

The Event waiting mechanism must be adapted to the new Multi-Core spinlock functionality:

A Task might be de-scheduled when calling WaitEvent, in which case it would not be able to release the spinlock. WaitEvent must therefore check if the calling Task holds a spinlock. As with Resources, spinlocks cannot be occupied by Tasks in wait state.

7.9.18.1 Requirements

[SWS_Os_00622]

Upstream requirements: SRS_Os_80021

⌈The AUTOSAR Operating System WaitEvent API service shall check if it has been called while the calling Task has occupied a spinlock. In extended status an error E_OS_SPINLOCK shall be returned and the Task shall not enter the wait state.⌋

7.9.19 Calling trusted functions

Functions can be declared as trusted as part of an OS-Application. They can then only be executed through the CallTrustedFunction API function. Assuming that the access rights are configured accordingly, a Task from OS-Application A can call a trusted function from OS-Application B.

On a Multi-Core system, these trusted function calls from one OS-Application to another are limited to the same core.

7.9.19.1 Requirements

[SWS_Os_00623]

Upstream requirements: SRS_Os_80013

⌈The OS API function CallTrustedFunction shall return E_OS_ACCESS in extended status if the target trusted function is part of an OS-Application on another core.⌋

7.9.20 Invoking reschedule

The Schedule API service must be adapted to the new Multi-Core spinlock functionality in the same manner as WaitEvent.

A Task shall not actively force a de-scheduling while it occupies spinlocks.

7.9.20.1 Requirements

[SWS_Os_00624]

Upstream requirements: SRS_Os_80021

⌈The AUTOSAR Operating System Schedule API service shall check if it has been called while the calling Task has occupied a spinlock. In extended status an error E_OS_SPINLOCK shall be returned and the scheduler shall not be called.⌋

7.9.21 Resource handling

The GetResource function allows mutual exclusion between Tasks on the same core. The OS generator shall check offline that the Tasks are not on different cores.(see 7.9.29) and the GetResource function will check this requirement online.

The priority ceiling protocol (used by GetResource) temporarily changes the priority of a Task. Such an approach fails on Multi-Core systems as the priorities are local to each core. Therefore the ceiling protocol is not sufficient to protect a critical section against access from different cores.

[SWS_Os_00801]

Upstream requirements: SRS_Os_80021

⌈If Spinlocks and Resources are locked by a Task/ISR they have to be unlocked in strict LIFO order. ReleaseResource shall return E_OS_NOFUNC if the unlock order is violated. No other functionality shall be performed.⌋

[SWS_Os_00851] ⌈If OsUseResScheduler is TRUE, the OS generation tool shall create a virtual instance of RES_SCHEDULER for each configured core.⌋

[SWS_Os_00852] ⌈It shall be possible for tasks running on different cores to occupy their own instance of RES_SCHEDULER at the same time.⌋

[SWS_Os_00853] ⌈The ceiling priority of each instance of RES_SCHEDULER shall prevent the execution of any other task on the core on which it is occupied but shall have no effect on the scheduling on any other core.⌋

[SWS_Os_00854] ⌈If OsUseResScheduler is FALSE AND the configuration contains a resource called RES_SCHEDULER, the configured resource shall behave the same as any other configured resource.⌋

[SWS_Os_00855] ⌈It shall be possible to configure a LINKED resource that links to RES_SCHEDULER. In a multi-core configuration with OsUseResScheduler=TRUE, the linkage shall be to the instance of RES_SCHEDULER on the core to which the LINKED resource is assigned.⌋

7.9.22 The CoreID

Every HW assigns a unique physical Id to a core. The physical core Id is the only way to distinguish between cores. The physical core Ids of a μC are not necessarily consecutive and do not necessarily start with zero.

The SW requires a mechanism to identify a core, e.g. to use core specific variables. Because the physical core Id usually cannot be used as a direct array index for core specific variables, a logical CoreID is necessary to map physical core Ids to array indexes. In the SW it is not necessary to know the physical core Id, the logical CoreID is sufficient.

The mapping of OS-Applications and other SW objects to cores is specified in the configuration files. All such mappings shall be HW independent and therefore shall not be based on the physical core Id but on the logical CoreID.

The function GetCoreID internally maps the physical core Id to the logical CoreID. The value is defined in the configuration parameter EcucCoreId. GetCoreID can be either a C function or a macro.

7.9.22.1 Requirements

[SWS_Os_00625]

Upstream requirements: SRS_Os_80006

⌈The AUTOSAR Operating System API function GetCoreID shall be callable before StartOS.⌋

[SWS_Os_00627]

Upstream requirements: SRS_Os_80001

⌈An implementation shall define a set of constants OS_CORE_ID_<No> of the type CoreIdType with <No> a value from 0 to OsNumberOfCores-1.⌋

[SWS_Os_00628]

Upstream requirements: SRS_Os_80001

⌈An implementation shall offer a constant OS_CORE_ID_MASTER of the type CoreIdType that refers to the master core.⌋

7.9.23 `Counter`s, background & rationale

A `Counter` is represented by a counter value, measured in "ticks", and some counter specific constants.

Similarly to Single-Core situation, each operating system (on each core) offers at least one `Counter` that is derived from a timer. Therefore, it is possible to define several `Counter`s which belong to different OS-Applications and either resides on the same or different cores.

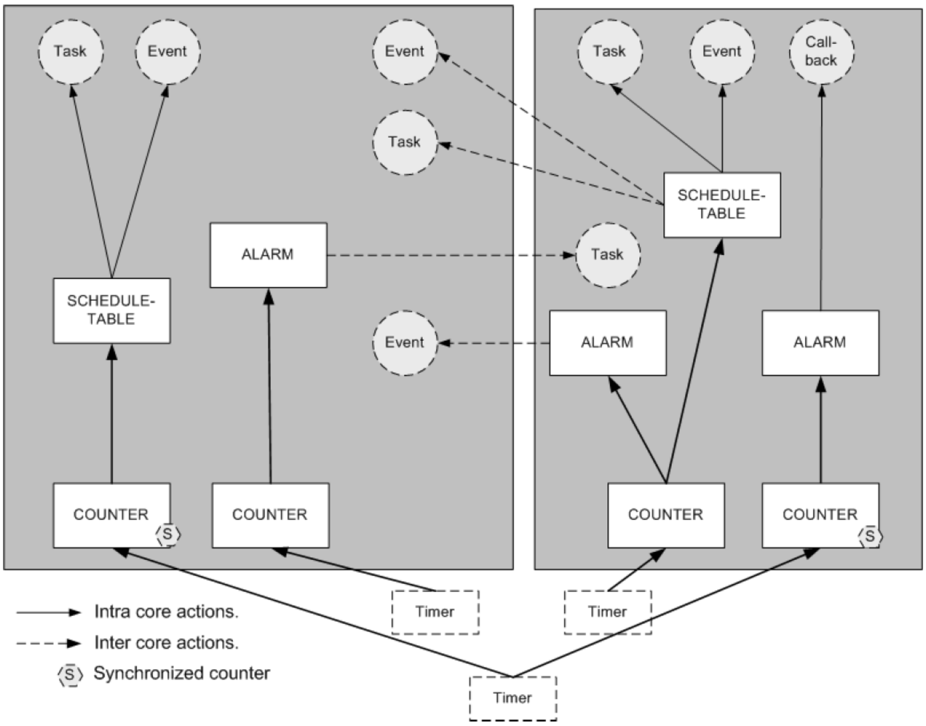

Figure 7.18: Examples of allowed configurations for `Counter`s, `Alarm`s, Schedule-tables and `ISR`s

7.9.24 Multi-Core restrictions on `Counter`s

The AUTOSAR OS can only increment `Counter`s on the core on which it resides. A `Counter` which is assigned to an OS-Application X cannot be incremented by an OS-Application Y if X and Y are assigned to different cores.

7.9.24.1 Requirements

[SWS_Os_00629]

Upstream requirements: SRS_Os_80013

⌈A Counter belonging to an OS-Application shall be incremented by the core on which the OS-Application resides. The Counter shall not be incremented by other cores.⌋

[SWS_Os_00630]

Upstream requirements: SRS_Os_80013

⌈It shall not be allowed to drive a ScheduleTable from a Counter, which is assigned to a different core.⌋

[SWS_Os_00631]

Upstream requirements: SRS_Os_80013

⌈It shall not be allowed to drive an Alarm from a Counter, which is assigned to a different core.⌋

There are two different reasons for these restrictions:

- Race conditions can occur when cross-core modification of Counter is allowed (one core waits for a Counter to be modified by another core).
- The core which is incrementing the Counter has to check if Alarms which are based on the Counter have expired. Handling of expired Alarms is more complex when different cores manipulate the same Alarms, because mutual exclusion becomes necessary.

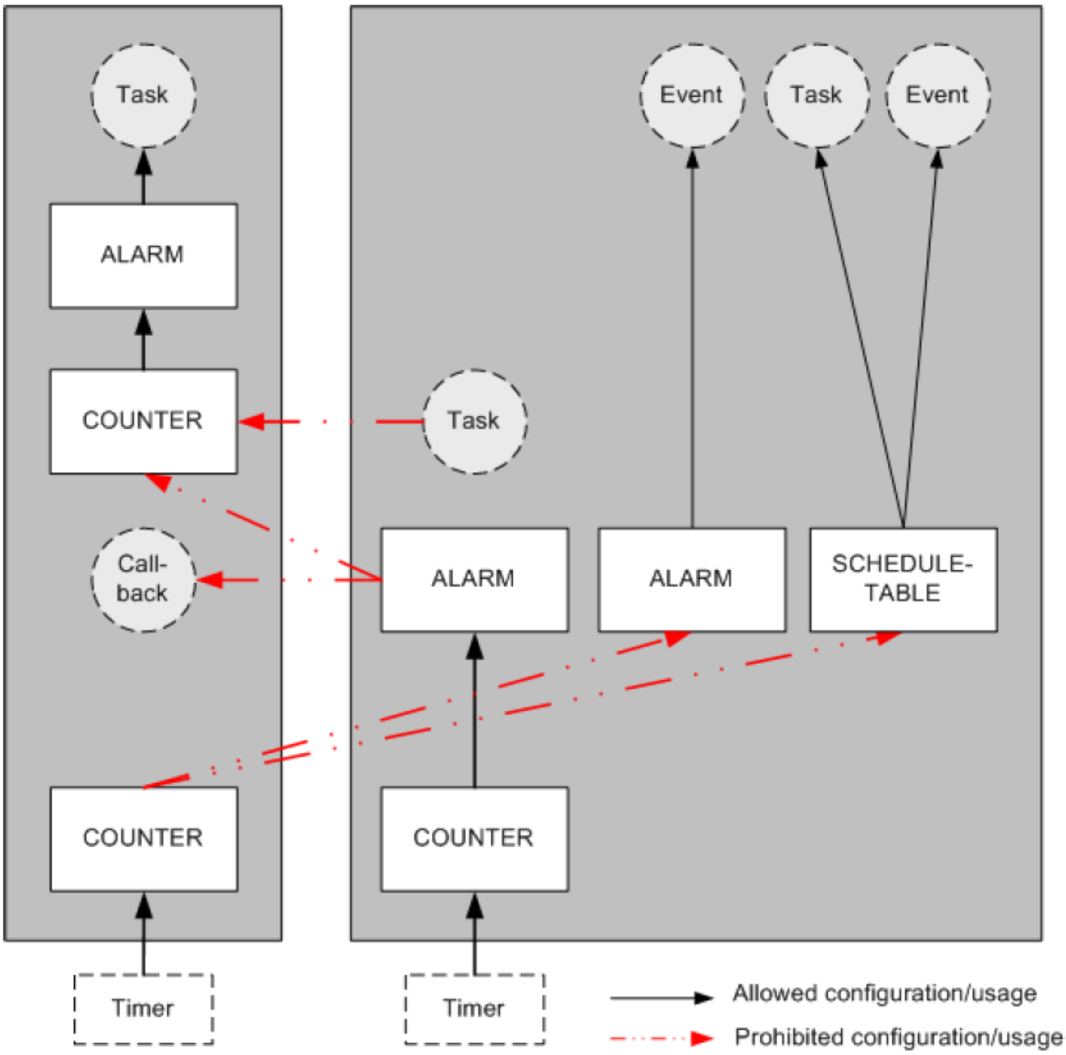

Figure 7.19: Example of disallowed configurations for `Counters`, `Alarms`, Schedule-tables and Call-backs

7.9.25 Synchronization of `Counters`

`Counter`s are used to drive `Alarm`s and `ScheduleTable`s. To synchronize `Alarm`s and `ScheduleTable`s that reside on different cores, the corresponding `Counter`s have to be synchronized. For example, if the hardware supports this, it is possible that corresponding free running hardware counters on different cores use the same timer (same counter value maintained by the peripheral) and therefor provide the same timebase on different cores. Software `Counter`s can then get advanced by alarms attached to these core local corresponding hardware counters, e.g. to drive synchronized `ScheduleTable`s on different cores. The quality of the synchronicity depends on the hardware architecture and on the system configuration. .

7.9.26 Alarms

The Alarm mechanism of the AUTOSAR Operating System provides services to activate Tasks, set Events, increment Counters, or call an Alarm call-back (OsAlarmCallbackName).

As stated above, Alarms can only be bound to a Counter which resides on the same core. Tasks can be activated and Events can be set with an Alarm action regardless of the core to which the Task is bound. The access rights defined by OS-Applications have to be respected, however. Additionally it shall be allowed to manipulate Alarms when they are bound to other cores. The API-services SetRelAlarm, SetAbsAlarm, and CancelAlarm can be used to manipulate parameters of Alarms on other cores.

7.9.26.1 Requirements

[SWS_Os_00632]

Upstream requirements: SRS_Os_80018

⌈If an Alarm expires, it shall be allowed to activate a Task on a different core.⌋

[SWS_Os_00633]

Upstream requirements: SRS_Os_80018

⌈If an Alarm expires, it shall be allowed to set an Event on a different core.⌋

[SWS_Os_00634]

Upstream requirements: SRS_Os_80018

⌈The AUTOSAR Operating System shall process an Alarm on the core on which its corresponding OS-Application resides.⌋

[SWS_Os_00635]

Upstream requirements: SRS_Os_80013

⌈Alarm callbacks shall be executed on the core to which the Alarm is bound. This is only applicable to SC1 systems, because otherwise Alarm Callback are not allowed ([SWS_Os_00242]).⌋

[SWS_Os_00636]

Upstream requirements: SRS_Os_80013

⌈SetRelAlarm shall also work on an Alarm that is bound to another core.⌋

[SWS_Os_00637]

Upstream requirements: SRS_Os_80013

⌈SetAbsAlarm shall also work on an Alarm that is bound to another core.⌋

[SWS_Os_00638]

Upstream requirements: SRS_Os_80013

⌈CancelAlarm shall also work on an Alarm that is bound to another core.⌋

[SWS_Os_00639]

Upstream requirements: SRS_Os_80013

⌈GetAlarmBase shall also work on an Alarm that is bound to another core.⌋

[SWS_Os_00640]

Upstream requirements: SRS_Os_80013

⌈GetAlarm shall also work on an Alarm that is bound to another core.⌋

7.9.27 ScheduleTables

Similarly to Alarms, ScheduleTables can be used to activate Tasks and set Events. As with Alarms, a ScheduleTable can only be bound to a Counter which resides on the same core.

To simplify system startup, it should be possible to start ScheduleTables on other cores. The system designer is responsible for the correct handling of ScheduleTables. For example, ScheduleTables can be controlled from one core.

7.9.27.1 Requirements

[SWS_Os_00641]

Upstream requirements: SRS_Os_80018

⌈A ScheduleTable shall be able to activate a Task bound on a core other than the one upon which the ScheduleTables resides.⌋

[SWS_Os_00642]

Upstream requirements: SRS_Os_80018

⌈A ScheduleTable shall be able to set an Event on a core other than the one upon which the ScheduleTables resides⌋

[SWS_Os_00643]

Upstream requirements: SRS_Os_80013

⌈The AUTOSAR Operating System shall process a `ScheduleTable` on the core on which its corresponding OS-Application resides.⌋

[SWS_Os_00644]

Upstream requirements: SRS_Os_80018

⌈The API call `StartScheduleTableAbs` shall be able to start `ScheduleTable`s of OS-Applications residing on other cores.⌋

[SWS_Os_00645]

Upstream requirements: SRS_Os_80013

⌈The API call `StartScheduleTableRel` shall be able to start `ScheduleTable`s of OS-Applications residing on other cores.⌋

[SWS_Os_00646]

Upstream requirements: SRS_Os_80013

⌈The API call `StopScheduleTable` shall be able to stop `ScheduleTable`s of OS-Applications residing on other cores.⌋

[SWS_Os_00647]

Upstream requirements: SRS_Os_80013

⌈The API service `GetScheduleTableStatus` shall be able to get the status of a `ScheduleTable` that is part of an OS-Application residing on a different core.⌋

7.9.28 The spinlock mechanism

With the Multi-Core concept, a new mechanism is needed to support mutual exclusion for `Task`s on different cores. This new mechanism shall not be used between `Task`s on the same core because it makes no sense. In such cases the AUTOSAR Operating System returns an error.

A *SpinlockType*, which is similar to OSEK's `ResourceType`, shall be used. Spinlocks are configured offline.

A spinlock is a busy waiting mechanism that polls a (lock) variable until it becomes available. Typically, this requires an atomic *test and set* functionality, the details of which are implementation specific.

Once a lock variable is occupied by a Task/Category 2 ISR, other Tasks/Category 2 ISRs on other cores shall be unable to occupy the lock variable. The spinlock mechanism will not de-schedule these other Tasks while they poll the lock variable. However it might happen that a Task/ISR with a higher priority becomes ready while the lock variable is being polled. In such cases the spinning Task will be interfered. This is illustrated in figure 7.20.

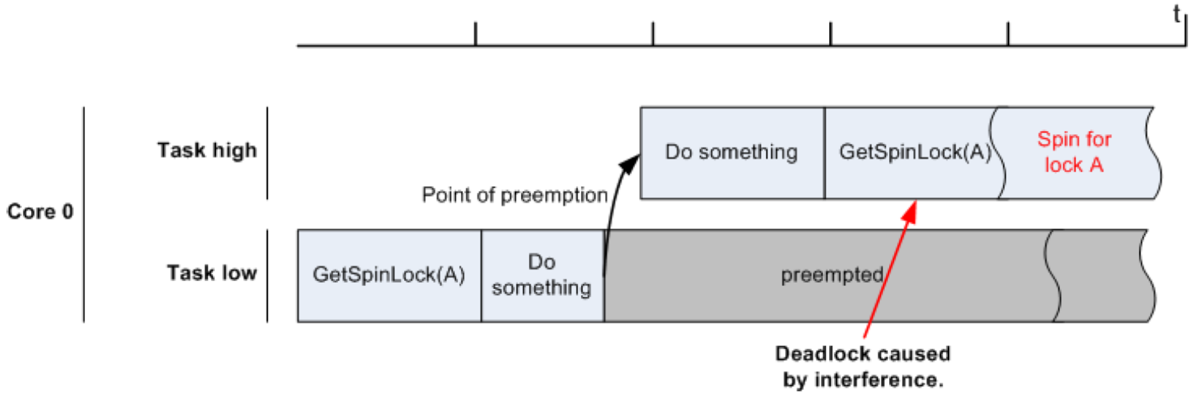

Figure 7.20: A deadlock situation caused by interference, the high priority Task spins indefinitely because the low priority Task has occupied the spinlock. In such cases the second GetSpinlock call will return with an error.

A user can protect a Task against such a situation by, for example, rapping the spinlock with SuspendAllInterrupts, so that it cannot be interfered by other Tasks. The OS can do this automatically for the caller - see OsSpinlockLockMethod.

A second deadlock situation can be created by nested spinlocks calls, as illustrated in figure 7.21.

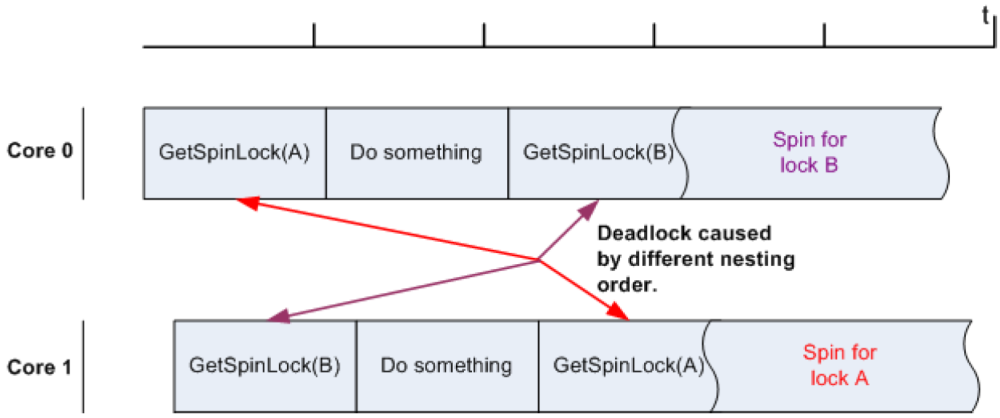

Figure 7.21: This figure shows a typical deadlock caused by two spinlocks taken in different order by Tasks on two different cores

To avoid deadlocks it is not allowed to nest different spinlocks. Optionally if spinlocks shall be nested, a unique order has to be defined. Spinlocks can only be taken in this order whereas it is allowed to skip individual spinlocks. Cycles are not allowed within the defined order. This is illustrated in figure 7.22.

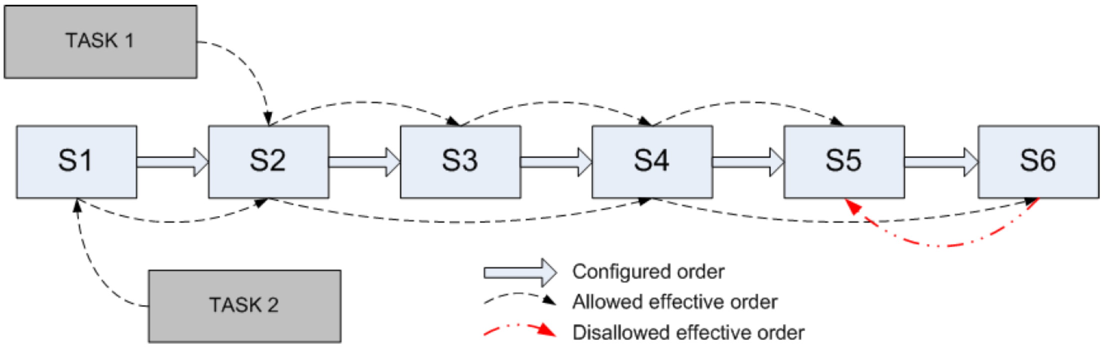

Figure 7.22: Usage of spinlocks

This figure 7.22 shows an example in which two `Task`s have access to a set of spinlocks S1 – S6. It is allowed to occupy the spinlocks in the predefined order and it is allowed to skip spinlocks. If multiple spinlocks are occupied at the same time, locking and unlocking has to occur in strict LIFO order

The spinlock mechanism is not deadlock free by itself. The order in which spinlocks from `Task`s/`ISR`s are requested has to be mentioned in the configuration description. If a `Task` occupies a spinlock, scheduling shall be restricted.

Note: AUTOSAR does not prescribe which algorithms are used to implement spinlocks. Since users may want to analyze the timing behavior (e.g. lock times) an implementation shall document the real behavior.

7.9.28.1 Requirements

[SWS_Os_00648]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈The AUTOSAR Operating System shall provide a spinlock mechanism that works across cores.⌋

[SWS_Os_00649]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈The AUTOSAR Operating System shall provide a `GetSpinlock` function which occupies a spinlock. If the spinlock is already occupied, `GetSpinlock` shall keep on trying to occupy the spinlock until it succeeds.⌋

[SWS_Os_00650]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈`GetSpinlock` shall be callable from `Task` level.⌋

[SWS_Os_00651]

Upstream requirements: SRS_Os_80021

⌈GetSpinlock shall be callable from Category 2 ISR level.⌋

The behavior of GetSpinlock is undefined if called from a category 1 ISR

[SWS_Os_00652]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈The AUTOSAR Operating System shall provide a TryToGetSpinlock function which occupies a spinlock. If the spinlock is already occupied by a Task, TryToGetSpinlock shall return.⌋

[SWS_Os_00653]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈TryToGetSpinlock shall be callable from Task level.⌋

[SWS_Os_00654]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈TryToGetSpinlock shall be callable from Category 2 ISR level.⌋

[SWS_Os_00655]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈The AUTOSAR Operating System shall provide a ReleaseSpinlock function which releases an occupied spinlock. If the spinlock is not occupied an error shall be returned.⌋

[SWS_Os_00656]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈ReleaseSpinlock shall be callable from Task level.⌋

[SWS_Os_00657]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈ReleaseSpinlock shall be callable from Category 2 ISR level.⌋

[SWS_Os_00658]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈The AUTOSAR Operating System shall generate an error if a Task tries to occupy a spinlock that is assigned to a Task/Category 2 ISR on the same core (including itself).⌋

[SWS_Os_00659]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈The AUTOSAR Operating System shall generate an error if an Category 2 ISR tries to occupy a spinlock that is assigned to a Task/Category 2 ISR on the same core.⌋

[SWS_Os_00660]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈A unique order in which multiple spinlocks can be occupied by a Task/Category 2 ISR on one core should be configurable in the AUTOSAR Operating System. This might be realized by the configuration item (OsSpinlockSuccessor{NEXT_SPINLOCK}) where NEXT_SPINLOCK refers to the consecutive spinlock. (See OsSpinlockSuccessor)⌋

[SWS_Os_00661]

Upstream requirements: SRS_Os_80018, SRS_Os_80021

⌈The AUTOSAR Operating System shall generate an error if a Task/Category 2 ISR on a core, where the same or a different Task/ISR already holds a spinlock, tries to seize another spinlock that has not been configured as a direct or indirect successor of the latest acquired spinlock (by means of the OsSpinlockSuccessor configuration parameter) or if no successor is configured.⌋

7.9.29 Offline checks

AUTOSAR Resources cannot be shared between Tasks/ISRs on different cores. The OS generator has to check if a user tries to assign a Resource to Tasks on different cores and stop the generation process with an error.

Counters cannot be accessed from OS-Applications on different cores. The OS generator has to reject configurations that violate this rule.

The linked list of spinlocks must be free of cycles to allow correct nesting of spinlocks in order to prevent deadlocks.

The OS generator tool must check that an OS-Application does not get assigned to a non-existing core. Additional checks at configuration time, e.g. by an AUTOSAR description editor are recommended.

7.9.29.1 Requirements

[SWS_Os_00662]

Upstream requirements: SRS_Os_80021

⌈The OS generator tool shall return with an error if it detects a `Resource` referred to by any `Task`s or `ISR`s assigned to different cores.⌋

[SWS_Os_00663]

Upstream requirements: SRS_Os_80013

⌈The OS generator tool shall return with an error if an `Alarm` is assigned to a `Counter` on a different core.⌋

[SWS_Os_00664]

Upstream requirements: SRS_Os_80013

⌈The OS generator tool shall return with an error if a `Counter` on a different core shall be incremented as an `Alarm` action.⌋

[SWS_Os_00665]

Upstream requirements: SRS_Os_80013

⌈The OS generator tool shall return with an error if a `ScheduleTable` is assigned to a `Counter` on a different core.⌋

[SWS_Os_00666]

Upstream requirements: SRS_Os_80021

⌈The OS generator tool shall return with an error if the linked list of spinlocks is not free of cycles.⌋

[SWS_Os_00667]

Upstream requirements: SRS_Os_80005

⌈The OS generator tool shall check the assignment of `OsApplication`s (including the `Task`s assigned to the `OsApplication`) to cores and return an error in case any of these cores does not exist.⌋

7.9.30 Auto start Objects

Before scheduling starts the AUTOSAR Operating System[5] activates all auto-start objects that are configured. This mechanism shall work similar on a Multi-Core system.

[5] StartOs

Before scheduling starts, the Multi-Core OS shall activate all configured auto-start objects on the respective core. Due to the fact that OS-Applications are defined as the locatable entity no further configuration container is required. Auto-start objects are already configured as part of an OS-Application.

7.9.30.1 Requirements

[SWS_Os_00668]

Upstream requirements: SRS_Os_80006

⌈The AUTOSAR Operating System shall automatically activate all auto-start `Task`s configured for the current AppMode, with respect to the core, before the initial start of the scheduling.⌋

[SWS_Os_00669]

Upstream requirements: SRS_Os_80006

⌈The AUTOSAR Operating System shall automatically activate all auto-start `Alarm`s configured for the current AppMode, with respect to the core, before the initial start of the scheduling.⌋

[SWS_Os_00670]

Upstream requirements: SRS_Os_80006

⌈The AUTOSAR Operating System shall automatically activate all auto-start `ScheduleTable`s configured for the current AppMode, with respect to the core, before the initial start of the scheduling.⌋

7.10 Inter-OS-Application Communicator (IOC)

7.10.1 Background & Rationale

IOC stands for Inter OS-Application Communicator.

The "IOC" is responsible for the communication between OS-Applications and in particular for the communication crossing core or memory protection boundaries. Its internal functionality is closely connected to the Operating System.

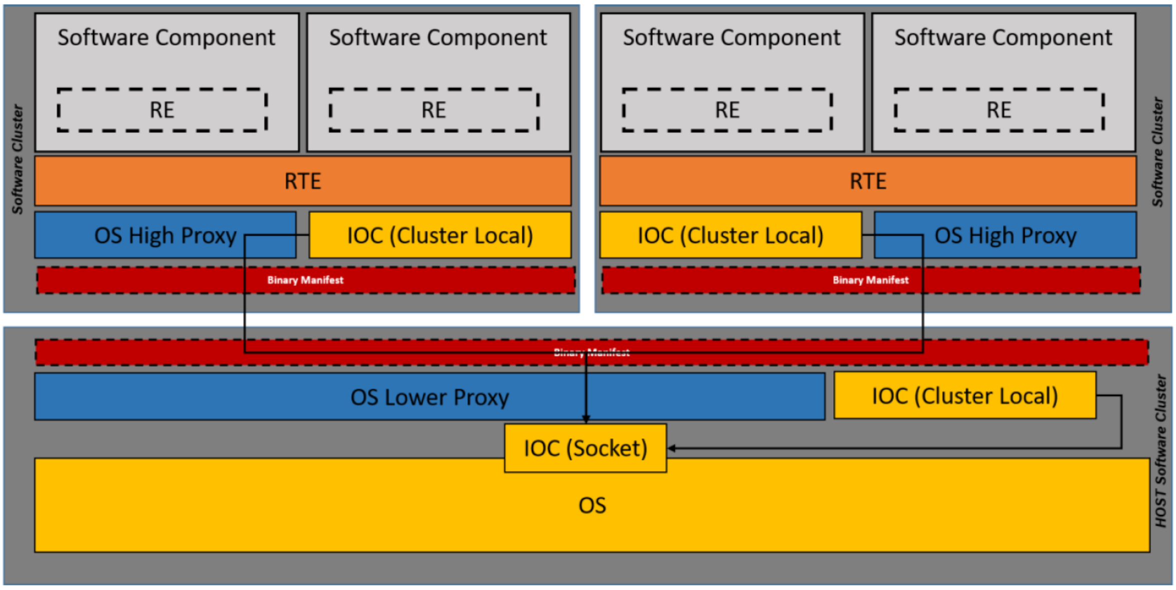

Figure 7.23: IOC overall view

There are use cases where 1 to N IOC code instances needs to be generated on top of the OS code which is used by multiple different Software Clusters. As those Software Clusters use different IOC configurations, as a consequence the OS code shall not include any code depending on a specific IOC configuration.

To ensure compatibility between IOC and OS code, there is still a dependency in that it is necessary to use the same OS configuration for the generation of the different IOC code Instances. Furthermore, the OS and IOC code should be generated from an OS Generator coming from the same vendor.

[SWS_Os_00671]

Upstream requirements: SRS_Os_80020

⌈The IOC implementation shall be part of the Operating System

The IOC is a third type of communication, in addition to

- Intra OS-Application communication: Always handled within the RTE
- Inter ECU communication: Already available via well-defined interfaces to the communication stack (COM)

⌋

IOC mode: This is the mode where the OS generator is invoked with a configuration parameter to generate the IOC code only.

OS mode: This is the mode where the OS generator is invoked with a configuration parameter to generate the OS code only.

Default mode: This is the current behavior where the IOC code is generated along with OS code.

[SWS_Os_00831] DRAFT

Upstream requirements: SRS_Os_80020

⌈The OS Generator shall provide configuration parameters allowing IOC communication code ("IOC mode") to be generated separately from OS code (("OS mode").⌋

[SWS_Os_00831] means that the OS Generator shall be able to produce only OS code or only IOC code in a single invocation.

[SWS_Os_00832] DRAFT

Upstream requirements: SRS_Os_80020

⌈The Operating System in the Host Software Cluster shall be able to handle multiple IOC code Instances related to different Software Clusters.⌋

[SWS_Os_00833] DRAFT

Upstream requirements: SRS_Os_80020

⌈When the OS generator is invoked in "OS mode" it shall only generate the OS code. Thereby the OS code shall not include any code that depends on a specific IOC configuration, because different Clusters will use different IOC configurations with the same OS code.⌋

Please note that it is mandatory to use the same OS configuration for the generation of the different IOC instances to ensure compatibility between the IOC and OS code.

[SWS_Os_00834] DRAFT

Upstream requirements: SRS_Os_80020

⌈When the OS generator is invoked in "IOC mode" it shall only generate the IOC code. Thereby the name of the C module containing the generated IOC code shall be Ioc.c and the name of the header file containing the generated IOC APIs shall be Ioc.h.⌋

Requirements [SWS_Os_00833] and [SWS_Os_00834] ensure that OS and IOC can be generated independently from each other but linked together while building the ECU instance /Machine. ()

[SWS_Os_00835] DRAFT

Upstream requirements: SRS_Os_80020

⌈If the IOC is configured, there shall be a function `IocInit` responsible for the initialization of the data structures of the IOC.⌋

Memory protection boundaries are a characteristic of OS-Applications and special communication mechanisms are needed to cross them. Multi-Core systems may also need additional measures to make communication between cores safe.

All AUTOSAR software, both BSW and software components, must belong to an OS-Application (see 7.9.3), but not necessarily to the same one. It is expected that the BSW will be trusted code, but it shall be defined as one or more OS-Applications.

The IOC provides communication services between OS-Applications and in particular over core boundaries in Multi-Core systems. Because the cross-core communication is always an inter-OS-Application communication, the two mechanisms are combined. An inter OS-Application communication may not necessarily require a cross core communication, however.

Communication between OS-Applications is expected to be more frequent than inter ECU communication. This would be the case when existing; closely related Software Components and their runnable entities are distributed to two or more cores to increase system performance. Meeting timing constraints is expected to become more difficult, when runnables which have been designed to run on a single core are distributed over several cores.

In systems with only one core, the IOC can be omitted completely, if just one OS-Application is available, or if no OS-Application uses memory protection mechanisms.

The IOC does not provide standardized support for measurement of IOC channels.

7.10.2 IOC - General purpose

The IOC provides communication services which can be accessed by clients which need to communicate across OS-Application boundaries on the same ECU or Software Cluster.

The RTE uses IOC services to communicate across such boundaries. All communication must be routed through the RTE on sender (or client) and on receiver (or server) side.

Direct access to IOC services by clients other than the RTE is currently not supported, but possible, if the client (e.g. a CDD) provides a hand written or generated IOC Configuration Description as specified and specific callback functions if necessary. Only sender/receiver communication is supported however by the IOC.

To keep the RTE as hardware independent as possible, all inter OS-Application and inter core communication mechanisms and implementation variants are encapsulated in the IOC. The IOC internal functionality is dependent on hardware architecture properties, in particular on the memory architecture.

The IOC has to guarantee data consistency in inter OS-Application and inter core (Multi-Core systems) communication, this means in particular:

- In queued communication the sequential order of communication operations shall remain unchanged. In the N:1 communication case, the order of the messages from the different sources is a property of the implementation.
- The content of all data sent in one communication operation shall remain unchanged, i.e. each communication operation shall be treated as atomic operation.
- The lock mechanism (interrupt locks; spinlocks; lock free implementation; ...) which is used by the IOC to guarantee the data consistency is not standardized.

7.10.3 IOC functionality

7.10.3.1 Communication

The IOC provides sender-receiver (signal passing) communication only. The RTE (or adapted BSW modules in a future release of this specification) translates Client-Server invocations and response transmissions into Sender-Receiver communication.

1:1, N:1 and N:M (unqueued only) communication are supported by the IOC.

The IOC allows the transfer of one data item per atomic communication operation. A data item can either be a value for atomic basic data types or a reference for complex data structures. The data structure must be implemented as a single memory block, however. This way the data item can be transmitted in one piece. The IOC does not need to know the internal data structure. The basic memory address and length (which can be calculated from the type of the data item) is sufficient. The IOC does, e.g., not support a conversion of endianness between cores.

Transferring more than one data item in one operation is also supported for 1:1 communication only. In this case several types and memory addresses have to be used by the IOC function. The advantage compared to sequential IOC calls is that mechanisms to open memory protection boundaries and to notify the receiver have to be executed just once. Additionally, all data items are guaranteed to be consistent, because they are transferred in one atomic operation.

The IOC provides both, unqueued (Last-is-Best, data semantics) or queued (First-In-First-Out, event semantics) communication operations. If present, the IOC internal queue has a configurable length.

Each atomic communication operation gets specified individually by its own description block in a Configuration Description with regard to sender, receiver, data type(s), notification, and queuing.

7.10.3.2 Notification

The IOC optionally notifies the receiver as soon as the transferred data is available for access on the receiver side, by calling a configured callback function which gets provided by the user of the communication.

A possible implementation is to trigger an interrupt (Category 2 `ISR`) mechanism to invoke the callback function from the `ISR` on receiver side, or to use a microcontroller supplied trap. The callback function shall be efficient and compact, because it is called from within the `ISR`.

In certain cases, it might not be necessary to trigger an `ISR` to notify the receiver. The IOC generator can then select the appropriate IOC internal notification method based on the hardware architecture and other constraints. This might be more efficient than an `ISR` for communication between OS-Applications on the same core.

The notification might be handled completely by the client of the IOC, e.g. when the RTE calls the IOC send function, and then notifies the receiver side RTE that new data are available from the IOC. In this case, the IOC is not affected at all by the details of the notification mechanism.

In case such alternative solutions prove to be more efficient, the IOC internal notification might get removed in future AUTOSAR releases.

7.10.4 IOC interface

The interface between RTE and IOC shall be similar to the interface between Software Components and the RTE, i.e. by generating specific interfaces for each communication operation instead of providing a generic API.

This supports optimization methods (like function inlining or replacing function calls by macros) much better than standardized interfaces. Most of the optimization can be performed offline at code generation time instead of consuming valuable real-time resources.

There is a unique set of IOC service APIs (at least to send and receive data) for each data communication specified in the IOC Configuration Description. Each service API gets generated and can be identified by a unique Id for each data communication. In case of N:1 communication, each sender must use its own API.

The same IOC service API and hence the same 1:1 communication can get used by more than one runnable inside the same SWC both on sender and on receiver side. However, the IOC functions are not reentrant, because otherwise e.g. spinlock errors could occur in case the IOC uses spinlocks in Multi-Core systems. The same IOC API must therefore only be called sequentially. This is no problem, if all runnable entities are scheduled within the same `Task`, otherwise the caller is responsible to guarantee that the same IOC API is not called again before it returns from a different invocation.

Software Components may access the IOC only via RTE. Only the RTE decides which communication services to use to support the communication needs of Software Components.

Direct access to IOC services by BSW modules is not supported, but allowed for CDDs and other modules, if unavoidable. The clients have to provides a hand written or generated IOC Configuration Description as specified. In case of notification of the receiver, a specific callback function has to be specified and provided by the client. Only sender/receiver communication is supported however by the IOC.

7.10.5 IOC internal structure

This section gives some hints on possible IOC implementation options.

The IOC may enter the privileged mode to cross the protection boundaries between OS-Applications. The IOC therefore has to be part of the OS. Note that functionality that is placed in the kernel context might be non-interruptible by `Task`s or Category 2 `ISR`. The functionality can be interrupted by Cat1 `ISR`s, however.

The IOC send service writes data into a buffer located in a memory area which is shared with the receiving communication partners (This is one possible implementation example using shared memory). Depending on the hardware architecture and other constraints, different implementation options might be available within the IOC. These options shall be transparent to the client (RTE), however.

The IOC ensures data consistency, i.e. there is a protection against concurrent access to the same data from all senders and the receiver for protection against inconsistent behavior and data corruption. The implementation can be hardware dependent.

In systems with shared memory, there can be a specific communication buffer for each data item in a memory section which is shared between the sending and receiving OS-Applications.

If an IOC communication with event semantics (queued) is configured the length of the queue shall be defined.

7.10.6 IOC configuration and generation

Data element specific interfaces between RTE and IOC require extensive code generation. Instead of generating the IOC together with the RTE, a sequential code generation process is used, to separate generic RTE code generation and hardware dependent IOC code generation as much as possible. The following steps shall be performed:

- Step 1: Specify all information about the allocation of Software Components to OS-Applications and cores in the ECU Configuration Description file.

- Step 2: Generate the RTE. The RTE generator creates data element specific IOC services calls and the corresponding IOC Configuration Description blocks (XML format) to specify the communication relations for each data element.
- Step 3: Generate the IOC code, according to the IOC Configuration Description (Step 2) while considering the hardware description files. Additionally, generate a header file (Ioc.h) for inclusion in RTE.c to provide definitions, function prototypes and macros.

Each atomic communication has to be specified in the IOC Configuration Description in a standardized XML format. There is one description block per communication operation specifying:

- Unique identifier
- Data type(s)
- Sender properties
- Receiver properties
- Name of callback function on receiver side in case of notification.
- Whether communication is queued or unqueued (last is best)
- In case of queued communication: Length of the queue

For details see chapter 10.3

For each inter-OS-Application communication, the RTE generator creates one or more calls to an IOC function to send or receive data, and adds a corresponding description block to the IOC Configuration Description.

There are possibly multiple sources which contribute to the IOC configuration (e.g., RTE, CDD). The main input will come from the RTE generator. Other sources for the IOC Configuration Description (not supported in this specification revision) might be BSW module configuration tools or non-AUTOSAR components, which are allowed to use BSW services.

In ECUs or Software Clusters with only one OS-Application, the IOC Configuration Description can be omitted.

[SWS_Os_00824] ⌈All the data allocated by the OS for the IOC communication shall be wrapped with the memory allocation keywords mechanism

```
#define OS_<IE>_START_SEC_<sadm>
#include "Os_MemMap.h"

<IOC buffers>

#define OS_<IE>_STOP_SEC_<sadm>
#include "Os_MemMap.h"
```

where <IE> is the shortName of the sending OsApplication configured in OsIocSendingOsApplicationRef of the respective OsIocCommunication channel, and <sadm> is the shortName of the referred swAddrMethod, if configured in OsMemoryMappingCodeLocationRef of the respective OsIocDataProperties within the OsIocCommunication channel. If the OsMemoryMappingCodeLocationRef is not defined the OS is permitted to select an appropriate swAddrMethod.⌋

7.10.7 IOC integration examples

This section describes two typical use cases that show how the IOC can support communication between OS-Applications. In both examples the OS-Applications are located on different cores of a Multi-Core system.

7.10.7.1 Example 1 - 1:1 sender/receiver communication without notification

One Software Component sends data items in *event* semantics (queued) to another Software Component located on a different core. A runnable entity on the receiver side is invoked periodically (e.g. by an Alarm) and receives the data via RTE (see figure 7.24).

Because the communication crosses core boundaries, the RTE invokes the IOC to transfer the data from core 0 to core 1.

On the sending side, the

```
Rte_Send_<port>_<item> (..., <data>)
```

call is mapped to an

```
IocSend_<Id> (<data>)
```

call.

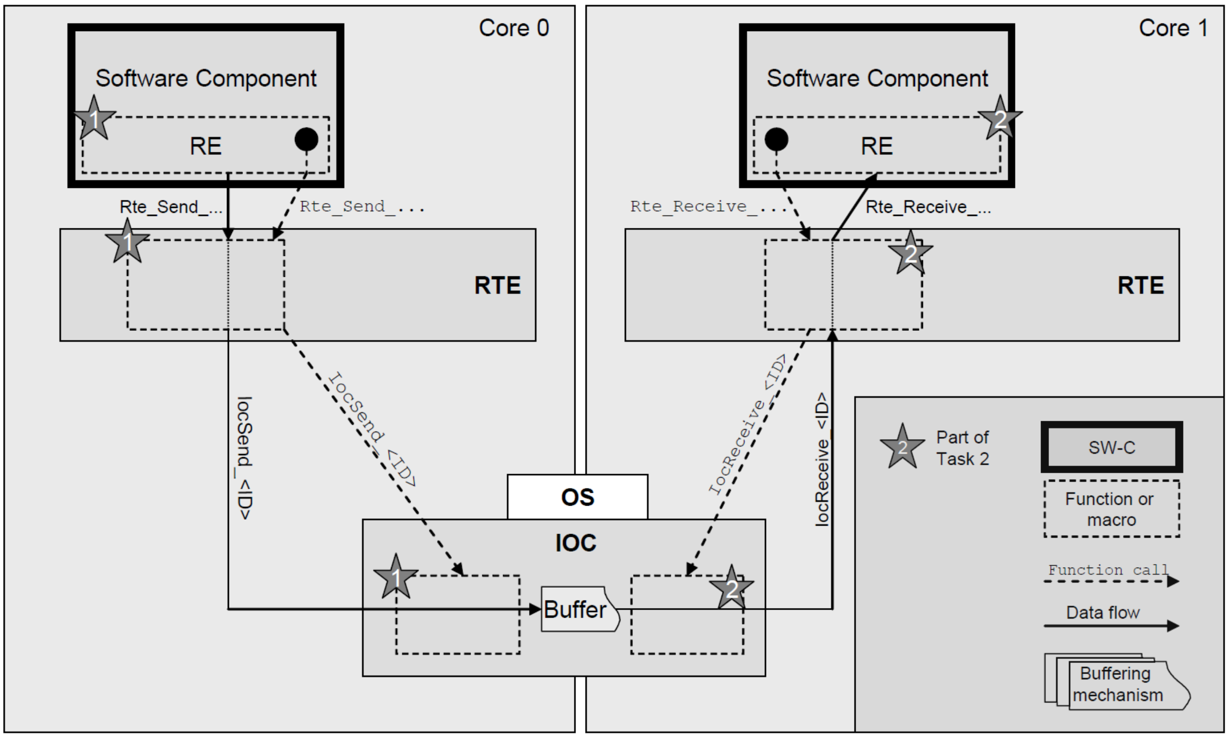

Figure 7.24: IOC without notification

In this example, the `IocSend` service writes the data into a buffer, located in a shared memory area which can get read by the receiver via the IOC.

On the receiving side, the receiving runnable gets invoked periodically. The

`Rte_Receive_<port>_<item> (..., <data>)`

call is mapped to an

`IocReceive_<Id> (<data>)`

call to read data from the IOC internal queue. An additional queue within the RTE is not necessary for 1:1 communication.

The IOC generator generates all the send and receive functions. The functions might be defined as macros for optimization purposes.

This kind of port to port communication without notification is suitable for:

- Sender/receiver communication
- Queued or unqueued communication
- 1:1 communication.

7.10.7.2 Example 2 - N:1 client/server communication with receiver notification by RTE

One Software Component invokes a service operation that is provided by another Software Component located on a different core. A runnable entity on the receiver side is activated to calculate the result (see figure 7.25).

The RTE realizes the service on client side by mapping the client/server call to a sender/receiver communication. Because the communication crosses core boundaries, the RTE uses the IOC to transfer the data from Core 0 to Core 1.

On the sending side, the

```
Rte_Call_<port>_<op> (..., <data>)
```

call is mapped to a

```
IocSend_<Id> (<data>)
```

call to transmit the parameters over the IOC to the core hosting the server runnable.

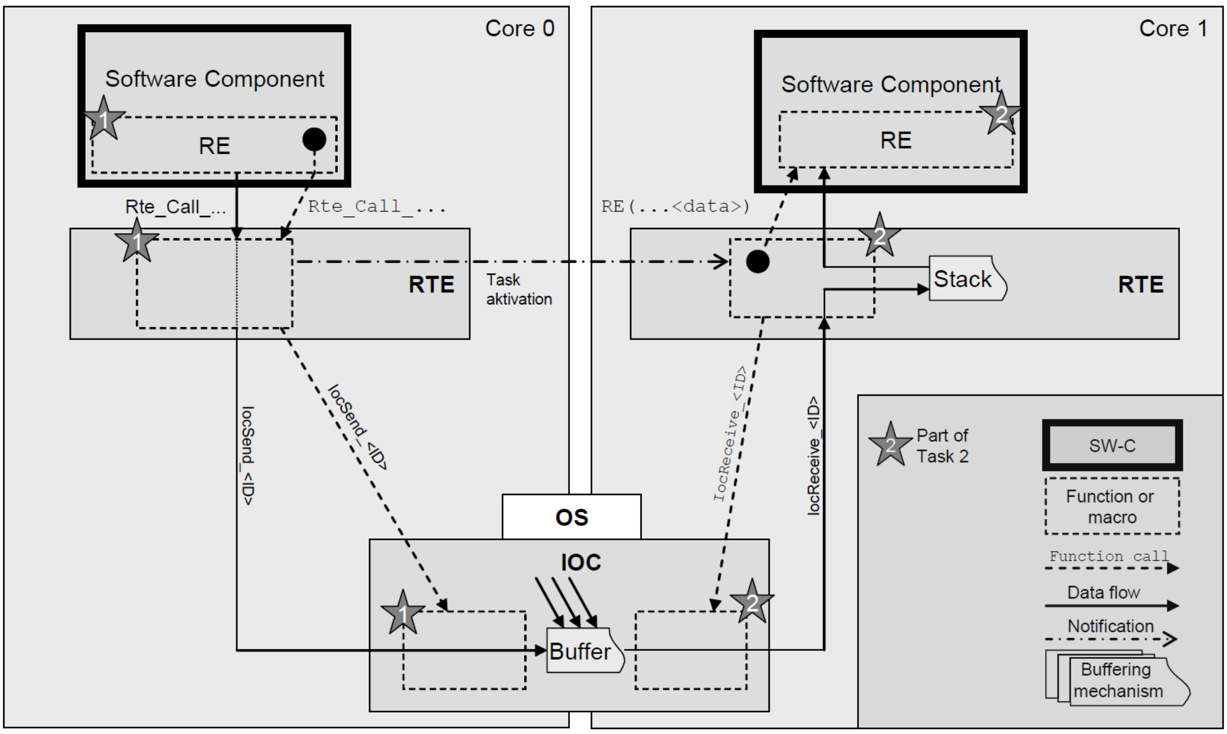

Figure 7.25: IOC with notification by RTE

After writing the data into the IOC internal queue buffer, the `Rte_Call` function uses an OS call to notify the receiver by activating the server `Task` on the receiving core. This `Task` is provided by the RTE. This `Task` body is responsible for reading the data from the IOC buffer by calling `IocReceive` function and for forwarding the data to the server runnable. Depending on the return value of the IOC function, the `IocReceive` and server runnable calls might be repeated several times to empty the IOC internal queued buffer (if specified).

The result of the service on Core 1 is transferred back to the client on Core 0 in a similar way. The communication path of the result is not displayed in figure 7.25.

This kind of port to port communication with notification by the RTE is suitable for:

- Sender/receiver communication with notification
- Client/server communication. In this case the RTE has to provide services to map the server call into 1:1 sender/receiver communication for the server call and another sender/receiver communication to return the result to the client
- Queued or unqueued communication
- 1:1 communication, if the receiver does not poll for data periodically (In this case, the solution in example 1 might have been more suitable)
- N:1 communication.

7.10.8 Future extensions

Some features are not supported by the first release of this specification, but might get added in a later release:

- In the future, the IOC will handle direct and efficient communication among BSW modules or between BSW modules and Software Components (via the RTE) located in different OS applications. Additional support of direct access from BSW modules to IOC services will be added.
- Other notification options (like activation of a specified `Task` on receiver side) might be added later to the IOC.

7.11 System Scalability

7.11.1 Background & Rationale

In order to customize the operating system to the needs of the user and to take full advantage of the processor features the operating system can be scaled accordingly with scalability classes, see [SWS_Os_00241].

Feature	Scalability Class 1	Scalability Class 2	Scalability Class 3	Scalability Class 4
Minimum number of `ScheduleTable`s supported	2	8	2	8

▽

△

Minimum number of OS-Applications supported	0	0	2	2
Minimum number of software Counters supported	8	8	8	8

Table 7.4: Minimum requirements of scalability classes

7.11.2 Requirements

[SWS_Os_00240]

Upstream requirements: SRS_Os_11012, SRS_Os_11016

⌈If an implementation of a lower scalability class supports features of higher classes then the interfaces for the features must comply with this Operating System software specification.⌋

[SWS_Os_00241] Scalability classes

Upstream requirements: SRS_Os_11012, SRS_Os_11016

⌈

Feature	Described in Section	Scalability Class 1	Scalability Class 2	Scalability Class 3	Scalability Class 4	Hardware requirements
OSEK OS (all conformance classes)	Chapter 7.1	Yes	Yes	Yes	Yes	
Counter Interface	IncrementCounter	Yes	Yes	Yes	Yes	
SWFRT Interface	GetCounterValue, GetElapsedValue	Yes	Yes	Yes	Yes	
ScheduleTables	Chapter 7.3	Yes	Yes	Yes	Yes	
Stack Monitoring	Chapter 7.5	Yes	Yes	Yes	Yes	
ProtectionHook	Chapter 7.8		Yes	Yes	Yes	
Timing Protection	Chapter 7.7.2		Yes		Yes	Timer(s) with high priority interrupt
Global Time/Synchronization Support	Chapter 7.4		Yes		Yes	Global time source
Memory Protection	Chapter 7.7.1, Chapter 7.7.4			Yes	Yes	MPU
OS-Applications	Chapter 7.6, Chapter 7.12	⋆[6]	⋆[7]	Yes	Yes	
Service Protection	Chapter 7.7.3			Yes	Yes	

▽

[6] see [SWS_Os_00764]
[7] see [SWS_Os_00764]

△

CallTrustedFunction	Chapter 7.7.5			Yes	Yes	(Non-)privileged Modes

The Operating System module shall support the features according to this given table.

⌋

[SWS_Os_00327] ⌈The Operating System module shall always use extended status in Scalability Class 3 and 4.⌋

7.12 Hook Functions

7.12.1 Background & Rationale

Hook routines as defined in OSEK OS run at the level of the Operating System module and therefore can only belong to the trusted environment. Furthermore, these hook routines are global to the system (system-specific) and will probably be supplied by the ECU integrator.

In AUTOSAR however, each OS-Application may have the need to execute application specific code e.g. initialize some hardware in its own additional (application-specific) startup hook. These are called application specific hook routines. In general the application specific hooks have the same properties as the hook routines described in the OSEK OS specification. Differences are described below.

7.12.2 Requirements

[SWS_Os_00439] ⌈The Operating System module shall provide the OSEK error macros (`OSError...()`) to all configured error hooks AND there shall be two (like in OIL) global configuration parameters to switch these macros on or off.⌋

StartupHook

[SWS_Os_00060] ⌈If an application-specific startup hook is configured for an OS-Application <App>, the Operating System module shall call StartupHook_<App> on startup of the Operating System module.⌋

[SWS_Os_00226] ⌈The Operating System module shall execute an application-specific startup hook with the access rights of the associated OS-Application.⌋

[SWS_Os_00236] ⌈If both a system-specific and one (or more) application specific startup hook(s) are configured, the Operating System module shall call the system-specific startup hook before the application-specific startup hook(s).⌋

ShutdownHook

[SWS_Os_00112] ⌈If an application-specific shutdown hook is configured for an OS-Application <App>, the Operating System module shall call `ShutdownHook_<App>` on shutdown of the OS.⌋

[SWS_Os_00225] ⌈The Operating System module shall execute an application-specific shutdown hook with the access rights of the associated OS-Application.⌋

[SWS_Os_00237] ⌈If both a system-specific and one (or more) application specific shutdown hook(s) are configured, the Operating System module shall call the system-specific shutdown hook after the application-specific shutdown hook(s).⌋

ErrorHook

[SWS_Os_00246]

Upstream requirements: SRS_Os_11013

⌈When an error occurs AND an application-specific error hook is configured for the faulty OS-Application <App>, the Operating System module shall call that application-specific error hook `ErrorHook_<App>` after the system specific error hook is called (if configured).⌋

[SWS_Os_00085] ⌈The Operating System module shall execute an application-specific error hook with the access rights of the associated OS-Application.⌋

[SWS_Os_00367] ⌈Operating System module's services which do not return a `StatusType` - except `ActivateTaskAsyn` and `SetEventAsyn` - shall not raise the error hook(s).⌋

7.13 Hardware peripheral access

7.13.1 Background & Rationale

On some MCU architectures, there are memory mapped hardware registers (peripheral area), which are only accessible in specific modes (e.g. in privileged mode). As long as a `Task`s/`ISR`s is running with full hardware access they can directly access these registers. If memory protection is used by the Operating System, Task/ISRs of non-trusted Os-Applications cannot access such registers directly because this would be recognized as a memory violation by the Operating System.

To allow access to such registers even from non-trusted applications the Operating Systems offers the following APIs to read, write and modify registers:

- ReadPeripheral8
- ReadPeripheral16
- ReadPeripheral32
- WritePeripheral8
- WritePeripheral16
- WritePeripheral32
- ModifyPeripheral8
- ModifyPeripheral16
- ModifyPeripheral32

In order to control the access to the registers the access has to be configured for each OsApplication. By this the Os can check during run-time if a caller has sufficient rights.

7.13.2 Requirements

[SWS_Os_00806]

Upstream requirements: SRS_Os_11005

⌈Check access to peripheral registers

The Operating System shall only execute access to peripheral registers via APIs Read PeripheralX, WritePeripheralX and ModifyPeripheralX if :

- parameter Address is in range of OsPeripheralAreaStartAddress and OsPeripheralAreaEndAddress
- parameter Area is valid
- the caller is configured to have sufficient rights (OsPeripheralAreaAccessingApplication).

⌋

[SWS_Os_00807]

Upstream requirements: SRS_Os_11005

⌈Error handling of peripheral access API

If the Operating System detects an error (see [[SWS_Os_00806]]) while executing a ReadPeripheralX, WritePeripheralX and ModifyPeripheralX the OS shall return the appropriate `StatusType` and call the `ErrorHook`. Otherwise `E_OK` shall be returned.⌋

7.14 Interrupt source API

7.14.1 Background & Rationale

The Operating System needs to guarantee the scheduling, wherefore it needs to be the only component which accesses the interrupt controller. Therefore it provides to other BSW/CDD components the interfaces `DisableInterruptSource`, `EnableInterruptSource` and `ClearPendingInterrupt` to give access to the interrupt control registers of category 2 `ISR`s.

The pair of `DisableInterruptSource`/`EnableInterruptSource` may be used for two different purposes:

1. A specific interrupt should be masked for a short time (potentially to avoid data consistency problems). A masked request shall be served afterwards, once the interrupt source gets enabled again.

2. Interrupt requests of a specific source should be ignored for a specific time (potentially a longer time e.g. while the CAN driver sleeps). After enabling the source, only new requests should be considered.

7.14.2 Requirements

[SWS_Os_00808]

Upstream requirements: SRS_Os_11011

⌈The Operating System shall provide for each category 2 interrupt source (`OsIsrCategory` == `CATEGORY_2`) the APIs `DisableInterruptSource`, `EnableInterruptSource` and `ClearPendingInterrupt`.⌋

`DisableInterruptSource`/`EnableInterruptSource` does not support nested calls.

[SWS_Os_00809]

Upstream requirements: SRS_Os_11011

⌈Nested calls of interrupt source control API

The Operating System shall return E_OS_NOFUNC (in EXTENDED status) in case DisableInterruptSource is called for an interrupt source which is already disabled or EnableInterruptSource is called for an interrupt source which is already enabled.⌋

[SWS_Os_00810]

Upstream requirements: SRS_Os_11011

⌈Error handling of interrupt source control API

If the Operating System detects an error while executing a DisableInterruptSource, EnableInterruptSource and ClearPendingInterrupt the OS shall return the appropriate StatusType and call the ErrorHook. Otherwise E_OK shall be returned.⌋

[SWS_Os_00811]

Upstream requirements: SRS_Os_11011

⌈A call of EnableInterruptSource shall enable the requested interrupt source by modifying the interrupt controller registers. Additionally it shall clear the interrupt pending flag.⌋

[SWS_Os_00812]

Upstream requirements: SRS_Os_11011

⌈A call of DisableInterruptSource shall disable the requested interrupt source by modifying the interrupt controller registers.⌋

[SWS_Os_00813]

Upstream requirements: SRS_Os_11011

⌈A call of ClearPendingInterrupt shall clear the interrupt pending flag by modifying the respective interrupt controller registers.⌋

[SWS_Os_00814]

Upstream requirements: SRS_Os_11011

⌈Clearing of pending interrupts shall be restricted to clearing the pending flag in the interrupt controller.⌋

Note: This does not necessarily guarantee that the interrupt request is cleared successfully, i.e. the ISR may still be serviced afterwards. (This may happen due to racing conditions or as the request needs to be cleared in the requesting hardware unit also.)

7.15 Error classification

AUTOSAR BSW modules normally report their errors to Det (development errors) or Dem (production errors). The OS handles errors differently (see also [2]) and does not report its errors to Dem/Det. If a reporting of errors to Dem/Det is needed the user can perform these actions in the ErrorHook.

The following table contains all error codes which might be reported from the OS (besides those already defined in [2])

[SWS_Os_91025] Definiton of development errors in module Os

Upstream requirements: SRS_BSW_00480

⌈

Type of error	*Related error code*	*Error value*
An invalid address is given as a parameter to a service.	E_OS_ILLEGAL_ADDRESS	Assigned by implementation
A memory access violation occurred	E_OS_PROTECTION_MEMORY	Assigned by implementation
A stack fault detected via stack monitoring by the OS	E_OS_STACKFAULT	Assigned by implementation
Core is not available	E_OS_CORE	Assigned by implementation
Potential deadlock due to wrong nesting	E_OS_NESTING_DEADLOCK	Assigned by implementation
Tasks terminates without a TerminateTask() or ChainTask() call.	E_OS_MISSINGEND	Assigned by implementation
A Task/Category 2 ISR blocks for too long	E_OS_PROTECTION_LOCKED	Assigned by implementation
De-scheduling with occupied spinlock	E_OS_SPINLOCK	Assigned by implementation
Service cannot be called.	E_OS_SERVICEID	Assigned by implementation
A trap occurred	E_OS_PROTECTION_EXCEPTION	Assigned by implementation
Deadlock situation due to interference	E_OS_INTERFERENCE_DEADLOCK	Assigned by implementation
A Task or Category 2 ISR exceeds its execution time budget	E_OS_PROTECTION_TIME	Assigned by implementation
A service of the OS is called inside an interrupt disable/enable pair.	E_OS_DISABLEDINT	Assigned by implementation
A Task/Category 2 ISR arrives before its timeframe has expired	E_OS_PROTECTION_ARRIVAL	Assigned by implementation

⌋

7.16 ARTI Debug Information

[SWS_Os_00858]

Upstream requirements: SRS_Os_12001

⌈The OS shall create an ARTI module description file.⌋

[SWS_Os_00829]

Upstream requirements: SRS_Os_12003

⌈ARTI module description file shall support all ORTI containers.⌋

The ARTI Debug Information intends to enable the attached tool to evaluate and display information about the operating system, its state, its performance, the different `Task` states, the different operating system objects etc.

Additionally the ARTI Debug Information contains dynamic information as a set of attributes that are represented by formulas to access corresponding dynamic values. Formulas for dynamic data access are comprised of constants, operations, and symbolic names within the target file. To obtain internal values of the required OS objects, the debug tool can then evaluate the given formula.

7.16.1 OS ARTI Objects

It describes a set of attributes for system objects and a method for interpreting the data obtained. The types defined in the section are specified to allow the debugger to determine the target memory access method as well as the best way of displaying the retrieved data. In most cases the information that the user will require to see is a textual description of an attribute rather than the actual value read from the variable.

An example of this is as follows; when a user requests the current state of a `Task` he will expect to see something like `RUNNING`, `WAITING`, `READY` or `SUSPENDED`, instead of the actual numeric value that is used by the OS to represent this information internally. For this reason a mapping is specified, which allows a kernel manufacturer to describe how an internal OS value must be mapped to a descriptive value.

- ArtiOs
- ArtiHwCore
- ArtiOsAlarm
- ArtiOsContext
- ArtiOsIsr
- ArtiOsResource

- ArtiOsMessageContainer
- ArtiOsScheduleTable
- ArtiOsSpinlock
- ArtiOsStack
- ArtiOsTask

These objects are declared in Arti containers with definitions named "*Class". The instances of these objects are placed in the same Arti container with definitions named "*Instance".

7.17 ARTI Hook Macros

[SWS_Os_00836]

Upstream requirements: RS_ARTIFO_00014, SRS_Os_12002

⌈The OS shall incorporate special macros that can be used by an ARTI trace tool to insert tracing functionality of any kind.⌋

[SWS_Os_00837]

Upstream requirements: RS_ARTIFO_00014, SRS_Os_12002

⌈The hooks for an AUTOSAR CP OS shall follow the general structure of ARTI macros: `ARTI_TRACE(_contextName, _className, _instanceName, instanceParameter, _eventName, eventParameter);`⌋

Some of the parameters are using literal text (Token) rather than a symbolic identifier. This allows a macro definition concatenating these parameters to more specific macros. Passing and evaluating all parameters at run-time would be very costly especially by means of run-time consumption. Here is a possible implementation of the generic `ARTI_TRACE` macro as it could be defined by a ARTI trace tool vendor to match the interface of his trace tool:

```
#define ARTI_TRACE(_contextName, _className, _instanceName,
    instanceParameter, _eventName, eventParameter) \
ARTI_TRACE ## _ ## _className ## _ ## _eventName ## _ ## _instanceName
    ## _ ## _contextName ( (instanceParameter), (eventParameter) )
```

Such an implementation will generate one hook for all the possible combinations of _className, _eventName and _contextName and pass only parameters instance_id and event_value at run-time.

The parameters' meanings are described in the following.

- _contextName Token, literal text, name of the context. One of the following:

  - NOSUSP indicating that the hook gets called in a context where interrupts are disabled
  - SPRVSR indicating that the called hook may disable interrupts
  - USER indicating the called hook cannot disable interrupts
- _className Token, literal text, name of the class of macros. Predefined classes for an AUTOSAR OS are:
  - AR_CP_OS_APPLICATION starts and stops the application
  - AR_CP_OS_TASK schedules `Task`s
  - AR_CP_OS_CAT2ISR dispatches Category 2 interrupts
  - AR_CP_OS_SERVICECALLS calls service routines
  - AR_CP_OS_SPINLOCK calls spinlocks
  - AR_CP_OS_HOOK calls OS hooks
- _instanceName Short name of the OS instance as defined in the ARXML.
- instanceParameter Index [uint32] 0..4294967295 of the CPU core as seen by the OS (<Core Index>). Should always start with 0 and count up consecutively. This might be equal to the index of the physical core, but doesn't have to be.
- _eventName Token, literal text, name of the event as defined for a particular class.
- eventParameter A [uint32] 0..4294967295 value as an argument to an event.

Therefore all ARTI macros for an AUTOSAR OS do compile the following template:

```
ARTI_TRACE(_contextName, <AR OS Class Name>, <OS Short Name>, <Core
    Index>, <Event Name>, <Event Parameter>)
```

Example of hook call in OS:

```
ARTI_TRACE( NOSUSP, AR_CP_OS_TASK, OS1, (uint32)GetCoreID(),
    OsTask_Activation, (uint32)GetTaskID() );
```

Example of preprocessed output:

```
ARTI_TRACE_NOSUSP_AR_CP_OS_TASK_OS1_OsTask_Activation( (uint32)
    GetCoreID(), (uint32)GetTaskID() );
```

7.17.1 Class AR_CP_OS_APPLICATION

[SWS_Os_00838]

Upstream requirements: RS_Arti_00029

⌈The OS shall create events of class AR_CP_OS_APPLICATION to allow tracing of OS applications [as defined for the AUTOSAR Classic Platform]⌋

The states used by ARTI are based on the states of OS-Applications, see figure 7.10 in chapter Background & Rationale 7.6.1 for details.

States used by ARTI:

ARTI	OS
Initial	-
Accessible	APPLICATION_ACCESSIBLE
Terminated	APPLICATION_TERMINATED

Transitions used by ARTI:

Name	Transition	Event Name
Start	Initial -> Accessible	OsApplication_Start
Terminate	Accessible -> Terminated	OsApplication_Terminate

[SWS_Os_00839]

Upstream requirements: RS_ARTIFO_00015

⌈ARTI macros of the class AR_CP_OS_APPLICATION shall compile the following template:

```
ARTI_TRACE(_contextName, AR_CP_OS_APPLICATION, <OS Short Name>, <Core
    ID>, <Event Name>, <Application ID>)
```

⌋

The <Core ID> for any event shall represent the core id where the corresponding application is running on.

The <Event Name> should follow the transition table above.

The <Application ID> shall be a numeric identifier of the OS Application.

7.17.2 Class AR_CP_OS_TASK

ARTI needs to trace all Task states and all state transitions within the OS. For some timing parameters (e.g. the "runtime" of a Task, which goes from started to terminated), the simple "ready" state of the OS is not enough. Tools evaluating the timings need to reconstruct a more complex state diagram by calculating the transitions from history. To be compatible to the pure OS state diagram, AR_CP_OS_TASK refers to this state model, knowing that tools need to postprocess the event flow to get all relevant information. However, if an OS implementation can provide a more detailed state diagram, ARTI allows to define more events that won't need postprocessing and allow earlier synchronization of the trace if it is truncated (limited trace buffers). This state diagram is then handled with the class "AR_CP_OSARTI_TASK". If possible, the second state machine is to be preferred.

AR_CP_OS_TASK

[SWS_Os_00840]

Upstream requirements: RS_Arti_00030

⌈The OS shall create events of class AR_CP_OS_TASK to allow tracing of `Task`s.⌋

The following state diagram shows the states and transitions as defined by the OS:

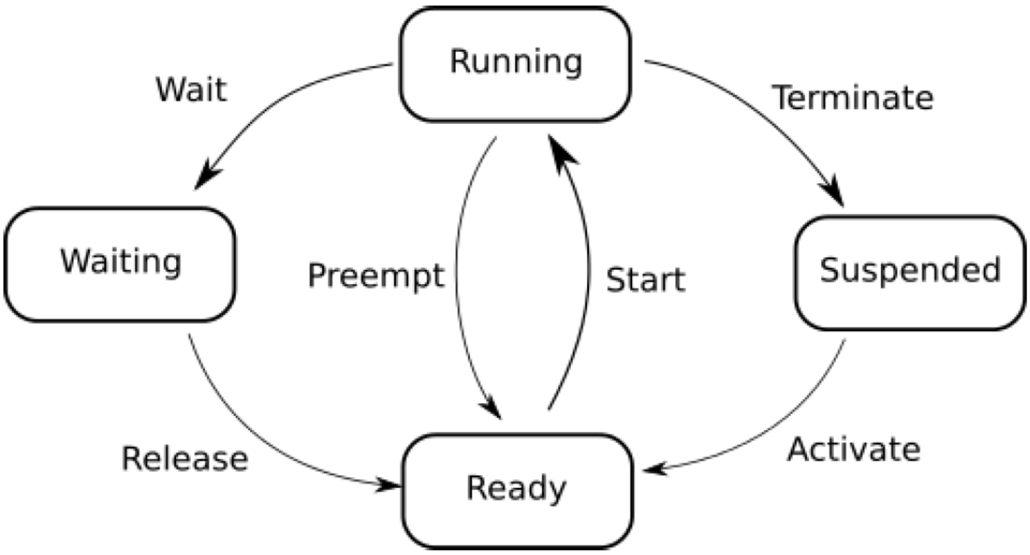

Figure 7.26: ARTI `Task` states

Transitions used by ARTI:

Name	Transition	`Event` Name
Activate	Suspended -> Ready	OsTask_Activate
Start	Ready -> Running	OsTask_Start
Preempt	Running -> Ready	OsTask_Preempt
Wait	Running -> Waiting	OsTask_Wait
Release	Waiting -> Ready	OsTask_Release
Terminate	Running -> Suspended	OsTask_Terminate

AR_CP_OSARTI_TASK

The class AR_CP_OSARTI_TASK contains events allowing the tracing of OS `Task`s with an enhanced state model.

The following states diagram shows the state machine as used by ARTI:

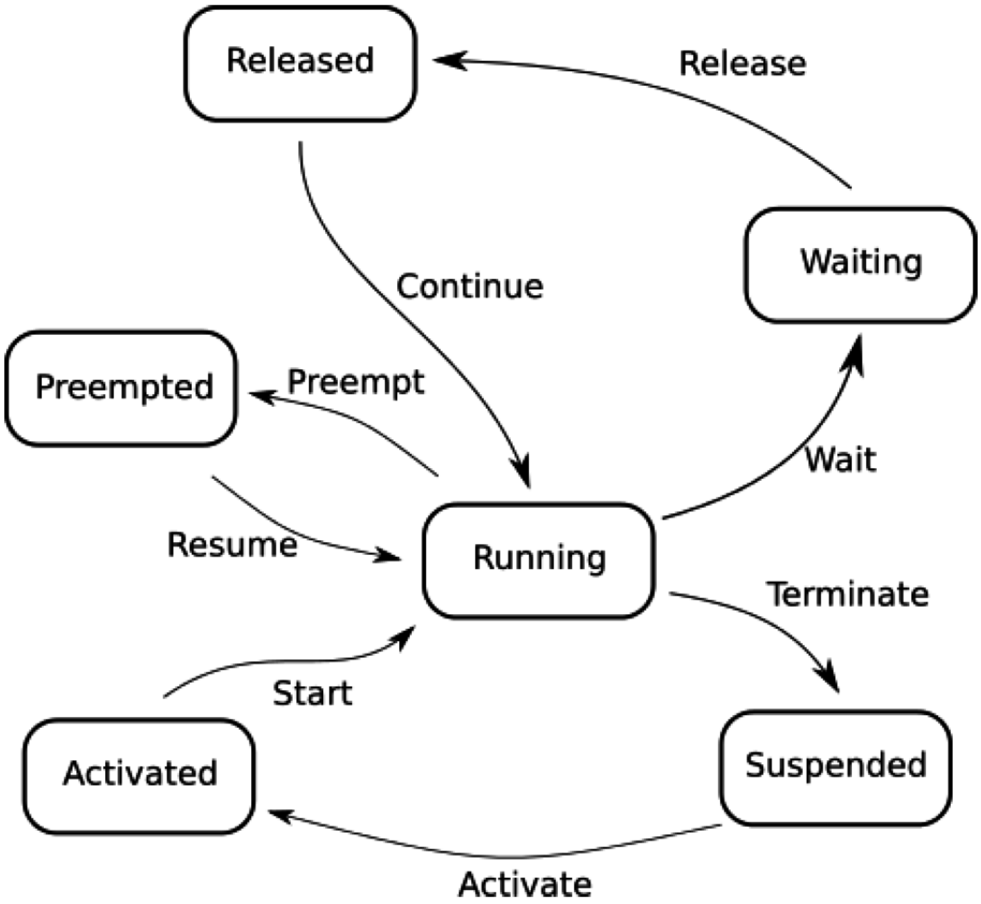

Figure 7.27: ARTI enhanced `Task` states

States used by ARTI:

ARTI	OS
Suspended	`SUSPENDED`
Activated	`READY`
Running	`RUNNING`
Preempted	`READY`
Waiting	`WAITING`
Released	`READY`

Transitions used by ARTI:

Name	Transition	`Event` Name
Activate	Suspended -> Activated	OsTask_Activate
Start	Activated -> Running	OsTask_Start
Preempt	Running -> Preempted	OsTask_Preempt
Resume	Preempted -> Running	OsTask_Resume
Wait	Running -> Waiting	OsTask_Wait

▽

△

Name	Transition	Event Name
Release	Waiting -> Released	OsTask_Release
Continue	Released -> Running	OsTask_Continue
Terminate	Running -> Suspended	OsTask_Terminate

[SWS_Os_00841]

Upstream requirements: RS_ARTIFO_00015

⌈ARTI macros of the classes AR_CP_OS_TASK and AR_CP_OSARTI_TASK shall compile the following templates:

```
ARTI_TRACE(_contextName, AR_CP_OS_TASK, <OS Short Name>, <Core ID>, <
    Event Name>, <Task ID>)
ARTI_TRACE(_contextName, AR_CP_OSARTI_TASK, <OS Short Name>, <Core ID>,
     <Event Name>, <Task ID>)
```

⌋

The <Core ID> for any event shall represent the core id where the corresponding Task is scheduled on.

The <Event Name> should follow the transition table above.

The <Task ID> shall be a numeric identifier of the OS Task.

7.17.3 Class AR_CP_OS_CAT2ISR

[SWS_Os_00849]

Upstream requirements: RS_Arti_00031

⌈The OS shall create events to trace all states of Cat2Isrs and all state transitions within the OS ("Cat2Isr" refers to a category 2 interrupt service routine).⌋

For some timing parameters (e.g. the interrupt pending time), the simple Category 2 interrupt start/stop of the OS is not enough. Tools evaluating the timings need to reconstruct a more complex state diagram by calculating the transitions from history. To be compatible to the OS, AR_CP_OS_CAT2ISR refers to this state model, knowing that tools need to postprocess the event flow to get all relevant information. However, if an OS implementation can provide a more detailed state diagram, ARTI allows to define more events that won't need postprocessing and allow earlier synchronization of the trace if it is truncated (limited trace buffers). This state diagram is then handled with the class "AR_CP_OSARTI_CAT2ISR". If possible, the second state machine is to be preferred.

AR_CP_OS_CAT2ISR

The class AR_CP_OS_CAT2ISR contains events allowing the tracing of Category 2 interrupts as defined for the AUTOSAR Classic Platform.

The following state diagram shows the states and transitions as defined by the OS:

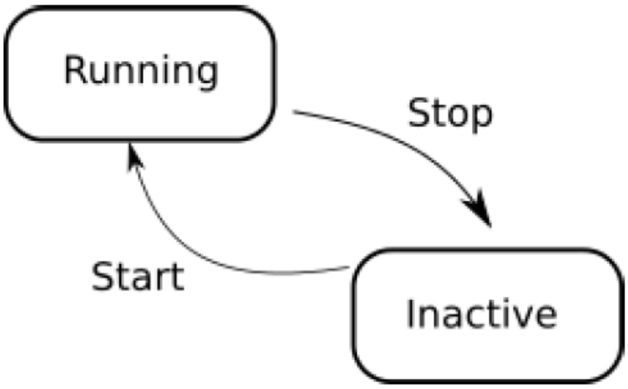

Figure 7.28: ARTI category 2 `ISR` states

Transitions used by ARTI:

Name	Transition	`Event` Name
Start	Inactive -> Running	OsCat2Isr_Start
Stop	Running -> Inactive	OsCat2Isr_Stop

AR_CP_OSARTI_CAT2ISR

The class AR_CP_OSARTI_CAT2ISR contains events allowing the tracing of Category 2 interrupts with an enhanced state model.

The following state diagram shows the state machine as used by ARTI:

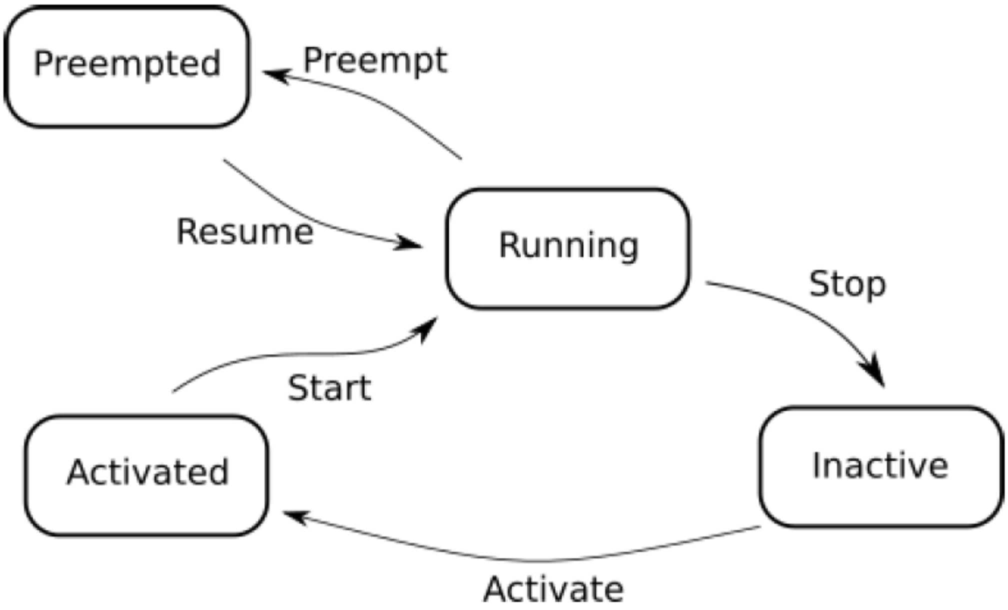

Figure 7.29: ARTI enhanced category 2 ISR states

States used by ARTI:

ARTI	OS
Inactive	Inactive
Activated	Inactive
Running	Running
Preempted	Running

Transitions used by ARTI:

Name	Transition	Event Name
Activate	Inactive-> Activated	OsCat2Isr_Activate
Start	Activated -> Running	OsCat2Isr_Start
Preempt	Running -> Preempted	OsCat2Isr_Preempt
Resume	Preempted -> Running	OsCat2Isr_Resume
Stop	Running -> Inactive	OsCat2Isr_Stop

[SWS_Os_00842]

Upstream requirements: RS_ARTIFO_00015

⌈ARTI macros of the classes AR_CP_OS_CAT2ISR and AR_CP_OSARTI_CAT2ISR shall compile the following template:

```
ARTI_TRACE(_contextName, AR_CP_OS_CAT2ISR, <OS Short Name>, <Core Index
    >, <Event Name>, <Cat2Isr Index>)
ARTI_TRACE(_contextName, AR_CP_OSARTI_CAT2ISR, <OS Short Name>, <Core
    Index>, <Event Name>, <Cat2Isr Index>)
```

⌋

The <Core Index> for any event shall represent the core index where the corresponding Category 2 interrupt is scheduled on.

The <Event Name> should follow the transition table above.

The <Cat2Isr Index> shall be a numeric identifier of the Category 2 interrupt.

7.17.4 Class AR_CP_OS_SERVICECALLS

[SWS_Os_00843]

Upstream requirements: RS_Arti_00032

⌈The OS shall create events of class AR_CP_OS_SERVICECALLS when entering and exiting the service call from an application context.⌋

These hooks shall only be called, if the service call is called from an application context. It shall not be called, if the service call is used within the OS context.

The events apply only to the entries and exits of the service calls, not to the objects (and their states) handled by the service call.

[SWS_Os_00844]

Upstream requirements: RS_ARTIFO_00015

⌈ARTI macros of the class AR_CP_OS_SERVICECALLS shall compile the following template:

```
ARTI_TRACE(_contextName, AR_CP_OS_SERVICECALLS, <OS Short Name>, <Core
    Index>, <eventName>, <eventParameter>)
```

⌋

The <Core Index> for any event in the following table shall represent the core id where the corresponding service call is called.

The <eventName> is a string literal composed of a prefix "OsServiceCall", the service call name and "_Start" or "_Return" for the entry or exit of the service call. E.g. when ActivateTask is called, the event names on entry and exit are OsServiceCall_ActivateTask_Start rsp. OsServiceCall_ActivateTask_Return.

The <eventParamter> is an uint32 representation of either one of the function parameters or the return value. It depends on the service call and is listed in the following table:

OS Service Call	From	eventParameter on Start	on Return
ActivateTask	OSEK	TaskID	(StatusType) returnValue
TerminateTask	OSEK	TaskID	(StatusType) returnValue
ChainTask	OSEK	TaskID	(StatusType) returnValue
Schedule	OSEK	0	(StatusType) returnValue
GetTaskID	OSEK	0	(TaskType) *TaskID
GetTaskState	OSEK	TaskID	(TaskStateType) *State
EnableAllInterrupts	OSEK	0	0
DisableAllInterrupts	OSEK	0	0
ResumeAllInterrupts	OSEK	0	0
SuspendAllInterrupts	OSEK	0	0
ResumeOSInterrupts	OSEK	0	0
SuspendOSInterrupts	OSEK	0	0
GetResource	OSEK	ResID	(StatusType) returnValue
ReleaseResource	OSEK	ResID	(StatusType) returnValue
SetEvent	OSEK	TaskID	(StatusType) returnValue
ClearEvent	OSEK	Mask	(StatusType) returnValue
GetEvent	OSEK	TaskID	(EventMaskType) * Event
WaitEvent	OSEK	Mask	(StatusType) returnValue
GetAlarmBase	OSEK	AlarmID	(AlarmBaseRefType) Info
GetAlarm	OSEK	AlarmID	(TickType) *Tick
SetRelAlarm	OSEK	AlarmID	(StatusType) returnValue
SetAbsAlarm	OSEK	AlarmID	(StatusType) returnValue
CancelAlarm	OSEK	AlarmID	(StatusType) returnValue
GetActiveApplicationMode	OSEK	0	(AppModeType) returnValue
StartOS	OSEK	Mode	not applicable
ShutdownOS	OSEK	Error	not applicable
GetApplicationID	AUTOSAR	0	(ApplicationType) return Value
GetCurrentApplicationID	AUTOSAR	0	(ApplicationType) return Value
GetISRID	AUTOSAR	0	(ISRType) returnValue
CallTrustedFunction	AUTOSAR	FunctionIndex	(StatusType) returnValue
CheckISRMemoryAccess	AUTOSAR	ISRID	(AccessType) returnValue
CheckTaskMemoryAccess	AUTOSAR	TaskID	(AccessType) returnValue
CheckObjectAccess	AUTOSAR	ApplID	(ObjectAccessType) return Value
CheckObjectOwnership	AUTOSAR	ObjectTypeType	(ApplicationType) return Value
StartScheduleTableRel	AUTOSAR	ScheduleTableID	(StatusType) returnValue
StartScheduleTableAbs	AUTOSAR	ScheduleTableID	(StatusType) returnValue
StopScheduleTable	AUTOSAR	ScheduleTableID	(StatusType) returnValue
NextScheduleTable	AUTOSAR	ScheduleTableID_To	(StatusType) returnValue
StartScheduleTableSynchron	AUTOSAR	ScheduleTableID	(StatusType) returnValue
SyncScheduleTable	AUTOSAR	ScheduleTableID	(StatusType) returnValue
SetScheduleTableAsync	AUTOSAR	ScheduleTableID	(StatusType) returnValue

▽

△

OS Service Call	From	eventParameter on Start	on Return
GetScheduleTableStatus	AUTOSAR	ScheduleTableID	(ScheduleTableStatusType) *Schedule Status
IncrementCounter	AUTOSAR	CounterID	(StatusType) returnValue
GetCounterValue	AUTOSAR	CounterID	(TickType) *Value
GetElapsedValue	AUTOSAR	CounterID	(TickType) *ElapsedValue
TerminateApplication	AUTOSAR	Application	(StatusType) returnValue
GetApplicationState	AUTOSAR	Application	(ApplicationStateType) *Value
GetNumberOfActivatedCores	AUTOSAR	0	(uint32) returnValue
GetCoreID	AUTOSAR	0	(CoreIdType) returnValue
StartCore	AUTOSAR	CoreID	(StatusType) *Status
GetSpinlock	AUTOSAR	SpinlockId	(StatusType) returnValue
ReleaseSpinlock	AUTOSAR	SpinlockId	(StatusType) returnValue
TryToGetSpinlock	AUTOSAR	SpinlockId	(TryToGetSpinlockType) *Success
ShutdownAllCores	AUTOSAR	Error	0
ControlIdle	AUTOSAR	IdleMode	(StatusType) returnValue
ReadPeripheral8	AUTOSAR	Address	(uint8) *ReadValue
ReadPeripheral16	AUTOSAR	Address	(uint16) *ReadValue
ReadPeripheral32	AUTOSAR	Address	(uint32) *ReadValue
WritePeripheral8	AUTOSAR	Address	(StatusType) returnValue
WritePeripheral16	AUTOSAR	Address	(StatusType) returnValue
WritePeripheral32	AUTOSAR	Address	(StatusType) returnValue
ModifyPeripheral8	AUTOSAR	Address	(StatusType) returnValue
ModifyPeripheral16	AUTOSAR	Address	(StatusType) returnValue
ModifyPeripheral32	AUTOSAR	Address	(StatusType) returnValue
EnableInterruptSource	AUTOSAR	ISRID	(StatusType) returnValue
DisableInterruptSource	AUTOSAR	ISRID	(StatusType) returnValue
ClearPendingInterrupt	AUTOSAR	ISRID	(StatusType) returnValue
ActivateTaskAsyn	AUTOSAR	id	0
SetEventAsyn	AUTOSAR	id	0
isOsStarted	AUTOSAR	0	(boolean) returnValue

If the eventParameter of a returning service call is not of type StatusType, and if the service call does not return E_OK, the hook shall be called with a non-valid value as eventParameter, to give the hook consuming tool the possibility to detect the failure of the call.

7.17.5 Class AR_CP_OS_SPINLOCK

[SWS_Os_00845]

Upstream requirements: RS_Arti_00033

⌈The OS shall create events of class AR_CP_OS_SPINLOCK to allow tracing of OS spinlocks and all state transistions within the OS.⌋

These macros mark an event of an actual state change, not the OS service call. (E.g. getting a spinlock may happen later than requesting it; a request to release may not cause a release if it is already released.)

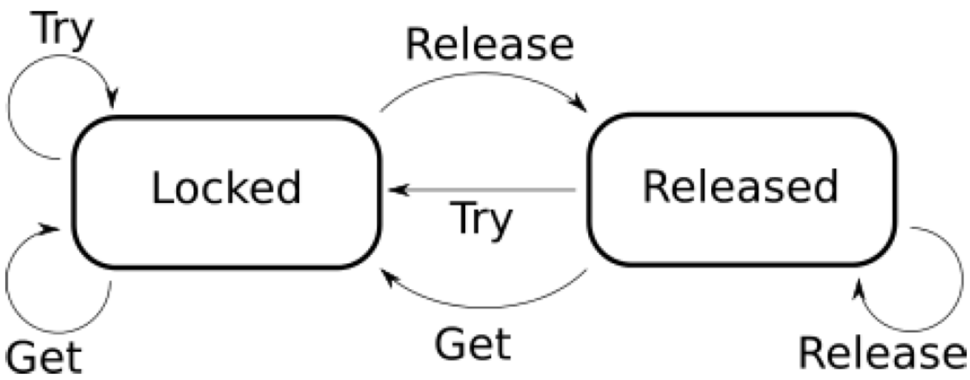

Figure 7.30: ARTI spin lock states

[SWS_Os_00846]

Upstream requirements: RS_ARTIFO_00015

⌈ARTI macros of the class AR_CP_OS_SPINLOCK shall compile the following template:

```
ARTI_TRACE(_contextName, AR_CP_OS_SPINLOCK, <OS Short Name>, <Core
    Index>, <_eventName>, <eventParameter>)
```

⌋

The <Core Index> for any event in the following table shall represent the core id where the corresponding service call is called.

The following events are part of the class AR_CP_OS_SPINLOCK:

Event description	State transition	_eventName	eventParameter
Locking Spinlock	Released -> Locked	OsSpinlock_Locked	SpinlockId
Releasing Spinlock	Locked -> Released	OsSpinlock_Released	SpinlockId

7.17.6 Class AR_CP_OS_HOOK

[SWS_Os_00856]

Upstream requirements: RS_Arti_00034

⌈The OS shall create events of class AR_CP_OS_HOOK when entering and exiting the hook function.⌋

[SWS_Os_00857]

Upstream requirements: RS_Arti_00034, RS_ARTIFO_00015

⌈ARTI macros of the class AR_CP_OS_HOOK shall compile the following template:

```
ARTI_TRACE(_contextName, AR_CP_OS_HOOK, <OS Short Name>, <Core Index>,
    <eventName>, <eventParameter>)
```

⌋

The <Core Index> for any event in the following table shall represent the core id on which the corresponding hook function is executed.

The <eventName> is a string literal composed of the prefix OsHook, the hook function name and _Start or _Return for the entry or exit of the hook function. E.g. when the ErrorHook is called, the event names on entry and exit are OsHook_ErrorHook_Start respectively OsHook_ErrorHook_Return.

The <eventParamter> is an uint32 representation of either the function parameter or the return value. It depends on the hook function and is listed in the following table:

OS hook function	Origin	eventParameter on Start	eventParameter on Return
ErrorHook	OSEK	Error	0
ErrorHook_<App>	AUTOSAR	Error	0
PostTaskHook	OSEK	0	0
PreTaskHook	OSEK	0	0
ProtectionHook	AUTOSAR	Fatalerror	ReturnValue
StartupHook	OSEK	0	0
StartupHook_<App>	AUTOSAR	0	0
ShutdownHook	OSEK	Error	0
ShurtdownHook_<App>	AUTOSAR	Fatalerror	0

The ARTI hook which indicates the exit of the ProtectionHook (e.g. eventName is OsHook_ProtectionHook_Return) shall be invoked after the OS has checked the ReturnValue of the ProtectionHook (based on the requirements described in chapter 7.8.2., for example [SWS_Os_00506] or [SWS_Os_00475]). The eventParameter of this ARTI hook shall reflect the action which is taken by the OS as a result of the return value of the ProtectionHook.

8 API specification

This chapter contains the APIs offered by the operating system. Note that not all services are available in all scalability classes, and that the behavior of some services is extended for specific scalability classes. For example, API to relatively start a ScheduleTable has an additional check if the ScheduleTable allows implicit synchronization. This check is only performed in SC2 and SC4 where synchronization of ScheduleTables is supported.

8.1 Constants

8.1.1 Error codes of type StatusType

The following constants are available in a multi-core environment.

[SWS_Os_91007] Definition of datatype AppModeType ⌈

Name	AppModeType		
Kind	Enumeration		
Range	DONOTCARE	–	–
Description	AppMode of the core shall be inherited from another core.		
Available via	Os.h		

⌋

[SWS_Os_91002] Definition of datatype TotalNumberOfCores ⌈

Name	TotalNumberOfCores		
Kind	Type		
Derived from	scalar		
Range	1..65535	–	–
Description	The total number of cores		
Available via	Os.h		

⌋

Additional constants are in section 7.15 and [2].

8.2 Macros

OSMEMORY_IS_READABLE(<AccessType>)

OSMEMORY_IS_WRITEABLE(<AccessType>)

OSMEMORY_IS_EXECUTABLE(<AccessType>)

OSMEMORY_IS_STACKSPACE(<AccessType>)

These macros return a value not equal to zero if the memory is readable / writable / executable or stack space. The argument of the macros must be of type AccessType. Typically the return value of the service CheckTaskMemoryAccess (or CheckISRMemoryAccess) is used as argument for these macros.

8.3 Type definitions

8.3.1 ApplicationType (for OS-Applications)

[SWS_Os_00772] Definition of datatype ApplicationType ⌈

Name	ApplicationType		
Kind	Type		
Derived from	uint32		
Range	INVALID_OSAPPLICATION	–	–
Description	This data type identifies the OS-Application.		
Available via	Os.h		

⌋

[SWS_Os_00826]

Upstream requirements: SRS_Os_80005

⌈The range of valid OS-Applications described by ApplicationType shall be zero-based and consecutive. The value shall be defined by the EcucPartitionId of the EcucPartition referenced by the OS-Application. The Value of INVALID_OSAPPLICATION shall lie outside the range of valid OS-Application IDs.⌋

Note: The OS may use other representations internally for a performance optimal implementation.

[SWS_Os_CONSTR_00001]

Upstream requirements: SRS_Os_80005

⌈The relationship between OsApplication and EcucPartition is supposed to be unique. This means that an EcucPartition must not be referenced by multiple OsAppEcucPartitionRefs.⌋

[SWS_Os_CONSTR_00002]

Upstream requirements: SRS_Os_80005

⌈EcucPartitionIds shall be unique, zero based and consecutive.⌋

8.3.2 ApplicationStateType

[SWS_Os_00773] Definition of datatype ApplicationStateType ⌈

Name	ApplicationStateType		
Kind	Type		
Derived from	scalar		
Range	APPLICATION_ ACCESSIBLE	–	–
	APPLICATION_ TERMINATED	–	–
Description	This data type identifies the state of an OS-Application.		
Available via	Os.h		

⌋

8.3.3 ApplicationStateRefType

[SWS_Os_00774] Definition of datatype ApplicationStateRefType ⌈

Name	ApplicationStateRefType
Kind	Type
Derived from	pointer
Description	This data type points to location where a ApplicationStateType can be stored.
Available via	Os.h

⌋

8.3.4 TrustedFunctionIndexType

[SWS_Os_00775] Definition of datatype TrustedFunctionIndexType ⌈

Name	TrustedFunctionIndexType
Kind	Type
Derived from	scalar
Description	This data type identifies a trusted function.
Available via	Os.h

⌋

8.3.5 TrustedFunctionParameterRefType

[SWS_Os_00776] Definition of datatype TrustedFunctionParameterRefType ⌈

Name	TrustedFunctionParameterRefType
Kind	Type
Derived from	pointer
Description	This data type points to a structure which holds the arguments for a call to a trusted function.
Available via	Os.h

⌋

8.3.6 AccessType

[SWS_Os_00777] Definition of datatype AccessType ⌈

Name	AccessType
Kind	Type
Derived from	integral
Description	This type holds information how a specific memory region can be accessed.
Available via	Os.h

⌋

8.3.7 ObjectAccessType

[SWS_Os_00778] Definition of datatype ObjectAccessType ⌈

Name	ObjectAccessType		
Kind	Type		
Derived from	implementation_specific		
Range	ACCESS	–	–
	NO_ACCESS	–	–
Description	This data type identifies if an OS-Application has access to an object.		
Available via	Os.h		

⌋

8.3.8 ObjectTypeType

[SWS_Os_00779] Definition of datatype ObjectTypeType ⌈

Name	ObjectTypeType		
Kind	Type		
Derived from	implementation_specific		
Range	OBJECT_TASK	–	–
	OBJECT_ISR	–	–
	OBJECT_ALARM	–	–
	OBJECT_RESOURCE	–	–
	OBJECT_COUNTER	–	–
	OBJECT_ SCHEDULETABLE	–	–
Description	This data type identifies an object.		
Available via	Os.h		

⌋

8.3.9 MemoryStartAddressType

[SWS_Os_00780] Definition of datatype MemoryStartAddressType ⌈

Name	MemoryStartAddressType
Kind	Pointer
Type	void*
Description	This data type is a pointer which is able to point to any location in the MCU address space.
Available via	Os.h

⌋

8.3.10 MemorySizeType

[SWS_Os_00781] Definition of datatype MemorySizeType ⌈

Name	MemorySizeType
Kind	Type
Derived from	implementation_specific
Description	This data type holds the size (in bytes) of a memory region.
Available via	Os.h

⌋

8.3.11 ISRType

[SWS_Os_00782] Definition of datatype ISRType ⌈

Name	ISRType		
Kind	Type		
Derived from	implementation_specific		
Range	INVALID_ISR	–	–
Description	This data type identifies an interrupt service routine (ISR).		
Available via	Os.h		

⌋

8.3.12 ScheduleTableType

[SWS_Os_00783] Definition of datatype ScheduleTableType ⌈

Name	ScheduleTableType
Kind	Type
Derived from	implementation_specific
Description	This data type identifies a schedule table.
Available via	Os.h

⌋

8.3.13 ScheduleTableStatusType

[SWS_Os_00784] Definition of datatype ScheduleTableStatusType ⌈

Name	ScheduleTableStatusType		
Kind	Type		
Derived from	implementation_specific		
Range	SCHEDULETABLE_STOPPED	–	–
	SCHEDULETABLE_NEXT	–	–
	SCHEDULETABLE_WAITING	–	–
	SCHEDULETABLE_RUNNING	–	–

▽

△

	SCHEDULETABLE_ RUNNING_AND_ SYNCHRONOUS	–	–
Description	This type describes the status of a schedule. The status can be one of the following: • The schedule table is not started (SCHEDULETABLE_STOPPED) • The schedule table will be started after the end of currently running schedule table (schedule table was used in NextScheduleTable() service) (SCHEDULETABLE_NEXT) • The schedule table uses explicit synchronization, has been started and is waiting for the global time. (SCHEDULETABLE_WAITING) • The schedule table is running, but is currently not synchronous to a global time source (SCHEDULETABLE_RUNNING) • The schedule table is running and is synchronous to a global time source (SCHEDULETABLE_ RUNNING_AND_SYNCHRONOUS)		
Available via	Os.h		

⌋

8.3.14 ScheduleTableStatusRefType

[SWS_Os_00785] Definition of datatype ScheduleTableStatusRefType ⌈

Name	ScheduleTableStatusRefType
Kind	Pointer
Type	ScheduleTableStatusType*
Description	This data type points to a variable of the data type ScheduleTableStatusType.
Available via	Os.h

⌋

8.3.15 ProtectionReturnType

[SWS_Os_00787] Definition of datatype ProtectionReturnType ⌈

Name	ProtectionReturnType		
Kind	Type		
Derived from	implementation_specific		
Range	PRO_IGNORE	–	–
	PRO_TERMINATETASKISR	–	–
	PRO_TERMINATEAPPL	–	–
	PRO_SHUTDOWN	–	–
	PRO_PREVENT_ ARRIVAL_RATE	–	–

▽

△

Description	This data type identifies a value which controls further actions of the OS on return from the protection hook.
Available via	Os.h

⌋

8.3.16 RestartType

[SWS_Os_00788] Definition of datatype RestartType ⌈

Name	RestartType		
Kind	Type		
Derived from	implementation_specific		
Range	OS_OSAPPLICATION_ RESTART	–	–
Description	This data type defines the use of a Restart Task after terminating an OS-Application.		
Available via	Os.h		

⌋

8.3.17 PhysicalTimeType

[SWS_Os_00789] Definition of datatype PhysicalTimeType ⌈

Name	PhysicalTimeType
Kind	Type
Derived from	implementation_specific
Description	This data type is used for values returned by the conversion macro (see SWS_Os_00393) OS_ TICKS2<Unit>_<Counter>().
Available via	Os.h

⌋

8.3.18 CoreIdType

[SWS_Os_00790] Definition of datatype CoreIdType ⌈

Name	CoreIdType		
Kind	Type		
Derived from	scalar		
Range	OS_CORE_ID_MASTER	–	refers to the master core, may be an alias for OS_CORE_ID_<x>
	OS_CORE_ID_0..OS_CORE_ID_65533	–	refers to logical core 0, core 1 etc.
Description	CoreIdType is a scalar that allows identifying a single core. The CoreIdType shall represent the logical CoreID		
Available via	Os.h		

⌋

[SWS_Os_00825]

Upstream requirements: SRS_Os_80011

⌈The range of valid Core-IDs described by `CoreIdType` shall be zero-based and consecutive.⌋

8.3.19 SpinlockIdType

[SWS_Os_00791] Definition of datatype SpinlockIdType ⌈

Name	SpinlockIdType		
Kind	Type		
Derived from	scalar		
Range	1..65535	–	0x01, 0x02, ...: identifies a spinlock instance
	INVALID_SPINLOCK	0	represents an invalid spinlock instance
Description	SpinlockIdType identifies a spinlock instance and is used by the API functions: GetSpinlock, ReleaseSpinlock and TryToGetSpinlock.		
Available via	Os.h		

⌋

8.3.20 TryToGetSpinlockType

[SWS_Os_00792] Definition of datatype TryToGetSpinlockType

Upstream requirements: SRS_Os_80021

⌈

Name	TryToGetSpinlockType		
Kind	Enumeration		
Range	TRYTOGETSPINLOCK_SUCCESS	–	Spinlock successfully occupied
	TRYTOGETSPINLOCK_NOSUCCESS	–	Unable to occupy the spinlock
Description	The TryToGetSpinlockType indicates if the spinlock has been occupied or not.		
Available via	Os.h		

⌋

8.3.21 IdleModeType

[SWS_Os_00793] Definition of datatype IdleModeType ⌈

Name	IdleModeType		
Kind	Type		
Derived from	scalar		
Range	IDLE_NO_HALT	–	the core does not perform any specific actions during idle time
Description	This data type identifies the idle mode behavior.		
Available via	Os.h		

⌋

8.3.22 AreaIdType

[SWS_Os_91000] Definition of datatype AreaIdType ⌈

Name	AreaIdType		
Kind	Type		
Derived from	scalar		
Range	0..65534	–	identifies a peripheral area

▽

△

Description	AreaIdType identifies a peripheral area and is used by the API functions: ReadPeripheralX, Write PeripheralX and ModifyPeripheralX
Available via	Os.h

⌋

8.4 Function definitions

The availability of the following services is defined in table [SWS_Os_00241]. The use of these services may be restricted depending on the context they are called from. See table 7.1 for details.

8.4.1 `GetApplicationID`

[SWS_Os_00016] Definition of API function GetApplicationID ⌈

Service Name	GetApplicationID	

Syntax	`ApplicationType GetApplicationID (`
	`  void`
	`)`	

Service ID [hex]	0x00	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	None	
Return value	ApplicationType	<identifier of running OS-Application> or `INVALID_OSAPPLICATION`
Description	This service determines the OS-Application (a unique identifier has to be allocated to each application) where the caller originally belongs to (was configured to).	
Available via	Os.h	

⌋

[SWS_Os_00261] ⌈`GetApplicationID` shall return the application identifier to which the executing `Task`/Cat2 `ISR`/hook was configured.⌋

This means that the return value of `GetApplicationID`, when called from a category 1 ISR, is undefined.

[SWS_Os_00262] ⌈If no OS-Application is running, `GetApplicationID` shall return `INVALID_OSAPPLICATION`.⌋

[SWS_Os_00514] ⌈Availability of GetApplicationID: Available in Scalability Classes 3 and 4 and in multi-core systems.⌋

8.4.2 GetCurrentApplicationID

[SWS_Os_00797] Definition of API function GetCurrentApplicationID ⌈

Service Name	GetCurrentApplicationID	
Syntax	`ApplicationType GetCurrentApplicationID ( void )`	
Service ID [hex]	0x27	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	None	
Return value	ApplicationType	<identifier of the OS-Application> or INVALID_OSAPPLICATION
Description	This service determines the OS-Application where the caller of the service is currently executing. Note that if the caller is not within a CallTrustedFunction() call the value is equal to the result of GetApplicationID().	
Available via	Os.h	

⌋

[SWS_Os_00798] ⌈GetCurrentApplicationID shall return the application identifier in which the current Task/Cat2 ISR/hook is executed.⌋

This means that the return value of GetCurrentApplicationID, when called from a category 1 ISR, is undefined.

[SWS_Os_00799] ⌈If no OS-Application is running, GetCurrentApplicationID shall return INVALID_OSAPPLICATION.⌋

[SWS_Os_00800] ⌈Availability of GetCurrentApplicationID: Available in Scalability Classes 3 and 4.⌋

8.4.3 GetISRID

[SWS_Os_00511] Definition of API function GetISRID ⌈

Service Name	GetISRID	
Syntax	`ISRType GetISRID ( void )`	
Service ID [hex]	0x01	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	None	
Return value	ISRType	<Identifier of running ISR> or INVALID_ISR
Description	This service returns the identifier of the currently executing ISR.	
Available via	Os.h	

⌋

[SWS_Os_00263] ⌈If called from category 2 ISR (or Hook routines called inside a category 2 ISR), GetISRID shall return the identifier of the currently executing ISR.⌋

[SWS_Os_00264] ⌈If its caller is not a category 2 ISR (or Hook routines called inside a category 2 ISR), GetISRID shall return INVALID_ISR.⌋

[SWS_Os_00515] ⌈Availability of GetISRID: Available in all Scalability Classes.⌋

8.4.4 CallTrustedFunction

[SWS_Os_00097] Definition of API function CallTrustedFunction ⌈

Service Name	CallTrustedFunction	
Syntax	`StatusType CallTrustedFunction ( TrustedFunctionIndexType FunctionIndex, TrustedFunctionParameterRefType FunctionParams )`	
Service ID [hex]	0x02	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	FunctionIndex	Index of the function to be called.

▽

△

	FunctionParams	Pointer to the parameters for the function - specified by the FunctionIndex - to be called. If no parameters are provided, a NULL_PTR has to be passed.
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK`: No Error `E_OS_SERVICEID`: No function defined for this index
Description	A (trusted or non-trusted) OS-Application uses this service to call a trusted function	
Available via	Os.h	

⌋

[SWS_Os_00265] ⌈If <FunctionIndex> is a defined function index, `CallTrustedFunction` shall call the function <FunctionIndex> out of a list of implementation specific trusted functions with the protection settings of the OS-Application which provides the trusted function AND shall return `E_OK` after completion.⌋

[SWS_Os_00312] ⌈Caveats of `CallTrustedFunction`:

- The called trusted function must conform to the following C prototype: `void TRUSTED_<name_of_the_trusted_service>( TrustedFunctionIndex Type,TrustedFunctionParameterRefType);` (The arguments are the same as the arguments of `CallTrustedFunction`).
- Normally, a user will not directly call this service, but it will be part of some standard interface, e.g. a standard I/O interface.
- It is the duty of the called trusted function to check rights of passed parameters, especially if parameters are interpreted as out parameters.
- It should be noted that the `CallTrustedFunction` does not disable timing protection for the `Task` which called the service. This may lead to timing faults (calls of the `ProtectionHook`) even inside of a trusted OS-Application. It is therefore recommended to use `CallTrustedFunction` only for stateless functions (e.g. functions which do not write or do not have internal states)

⌋

[SWS_Os_00266] ⌈When `CallTrustedFunction` calls the function <FunctionIndex>, that function shall be executed with the same processor mode, memory protection boundaries and the service protection limitations of the OS-Application to which it belongs. The notion of "current application" shall remain that of the calling `Task` or Category 2 `ISR`.⌋

Reaction to timing protection can be defined to terminate the OS-Application. If a `Task` is inside `CallTrustedFunction` and `Task` rescheduling takes place within the same OS-Application, the newly running higher priority `Task` may cause timing protection and terminate the OS-Application, thus indirectly aborting the trusted function. To avoid this, the scheduling of other Tasks which belong to the same OS-Application as the caller can be restricted, as well as the availability of interrupts of the same OS-Application.

[SWS_Os_00565] ⌈When CallTrustedFunction is called and the caller of CallTrustedFunction is supervised with timing protection, the Operating System shall delay any timing protection errors until the CallTrustedFunction returns to a OsApplication with OsTrustedApplicationDelayTimingViolationCall == FALSE.⌋

[SWS_Os_00563] ⌈

If OsLockTrustedFunctionCall == TRUE the OperatingSystem shall not schedule any other Tasks which belong to the same OS-Application as the non-trusted caller of the service. Also interrupts of Category 2 which belong to the same OS-Application shall be disabled during the execution of the service.⌋

The lock/disabling in [SWS_Os_00563] is required to support timing supervision. Since the caller of a trusted function can be any Task or Category 2 ISR the Operating System has to make sure that no other calls can preempt/interrupt the ongoing trusted function.

[SWS_Os_00364] ⌈If CallTrustedFunction calls the trusted function, that function shall continue to run on the same interrupt/task priority and be allowed to call system services defined for inside trusted functions.⌋

See also table in chapter 7.7.3.3.

[SWS_Os_00292] ⌈If the function index <FunctionIndex> in a call of CallTrustedFunction is undefined, CallTrustedFunction shall return E_OS_SERVICEID.⌋

[SWS_Os_00516] ⌈Availability of CallTrustedFunction: Available in Scalability Classes 3 and 4.⌋

8.4.5 CheckISRMemoryAccess

[SWS_Os_00512] Definition of API function CheckISRMemoryAccess ⌈

Service Name	CheckISRMemoryAccess	

Syntax	`AccessType CheckISRMemoryAccess (`
	`  ISRType ISRID,`
	`  MemoryStartAddressType Address,`
	`  MemorySizeType Size`
	`)`	

Service ID [hex]	0x03	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ISRID	ISR reference
	Address	Start of memory area
	Size	Size of memory area
Parameters (inout)	None	
Parameters (out)	None	
Return value	AccessType	Value which contains the access rights to the memory area.
Description	This service checks if a memory region is write/read/execute accessible and also returns information if the memory region is part of the stack space.	
Available via	Os.h	

⌋

[SWS_Os_00267] ⌈If the ISR reference <ISRID> in a call of CheckISRMemoryAccess is valid, CheckISRMemoryAccess shall return the access rights of the ISR on the specified memory area.⌋

[SWS_Os_00313] ⌈If an access right (e.g. "read") is not valid for the whole memory area specified in a call of CheckISRMemoryAccess, CheckISRMemoryAccess shall yield no access regarding this right.⌋

[SWS_Os_00268] ⌈If the ISR reference <ISRID> is not valid, CheckISRMemoryAccess shall yield no access rights.⌋

[SWS_Os_00517] ⌈Availability of CheckISRMemoryAccess: Available in Scalability Classes 3 and 4.⌋

8.4.6 CheckTaskMemoryAccess

[SWS_Os_00513] Definition of API function CheckTaskMemoryAccess ⌈

Service Name	CheckTaskMemoryAccess	
Syntax	`AccessType CheckTaskMemoryAccess ( TaskType TaskID, MemoryStartAddressType Address, MemorySizeType Size )`	
Service ID [hex]	0x04	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	TaskID	Task reference
	Address	Start of memory area
	Size	Size of memory area
Parameters (inout)	None	
Parameters (out)	None	
Return value	AccessType	Value which contains the access rights to the memory area.
Description	This service checks if a memory region is write/read/execute accessible and also returns information if the memory region is part of the stack space.	
Available via	Os.h	

⌋

[SWS_Os_00269] ⌈If the `Task` reference <`Task`ID> in a call of `CheckTaskMemoryAccess` is valid, `CheckTaskMemoryAccess` shall return the access rights of the `Task` on the specified memory area.⌋

[SWS_Os_00314] ⌈If an access right (e.g. "read") is not valid for the whole memory area specified in a call of `CheckTaskMemoryAccess`, `CheckTaskMemoryAccess` shall yield no access regarding this right.⌋

[SWS_Os_00270] ⌈If the `Task` reference <`Task`ID> in a call of `CheckTaskMemoryAccess` is not valid, `CheckTaskMemoryAccess` shall yield no access rights.⌋

[SWS_Os_00518] ⌈Availability of `CheckTaskMemoryAccess`: Available in Scalability Classes 3 and 4⌋

8.4.7 CheckObjectAccess

[SWS_Os_00256] Definition of API function CheckObjectAccess ⌈

Service Name	CheckObjectAccess	
Syntax	`ObjectAccessType CheckObjectAccess ( ApplicationType ApplID, ObjectTypeType ObjectType, void ... )`	
Service ID [hex]	0x05	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ApplID	OS-Application identifier
	ObjectType	Type of the following parameter
	...	The object to be examined
Parameters (inout)	None	
Parameters (out)	None	
Return value	ObjectAccessType	ACCESS if the ApplID has access to the object NO_ACCESS otherwise
Description	This service determines if the OS-Applications, given by ApplID, is allowed to use the IDs of a Task, Resource, Counter, Alarm or Schedule Table in API calls.	
Available via	Os.h	

⌋

[SWS_Os_00271] ⌈If the OS-Application <ApplID> in a call of CheckObjectAccess has access to the queried object, CheckObjectAccess shall return ACCESS.⌋

[SWS_Os_00272] ⌈If the OS-Application <ApplID> in a call of CheckObjectAccess has no access to the queried object, CheckObjectAccess shall return NO_ACCESS.⌋

[SWS_Os_00423] ⌈If in a call of CheckObjectAccess the object to be examined is not a valid object OR <ApplID> is invalid OR <ObjectType> is invalid THEN CheckObjectAccess shall return NO_ACCESS.⌋

[SWS_Os_00519] ⌈Availability of CheckObjectAccess: Available in Scalability Classes 3 and 4.⌋

8.4.8 CheckObjectOwnership

[SWS_Os_00017] Definition of API function CheckObjectOwnership ⌈

Service Name	CheckObjectOwnership	
Syntax	`ApplicationType CheckObjectOwnership ( ObjectTypeType ObjectType, void ... )`	
Service ID [hex]	0x06	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ObjectType	Type of the following parameter
	...	The object to be examined
Parameters (inout)	None	
Parameters (out)	None	
Return value	ApplicationType	<OS-Application>: the OS-Application to which the object Object Type belongs or `INVALID_OSAPPLICATION` if the object does not exists
Description	This service determines to which OS-Application a given Task, ISR, Counter, Alarm or Schedule Table belongs	
Available via	Os.h	

⌋

[SWS_Os_00273] ⌈If the object <ObjectType> specified in a call of `CheckObjectOwnership` exists, `CheckObjectOwnership` shall return the identifier of the OS-Application to which the object belongs.⌋

[SWS_Os_00274] ⌈If in a call of `CheckObjectOwnership` the specified object <ObjectType> is invalid OR the argument of the type (the "...") is invalid OR the object does not belong to any OS-Application, `CheckObjectOwnership` shall return `INVALID_OSAPPLICATION`.⌋

[SWS_Os_00520] ⌈Availability of `CheckObjectOwnership`: Available in Scalability Classes 3 and 4 and in multi-core systems.⌋

8.4.9 StartScheduleTableRel

[SWS_Os_00347] Definition of API function StartScheduleTableRel ⌈

Service Name	StartScheduleTableRel	

Syntax	`StatusType StartScheduleTableRel (`
	`  ScheduleTableType ScheduleTableID,`
	`  TickType Offset`
	`)`	

Service ID [hex]	0x07	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID	Schedule table to be started
	Offset	Number of ticks on the counter before the the schedule table processing is started
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No Error E_OS_ID (only in EXTENDED status): ScheduleTableID not valid. E_OS_VALUE (only in EXTENDED status): Offset is greater than (OsCounterMaxAllowedValue - InitialOffset) or is equal to 0. E_OS_STATE: Schedule table was already started.
Description	This service starts the processing of a schedule table at "Offset" relative to the "Now" value on the underlying counter.	
Available via	Os.h	

⌋

[SWS_Os_00275] ⌈If the ScheduleTable <ScheduleTableID> in a call of StartScheduleTableRel is not valid, StartScheduleTableRel shall return E_OS_ID.⌋

[SWS_Os_00452] ⌈If the ScheduleTable <ScheduleTableID> in a call of StartScheduleTableRel is implicitely synchronized (OsScheduleTblSyncStrategy = IMPLICIT), StartScheduleTableRel shall return E_OS_ID.⌋

[SWS_Os_00332] ⌈If <Offset> in a call of StartScheduleTableRel is zero StartScheduleTableRel shall return E_OS_VALUE.⌋

[SWS_Os_00276] ⌈If the offset <Offset>) is greater than OsCounterMaxAllowedValue of the underlying Counter minus the Initial Offset, StartScheduleTableRel shall return E_OS_VALUE.⌋

[SWS_Os_00277] ⌈If the ScheduleTable <ScheduleTableID> in a call of StartScheduleTableRel is not in the state SCHEDULETABLE_STOPPED, StartScheduleTableRel shall return E_OS_STATE.⌋

[SWS_Os_00278] ⌈If the input parameters of StartScheduleTableRel are valid and the state of ScheduleTable <ScheduleTableID> is SCHEDULETABLE_STOPPED, then StartScheduleTableRel shall start the processing of a ScheduleTable <ScheduleTableID>. The Initial Expiry Point shall be processed after <Offset> + Initial Offset ticks have elapsed on the underlying Counter. The state of <ScheduleTable ID> is set to SCHEDULETABLE_RUNNING before the service returns to the caller.⌋

[SWS_Os_00521] ⌈Availability of StartScheduleTableRel: Available in all Scalability Classes.⌋

8.4.10 StartScheduleTableAbs

[SWS_Os_00358] Definition of API function StartScheduleTableAbs ⌈

Service Name	StartScheduleTableAbs	
Syntax	`StatusType StartScheduleTableAbs ( ScheduleTableType ScheduleTableID, TickType Start )`	
Service ID [hex]	0x08	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID	Schedule table to be started
	Start	Absolute counter tick value at which the schedule table is started
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No Error E_OS_ID (only in EXTENDED status): ScheduleTableID not valid E_OS_VALUE (only in EXTENDED status): "Start" is greater than OsCounterMaxAllowedValue E_OS_STATE: Schedule table was already started
Description	This service starts the processing of a schedule table at an absolute value "Start" on the underlying counter.	
Available via	Os.h	

⌋

[SWS_Os_00348] ⌈If the ScheduleTable <ScheduleTableID> in a call of StartScheduleTableAbs is not valid, StartScheduleTableAbs shall return E_OS_ID.⌋

[SWS_Os_00349] ⌈If the <Start> in a call of StartScheduleTableAbs is greater than the OsCounterMaxAllowedValue of the underlying Counter, StartScheduleTableAbs shall return E_OS_VALUE.⌋

[SWS_Os_00350] ⌈If the ScheduleTable <ScheduleTableID> in a call of StartScheduleTableAbs is not in the state SCHEDULETABLE_STOPPED, StartScheduleTableAbs shall return E_OS_STATE.⌋

[SWS_Os_00351] ⌈If the input parameters of StartScheduleTableAbs are valid and <ScheduleTableID> is in the state SCHEDULETABLE_STOPPED, StartScheduleTableAbs shall start the processing of ScheduleTable <ScheduleTableID> when the underlying Counter next equals <Start> and shall set the state of <Schedule TableID> to

- SCHEDULETABLE_RUNNING (for a non-synchronized / Explicitly synchronized ScheduleTable) OR

- SCHEDULETABLE_RUNNING_AND_SYNCHRONOUS (for implicitly synchronized ScheduleTable)

before returning to the user. (The Initial Expiry Point will be processed when the underlying Counter next equals <Start>+Initial Offset).⌋

[SWS_Os_00522] ⌈Availability of StartScheduleTableAbs: Available in all Scalability Classes.⌋

8.4.11 StopScheduleTable

[SWS_Os_00006] Definition of API function StopScheduleTable ⌈

Service Name	StopScheduleTable	
Syntax	StatusType StopScheduleTable (ScheduleTableType ScheduleTableID)	
Service ID [hex]	0x09	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID	Schedule table to be stopped
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No Error E_OS_ID (only in EXTENDED status): ScheduleTableID not valid. E_OS_NOFUNC: Schedule table was already stopped
Description	This service cancels the processing of a schedule table immediately at any point while the schedule table is running.	
Available via	Os.h	

⌋

[SWS_Os_00279] ⌈If the ScheduleTable identifier <ScheduleTableID> in a call of StopScheduleTable is not valid, StopScheduleTable shall return E_OS_ID.⌋

[SWS_Os_00280] ⌈If the ScheduleTable with identifier <ScheduleTableID> is in state SCHEDULETABLE_STOPPED when calling StopScheduleTable, StopScheduleTable shall return E_OS_NOFUNC.⌋

[SWS_Os_00281] ⌈If the input parameters of StopScheduleTable are valid, StopScheduleTableshall set the state of <ScheduleTableID> to SCHEDULETABLE_STOPPED and (stop the ScheduleTable <ScheduleTableID> from processing any further expiry points and) shall return E_OK.⌋

[SWS_Os_00523] ⌈Availability of StopScheduleTable: Available in all Scalability Classes.⌋

8.4.12 NextScheduleTable

[SWS_Os_00191] Definition of API function NextScheduleTable

Upstream requirements: SRS_Os_00099

⌈

Service Name	NextScheduleTable	
Syntax	`StatusType NextScheduleTable ( ScheduleTableType ScheduleTableID_From, ScheduleTableType ScheduleTableID_To )`	
Service ID [hex]	0x0a	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID_From	Currently processed schedule table
	ScheduleTableID_To	Schedule table that provides its series of expiry points
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No error E_OS_ID (only in EXTENDED status): ScheduleTableID_From or ScheduleTableID_To not valid E_OS_NOFUNC: ScheduleTableID_From not started E_OS_STATE: ScheduleTableID_To is started or next
Description	This service switches the processing from one schedule table to another schedule table.	
Available via	Os.h	

⌋

[SWS_Os_00282] ⌈If the input parameter <ScheduleTableID_From> or <ScheduleTableID_To> in a call of NextScheduleTable is not valid, NextScheduleTable shall return E_OS_ID.⌋

[SWS_Os_00330] ⌈If in a call of NextScheduleTable ScheduleTable <ScheduleTableID_To> is driven by different Counter than ScheduleTable <ScheduleTableID_From> then NextScheduleTable shall return an error E_OS_ID.⌋

[SWS_Os_00283] ⌈If the ScheduleTable <ScheduleTableID_From> in a call of NextScheduleTable is in state SCHEDULETABLE_STOPPED OR in state SCHEDULETABLE_NEXT, NextScheduleTable shall leave the state of <ScheduleTable_From> and <ScheduleTable_To> unchanged and return E_OS_NOFUNC.⌋

[SWS_Os_00309] ⌈If the ScheduleTable <ScheduleTableID_To> in a call of NextScheduleTable is not in state SCHEDULETABLE_STOPPED, NextScheduleTable shall leave the state of <ScheduleTable_From> and <ScheduleTable_To> unchanged and return E_OS_STATE.⌋

[SWS_Os_00484] ⌈If OsScheduleTblSyncStrategy of <ScheduleTableID_To> in a call of NextScheduleTable is not equal to the OsScheduleTblSyncStrategy of <ScheduleTableID_From> then NextScheduleTable shall return E_OS_ID.⌋

[SWS_Os_00284] ⌈If the input parameters of NextScheduleTable are valid then NextScheduleTable shall start the processing of ScheduleTable <ScheduleTableID_To> <ScheduleTableID_From>.FinalDelay ticks after the Final Expiry Point on <ScheduleTableID_From> is processed and shall return E_OK. NextScheduleTable shall process the Initial Expiry Point on <ScheduleTableID_To> at <ScheduleTableID_From>.Final Delay + <ScheduleTable_To>.Initial Offset ticks after the Final Expiry Point on <ScheduleTableID_From> is processed .⌋

[SWS_Os_00324] ⌈If the input parameters of NextScheduleTable are valid AND the <ScheduleTableID_From> already has a "next" ScheduleTable then NextScheduleTableshall replace the previous "next" ScheduleTable with <ScheduleTableID_To> and shall change the old "next" ScheduleTable state to SCHEDULETABLE_STOPPED.⌋

[SWS_Os_00505] ⌈If OsScheduleTblSyncStrategy of the ScheduleTables <ScheduleTableID_From> and <ScheduleTableID_To> in a call of NextScheduleTable is EXPLICIT and the Operating System module already synchronizes <ScheduleTableID_From>, NextScheduleTable shall continue synchonization after the start of processing <ScheduleTableID_To>.⌋

[SWS_Os_00453] ⌈If the <ScheduleTableID_From> in a call of NextScheduleTable is stopped, NextScheduleTable shall not start the "next" ScheduleTable and change its state to SCHEDULETABLE_STOPPED.⌋

[SWS_Os_00524] ⌈Availability of NextScheduleTable: Available in all Scalability Classes.⌋

8.4.13 StartScheduleTableSynchron

[SWS_Os_00201] Definition of API function StartScheduleTableSynchron

Upstream requirements: SRS_Os_11002

⌈

Service Name	StartScheduleTableSynchron	

Syntax	`StatusType StartScheduleTableSynchron (`
	`  ScheduleTableType ScheduleTableID`
	`)`	

Service ID [hex]	0x0b	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID	Schedule table to be started
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No Error E_OS_ID (only in EXTENDED status): ScheduleTableID not valid E_OS_STATE: Schedule table was already started
Description	This service starts an explicitly synchronized schedule table synchronously.	
Available via	Os.h	

⌋

[SWS_Os_00387] ⌈If in a call of StartScheduleTableSynchron the Schedule Table <ScheduleTableID> is not valid OR the ScheduleTable <ScheduleTable ID> is not explicitly synchronized (OsScheduleTblSyncStrategy != EXPLICIT) StartScheduleTableSynchron shall return E_OS_ID.⌋

[SWS_Os_00388] ⌈If the ScheduleTable <ScheduleTableID> in a call of StartScheduleTableSynchron is not in the state SCHEDULETABLE_STOPPED, StartScheduleTableSynchron shall return E_OS_STATE.⌋

[SWS_Os_00389] ⌈If <ScheduleTableID> in a call of StartScheduleTableSynchron is valid, StartScheduleTableSynchron shall set the state of <Schedule TableID> to SCHEDULETABLE_WAITING and start the processing of ScheduleTable <ScheduleTableID> after the synchronization count of the ScheduleTable is set via

SyncScheduleTable. The Initial Expiry Point shall be processed when (Duration-SyncValue)+InitialOffset ticks have elapsed on the synchronization Counter where:

- Duration is <ScheduleTableID>.OsScheduleTableDuration
- SyncValue is the <Value> parameter passed to the SyncScheduleTable
- InitialOffset is the shortest expiry point offset in <ScheduleTableID>

⌋

[SWS_Os_00525] ⌈Availability of StartScheduleTableSynchron: Available in Scalability Classes 2 and 4.⌋

8.4.14 SyncScheduleTable

[SWS_Os_00199] Definition of API function SyncScheduleTable

Upstream requirements: SRS_Os_11002

⌈

Service Name	SyncScheduleTable	
Syntax	StatusType SyncScheduleTable (ScheduleTableType ScheduleTableID, TickType Value)	
Service ID [hex]	0x0c	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID	Schedule table to be synchronized
	Value	The current value of the synchronization counter
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No errors E_OS_ID (only in EXTENDED status): The ScheduleTableID was not valid or schedule table can not be synchronized (OsScheduleTblSyncStrategy not set or OsScheduleTblSyncStrategy = IMPLICIT) E_OS_VALUE (only in EXETENDED status): The <Value> is out of range E_OS_STATE: The state of schedule table <ScheduleTableID> is equal to SCHEDULETABLE_STOPPED
Description	This service provides the schedule table with a synchronization count and start synchronization.	
Available via	Os.h	

⌋

[SWS_Os_00454] ⌈If the <ScheduleTableID> in a call of SyncScheduleTable is not valid OR ScheduleTable can not be explicitely synchronized (OsScheduleTblSyncStrategy is not equal to EXPLICIT) SyncScheduleTable shall return E_OS_ID.⌋

[SWS_Os_00455] ⌈If the <Value> in a call of SyncScheduleTable is greater or equal than the OsScheduleTableDuration, SyncScheduleTable shall return E_OS_VALUE.⌋

[SWS_Os_00456] ⌈If the state of the ScheduleTable <ScheduleTableID> in a call of SyncScheduleTable is equal to SCHEDULETABLE_STOPPED or SCHEDULETABLE_NEXT SyncScheduleTable shall return E_OS_STATE.⌋

[SWS_Os_00457] ⌈If the parameters in a call of SyncScheduleTable are valid, SyncScheduleTable shall provide the Operating System module with the current synchronization count for the given ScheduleTable. (It is used to synchronize the processing of the ScheduleTable to the synchronization Counter.)⌋

[SWS_Os_00526] ⌈Availability of SyncScheduleTable: Available in Scalability Classes 2 and 4.⌋

8.4.15 SetScheduleTableAsync

[SWS_Os_00422] Definition of API function SetScheduleTableAsync ⌈

Service Name	SetScheduleTableAsync	

Syntax	`StatusType SetScheduleTableAsync (`
	`  ScheduleTableType ScheduleTableID`
	`)`	

Service ID [hex]	0x0d	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID	Schedule table for which status is requested
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No Error E_OS_ID (only in EXTENDED status): Invalid ScheduleTableID
Description	This service stops synchronization of a schedule table.	
Available via	Os.h	

⌋

[SWS_Os_00362] ⌈If SetScheduleTableAsync is called for a running Schedule Table, the Operating System module shall stop further synchronization until a Sync-ScheduleTable call is made.⌋

[SWS_Os_00323] ⌈If SetScheduleTableAsync is called for a running Schedule Table the Operating System module shall continue to process expiry points on the ScheduleTable.⌋

[SWS_Os_00458] ⌈If OsScheduleTblSyncStrategy of <ScheduleTableID> in a call of SetScheduleTableAsync is not equal to EXPLICIT OR if <ScheduleTable ID> is invalid then SetScheduleTableAsync shall return E_OS_ID.⌋

[SWS_Os_00483] ⌈If the current state of the <ScheduleTableID> in a call of SetScheduleTableAsync equals to SCHEDULETABLE_STOPPED, SCHED-ULETABLE_NEXT or SCHEDULETABLE_WAITING then SetScheduleTableAsync shall return E_OS_STATE.⌋

[SWS_Os_00300] ⌈If the current state of <ScheduleTableID> in a call of SetSched-uleTableAsync equals SCHEDULETABLE_RUNNING_AND_SYNCHRONOUS (or SCHEDULETABLE_RUNNING) then SetScheduleTableAsync shall set (or keep in case of SCHEDULETABLE_RUNNING) the status of <ScheduleTableID> to SCHED-ULETABLE_RUNNING.⌋

[SWS_Os_00527] ⌈Availability of SetScheduleTableAsync: Available in Scalability Classes 2 and 4.⌋

8.4.16 GetScheduleTableStatus

[SWS_Os_00227] Definition of API function GetScheduleTableStatus

Upstream requirements: SRS_Os_11002

⌈

Service Name	GetScheduleTableStatus	

Syntax	`StatusType GetScheduleTableStatus (`
	`  ScheduleTableType ScheduleTableID,`
	`  ScheduleTableStatusRefType ScheduleStatus`
	`)`	

Service ID [hex]	0x0e	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ScheduleTableID	Schedule table for which status is requested

▽

△

Parameters (inout)	None	
Parameters (out)	ScheduleStatus	Reference to ScheduleTableStatusType
Return value	StatusType	E_OK: No Error E_OS_ID (only in EXTENDED status): Invalid ScheduleTableID
Description	This service queries the state of a schedule table (also with respect to synchronization).	
Available via	Os.h	

⌋

[SWS_Os_00289] ⌈If the ScheduleTable <ScheduleTableID> in a call of GetScheduleTableStatus is NOT started, GetScheduleTableStatus shall pass back SCHEDULETABLE_STOPPED via the reference parameter <ScheduleStatus> AND shall return E_OK.⌋

[SWS_Os_00353] ⌈If the ScheduleTable <ScheduleTableID> in a call of GetScheduleTableStatus was used in a NextScheduleTable call AND waits for the end of the current ScheduleTable, GetScheduleTableStatus shall return SCHEDULETABLE_NEXT via the reference parameter <ScheduleStatus> AND shall return E_OK.⌋

[SWS_Os_00354] ⌈If the ScheduleTable <ScheduleTableID> in a call of GetScheduleTableStatus is configured with explicit synchronization AND <ScheduleTableID> was started with StartScheduleTableSynchronAND no synchronization count was provided to the Operating System, GetScheduleTableStatus shall return SCHEDULETABLE_WAITING via the reference parameter <ScheduleStatus> AND shall return E_OK.⌋

[SWS_Os_00290] ⌈If the ScheduleTable <ScheduleTableID> in a call of GetScheduleTableStatus is started AND synchronous, GetScheduleTableStatus shall pass back SCHEDULETABLE_RUNNING_AND_SYNCHRONOUS via the reference parameter <ScheduleStatus> AND shall return E_OK.⌋

[SWS_Os_00291] ⌈If the ScheduleTable <ScheduleTableID> in a call of GetScheduleTableStatus is started AND NOT synchronous (deviation is not within the precision interval OR the ScheduleTable has been set asynchronous), GetScheduleTableStatus shall pass back SCHEDULETABLE_RUNNING via the reference parameter ScheduleStatus AND shall return E_OK.⌋

[SWS_Os_00293] ⌈If the identifier <ScheduleTableID> in a call of GetScheduleTableStatus is NOT valid, GetScheduleTableStatus shall return E_OS_ID.⌋

[SWS_Os_00528] ⌈Availability of GetScheduleTableStatus: Available in all Scalability Classes.⌋

8.4.17 IncrementCounter

[SWS_Os_00399] Definition of API function IncrementCounter ⌈

Service Name	IncrementCounter	
Syntax	`StatusType IncrementCounter ( CounterType CounterID )`	
Service ID [hex]	0x0f	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	CounterID	The Counter to be incremented
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK`: No errors `E_OS_ID` (only in EXTENDED status): The CounterID was not valid or counter is implemented in hardware and can not be incremented by software
Description	This service increments a software counter.	
Available via	Os.h	

⌋

[SWS_Os_00285] ⌈If the input parameter <`Counter`ID> in a call of `IncrementCounter` is not valid OR the `Counter` is a hardware `Counter`, `IncrementCounter` shall return `E_OS_ID`.⌋

[SWS_Os_00286]

Upstream requirements: SRS_Os_11020

⌈If the input parameter of `IncrementCounter` is valid, `IncrementCounter` shall increment the `Counter` <`Counter`ID> by one (if any alarm connected to this `Counter` expires, the given action, e.g. `Task` activation, is done) and shall return `E_OK`.⌋

[SWS_Os_00321] ⌈If in a call of `IncrementCounter` an error happens during the execution of an alarm action, e.g. `E_OS_LIMIT` caused by a `Task` activation, `IncrementCounter` shall call the error hook(s), but the `IncrementCounter` service itself shall return `E_OK`.⌋

[SWS_Os_00529] ⌈Caveats of `IncrementCounter`: If called from a `Task`, rescheduling may take place.⌋

[SWS_Os_00530] ⌈Availability of `IncrementCounter`: Available in all Scalability Classes.⌋

8.4.18 GetCounterValue

[SWS_Os_00383] Definition of API function GetCounterValue ⌈

Service Name	GetCounterValue	
Syntax	`StatusType GetCounterValue ( CounterType CounterID, TickRefType Value )`	
Service ID [hex]	0x10	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	CounterID	The Counter which tick value should be read
Parameters (inout)	None	
Parameters (out)	Value	Contains the current tick value of the counter
Return value	StatusType	E_OK: No errors E_OS_ID (only in EXTENDED status): The <CounterID> was not valid
Description	This service reads the current count value of a counter (returning either the hardware timer ticks if counter is driven by hardware or the software ticks when user drives counter).	
Available via	Os.h	

⌋

[SWS_Os_00376] ⌈If the input parameter <CounterID> in a call of GetCounterValue is not valid, GetCounterValue shall return E_OS_ID.⌋

[SWS_Os_00377] ⌈If the input parameter <CounterID> in a call of GetCounterValue is valid, GetCounterValue shall return the current tick value of the Counter via <Value> and return E_OK.⌋

[SWS_Os_00531] ⌈Caveats of GetCounterValue: Note that for counters of OsCounterType = HARDWARE the real timer value (the - possibly adjusted - hardware value, see [SWS_Os_00384]) is returned, whereas for counters of OsCounterType = SOFTWARE the current "software" tick value is returned.⌋

[SWS_Os_00532] ⌈Availability of GetCounterValue: Available in all Scalability Classes.⌋

8.4.19 GetElapsedValue

[SWS_Os_00392] Definition of API function GetElapsedValue ⌈

Service Name	GetElapsedValue	
Syntax	`StatusType GetElapsedValue ( CounterType CounterID, TickRefType Value, TickRefType ElapsedValue )`	
Service ID [hex]	0x11	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	CounterID	The Counter to be read
Parameters (inout)	Value	in: the previously read tick value of the counter out: the current tick value of the counter
Parameters (out)	ElapsedValue	The difference to the previous read value
Return value	StatusType	E_OK: No errors E_OS_ID (only in EXTENDED status): The CounterID was not valid E_OS_VALUE (only in EXTENDED status): The given Value was not valid
Description	This service gets the number of ticks between the current tick value and a previously read tick value.	
Available via	Os.h	

⌋

[SWS_Os_00381] ⌈If the input parameter <CounterID> in a call of GetElapsedValue is not valid GetElapsedValue shall return E_OS_ID.⌋

[SWS_Os_00391] ⌈If the <Value> in a call of GetElapsedValue is larger than the max allowed value of the <CounterID>, GetElapsedValue shall return E_OS_VALUE.⌋

[SWS_Os_00382] ⌈If the input parameters in a call of GetElapsedValue are valid, GetElapsedValue shall return the number of elapsed ticks since the given <Value> value via <ElapsedValue> and shall return E_OK.⌋

[SWS_Os_00460] ⌈GetElapsedValue shall return the current tick value of the Counter in the <Value> parameter.⌋

[SWS_Os_00533] ⌈Caveats of GetElapsedValue:If the timer already passed the <Value> value a second (or multiple) time, the result returned is wrong. The reason is that the service can not detect such a relative overflow.⌋

[SWS_Os_00534] ⌈Availability of GetElapsedValue: Available in all Scalability Classes.⌋

8.4.20 TerminateApplication

[SWS_Os_00258] Definition of API function TerminateApplication

Upstream requirements: SRS_Os_11022

⌈

Service Name	TerminateApplication	
Syntax	`StatusType TerminateApplication ( ApplicationType Application, RestartType RestartOption )`	
Service ID [hex]	0x12	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Application	The identifier of the OS-Application to be terminated. If the caller belongs to <Application> the call results in a self termination.
	RestartOption	Parameter is no longer used and ignored.
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	E_OK: No errors E_OS_ID: <Application> was not valid (only in EXTENDED status) E_OS_ACCESS: The caller does not have the right to terminate <Application> (only in EXTENDED status) E_OS_STATE: The state of <Application> does not allow terminating <Application>
Description	This service terminates the OS-Application to which the calling Task/Category 2 ISR/application specific error hook belongs.	
Available via	Os.h	

⌋

[SWS_Os_00493] ⌈If the input parameter <Application> in a call of `TerminateApplication` is not valid `TerminateApplication` shall return `E_OS_ID`.⌋

[SWS_Os_00494] ⌈If the input parameter <Application> in a call of `TerminateApplication` is valid AND the caller belongs to a non-trusted OS-Application AND the caller does not belong to <Application> `TerminateApplication` shall return `E_OS_ACCESS`.⌋

[SWS_Os_00507] ⌈If the state of <Application> in a call of `TerminateApplication` is `APPLICATION_TERMINATED` `TerminateApplication` shall return `E_OS_STATE`.⌋

[SWS_Os_00287] ⌈If the parameters in a call of `TerminateApplication` are valid and the above criteria are met `TerminateApplication` shall terminate <Application> (i.e. to kill all `Task`s, disable the interrupt sources of those `ISR`s which belong to the OS-Application and free all other OS resources associated with the application).

The <Application> state is set to APPLICATION_TERMINATED. If the caller belongs to <Application> TerminateApplication shall not return, otherwise it shall return E_OK.⌋

[SWS_Os_00535] ⌈Caveats of TerminateApplication:

- If no applications are configured the implementation shall make sure that this service is not available.
- Tasks and interrupts that are owned by a trusted application can terminate any OS-Application. Tasks and interrupts that are owned by a non-trusted application can only terminate their owning OS-Application.

⌋

Note: Although trusted OS-Application can be forcibly terminated by Tasks/Interrupts of other trusted OS-Applications it is not recommended. This may have further impacts, e.g. to users who are currently part of such an OS-Application via a CallTrustedFunction call.

[SWS_Os_00536] ⌈Availability of TerminateApplication: Available in Scalability Classes 3 and 4.⌋

8.4.21 GetApplicationState

[SWS_Os_00499] Definition of API function GetApplicationState ⌈

Service Name	GetApplicationState	

Syntax	`StatusType GetApplicationState (`
	`  ApplicationType Application,`
	`  ApplicationStateRefType Value`
	`)`	

Service ID [hex]	0x14	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Application	The OS-Application from which the state is requested
Parameters (inout)	None	
Parameters (out)	Value	The current state of the application
Return value	StatusType	E_OK: No errors E_OS_ID: <Application> is not valid (only in EXTENDED status)
Description	This service returns the current state of an OS-Application.	
Available via	Os.h	

⌋

[SWS_Os_00495] ⌈If the <Application> in a call of GetApplicationState is not valid GetApplicationState shall return E_OS_ID.⌋

[SWS_Os_00496] ⌈If the parameters in a call of GetApplicationState are valid, GetApplicationState shall return the state of OS-Application <Application> in <Value>.⌋

[SWS_Os_00537] ⌈Availability of GetApplicationState: Available in Scalability Classes 3 and 4.⌋

8.4.22 GetNumberOfActivatedCores

[SWS_Os_00672] Definition of API function GetNumberOfActivatedCores

Upstream requirements: SRS_Os_80001

⌈

Service Name	GetNumberOfActivatedCores	
Syntax	`uint32 GetNumberOfActivatedCores ( void )`	
Service ID [hex]	0x15	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	None	
Return value	uint32	Number of cores running the AUTOSAR OS (see below)
Description	The function returns the number of cores running the AUTOSAR OS. This function might be a macro.	
Available via	Os.h	

⌋

The function GetNumberOfActivatedCores shall be callable from within a Task and an Category 2 ISR. Otherwise the behavior is unspecified.

[SWS_Os_00673]

Upstream requirements: SRS_Os_80001

⌈The return value of GetNumberOfActivatedCores shall be less or equal to the configured value of OsNumberOfCores.⌋

8.4.23 GetCoreID

[SWS_Os_00674] Definition of API function GetCoreID

Upstream requirements: SRS_Os_80001

⌈

Service Name	GetCoreID	
Syntax	`CoreIdType GetCoreID ( void )`	
Service ID [hex]	0x16	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	None	
Return value	CoreIdType	The return value is the unique ID of the core.
Description	The function returns a unique core identifier.	
Available via	Os.h	

⌋

[SWS_Os_00675]

Upstream requirements: SRS_Os_80001

⌈The function `GetCoreID` shall return the unique logical CoreID of the core on which the function is called. The value is defined in the configuration parameter EcucCoreId.⌋

8.4.24 StartCore

[SWS_Os_00676] Definition of API function StartCore

Upstream requirements: SRS_Os_80006

⌈

Service Name	StartCore	
Syntax	`void StartCore ( CoreIdType CoreID, StatusType* Status )`	
Service ID [hex]	0x17	
Sync/Async	Synchronous	
Reentrancy	Non Reentrant	
Parameters (in)	CoreID	Core identifier

▽

△

Parameters (inout)	None	
Parameters (out)	Status	Return value of the function in extended status: E_OK: No Error E_OS_ID: Core ID is invalid. E_OS_ACCESS: The function was called after starting the OS. E_OS_STATE: The Core is already activated. Return value of the function in standard status E_OK: No Error
Return value	None	
Description	It is not supported to call this function after StartOS(). The function starts the core specified by the parameter CoreID. The OUT parameter allows the caller to check whether the operation was successful or not. If a core is started by means of this function StartOS shall be called on the core.	
Available via	Os.h	

⌋

[SWS_Os_00677]

Upstream requirements: SRS_Os_80006

⌈The function StartCore shall start one core that shall run under the control of the AUTOSAR OS.⌋

[SWS_Os_00678]

Upstream requirements: SRS_Os_80006

⌈Calls to the StartCore function after StartOS shall return with E_OS_ACCESS and the core shall not be started.⌋

[SWS_Os_00679]

Upstream requirements: SRS_Os_80006

⌈If the parameter CoreIDs refers to a core that was already started by the function StartCore the related core is ignored and E_OS_STATE shall be returned.⌋

[SWS_Os_00681]

Upstream requirements: SRS_Os_80006

⌈There is no call to the ErrorHook if an error occurs during StartCore.⌋

8.4.25 GetSpinlock

[SWS_Os_00686] Definition of API function GetSpinlock

Upstream requirements: SRS_Os_80021

⌈

Service Name	GetSpinlock	

Syntax	`StatusType GetSpinlock (`
	`  SpinlockIdType SpinlockId`
	`)`	

Service ID [hex]	0x19	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	SpinlockId	The value refers to the spinlock instance that shall be locked.
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` - In standard and extended status : No Error `E_OS_ID` - In extended status: The SpinlockId is invalid `E_OS_INTERFERENCE_DEADLOCK` - In extended status: A TASK tries to occupy the spinlock while the lock is already occupied by a TASK on the same core. This would cause a deadlock. `E_OS_NESTING_DEADLOCK` - In extended status: A TASK tries to occupy the spinlock while a TASK on the same core is holding a different spinlock in a way that may cause a deadlock. `E_OS_ACCESS` - In extended status: The spinlock cannot be accessed.
Description	GetSpinlock tries to occupy a spin-lock variable. If the function returns, either the lock is successfully taken or an error has occurred. The spinlock mechanism is an active polling mechanism. The function does not cause a de-scheduling.	
Available via	Os.h	

⌋

[SWS_Os_00687]

Upstream requirements: SRS_Os_80021

⌈The function `GetSpinlock` shall occupy a spinlock. If the spinlock is already occupied the function shall busy wait until the spinlock becomes available.⌋

[SWS_Os_00688]

Upstream requirements: SRS_Os_80021

⌈The function `GetSpinlock` shall return `E_OK` if no error was detected. The spinlock is now occupied by the calling `Task`/Category 2 `ISR` on the calling core.⌋

[SWS_Os_00689]

Upstream requirements: SRS_Os_80021

⌈The function `GetSpinlock` shall return `E_OS_ID` if the parameter SpinlockID refers to a spinlock that does not exist.⌋

[SWS_Os_00690]

Upstream requirements: SRS_Os_80021

⌈The function GetSpinlock shall return E_OS_INTERFERENCE_DEADLOCK if the spinlock referred by the parameter SpinlockID is already occupied by a Task/Category 2 ISR on the same core.⌋

[SWS_Os_00691]

Upstream requirements: SRS_Os_80021

⌈The function GetSpinlock shall return E_OS_NESTING_DEADLOCK if the sequence by which multiple spinlocks are occupied at the same time on one core do not comply with the configured order.⌋

[SWS_Os_00692]

Upstream requirements: SRS_Os_80021

⌈The function GetSpinlock shall return E_OS_ACCESS if the accessing OS-Application was not listed in the configuration (OsSpinlock).⌋

[SWS_Os_00693]

Upstream requirements: SRS_Os_80021

⌈It shall be allowed to call the function GetSpinlock while interrupts are disabled.⌋

[SWS_Os_00694]

Upstream requirements: SRS_Os_80021

⌈It shall be allowed to call the function GetSpinlock while a Resource is occupied.⌋

8.4.26 ReleaseSpinlock

[SWS_Os_00695] Definition of API function ReleaseSpinlock

Upstream requirements: SRS_Os_80021

⌈

Service Name	ReleaseSpinlock
Syntax	`StatusType ReleaseSpinlock ( SpinlockIdType SpinlockId )`
Service ID [hex]	0x1a
Sync/Async	Synchronous
Reentrancy	Reentrant

▽

△

Parameters (in)	SpinlockId	The value refers to the spinlock instance that shall be locked.
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` - In standard and extended status: No Error `E_OS_ID` - In extended status: The SpinlockId is invalid. `E_OS_STATE` - In extended status: The Spinlock is not occupied by the TASK `E_OS_ACCESS` - In extended status: The Spinlock cannot be accessed. `E_OS_NOFUNC` - In extended status: Attempt to release a spinlock while another spinlock (or resource) has to be released before.
Description	ReleaseSpinlock releases a spinlock variable that was occupied before. Before terminating a TASK all spinlock variables that have been occupied with GetSpinlock() shall be released. Before calling WaitEVENT all Spinlocks shall be released.	
Available via	Os.h	

⌋

[SWS_Os_00696]

Upstream requirements: SRS_Os_80021

⌈The function `ReleaseSpinlock` shall release a spinlock that has been occupied by the same (calling) `Task`. If the related `GetSpinlock` call used configured locks (`OsSpinlockLockMethod`) the function shall also perform the undo of the used lock.⌋

[SWS_Os_00697]

Upstream requirements: SRS_Os_80021

⌈The function `ReleaseSpinlock` shall return `E_OK` if no error was detected. The spinlock is now free and can be occupied by the same or other `Task`s.⌋

[SWS_Os_00698]

Upstream requirements: SRS_Os_80021

⌈The function `ReleaseSpinlock` shall return `E_OS_ID` if the parameter SpinlockID refers to a spinlock that does not exist.⌋

[SWS_Os_00699]

Upstream requirements: SRS_Os_80021

⌈The function `ReleaseSpinlock` shall return `E_OS_STATE` if the parameter Spinlock ID refers to a spinlock that is not occupied by the calling `Task`.⌋

[SWS_Os_00700]

Upstream requirements: SRS_Os_80021

⌈The function `ReleaseSpinlock` shall return `E_OS_ACCESS` if the `Task` has no access to the spinlock referred by the parameter SpinlockID⌋

[SWS_Os_00701]

Upstream requirements: SRS_Os_80021

⌈The function ReleaseSpinlock shall return E_OS_NOFUNC if the Task tries to release a spinlock while another spinlock (or Resource) has to be released before. No functionality shall be performed.⌋

8.4.27 TryToGetSpinlock

[SWS_Os_00703] Definition of API function TryToGetSpinlock

Upstream requirements: SRS_Os_80021

⌈

Service Name	TryToGetSpinlock	

Syntax	`StatusType TryToGetSpinlock (`
	`  SpinlockIdType SpinlockId,`
	`  TryToGetSpinlockType* Success`
	`)`	

Service ID [hex]	0x1b	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	SpinlockId	The value refers to the spinlock instance that shall be locked.
Parameters (inout)	None	
Parameters (out)	Success	Returns if the lock has been occupied or not
Return value	StatusType	E_OK - In standard and extended status: No Error E_OS_ID - In extended status: The SpinlockId is invalid. E_OS_INTERFERENCE_DEADLOCK - In extended status: A TASK tries to occupy the spinlock while the lock is already occupied by a TASK on the same core. This would cause a deadlock. E_OS_NESTING_DEADLOCK - In extended status: A TASK tries to occupy a spinlock while holding a different spinlock in a way that may cause a deadlock. E_OS_ACCESS - In extended status: The spinlock cannot be accessed.
Description	TryToGetSpinlock has the same functionality as GetSpinlock with the difference that if the spinlock is already occupied by a TASK on a different core the function sets the OUT parameter "Success" and returns with E_OK.	
Available via	Os.h	

⌋

[SWS_Os_00704]

Upstream requirements: SRS_Os_80021

⌈The function TryToGetSpinlock shall atomically test the availability of the spinlock and if available occupy it. The result of success is returned.⌋

[SWS_Os_00705]

Upstream requirements: SRS_Os_80021

⌈The function TryToGetSpinlock shall set the OUT parameter "Success" to TRYTOGETSPINLOCK_SUCCESS if the spinlock was successfully occupied, and TRYTOGETSPINLOCK_NOSUCCESS if not. In both cases E_OK shall be returned.⌋

[SWS_Os_00706]

Upstream requirements: SRS_Os_80021

⌈If the function TryToGetSpinlock does not return E_OK, the OUT parameter "Success" shall be undefined.⌋

[SWS_Os_00707]

Upstream requirements: SRS_Os_80021

⌈The function TryToGetSpinlock shall return E_OS_ID if the parameter SpinlockID refers to a spinlock that does not exist.⌋

[SWS_Os_00708]

Upstream requirements: SRS_Os_80021

⌈The function TryToGetSpinlock shall return E_OS_INTERFERENCE_DEADLOCK if the spinlock referred by the parameter SpinlockID is already occupied by a Task on the same core.⌋

[SWS_Os_00709]

Upstream requirements: SRS_Os_80021

⌈The function TryToGetSpinlock shall return E_OS_NESTING_DEADLOCK if a Task tries to occupy a spinlock while holding a different spinlock in a way that may cause a deadlock.⌋

[SWS_Os_00710]

Upstream requirements: SRS_Os_80021

⌈The function TryToGetSpinlock shall return E_OS_ACCESS if the Task has no access to the spinlock referred by the parameter SpinlockID⌋

[SWS_Os_00711]

Upstream requirements: SRS_Os_80021

⌈It shall be allowed to call the function TryToGetSpinlock while interrupts are disabled.⌋

[SWS_Os_00712]

Upstream requirements: SRS_Os_80021

⌈It shall be allowed to call the function `TryToGetSpinlock` while a `Resource` is occupied.⌋

8.4.28 `ShutdownAllCores`

[SWS_Os_00713] Definition of API function ShutdownAllCores

Upstream requirements: SRS_Os_80007, SRS_BSW_00336

⌈

Service Name	ShutdownAllCores	
Syntax	`void ShutdownAllCores ( StatusType Error )`	
Service ID [hex]	0x1c	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Error	<Error> needs to be a valid error code supported by the AUTOSAR OS.
Parameters (inout)	None	
Parameters (out)	None	
Return value	None	
Description	After this service the OS on all AUTOSAR cores is shut down. Allowed at TASK level and ISR level and also internally by the OS. The function will never return. The function will force other cores into a shutdown.	
Available via	Os.h	

⌋

[SWS_Os_00714]

Upstream requirements: SRS_Os_80007

⌈A synchronized shutdown shall be triggered by the API function `ShutdownAllCores`.⌋

[SWS_Os_00715]

Upstream requirements: SRS_Os_80007

⌈`ShutdownAllCores` shall not return.⌋

[SWS_Os_00716]

Upstream requirements: SRS_Os_80007

⌈If `ShutdownAllCores` is called from non trusted code the call shall be ignored.⌋

8.4.29 ControlIdle

[SWS_Os_00769] Definition of API function ControlIdle

Upstream requirements: SRS_Os_80022

⌈

Service Name	ControlIdle	
Syntax	`StatusType ControlIdle ( CoreIdType CoreID, IdleModeType IdleMode )`	
Service ID [hex]	0x1d	
Sync/Async	Synchronous	
Reentrancy	Non Reentrant	
Parameters (in)	CoreID	selects the core which idle mode is set
	IdleMode	the mode which shall be performed during idle time
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK`: No Error `E_OS_ID` (only EXTENDED status): Invalid core and/or invalid idleMode
Description	This API allows the caller to select the idle mode action which is performed during idle time of the OS (e.g. if no Task/ISR is active). It can be used to implement energy savings. The real idle modes are hardware dependent and not standardized. The default idle mode on each core is IDLE_NO_HALT.	
Available via	Os.h	

⌋

[SWS_Os_00770]

Upstream requirements: SRS_Os_80023

⌈The function `ControlIdle` shall return `E_OK` if no error was detected and the parameters are valid⌋

[SWS_Os_00771]

Upstream requirements: SRS_Os_80023

⌈The function `ControlIdle` shall return `E_OS_ID` if the parameter CoreID or Idle Mode is invalid (e.g. refered core does not exist; idle mode is not known). In single core systems the check of CoreID shall be omitted.⌋

[SWS_Os_00802]

Upstream requirements: SRS_Os_80023

⌈If the core (given by CoreID) is already in another idle mode (different to the given Idle Mode) the new IdleMode shall become effective the next time that core enters the idle mode.⌋

8.4.30 ReadPeripheral8, ReadPeripheral16, ReadPeripheral32

[SWS_Os_91013] Definition of API function ReadPeripheral8

Upstream requirements: SRS_Os_11005

⌈

Service Name	ReadPeripheral8	
Syntax	`StatusType ReadPeripheral8 ( AreaIdType Area, const uint8* Address, uint8* ReadValue )`	
Service ID [hex]	0x28	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
Parameters (inout)	None	
Parameters (out)	ReadValue	content of the given memory location (<Address>)
Return value	StatusType	`E_OK` No error `E_OS_ID` Area id is out of range (EXTENDED status) `E_OS_VALUE` Address does not belong to given Area (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling task or ISR is not allowed to access the given
Description	This service returns the content of a given memory location (<Address>).	
Available via	Os.h	

⌋

[SWS_Os_91015] Definition of API function ReadPeripheral16

Upstream requirements: SRS_Os_11005

⌈

Service Name	ReadPeripheral16	
Syntax	`StatusType ReadPeripheral16 ( AreaIdType Area, const uint16* Address, uint16* ReadValue )`	
Service ID [hex]	0x29	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
Parameters (inout)	None	
Parameters (out)	ReadValue	content of the given memory location (<Address>)

▽

△

Return value	StatusType	E_OK No error E_OS_ID Area id is out of range (EXTENDED status) E_OS_VALUE Address does not belong to given Area (EXTENDED status) E_OS_CALLEVEL Wrong call context of the API function (EXTENDED status) E_OS_ACCESS The calling task or ISR is not allowed to access the given
Description	This service returns the content of a given memory location (<Address>).	
Available via	Os.h	

⌋

[SWS_Os_91014] Definition of API function ReadPeripheral32

Upstream requirements: SRS_Os_11005

⌈

Service Name	ReadPeripheral32	

Syntax	`StatusType ReadPeripheral32 (`
	`  AreaIdType Area,`
	`  const uint32* Address,`
	`  uint32* ReadValue`
	`)`	

Service ID [hex]	0x2a	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
Parameters (inout)	None	
Parameters (out)	ReadValue	content of the given memory location (<Address>)
Return value	StatusType	E_OK No error E_OS_ID Area id is out of range (EXTENDED status) E_OS_VALUE Address does not belong to given Area (EXTENDED status) E_OS_CALLEVEL Wrong call context of the API function (EXTENDED status) E_OS_ACCESS The calling task or ISR is not allowed to access the given
Description	This service returns the content of a given memory location (<Address>).	
Available via	Os.h	

⌋

8.4.31 WritePeripheral8, WritePeripheral16, WritePeripheral32

[SWS_Os_91010] Definition of API function WritePeripheral8

Upstream requirements: SRS_Os_11005

⌈

Service Name	WritePeripheral8	

Syntax	`StatusType WritePeripheral8 (`
	`  AreaIdType Area,`
	`  uint8* Address,`
	`  uint8 WriteValue`
	`)`	

Service ID [hex]	0x2b	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
Parameters (inout)	None	
Parameters (out)	WriteValue	value to be written at the memory address
Return value	StatusType	`E_OK` No error `E_OS_ID` Area id is out of range (EXTENDED status) `E_OS_VALUE` Address does not belong to given Area (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling task or ISR is not allowed to access the given
Description	This service writes the <value> to a given memory location (<memory address>).	
Available via	Os.h	

⌋

[SWS_Os_91012] Definition of API function WritePeripheral16

Upstream requirements: SRS_Os_11005

⌈

Service Name	WritePeripheral16	

Syntax	`StatusType WritePeripheral16 (`
	`  AreaIdType Area,`
	`  uint16* Address,`
	`  uint16 WriteValue`
	`)`	

Service ID [hex]	0x2c	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
Parameters (inout)	None	
Parameters (out)	WriteValue	value to be written at the memory address

▽

△

Return value	StatusType	E_OK No error E_OS_ID Area id is out of range (EXTENDED status) E_OS_VALUE Address does not belong to given Area (EXTENDED status) E_OS_CALLEVEL Wrong call context of the API function (EXTENDED status) E_OS_ACCESS The calling task or ISR is not allowed to access the given
Description	This service writes the <value> to a given memory location (<memory address>).	
Available via	Os.h	

⌋

[SWS_Os_91011] Definition of API function WritePeripheral32

Upstream requirements: SRS_Os_11005

⌈

Service Name	WritePeripheral32	

Syntax	`StatusType WritePeripheral32 (`
	`  AreaIdType Area,`
	`  uint32* Address,`
	`  uint32 WriteValue`
	`)`	

Service ID [hex]	0x2d	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
Parameters (inout)	None	
Parameters (out)	WriteValue	content of the given memory location (<Address>)
Return value	StatusType	E_OK No error E_OS_ID Area id is out of range (EXTENDED status) E_OS_VALUE Address does not belong to given Area (EXTENDED status) E_OS_CALLEVEL Wrong call context of the API function (EXTENDED status) E_OS_ACCESS The calling task or ISR is not allowed to access the given
Description	This service writes the <value> to a given memory location (<memory address>).	
Available via	Os.h	

⌋

8.4.32 ModifyPeripheral8, ModifyPeripheral16, ModifyPeripheral32

[SWS_Os_91016] Definition of API function ModifyPeripheral8

Upstream requirements: SRS_Os_11005

⌈

Service Name	ModifyPeripheral8	

Syntax	`StatusType ModifyPeripheral8 (`
	`  AreaIdType Area,`
	`  uint8* Address,`
	`  uint8 Clearmask,`
	`  uint8 Setmask`
	`)`	

Service ID [hex]	0x2e	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
	Clearmask	memory address will be modified by an bit-AND
	Setmask	memory address will be modified by an bit-OR
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` No error `E_OS_ID` Area id is out of range (EXTENDED status) `E_OS_VALUE` Address does not belong to given Area (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling task or ISR is not allowed to access the given
Description	This service modifies a given memory location (<memory address>) with the formula: *<Address> = ((*<Address> & <clearmask>) | <setmask>)	
Available via	Os.h	

⌋

[SWS_Os_91018] Definition of API function ModifyPeripheral16

Upstream requirements: SRS_Os_11005

⌈

Service Name	ModifyPeripheral16

Syntax	`StatusType ModifyPeripheral16 (`
	`  AreaIdType Area,`
	`  uint16* Address,`
	`  uint16 Clearmask,`
	`  uint16 Setmask`
	`)`

Service ID [hex]	0x35
Sync/Async	Synchronous
Reentrancy	Reentrant

▽

△

Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
	Clearmask	memory address will be modified by an bit-AND
	Setmask	memory address will be modified by an bit-OR
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` No error `E_OS_ID` Area id is out of range (EXTENDED status) `E_OS_VALUE` Address does not belong to given Area (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling task or ISR is not allowed to access the given
Description	This service modifies a given memory location (<memory address>) with the formula: *<Address> = ((*<Address> & <clearmask>) | <setmask>)	
Available via	Os.h	

⌋

[SWS_Os_91017] Definition of API function ModifyPeripheral32

Upstream requirements: SRS_Os_11005

⌈

Service Name	ModifyPeripheral32	

Syntax	`StatusType ModifyPeripheral32 (`
	`  AreaIdType Area,`
	`  uint32* Address,`
	`  uint32 Clearmask,`
	`  uint32 Setmask`
	`)`	

Service ID [hex]	0x2f	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Area	hardware peripheral area reference
	Address	memory address
	Clearmask	memory address will be modified by an bit-AND
	Setmask	memory address will be modified by an bit-OR
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` No error `E_OS_ID` Area id is out of range (EXTENDED status) `E_OS_VALUE` Address does not belong to given Area (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling task or ISR is not allowed to access the given
Description	This service modifies a given memory location (<memory address>) with the formula: *<Address> = ((*<Address> & <clearmask>) | <setmask>)	
Available via	Os.h	

⌋

8.4.33 EnableInterruptSource

[SWS_Os_91020] Definition of API function EnableInterruptSource

Upstream requirements: SRS_Os_11011

⌈

Service Name	EnableInterruptSource	

Syntax	`StatusType EnableInterruptSource (`
	`  ISRType ISRID,`
	`  boolean ClearPending`
	`)`	

Service ID [hex]	0x31	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ISRID	The ID of a category 2 ISR.
	ClearPending	Defines whether the pending flag shall be cleared (TRUE) or not (FALSE).
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` No error. `E_OS_ID` ISRID is not a valid category 2 ISR identifier (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling application is not the owner of the ISR passed in ISRID (Service Protection)
Description	Enables the interrupt source by modifying the interrupt controller registers. Additionally it may clear the interrupt pending flag	
Available via	Os.h	

⌋

8.4.34 DisableInterruptSource

[SWS_Os_91019] Definition of API function DisableInterruptSource

Upstream requirements: SRS_Os_11011

⌈

Service Name	DisableInterruptSource

Syntax	`StatusType DisableInterruptSource (`
	`  ISRType ISRID`
	`)`

Service ID [hex]	0x30
Sync/Async	Synchronous
Reentrancy	Reentrant

▽

△

Parameters (in)	ISRID	The ID of a category 2 ISR.
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` No error. `E_OS_ID` ISRID is not a valid category 2 ISR identifier (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling application is not the owner of the ISR passed in ISRID (Service Protection)
Description	Disables the interrupt source by modifying the interrupt controller registers.	
Available via	Os.h	

⌋

8.4.35 `ClearPendingInterrupt`

[SWS_Os_91021] Definition of API function ClearPendingInterrupt

Upstream requirements: SRS_Os_11011

⌈

Service Name	ClearPendingInterrupt	

Syntax	`StatusType ClearPendingInterrupt (`
	`ISRType ISRID`
	`)`	

Service ID [hex]	0x32	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	ISRID	The ID of a category 2 ISR.
Parameters (inout)	None	
Parameters (out)	None	
Return value	StatusType	`E_OK` No error. `E_OS_ID` ISRID is not a valid category 2 ISR identifier (EXTENDED status) `E_OS_CALLEVEL` Wrong call context of the API function (EXTENDED status) `E_OS_ACCESS` The calling application is not the owner of the ISR passed in ISRID (Service Protection)
Description	Clears the interrupt pending flag by modifying the interrupt controller registers.	
Available via	Os.h	

⌋

8.4.36 ActivateTaskAsyn

[SWS_Os_91022] Definition of API function ActivateTaskAsyn

Upstream requirements: SRS_Os_80015

⌈

Service Name	ActivateTaskAsyn	
Syntax	`void ActivateTaskAsyn ( TaskType id )`	
Service ID [hex]	0x33	
Sync/Async	Asynchronous	
Reentrancy	Reentrant	
Parameters (in)	id	The id of the task to be activated
Parameters (inout)	None	
Parameters (out)	None	
Return value	None	
Description	Asynchronous version of the ActivateTask() function. Intended to be used for cross core task activation. Possible errors are not returned to the caller, but may be reported via error hooks.	
Available via	Os.h	

⌋

[SWS_Os_00818]

Upstream requirements: SRS_Os_80015

⌈Availability of `ActivateTaskAsyn`: Available in systems which support OS-Applications.⌋

Note: If during the `Task` activation an error occurs, and the caller is already gone (e.g. callers OS-Application is already terminated, OR callers core is shutting down OR ...) calls to error hooks are dropped and no reporting is done.

8.4.37 SetEventAsyn

[SWS_Os_91023] Definition of API function SetEventAsyn

Upstream requirements: SRS_Os_80015

⌈

Service Name	SetEventAsyn	
Syntax	`void SetEventAsyn ( TaskType id, EventMaskType m )`	
Service ID [hex]	0x34	
Sync/Async	Asynchronous	
Reentrancy	Reentrant	
Parameters (in)	id	The id of the task to be activated
	m	Mask of the events to be set
Parameters (inout)	None	
Parameters (out)	None	
Return value	None	
Description	Asynchronous version of the SetEvent() function. Intended to be used for cross core event setting. Possible errors are not returned to the caller, but may be reported via error hooks.	
Available via	Os.h	

⌋

[SWS_Os_00819]

Upstream requirements: SRS_Os_80015

⌈Availability of `SetEventAsyn`: Available in systems which support OS-Applications.⌋

Note: If during the event setting an error occurs and the caller is already gone (e.g. callers OS-Application is already terminated, OR callers core is shutting down OR ...) calls to error hooks are dropped and no reporting is done.

8.4.38 isOsStarted

[SWS_Os_91034] Definition of API function isOsStarted

Status: DRAFT

⌈

Service Name	isOsStarted (draft)	
Syntax	`boolean isOsStarted ( void )`	
Service ID [hex]	0x36	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	None	
Return value	boolean	returns true if StartOS() was called otherwise false.
Description	This API returns a boolean value which indicates if the Os was already started. In case of multi-core it shall check if StartOs was already called on the core where isOsStarted was called. If the Os was (locally) started it returns true otherwise false. The function is intended to be implemented as macro. The function is by nature also callable before StartOs, but assumes a valid and initialized C environment (e.g. main() was called before the use of isOsStarted) **Tags:** atp.Status=draft	
Available via	Os.h	

⌋

The `isOsStarted` API can be useful for drivers to detect if the Os was already started or not. Note that if called from within category 1 `ISR`s during startup it my happen that this interrupt just happened while the call to `StartOs` is processed. In such cases the correct return value of true is not guaranteed.

8.5 IOC

8.5.1 Imported types

In this chapter all types included from the following modules are listed:

[SWS_Os_91028] Definition of imported datatypes of module Os ⌈

Module	***Header File***	***Imported Type***
Std	Std_Types.h	Std_ReturnType

⌋

[SWS_Os_00827]

Upstream requirements: SRS_Os_80020

⌈If an `ImplementationDataType` is defined with the typeEmitter empty or set to RTE and is used for IOC communication, the IOC shall include Rte_Type.h⌋

[SWS_Os_00828]

Upstream requirements: SRS_Os_80020

⌈If an `ImplementationDataType` is defined with the typeEmitter != RTE and does end with ".h" and is used for IOC communication, the IOC shall include specified header file.⌋

8.5.2 Type definitions

None

8.5.3 Constants

Name	Communication	Type	Errorname / Value	Annotation
`IOC_E_OK`	All, SND/RCV	`Std_ReturnType`	`RTE_E_OK` / 0	No error occurred
`IOC_E_LENGTH`	Queued SND	`Std_ReturnType`	`RTE_E_LIMIT` / 130	In case of "event" (queued) semantic, the internal buffer within the IOC communication service is too small for the requested transmission size.
`IOC_E_LIMIT`	Queued SND	`Std_ReturnType`	`RTE_E_LIMIT` / 130	In case of "event" (queued) semantic, the internal buffer within the IOC communication service is full (Case: Receiver slower than sender). This error produces additionally an Overlayed Error on the receiver side at the next data reception.
`IOC_E_LOST_DATA`	Queued RCV	`Std_ReturnType`	Overlayed Error `RTE_E_LOST_DATA` / 64	In case of "event" (queued) semantic, this Overlayed Error indicates that the IOC service refuses an `IocSend` request due to internal buffer overflow.

▽

△

IOC_E_NO_DATA	Queued RCV	Std_ReturnType	RTE_E_NO_DATA / 131	In case of "event" (queued) semantic, no data is available for reception.

8.5.4 Function definitions

[SWS_Os_00805] :

Upstream requirements: SRS_Os_80020

⌈The optional length parameter of the API shall be generated if the VariableDataPrototype is of type dynamic and no size indicator is used in the according `ApplicationArrayDataType`.⌋

8.5.4.1 `IocInit` (DRAFT)

[SWS_Os_91026] Definition of API function IocInit

Status: DRAFT

⌈

Service Name	IocInit (draft)

Syntax	`void IocInit (`
	`  void`
	`)`

Service ID [hex]	0x37
Sync/Async	Synchronous
Reentrancy	Non Reentrant
Parameters (in)	None
Parameters (inout)	None
Parameters (out)	None
Return value	None
Description	This service initializes the data structures of the IOC. **Tags:** atp.Status=draft
Available via	Ioc.h

⌋

8.5.4.2 IocSend/IocWrite

The IocWrite API call is generated for "data" (unqueued) semantics and the IocSend API call is generated for "event" (queued) semantics.

[SWS_Os_00718] Definition of API function IocSend_<IocId>[_<SenderId>]

Upstream requirements: SRS_Os_80020

⌈

Service Name	IocSend_<IocId>[_<SenderId>]	
Syntax	Std_ReturnType IocSend_<IocId>[_<SenderId>] (<Data> IN, [uint16 numberOfBytesIN])	
Service ID [hex]	0x1e	
Sync/Async	Asynchronous	
Reentrancy	This function is generated individually for each sender. The individual function is not reentrant (if called from different runnable entities that belong to the same sender), but different functions can be called in parallel.	
Parameters (in)	IN	Data value to be sent over a communication identified by the <loc Id>. The parameter will be passed by value for primitive data elements and by reference for all other types. Example: Std_ReturnType IocSend_RTE_25 (const uint32 UI_Value); Std_ReturnType IocSend_RTE_42 (const TASKParams3 *pStr_Value);
	numberOfBytesIN	(optional) number of bytes to be send
Parameters (inout)	None	
Parameters (out)	None	
Return value	Std_ReturnType	IOC_E_OK: The data has been passed successfully to the communication service. IOC_E_LIMIT: IOC internal communication buffer is full (Case: Receiver is slower than sender). This error produces an IOC_E_LOST_DATA Overlayed Error on the receiver side at the next data reception. IOC_E_LENGTH: The <numberOfBytesIN> exceeds either the internal buffer or is equal zero, so no data is send.
Description	Performs an "explicit" sender-receiver transmission of data elements with "event" semantic for a unidirectional 1:1 or N:1 communication between OS-Applications located on the same or on different cores. <IocId> is a unique identifier that references a unidirectional 1:1 or N:1 communication. <SenderId> is used only in N:1 communication. Together with <IocId>, it uniquely identifies the sender. It is separated from <IocId> with an underscore. In case of 1:1 communication, it shall be omitted.	
Available via	Ioc.h	

⌋

[SWS_Os_91003] Definition of API function IocWrite_<IocId>[_<SenderId>] ⌈

Service Name	IocWrite_<IocId>[_<SenderId>]	

Syntax	`Std_ReturnType IocWrite_<IocId>[_<SenderId>] (`
	`<Data> IN,`
	`[uint16 numberOfBytesIN]`
	`)`	

Service ID [hex]	0x1f	
Sync/Async	Asynchronous	
Reentrancy	This function is generated individually for each sender. The individual function is not reentrant (if called from different runnable entities that belong to the same sender), but different functions can be called in parallel.	
Parameters (in)	IN	Data value to be sent over a communication identified by the <loc Id>. The parameter will be passed by value for primitive data elements and by reference for all other types. Example: Std_ReturnType IocWrite_RTE_25 (const uint32 UI_Value); Std_ReturnType IocWrite_RTE_42 (const TASKParams3 *pStr_Value);
	numberOfBytesIN	(optional) number of bytes to be send
Parameters (inout)	None	
Parameters (out)	None	
Return value	Std_ReturnType	`IOC_E_OK`: The data has been passed successfully to the communication service. `IOC_E_LENGTH`: The <numberOfBytesIN> exceeds either the internal buffer or is equal zero, so no data is send.
Description	Performs an "explicit" sender-receiver transmission of data elements with "data" semantic for a unidirectional 1:1 or N:1 communication between OS-Applications located on the same or on different cores. <IocId> is a unique identifier that references a unidirectional 1:1 or N:1 communication. <SenderId> is used only in N:1 communication. Together with <IocId>, it uniquely identifies the sender. It is separated from <IocId> with an underscore. In case of 1:1 communication, it shall be omitted. <numberOfBytesIN> specifies the size of the data to be transmitted (in bytes).	
Available via	Ioc.h	

⌋

General:

[SWS_Os_00719]

Upstream requirements: SRS_Os_80020

⌈`IocSend`/`IocWrite` is asynchronous in that way it shall not have to wait for the reception of the data on the receiving side to return from execution.⌋

[SWS_Os_00720]

Upstream requirements: SRS_Os_80020

⌈The `IocSend`/`IocWrite` function shall not return until the data given in parameter have been completely physically sent over the communication medium.

For example in case of communication over shared RAM, an IocSend/IocWrite shall return when all data have been copied in the target shared RAM.⌋

[SWS_Os_00721]

Upstream requirements: SRS_Os_80020

⌈In case of "event" (queued) semantic, the IocSend function shall guarantee the order of delivery. In case of senders from different cores, the order in which messages are received will be determined by the implementation.⌋

[SWS_Os_00722]

Upstream requirements: SRS_Os_80020

⌈The IocSend/IocWrite function shall support mechanism to guarantee data-Integrity during transmission.

The IocSend/IocWrite function shall solve the crossing of the protection boundaries of OS-Applications. It has to be generated in case of intra-core and inter-core communication.⌋

[SWS_Os_00820] ⌈The IocSend/IocWrite resp. IocSendGroup/IocWriteGroup function shall be wrapped with the memory allocation keywords mechanism

```

#define OS_START_SEC_<sadm>
#include "Os_MemMap.h"

<IocSend, IocSendGroup, IocWrite, IocWriteGroup >

#define OS_STOP_SEC_<sadm>
#include "Os_MemMap.h"
```

where <sadm> is the shortName of the SwAddrMethod referenced by the OsMemoryMappingCodeLocationRef of the sending OsApplication configured in OsIocSendingOsApplicationRef of the respective OsIocCommunication channel.

⌋

Parameters:

[SWS_Os_00723]

Upstream requirements: SRS_Os_80020

⌈The IN <Data> parameter of the IocSend/IocWrite function shall be passed

by value for primitive data types, as an pointer to the array base type for arrays and by reference for all other types.⌋

[SWS_Os_00724]

Upstream requirements: SRS_Os_80020

⌈For data passed as an pointer to the array base type or by reference, the IocSend/IocWrite function shall guarantee upon return that the parameter is safe for re-use.⌋

Returned values:

[SWS_Os_00725]

Upstream requirements: SRS_Os_80020

⌈The IocSend/IocWrite function shall return IOC_E_OK if the data was passed successfully to the communication service.⌋

[SWS_Os_00726]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic the IocSend function shall return IOC_E_LIMIT if an IOC internal transmission buffer became full (Case: Receiver is slower than sender or/and configured internal IOC buffer size is too small).

If this error occurs the IOC internal buffer could not be filled with the parameter. In that case this error shall produce an IOC_E_LOST_DATAOverlayed Error on the receiver side at the next data reception (s. SWS_Os_00745).⌋

Internal structures:

[SWS_Os_00727]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic the IOC shall configure its internal transmission buffer size with the value of the attribute OsIocBufferLength.⌋

8.5.4.3 IocSendGroup/IocWriteGroup

The IocWriteGroup API call is generated for "data" (unqueued) semantics and the IocSendGroup API call is generated for "event" (queued) semantics.

[SWS_Os_00728] Definition of API function IocSendGroup_<IocId>

Upstream requirements: SRS_Os_80020

⌈

Service Name	IocSendGroup_<IocId>	

Syntax	`Std_ReturnType IocSendGroup_<IocId> (`
	`<Data1> IN1,`
	`[uint16 numberOfBytesIN1],`
	`<Data2> IN2,`
	`[uint16 numberOfBytesIN2],`
	`...`
	`)`	

Service ID [hex]	0x20	
Sync/Async	Asynchronous	
Reentrancy	This function is generated individually for each sender. The individual function is not reentrant (if called from different runnable entities that belong to the same sender), but different functions can be called in parallel.	
Parameters (in)	IN1	List of parameters with data values to be sent over a communication identified by the <IocId>. The parameters will be passed by value for simple data elements and by reference for all other types. Example: Std_ReturnType IocSendGroup_RTE_G1 (const uint32 UI_Value1, const uint16 Value2, const uint8 Value3, const uint16 Value4);
	numberOfBytesIN1	(optional) number of bytes for parameter IN1 to be send.
	IN2	–
	numberOfBytesIN2	–
		–
Parameters (inout)	None	
Parameters (out)	None	
Return value	Std_ReturnType	`IOC_E_OK`: The data has been passed successfully to the communication service. `IOC_E_LIMIT`: IOC internal communication buffer is full (Case: Receiver is slower than sender). This error produces an `IOC_E_LOST_DATA` Overlayed Error on the receiver side at the next data reception. `IOC_E_LENGTH`: Al least one of the <numberOfBytesIN<x>> exceeds either the internal buffer or is equal zero, so no data is send.
Description	Performs an "explicit" sender-receiver transmission of data elements with "event" semantic for a unidirectional 1:1 communication between OS-Applications located on the same or on different cores. This API involves a group of data elements which values are specified in parameter. <IocId> is a unique identifier that references a unidirectional 1:1 communication involving many data elements. The optional parameter <numberOfBytesIN<x>> specifies the size of the data to be transmitted (in bytes) for parameter <IN<x>>.	
Available via	Ioc.h	

⌋

[SWS_Os_91004] Definition of API function IocWriteGroup_<IocId> ⌈

Service Name	IocWriteGroup_<IocId>	

Syntax	`Std_ReturnType IocWriteGroup_<IocId> (`
	`  <Data1> IN1,`
	`  [uint16 numberOfBytesIN1],`
	`  <Data2> IN2,`
	`  [uint16 numberOfBytesIN2],`
	`  ...`
	`)`	

Service ID [hex]	0x21	
Sync/Async	Asynchronous	
Reentrancy	This function is generated individually for each sender. The individual function is not reentrant (if called from different runnable entities that belong to the same sender), but different functions can be called in parallel.	
Parameters (in)	IN1	List of parameters with data values to be sent over a communication identified by the <IocId>. The parameters will be passed by value for simple data elements and by reference for all other types. Example: Std_ReturnType IocWriteGroup_RTE_G1 (const uint32 UI_Value1, const uint16 Value2, const uint8 Value3, const uint16 Value4);
	numberOfBytesIN1	(optional) number of bytes for parameter IN1 to be send.
	IN2	–
	numberOfBytesIN2	–
		–
Parameters (inout)	None	
Parameters (out)	None	
Return value	Std_ReturnType	`IOC_E_OK`: The data has been passed successfully to the communication service. `IOC_E_LENGTH`: Al least one of the <numberOfBytesIN<x>> exceeds either the internal buffer or is equal zero, so no data is send.
Description	Performs an "explicit" sender-receiver transmission of data elements with "data" semantic for a unidirectional 1:1 communication between OS-Applications located on the same or on different cores. This API involves a group of data elements which values are specified in parameter. <IocId> is a unique identifier that references a unidirectional 1:1 communication involving many data elements. The optional parameter <numberOfBytesIN<x>> specifies the size of the data to be transmitted (in bytes) for parameter <IN<x>>.	
Available via	Ioc.h	

⌋

General:

[SWS_Os_00729]

Upstream requirements: SRS_Os_80020

⌈`IocSendGroup`/`IocWriteGroup` is asynchronous in that way it shall not have to wait for the reception of the data on the receiving side to return from execution.⌋

[SWS_Os_00730]

Upstream requirements: SRS_Os_80020

⌈The IocSendGroup/IocWriteGroup function shall not return until the data given in parameter have been completely physically sent over the communication medium. For example in case of communication over shared RAM, an IocSendGroup/IocWriteGroup shall return when all data have been copied in the target shared RAM.⌋

[SWS_Os_00731]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic, the IocSendGroup function shall guarantee the order of delivery.⌋

[SWS_Os_00732]

Upstream requirements: SRS_Os_80020

⌈The IocSendGroup/IocWriteGroup function shall support mechanisms to guarantee data-Integrity during transmission.

The IocSendGroup/IocWriteGroup function shall solve the crossing of the protection boundaries of OS-Applications. It has to be generated in case of intra-core and inter-core communication.⌋

Parameters:

[SWS_Os_00733]

Upstream requirements: SRS_Os_80020

⌈The IN <DataN> parameters of the IocSendGroup/IocWriteGroup function shall be passed by values for primitive data types, as pointer to the array base type for arrays and by references for all other types.⌋

[SWS_Os_00734]

Upstream requirements: SRS_Os_80020

⌈For data passed as an pointer to the array base type or by reference, the IocSendGroup/IocWriteGroup function shall guarantee upon return that the parameter is safe for re-use.⌋

Returned values:

[SWS_Os_00735]

Upstream requirements: SRS_Os_80020

⌈The IocSendGroup/IocWriteGroup function shall return IOC_E_OK if the data was passed successfully to the communication service.⌋

[SWS_Os_00736]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic the IocSendGroup function shall return IOC_E_LIMIT if an IOC internal transmission buffer got full (Case: Receiver is slower than sender or/ and configured internal IOC buffer size is too small).

If this error occurs the IOC Internal buffer could not be filled with the parameter. In that case this error produces an IOC_E_LOST_DATAOverlayed Error on the receiver side at the next data reception.⌋

Internal structures:

[SWS_Os_00737]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic the IOC shall configure its internal transmission buffer size with the value of the attribute OsIocBufferLength.⌋

8.5.4.4 IocReceive/IocRead

The IocRead API call is generated for "data" and the IocReceive API call is generated for "events".

[SWS_Os_00738] Definition of API function IocReceive_<IocId>

Upstream requirements: SRS_Os_80020

⌈

Service Name	IocReceive_<IocId>	
Syntax	`Std_ReturnType IocReceive_<IocId> ( <Data> OUT, [uint16* numberOfBytesOUT] )`	
Service ID [hex]	0x22	
Sync/Async	Synchronous	
Reentrancy	This function is generated individually for each receiver. The individual function is not reentrant (if called from different runnable entities that belong to the same receiver), but different functions can be called in parallel.	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	OUT	Data reference to be filled with the received data element.
	numberOfBytesOUT	(optional) data reference to be filled with the length of the received data element in bytes.

▽

△

Return value	Std_ReturnType	`IOC_E_OK`: Data was received successfully `IOC_E_NO_DATA`: No data is available for reception. `IOC_E_LOST_DATA`: This Overlayed Error indicates that the IOC communication service refused an IOCSend request from sender due to an internal buffer overflow. There is no error in the data returned in parameter.
Description	Performs an "explicit" sender-receiver reception of data elements with "event" semantic for a unidirectional communication between OS-Applications located on the same or on different cores.. <IocId> is a unique identifier that references a unidirectional 1:1 or N:1 communication.	
Available via	Ioc.h	

⌋

[SWS_Os_91005] Definition of API function IocRead_<IocId>[_<ReceiverId>] ⌈

Service Name	IocRead_<IocId>[_<ReceiverId>]	

Syntax	`Std_ReturnType IocRead_<IocId>[_<ReceiverId>] (`
	`  <Data> OUT,`
	`  [uint16* numberOfBytesOUT]`
	`)`	

Service ID [hex]	0x23	
Sync/Async	Synchronous	
Reentrancy	Non Reentrant This function is generated individually for each receiver. The individual function is not reentrant (if called from different runnable entities that belong to the same receiver), but different functions can be called in parallel.	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	OUT	Data reference to be filled with the received data element.
	numberOfBytesOUT	(optional) data reference to be filled with the length of the received data element in bytes.
Return value	Std_ReturnType	`IOC_E_OK`: Data was received successfully
Description	Performs an "explicit" sender-receiver reception of data elements with "data" semantic for a unidirectional communication between OS-Applications located on the same or on different cores. <IocId> is a unique identifier that references a unidirectional 1:1 or N:1 communication. <ReceiverId> is used only in N:M communication. Together with <IocId>, it uniquely identifies the receiver. It is separated from <IocId> with an underscore. If communication is different from N:M it shall be omitted.	
Available via	Ioc.h	

⌋

General:

[SWS_Os_00739]

Upstream requirements: SRS_Os_80020

⌈A successful call to the IocReceive/IocRead function indicates that data has been received successfully in the OUT <Data> given in parameter.

The IocReceive/IocRead function has to be generated in case of intra-core and inter-core communication.⌋

[SWS_Os_00822] ⌈The IocReceive/IocRead resp. IocReceiveGroup/IocReadGroup function shall be wrapped with the memory allocation keywords mechanism

```
#define OS_START_SEC_<sadm>
#include "Os_MemMap.h"

 <IocReceive, IocReceiveGroup , IocRead, IocReadGroup>

#define OS_STOP_SEC_<sadm>
#include "Os_MemMap.h"
```

where <sadm> is the shortName of the SwAddrMethod referenced by the OsMemoryMappingCodeLocationRef of the reading OsApplication configured in OsIocReceivingOsApplicationRef of the respective OsIocCommunication channel.c()

⌋

[SWS_Os_00740]

Upstream requirements: SRS_Os_80020

⌈If the OsIocReceiverPullCB attribute is defined with a callback function name, the IOC shall call this function on the receiving core for each data transmission.⌋

Parameters:

[SWS_Os_00741]

Upstream requirements: SRS_Os_80020

⌈In case of "data" semantic the IocRead function shall always be able to deliver the last available datum. In case of senders from different cores, the precision of the order might be limited by the hardware and implementation.⌋

[SWS_Os_00742]

Upstream requirements: SRS_Os_80020

⌈The IocReceive/IocRead function shall guarantee upon returning from execution that the reference given in parameter is safe for use.⌋

[SWS_Os_00803]

Upstream requirements: SRS_Os_80020

⌈The OUT <Data> parameter of the IocReceive/IocRead function shall be passed as an pointer to the array base type for arrays and by reference for all other types.⌋

Returned values:

[SWS_Os_00743]

Upstream requirements: SRS_Os_80020

⌈The IocReceive/IocRead function shall return IOC_E_OK if the data was received successfully in the OUT <Data> parameter.⌋

[SWS_Os_00744]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic and if no data is available the function IocReceive shall return IOC_E_NO_DATA.⌋

[SWS_Os_00745]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic an IOC_E_LOST_DATAOverlayed Error shall be returned by the IocReceive function if the IOC communication service refused an IocSend request from sender due to an internal buffer overflow. There is no error in the data returned in parameter.⌋

8.5.4.5 IocReceiveGroup/IocReadGroup

The IocReadGroup API call is generated for "data" and the IocReceiveGroup API call is generated for "events".

[SWS_Os_00746] Definition of API function IocReceiveGroup_<IocId>

Upstream requirements: SRS_Os_80020

⌈

<table>
<tr><td>Service Name</td><td colspan="2">IocReceiveGroup_<IocId></td></tr>
<tr><td>Syntax</td><td colspan="2"><code>Std_ReturnType IocReceiveGroup_<IocId> (
  <Data1> OUT1,
  [uint16* numberOfBytesOUT1],
  <Data2> OUT2,
  [uint16* numberOfBytesOUT2],
  ...
)</code></td></tr>
<tr><td>Service ID [hex]</td><td colspan="2">0x24</td></tr>
<tr><td>Sync/Async</td><td colspan="2">Synchronous</td></tr>
<tr><td>Reentrancy</td><td colspan="2">This function is generated individually for each receiver. The individual function is not reentrant (if called from different runnable entities that belong to the same receiver), but different functions can be called in parallel.</td></tr>
<tr><td>Parameters (in)</td><td colspan="2">None</td></tr>
<tr><td>Parameters (inout)</td><td colspan="2">None</td></tr>
<tr><td rowspan="5">Parameters (out)</td><td>OUT1</td><td>List of data references to be filled with the received data elements. The specified order of the parameter shall match to the specified order in the corresponding send function.</td></tr>
<tr><td>numberOfBytesOUT1</td><td>(optional) data reference to be filled with the length of the received data element (OUT1) in bytes.</td></tr>
<tr><td>OUT2</td><td>–</td></tr>
<tr><td>numberOfBytesOUT2</td><td>–</td></tr>
<tr><td></td><td>–</td></tr>
<tr><td>Return value</td><td>Std_ReturnType</td><td><code>IOC_E_OK</code>: Data was received successfully
<code>IOC_E_NO_DATA</code>: No data is available for reception.
<code>IOC_E_LOST_DATA</code>: This Overlayed Error indicates that the IOC communication service refused an IOCSend request from sender due to an internal buffer overflow. There is no error in the data returned in parameter.</td></tr>
<tr><td>Description</td><td colspan="2">Performs an "explicit" sender-receiver transmission of data elements with "event" semantic for a unidirectional 1:1 communication between OS-Applications located on the same or on different cores.
This API involves a group of data elements which values are specified in parameter.
<IocId> is a unique identifier that references a unidirectional 1:1 communication involving many data elements.</td></tr>
<tr><td>Available via</td><td colspan="2">Ioc.h</td></tr>
</table>

⌋

[SWS_Os_91006] Definition of API function IocReadGroup_<IocId> ⌈

Service Name	IocReadGroup_<IocId>	

Syntax	Std_ReturnType IocReadGroup_<IocId> (
	  <Data1> OUT1,
	  [uint16* numberOfBytesOUT1],
	  <Data2> OUT2,
	  [uint16* numberOfBytesOUT2],
	  ...
	)	

Service ID [hex]	0x25	
Sync/Async	Synchronous	
Reentrancy	This function is generated individually for each receiver. The individual function is not reentrant (if called from different runnable entities that belong to the same receiver), but different functions can be called in parallel.	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	OUT1	List of data references to be filled with the received data elements. The specified order of the parameter shall match to the specified order in the corresponding send function.
	numberOfBytesOUT1	(optional) data reference to be filled with the length of the received data element (OUT1) in bytes.
	OUT2	–
	numberOfBytesOUT2	–
		–
Return value	Std_ReturnType	IOC_E_OK: Data was received successfully
Description	Performs an "explicit" sender-receiver transmission of data elements with a "data" semantic for a unidirectional 1:1 communication between OS-Applications located on the same or on different cores. This API involves a group of data elements which values are specified in parameter. <IocId> is a unique identifier that references a unidirectional 1:1 communication involving many data elements.	
Available via	Ioc.h	

⌋

General:

[SWS_Os_00747]

Upstream requirements: SRS_Os_80020

⌈A successful call to the IocReceiveGroup/IocReadGroup function indicates that data has been received successfully in the given parameters.

The IocReceiveGroup/IocReadGroup function has to be generated in case of intra-core and inter-core communication.⌋

[SWS_Os_00748]

Upstream requirements: SRS_Os_80020

⌈If the OsIocReceiverPullCB attribute is defined with a callback function name, the IOC shall call this function on the receiving core for each data transmission.⌋

Parameters:

[SWS_Os_00749]

Upstream requirements: SRS_Os_80020

⌈In case of "data" semantic the IocReadGroup function shall always be able to deliver the last available datum.⌋

[SWS_Os_00750]

Upstream requirements: SRS_Os_80020

⌈The IocReceiveGroup/IocReadGroup function shall guarantee upon returning from execution that the references given in parameters are safe for use.⌋

[SWS_Os_00804] ⌈The OUT <DataN> parameters of the IocReceiveGroup/IocReadGroup function shall be passed as pointer to the array base type for arrays and by references for all other types.⌋

Returned values:

[SWS_Os_00751]

Upstream requirements: SRS_Os_80020

⌈The IocReceiveGroup/IocReadGroup function shall return IOC_E_OK if the data was received successfully in the list of references given in parameter.⌋

[SWS_Os_00752]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic and if no data is available the function IocReceiveGroup shall return IOC_E_NO_DATA.⌋

[SWS_Os_00753]

Upstream requirements: SRS_Os_80020

⌈In case of "event" semantic an IOC_E_LOST_DATAOverlayed Error shall be returned by the IocReceiveGroup function if the IOC communication service refused an IocSendGroup request from sender due to an internal buffer overflow. There is no error in the data returned in parameter.⌋

8.5.4.6 IocEmptyQueue

[SWS_Os_00754] Definition of API function IocEmptyQueue_<IocId>

Upstream requirements: SRS_Os_80020

⌈

Service Name	IocEmptyQueue_<IocId>	
Syntax	`Std_ReturnType IocEmptyQueue_<IocId> ( void )`	
Service ID [hex]	0x26	
Sync/Async	Synchronous	
Reentrancy	Non reentrant	
Parameters (in)	None	
Parameters (inout)	None	
Parameters (out)	None	
Return value	Std_ReturnType	`IOC_E_OK`: Content of the queue was successfully deleted
Description	In case of queued communication identified by the <IocId> in the function name, the content of the IOC internal communication queue shall be deleted.	
Available via	Ioc.h	

⌋

General:

[SWS_Os_00755]

Upstream requirements: SRS_Os_80020

⌈The function `IocEmptyQueue`_<IocId> shall be present for all IOC elements with queued semantics.⌋

[SWS_Os_00756]

Upstream requirements: SRS_Os_80020

⌈The function `IocEmptyQueue`_<IocId> shall delete all contents from the associated data queue.

The `IocEmptyQueue` should be generated in a more efficient way than an iterative call to an `IocReceive` function.⌋

8.6 Expected Interfaces

In this chapter all interfaces required from other modules are listed.

8.6.1 Mandatory Interfaces

There are no mandatory interfaces for the IOC.

8.6.2 Optional Interfaces

8.6.2.1 ReceiverPullCB

[SWS_Os_00757] Definition of configurable interface <ReceiverPullCB>

Upstream requirements: SRS_Os_80020

⌈

Service Name	<ReceiverPullCB>
Syntax	`void <ReceiverPullCB> ( void )`
Sync/Async	Synchronous
Reentrancy	Reentrant
Parameters (in)	None
Parameters (inout)	None
Parameters (out)	None
Return value	None
Description	This callback function can be configured for the receiver of a communication. If configured, IOC calls this callback on the receiving core for each data reception. <ReceiverPullCB> is the callback function name configured by the receiver in the OsIocReceiverPullCB attribute to be called on data reception."
Available via	Os.h

⌋

[SWS_Os_00758]

Upstream requirements: SRS_Os_80020

⌈The <ReceiverPullCB> function name shall be defined within a configuration file for each IOC communication in the `OsIocReceiverPullCB` attribute.⌋

[SWS_Os_00759]

Upstream requirements: SRS_Os_80020

⌈The name of the callback shall be unique over the micro controller. For this purpose the following example can be considered as orientation for the IOC user:

Example: `Rte_IocReceiveCB_<IocId>`⌋

[SWS_Os_00760]

Upstream requirements: SRS_Os_80020

⌈The <ReceiverPullCB> function on the receiver side is using the access rights of the receiving OsApplication.⌋

Note: This means that such a callback cannot be reused by another OsApplication.

[SWS_Os_00761]

Upstream requirements: SRS_Os_80020

⌈This notification mechanism shall be supported for both queued and unqueued communication semantic.⌋

The owner of the <ReceiverPullCB> function shall pay attention that the execution time of the function shall not last too long. It shall be possible to call this function from an IOC-ISR.

8.7 Hook functions

Hook functions are called by the operating system if specific conditions are met. They are provided by the user. Besides the ProtectionHook below, the hooks from [7] and/or extensions from 7.12 may be called by the OS.

8.7.1 ProtectionHook

[SWS_Os_00538] Definition of configurable interface ProtectionHook ⌈

Service Name	ProtectionHook	

Syntax	`ProtectionReturnType ProtectionHook (`
	`  StatusType Fatalerror`
	`)`	

Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Fatalerror	The error which caused the call to the protection hook
Parameters (inout)	None	
Parameters (out)	None	
Return value	ProtectionReturnType	PRO_IGNORE PRO_TERMINATETASKISR PRO_TERMINATEAPPL PRO_SHUTDOWN The return value defines the action the OS shall take after the protection hook.

▽

△

Description	The protection hook is always called if a serious error occurs. E.g. exceeding the worst case execution time or violating against the memory protection.
Available via	Os_Externals.h

⌋

Depending on the return value the Operating System module will either:

- forcibly terminate the `Task`/Category 2 `ISR` which causes the problem OR
- forcibly terminate the OS-Application the `Task`/Category 2 `ISR` belong OR
- shutdown the system OR
- do nothing

(see 7.8.2)

[SWS_Os_00308] ⌈If `ProtectionHook` returns an invalid value, the Operating System module shall take the same action as if no protection hook is configured.⌋

[SWS_Os_00542] ⌈Availability of `ProtectionHook`: Available in Scalability Classes 2, 3 and 4.⌋

8.7.2 Application specific `StartupHook`

[SWS_Os_00539] Definition of configurable interface StartupHook_<App> ⌈

Service Name	StartupHook_<App>
Syntax	`void StartupHook_<App> ( void )`
Sync/Async	Synchronous
Reentrancy	Reentrant
Parameters (in)	None
Parameters (inout)	None
Parameters (out)	None
Return value	None
Description	The application specific startup hook is called during the start of the OS (after the user has started the OS via StartOS()).
Available via	Os_Externals.h

⌋

The application specific `StartupHook` is always called after the standard `StartupHook` (see [SWS_Os_00236]). If more than one OS-Application is configured which use startup hooks, the order of calls to the startup hooks of the different OS-Applications is not defined.

[SWS_Os_00543] ⌈Availability of `StartupHook_<App>`: Available in Scalability Classes 3 and 4.⌋

8.7.3 Application specific ErrorHook

[SWS_Os_00540] Definition of configurable interface ErrorHook_<App> ⌈

Service Name	ErrorHook_<App>	
Syntax	`void ErrorHook_<App> ( StatusType Error )`	
Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Error	The error which caused the call to the error hook
Parameters (inout)	None	
Parameters (out)	None	
Return value	None	
Description	The application specific error hook is called whenever a Task or Category 2 ISR which belongs to the OS-Application causes an error.	
Available via	Os_Externals.h	

⌋

If the general `ErrorHook` is configured, the general `ErrorHook` is called before the application specific error hook is called (see [SWS_Os_00246]).

[SWS_Os_00544] ⌈Availability of `ErrorHook_<App>`: Available in Scalability Classes 3 and 4.⌋

8.7.4 Application specific ShutdownHook

[SWS_Os_00541] Definition of configurable interface ShutdownHook_<App> ⌈

Service Name	ShutdownHook_<App>
Syntax	`void ShutdownHook_<App> ( StatusType Fatalerror )`

▽

△

Sync/Async	Synchronous	
Reentrancy	Reentrant	
Parameters (in)	Fatalerror	The error which caused the action to shut down the operating system.
Parameters (inout)	None	
Parameters (out)	None	
Return value	None	
Description	The application specific shutdown hook is called whenever the system starts the shut down of itself.	
Available via	Os_Externals.h	

⌋

If the general `ShutdownHook` is configured, the general `ShutdownHook` is called after all application specific shutdown hook(s) are called (see [SWS_Os_00237]). If more OS-Applications with an application specific shutdown hook exist the order of calls to these application specific shutdown hooks is not defined.

[SWS_Os_00545] ⌈Availability of `ShutdownHook_<App>`: Available in Scalability Classes 3 and 4.⌋

8.8 Service Interfaces

8.8.1 Port interface of Os

[SWS_Os_91027] Definition of Port OsService provided by module Os ⌈

Name	OsService		
Kind	ProvidedPort	***Interface***	OsService_{Counter}
Description	–		
Port Defined Argument Value(s)	***Type***	CounterType	
	Value	{ecuc(Os/OsCounter)}	
Variation	–		

⌋

8.8.2 Client-Server-Interfaces

8.8.2.1 Os_Service

[SWS_Os_00560] Definition of ClientServerInterface OsService_{Counter} ⌈

Name	OsService_{Counter}		
Comment	–		
IsService	true		
Variation	({ecuc(Os/OsCounter/OsSecondsPerTick)} != NULL) Counter = {ecuc(Os/OsCounter.SHORT-NAME)}		
Possible Errors	0	E_OK	Operation successful
	1	E_OS_ACCESS	–
	3	E_OS_ID	–
	7	E_OS_STATE	–
	8	E_OS_VALUE	–

Operation	GetCounterValue	
Comment	This service reads the current count value of a counter (returning either the hardware timer ticks if counter is driven by hardware or the software ticks when user drives counter).	
Mapped to API	GetCounterValue	
Variation	–	
Parameters	Value	
	Type	TimeInMicrosecondsType
	Direction	OUT
	Comment	Contains the current tick value of the counter
	Variation	–
Possible Errors	E_OK E_OS_ID	

Operation	GetElapsedValue	
Comment	This service gets the number of ticks between the current tick value and a previously read tick value.	
Mapped to API	GetElapsedValue	
Variation	–	
Parameters	Value	
	Type	TimeInMicrosecondsType
	Direction	INOUT
	Comment	in: the previously read tick value of the counter out: the current tick value of the counter
	Variation	–
	ElapsedValue	
	Type	TimeInMicrosecondsType
	Direction	OUT
	Comment	The difference to the previous read value
	Variation	–
Possible Errors	E_OK E_OS_ID E_OS_VALUE	

⌋

8.8.2.2 Implementation Data Types

[SWS_Os_00794] Definition of ImplementationDataType TimeInMicroseconds Type ⌈

Name	TimeInMicrosecondsType
Kind	Type
Derived from	uint64
Description	–
Variation	–
Available via	Rte_Os_Type.h

⌋

[SWS_Os_00786] Definition of ImplementationDataType CounterType ⌈

Name	CounterType
Kind	Type
Derived from	uint32
Description	This data type identifies a counter.
Variation	–
Available via	Rte_Os_Type.h

⌋

9 Sequence diagrams

9.1 Sequence chart for calling trusted functions

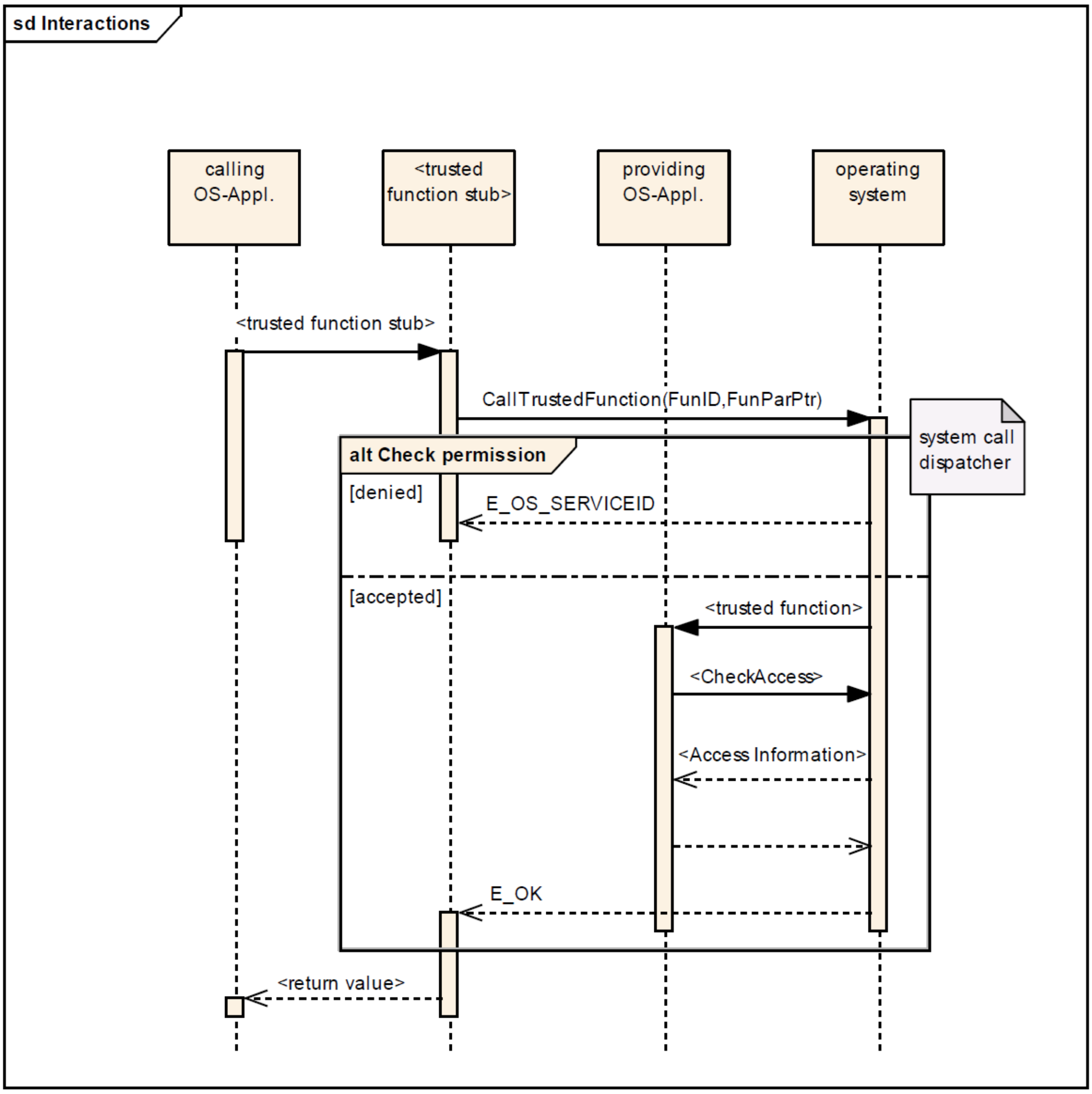

Figure 9.1: System Call sequence chart

The above sequence describes a call to the `CallTrustedFunction` service. It starts with a user who calls a service which requires itself a call to a trusted function. The service then packs the argument for the trusted function into a structure and calls `CallTrustedFunction` with the ID and the pointer as arguments. Afterwards the OS checks if the access to the requested service is valid. If no access is granted `E_OS_SERVICEID` is returned. Otherwise the trusted service itself is called and the function checks the arguments for access right, etc.

9.2 Sequence chart for usage of ErrorHook

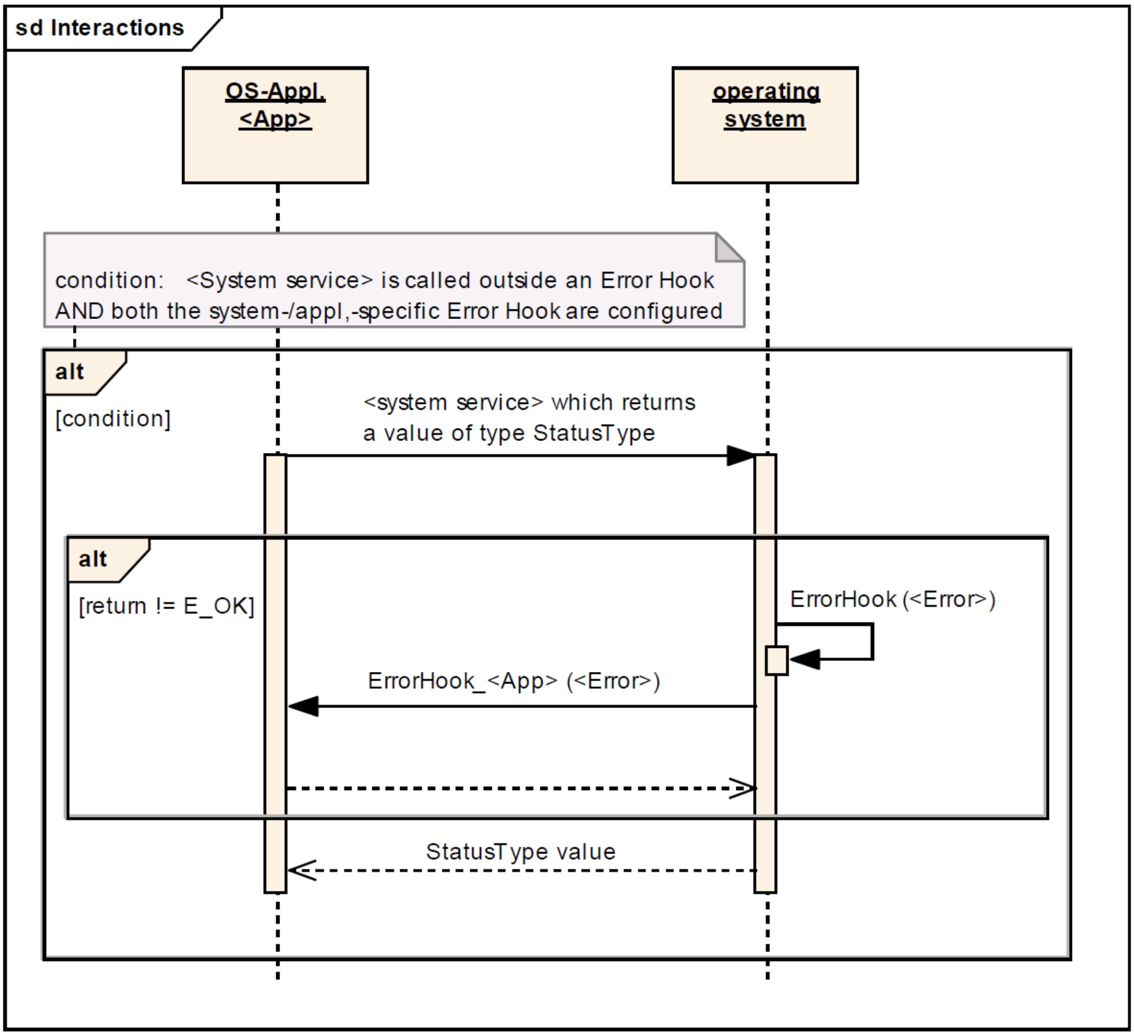

Figure 9.2: Error Hook sequence chart

The above sequence chart shows the sequence of error hook calls in case a service does not return with `E_OK`. Note that in this case the general error hook and the OS-Application specific error hook are called.

9.3 Sequence chart for ProtectionHook

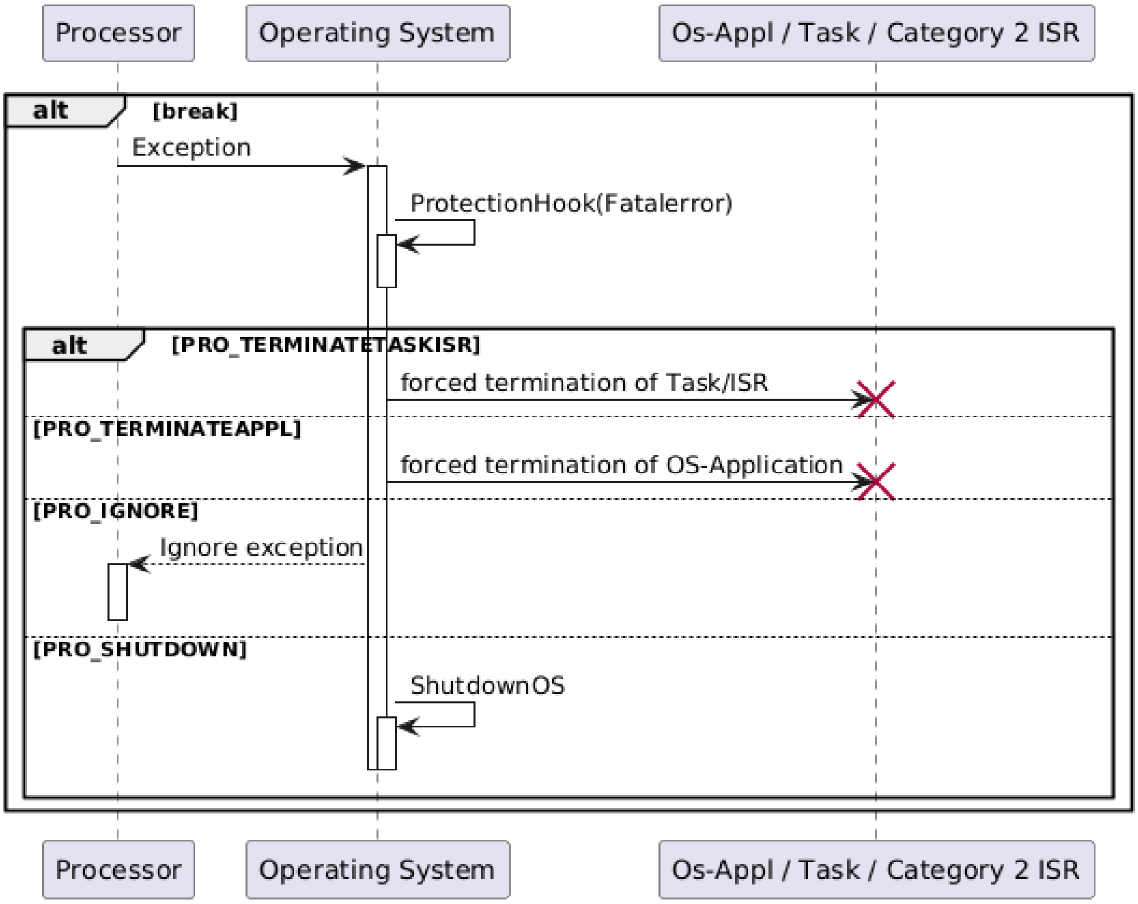

Figure 9.3: ProtectionHook sequence chart

The sequence shows the flow of control if a protection error occurs. Depending on the return values of the ProtectionHook, either the faulty Task/ISR is forcibly terminated or the OS-Application is forcibly terminated or the system is shut down.

9.4 Sequence chart for StartupHook

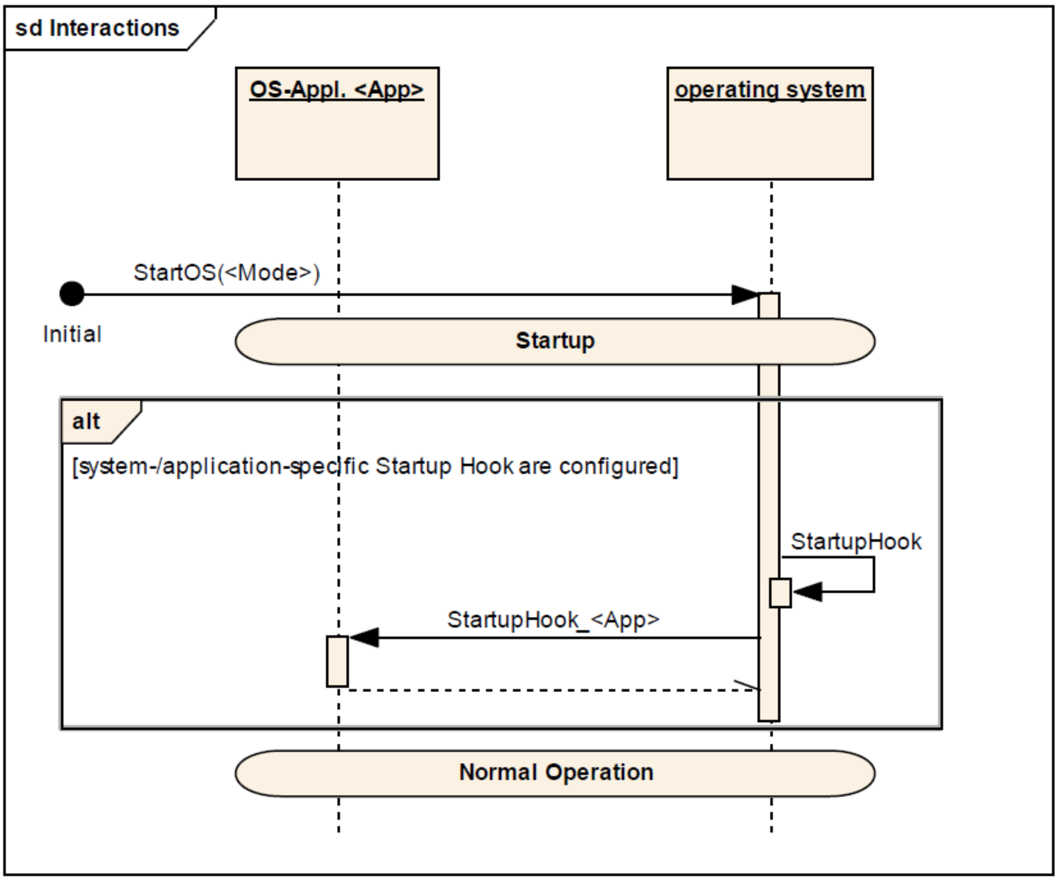

Figure 9.4: StartupHook sequence chart

The above sequence shows the flow of control during the startup of the OS. Like in OSEK OS the user calls the StartOS service to start the OS. During the startup the startup hooks are called in the above order. The rest of the startup sequence is identical to the defined behaviour of OSEK OS.

9.5 Sequence chart for ShutdownHook

The next sequence shows the behaviour in case of a shut down. The flow is the same as in OSEK OS with the exception that the shut down hooks of the OS-Applications are called before the general ShutdownHook is called. Note that the specific shutdown hooks of the application are not allowed to block, they must return to the caller.

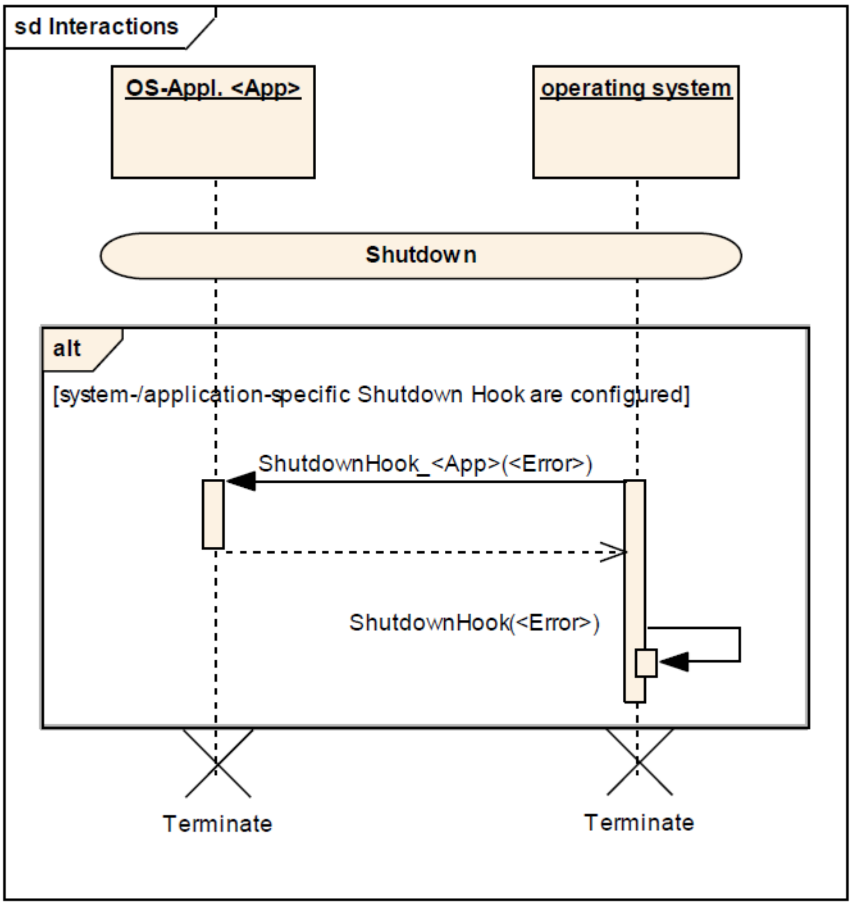

Figure 9.5: ShutdownHook sequence chart

9.6 Sequence diagrams of Sender Receiver communication over the IOC

9.6.1 Last-is-best communication

The 9.6 shows a sequence of successful and failure cases in the interaction between the IOC and the RTE in case of last-is-best communication ("data" semantic).

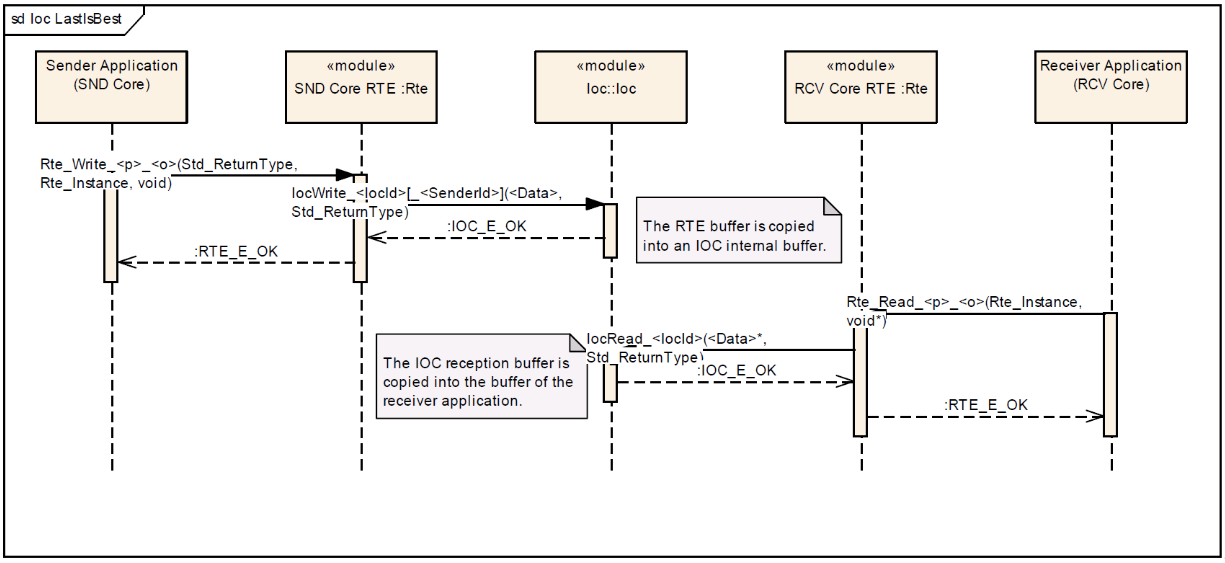

Figure 9.6: IOC - Last-is-best communication

9.6.2 Queued communication without pull callback

The figure 9.7 shows the interaction between IOC and RTE with a focus on the congestion control for a queued communication.

The defined communication has no callback functionality for data reception, has an internal buffer size of 2 data elements, no waitpoints are defined and the implicated OS-Applications are located on different cores.

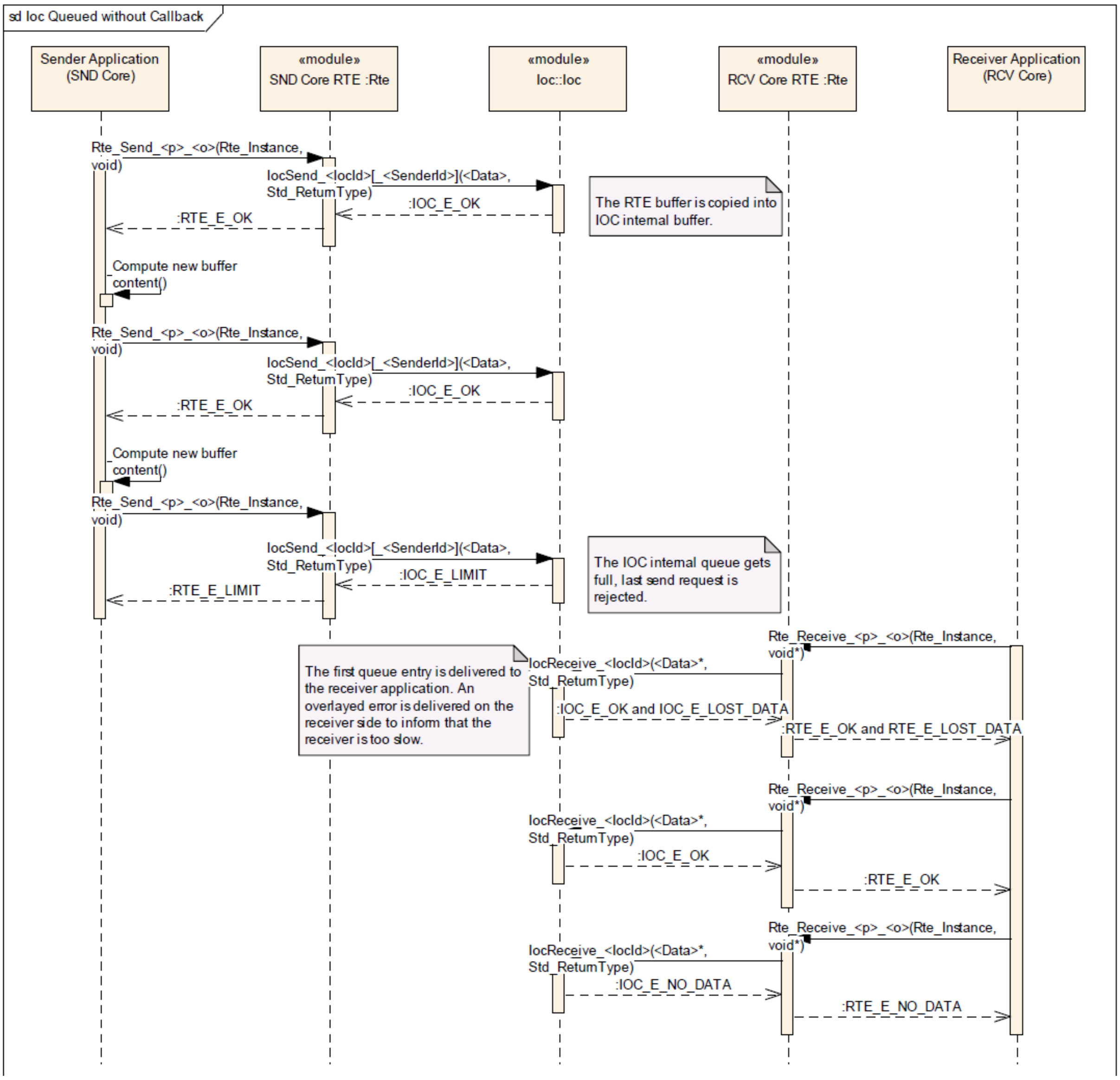

Figure 9.7: IOC - Queued communication without callback

9.6.3 Queued communication with pull callback

The figure 9.8 shows the interaction between IOC and RTE in case of a queued communication with an activated callback functionality. The RTE might handle notification internally and might therefore not provide any callback functions, but a similar scenario will occur in case of communication between CDDs on different cores. The receiving CDD will provide the callback function in this case.

The defined communication has no waitpoints and describes a communication implicating two OS-Applications located on different cores.

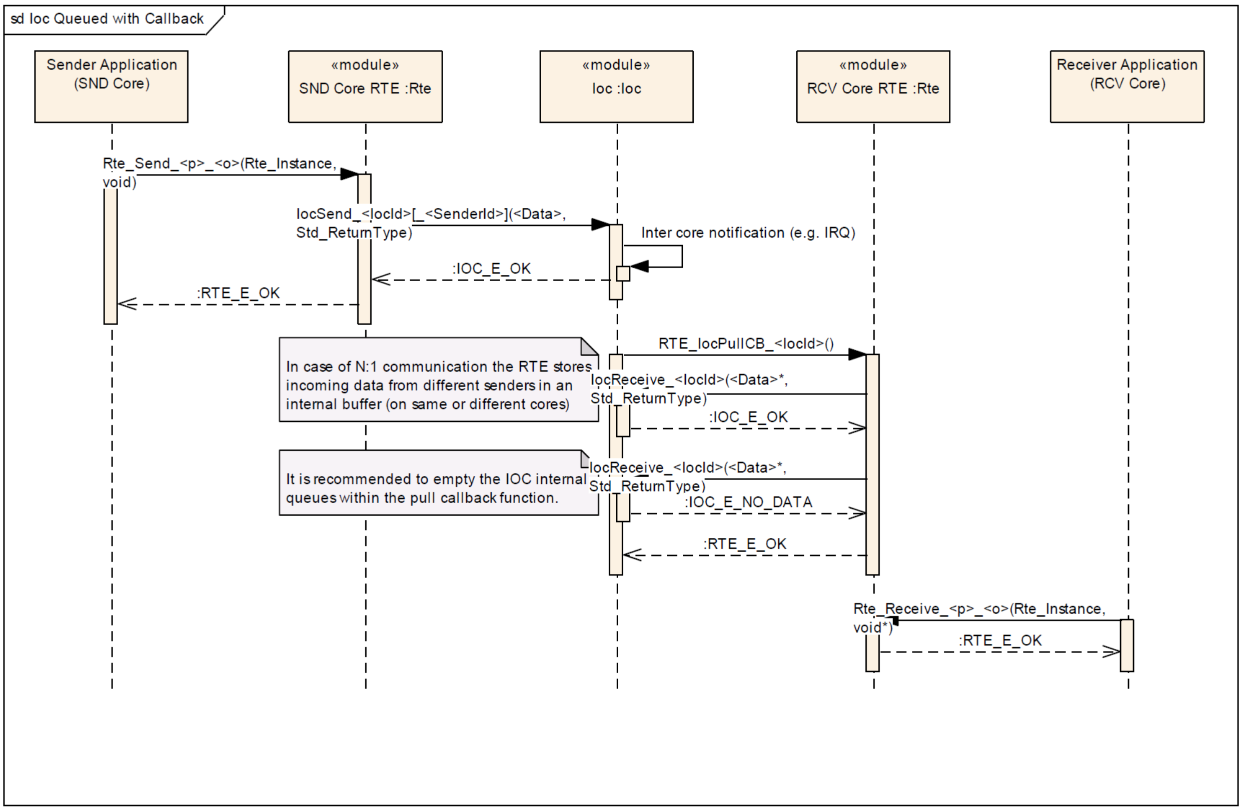

Figure 9.8: IOC Queued Communication with callback

10 Configuration specification

In general, this chapter defines configuration parameters and their clustering into containers. In order to support the specification Chapter 10.1 describes fundamentals. It also specifies a template (table) you shall use for the parameter specification. We intend to leave Chapter 10.1 in the specification to guarantee comprehension.

Chapter 10.2 specifies the structure (containers) and the parameters of the module Os.

Chapter 10.3 specifies the structure (containers) and the parameters of the Ioc.

Chapter 10.4 specifies the structure (containers) and the ARTI parameters for the Os and Ioc.

Chapter 10.5 specifies published information of the module Os.

10.1 How to read this chapter

For details refer to the chapter 10.1 “Introduction to configuration specification” in [4].

10.1.1 Rules for paramters

Some configuration parameters are configured as floating point values and sometimes these values must be rounded in order to be used. The following rules define the rounding of specific parameters:

- Execution times (for the timing protection) are "round down"
- Timeframes are "round down"

10.2 Containers and configuration parameters

The following chapters summarize all configuration parameters and their containers. Background information about the detailed meaning of the parameters can be found in chapters 7 and 8.

For better readability OIL names of the 2.1 OS specification are given in curly braces in the namefield of configuration parameters.

[SWS_Os_00861] ⌈The used EcucPartitionId(s) which are assigned to an OS-Application shall be zero-based and consecutive. If this is not the case the consistency check shall issue an error.⌋

[SWS_Os_00862] ⌈The used EcucCoreId(s) which are assigned to an OS-Application shall be zero-based and consecutive. If this is not the case the consistency check shall issue an error.⌋

10.2.1 Os

[ECUC_Os_00396] Definition of EcucModuleDef Os ⌈

Module Name	Os
Description	Configuration of the Os (Operating System) module.
Post-Build Variant Support	false
Supported Config Variants	VARIANT-PRE-COMPILE

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsAlarm	0..*	An OsAlarm may be used to asynchronously inform or activate a specific task. It is possible to start alarms automatically at system start-up depending on the application mode.
OsAppMode	1..*	OsAppMode is the object used to define ISO 17356-3 properties for an ISO 17356-3 application mode. No standard attributes are defined for AppMode. In a CPU, at least one AppMode object has to be defined. [source: ISO 17356-6] An OsAppMode called OSDEFAULTAPPMODE must always be there for ISO 17356 compatibility.
OsApplication	0..*	An AUTOSAR OS must be capable of supporting a collection of OS objects (tasks, interrupts, alarms, hooks etc.) that form a cohesive functional unit. This collection of objects is termed an OS-Application. All objects which belong to the same OS-Application have access to each other. Access means to allow to use these objects within API services. Access by other applications can be granted separately.
OsCounter	0..*	Configuration information for the counters that belong to the Os Application.
OsEvent	0..*	Representation of OS events in the configuration context. Adopted from the ISO 17356-6 specification.
OsIoc	0..1	Configuration of the IOC (Inter OS Application Communicator).
OsIsr	0..*	The OsIsr container represents an ISO 17356 interrupt service routine.
OsOS	1	OS is the object used to define ISO 17356-3 properties for an ISO 17356 application. Per CPU exactly one OS object has to be defined.
OsPeripheralArea	0..65534	Container to structure the configuration parameters of one peripheral area. The container short name can be used to access this area.

▽

△

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsResource	0..*	An OsResource object is used to co-ordinate the concurrent access by tasks and ISRs to a shared resource, e.g. the scheduler, any program sequence, memory or any hardware area.
OsScheduleTable	0..*	An OsScheduleTable addresses the synchronization issue by providing an encapsulation of a statically defined set of alarms that cannot be modified at runtime.
OsSpinlock	0..*	An OsSpinlock object is used to co-ordinate concurrent access by TASKs/ISR2s on different cores to a shared resource.
OsTask	0..*	This container represents an ISO 17356 task.

⌋

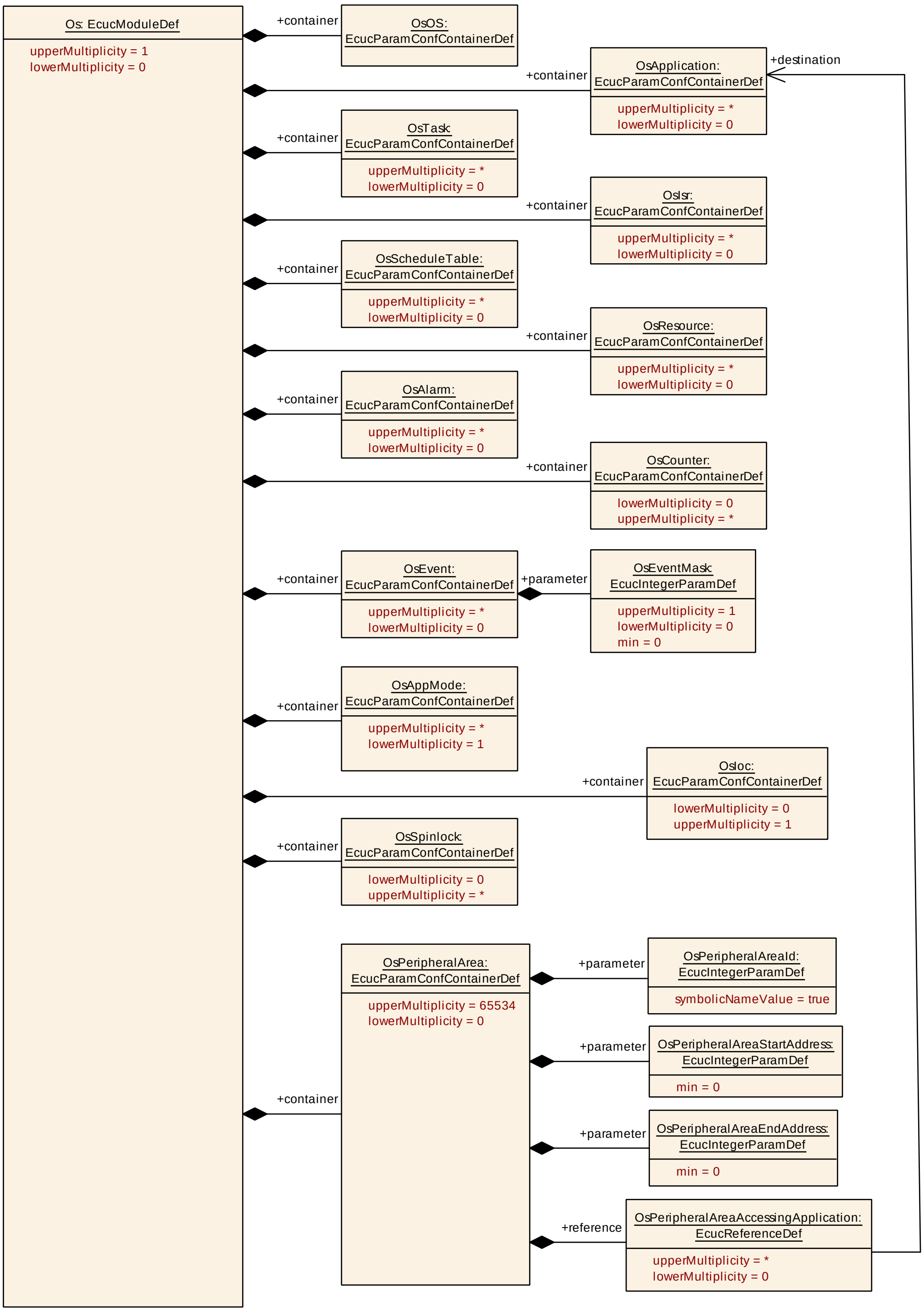

Figure 10.1: Os configuration overview

10.2.2 OsAlarmSetEvent

[ECUC_Os_00016] Definition of EcucParamConfContainerDef OsAlarmSetEvent
⌈

Container Name	OsAlarmSetEvent
Parent Container	OsAlarmAction
Description	This container specifies the parameters to set an event
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsAlarmSetEventRef	1	[ECUC_Os_00017]
OsAlarmSetEventTaskRef	1	[ECUC_Os_00018]

No Included Containers

⌋

[ECUC_Os_00017] Definition of EcucReferenceDef OsAlarmSetEventRef ⌈

Parameter Name	OsAlarmSetEventRef		
Parent Container	OsAlarmSetEvent		
Description	Reference to the event that will be set by that alarm action		
Multiplicity	1		
Type	Reference to OsEvent		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00018] Definition of EcucReferenceDef OsAlarmSetEventTaskRef ⌈

Parameter Name	OsAlarmSetEventTaskRef		
Parent Container	OsAlarmSetEvent		
Description	Reference to the task that will be activated by that event		
Multiplicity	1		
Type	Reference to OsTask		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.2.3 OsAlarm

[ECUC_Os_00003] Definition of EcucParamConfContainerDef OsAlarm ⌈

Container Name	OsAlarm
Parent Container	Os
Description	An OsAlarm may be used to asynchronously inform or activate a specific task. It is possible to start alarms automatically at system start-up depending on the application mode.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsAlarmAccessingApplication	0..*	[ECUC_Os_00004]
OsAlarmCounterRef	1	[ECUC_Os_00005]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsAlarmAction	1	This container defines which type of notification is used when the alarm expires.
OsAlarmAutostart	0..1	If present this container defines if an alarm is started automatically at system start-up depending on the application mode.

⌋

[ECUC_Os_00004] Definition of EcucReferenceDef OsAlarmAccessingApplication ⌈

Parameter Name	OsAlarmAccessingApplication		
Parent Container	OsAlarm		
Description	Reference to applications which have an access to this object.		
Multiplicity	0..*		
Type	Reference to OsApplication		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency			

⌋

[ECUC_Os_00005] Definition of EcucReferenceDef OsAlarmCounterRef ⌈

Parameter Name	OsAlarmCounterRef		
Parent Container	OsAlarm		
Description	Reference to the assigned counter for that alarm		
Multiplicity	1		
Type	Reference to OsCounter		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

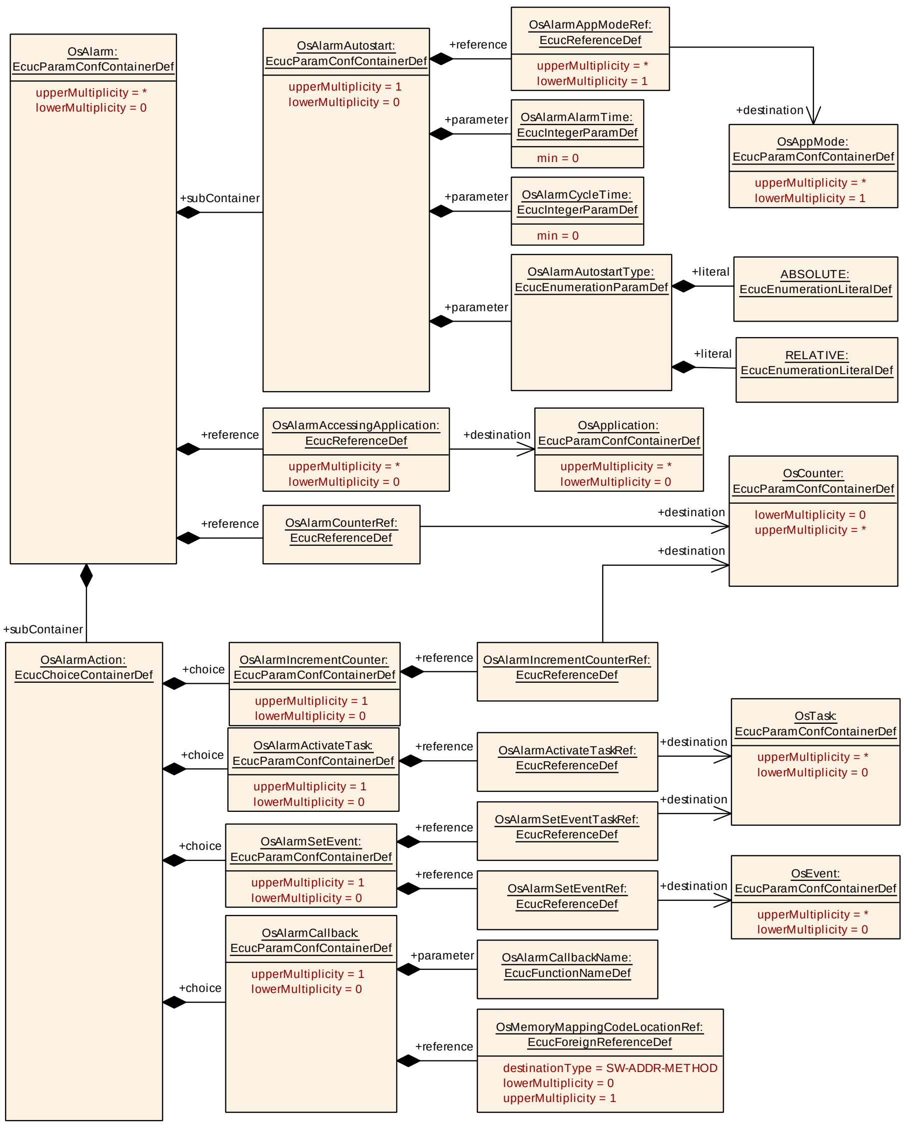

Figure 10.2: OsAlarm configuration overview

10.2.4 OsAlarmAction

[ECUC_Os_00006] Definition of EcucChoiceContainerDef OsAlarmAction ⌈

Choice Container Name	OsAlarmAction
Parent Container	OsAlarm
Description	This container defines which type of notification is used when the alarm expires.

No Included Parameters

Container Choices		
Container Name	**Multiplicity**	**Scope / Dependency**
OsAlarmActivateTask	0..1	This container specifies the parameters to activate a task.
OsAlarmCallback	0..1	This container specifies the parameters to call a callback OS alarm action.
OsAlarmIncrementCounter	0..1	This container specifies the parameters to increment a counter.
OsAlarmSetEvent	0..1	This container specifies the parameters to set an event

⌋

10.2.5 OsAlarmActivateTask

[ECUC_Os_00007] Definition of EcucParamConfContainerDef OsAlarmActivateTask ⌈

Container Name	OsAlarmActivateTask
Parent Container	OsAlarmAction
Description	This container specifies the parameters to activate a task.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsAlarmActivateTaskRef	1	[ECUC_Os_00008]

No Included Containers

⌋

[ECUC_Os_00008] Definition of EcucReferenceDef OsAlarmActivateTaskRef ⌈

Parameter Name	OsAlarmActivateTaskRef
Parent Container	OsAlarmActivateTask
Description	Reference to the task that will be activated by that alarm action

▽

△

Multiplicity	1		
Type	Reference to OsTask		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.2.6 OsAlarmAutostart

[ECUC_Os_00009] Definition of EcucParamConfContainerDef OsAlarmAutostart ⌈

Container Name	OsAlarmAutostart
Parent Container	OsAlarm
Description	If present this container defines if an alarm is started automatically at system start-up depending on the application mode.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsAlarmAlarmTime	1	[ECUC_Os_00010]
OsAlarmAutostartType	1	[ECUC_Os_00011]
OsAlarmCycleTime	1	[ECUC_Os_00012]
OsAlarmAppModeRef	1..*	[ECUC_Os_00013]

No Included Containers

⌋

[ECUC_Os_00010] Definition of EcucIntegerParamDef OsAlarmAlarmTime ⌈

Parameter Name	OsAlarmAlarmTime	
Parent Container	OsAlarmAutostart	
Description	The relative or absolute tick value when the alarm expires for the first time. Note that for an alarm which is RELATIVE the value must be at bigger than 0.	
Multiplicity	1	
Type	EcucIntegerParamDef	
Range	0 .. 18446744073709551615	
Default value	–	
Post-Build Variant Value	false	

▽

△

Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00011] Definition of EcucEnumerationParamDef OsAlarmAutostartType ⌈

Parameter Name	OsAlarmAutostartType		
Parent Container	OsAlarmAutostart		
Description	This specifies the type of autostart for the alarm..		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	ABSOLUTE	The alarm is started on startup via SetAbsAlarm().	
	RELATIVE	The alarm is started on startup via SetRelAlarm().	
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00012] Definition of EcucIntegerParamDef OsAlarmCycleTime ⌈

Parameter Name	OsAlarmCycleTime		
Parent Container	OsAlarmAutostart		
Description	Cycle time of a cyclic alarm in ticks. If the value is 0 than the alarm is not cyclic.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00013] Definition of EcucReferenceDef OsAlarmAppModeRef ⌈

Parameter Name	OsAlarmAppModeRef		
Parent Container	OsAlarmAutostart		
Description	Reference to the application modes for which the AUTOSTART shall be performed		
Multiplicity	1..*		
Type	Reference to OsAppMode		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.2.7 OsAlarmCallback

[ECUC_Os_00014] Definition of EcucParamConfContainerDef OsAlarmCallback ⌈

Container Name	OsAlarmCallback
Parent Container	OsAlarmAction
Description	This container specifies the parameters to call a callback OS alarm action.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsAlarmCallbackName	1	[ECUC_Os_00087]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00409]

No Included Containers

⌋

[ECUC_Os_00087] Definition of EcucFunctionNameDef OsAlarmCallbackName ⌈

Parameter Name	OsAlarmCallbackName
Parent Container	OsAlarmCallback
Description	Name of the function that is called when this alarm callback is triggered.
Multiplicity	1

▽

△

Type	EcucFunctionNameDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00409] Definition of EcucForeignReferenceDef OsMemoryMappingCodeLocationRef ⌈

Parameter Name	OsMemoryMappingCodeLocationRef		
Parent Container	OsAlarmCallback		
Description	Reference to the memory mapping containing details about the section where the code is placed.		
Multiplicity	0..1		
Type	Foreign reference to SW-ADDR-METHOD		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.2.8 OsAlarmIncrementCounter

[ECUC_Os_00302] Definition of EcucParamConfContainerDef OsAlarmIncrementCounter ⌈

Container Name	OsAlarmIncrementCounter
Parent Container	OsAlarmAction
Description	This container specifies the parameters to increment a counter.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsAlarmIncrementCounterRef	1	[ECUC_Os_00015]

No Included Containers

⌋

[ECUC_Os_00015] Definition of EcucReferenceDef OsAlarmIncrementCounterRef ⌈

Parameter Name	OsAlarmIncrementCounterRef		
Parent Container	OsAlarmIncrementCounter		
Description	Reference to the counter that will be incremented by that alarm action		
Multiplicity	1		
Type	Reference to OsCounter		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.2.9 OsApplication

[ECUC_Os_00114] Definition of EcucParamConfContainerDef OsApplication ⌈

Container Name	OsApplication
Parent Container	Os
Description	An AUTOSAR OS must be capable of supporting a collection of OS objects (tasks, interrupts, alarms, hooks etc.) that form a cohesive functional unit. This collection of objects is termed an OS-Application. All objects which belong to the same OS-Application have access to each other. Access means to allow to use these objects within API services. Access by other applications can be granted separately.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsTrusted	1	[ECUC_Os_00115]
OsTrustedApplicationDelayTimingViolationCall	1	[ECUC_Os_00395]
OsTrustedApplicationWithProtection	1	[ECUC_Os_00394]
OsAppAlarmRef	0..*	[ECUC_Os_00231]
OsAppCounterRef	0..*	[ECUC_Os_00234]
OsAppEcucPartitionRef	1	[ECUC_Os_00392]
OsAppIsrRef	0..*	[ECUC_Os_00221]
OsAppScheduleTableRef	0..*	[ECUC_Os_00230]
OsAppTaskRef	0..*	[ECUC_Os_00116]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00402]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsApplicationHooks	1	Container to structure the OS-Application-specific hooks
OsApplicationTrustedFunction	0..*	Container to structure the configuration parameters of trusted functions

⌋

[ECUC_Os_00115] Definition of EcucBooleanParamDef OsTrusted ⌈

Parameter Name	OsTrusted		
Parent Container	OsApplication		
Description	Parameter to specify if an OS-Application is trusted or not. true: OS-Application is trusted false: OS-Application is not trusted (default)		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	false		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 3 and 4.		

⌋

[ECUC_Os_00395] Definition of EcucBooleanParamDef OsTrustedApplicationDelayTimingViolationCall ⌈

Parameter Name	OsTrustedApplicationDelayTimingViolationCall		
Parent Container	OsApplication		
Description	Parameter to specify if a timing violation which occurs within an trusted OS-Application is raised immediately of if it is delayed until the current task returns to the calling OS-Application (return of CallTrustedFunction) true: violation / call to ProtectionHook() is delayed false: timing violation cause an immediate call to the ProtectionHook().		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	true		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00394] Definition of EcucBooleanParamDef OsTrustedApplicationWithProtection ⌈

Parameter Name	OsTrustedApplicationWithProtection		
Parent Container	OsApplication		
Description	Parameter to specify if a trusted OS-Application is executed with memory protection or not. true: OS-Application runs within a protected environment. This means that write access is limited. false: OS-Application has full write access (default)		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	false		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00231] Definition of EcucReferenceDef OsAppAlarmRef ⌈

Parameter Name	OsAppAlarmRef		
Parent Container	OsApplication		
Description	Specifies the OsAlarms that belong to the OsApplication.		
Multiplicity	0..*		
Type	Reference to OsAlarm		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00234] Definition of EcucReferenceDef OsAppCounterRef ⌈

Parameter Name	OsAppCounterRef
Parent Container	OsApplication
Description	References the OsCounters that belong to the OsApplication.
Multiplicity	0..*
Type	Reference to OsCounter
Post-Build Variant Multiplicity	false

▽

△

Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00392] Definition of EcucReferenceDef OsAppEcucPartitionRef ⌈

Parameter Name	OsAppEcucPartitionRef		
Parent Container	OsApplication		
Description	Denotes which "EcucPartition" is implemented by this "OSApplication".		
Multiplicity	1		
Type	Reference to EcucPartition		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00221] Definition of EcucReferenceDef OsAppIsrRef ⌈

Parameter Name	OsAppIsrRef		
Parent Container	OsApplication		
Description	references which OsIsrs belong to the OsApplication		
Multiplicity	0..*		
Type	Reference to OsIsr		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	

▽

△

Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00230] Definition of EcucReferenceDef OsAppScheduleTableRef ⌈

Parameter Name	OsAppScheduleTableRef		
Parent Container	OsApplication		
Description	References the OsScheduleTables that belong to the OsApplication.		
Multiplicity	0..*		
Type	Reference to OsScheduleTable		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00116] Definition of EcucReferenceDef OsAppTaskRef ⌈

Parameter Name	OsAppTaskRef		
Parent Container	OsApplication		
Description	references which OsTasks belong to the OsApplication		
Multiplicity	0..*		
Type	Reference to OsTask		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00402] Definition of EcucForeignReferenceDef OsMemoryMapping CodeLocationRef ⌈

Parameter Name	OsMemoryMappingCodeLocationRef		
Parent Container	OsApplication, OsApplicationHooks, OsHooks, OsIsr, OsTask		
Description	Reference to the memory mapping containing details about the section where the code is placed.		
Multiplicity	0..1		
Type	Foreign reference to SW-ADDR-METHOD		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

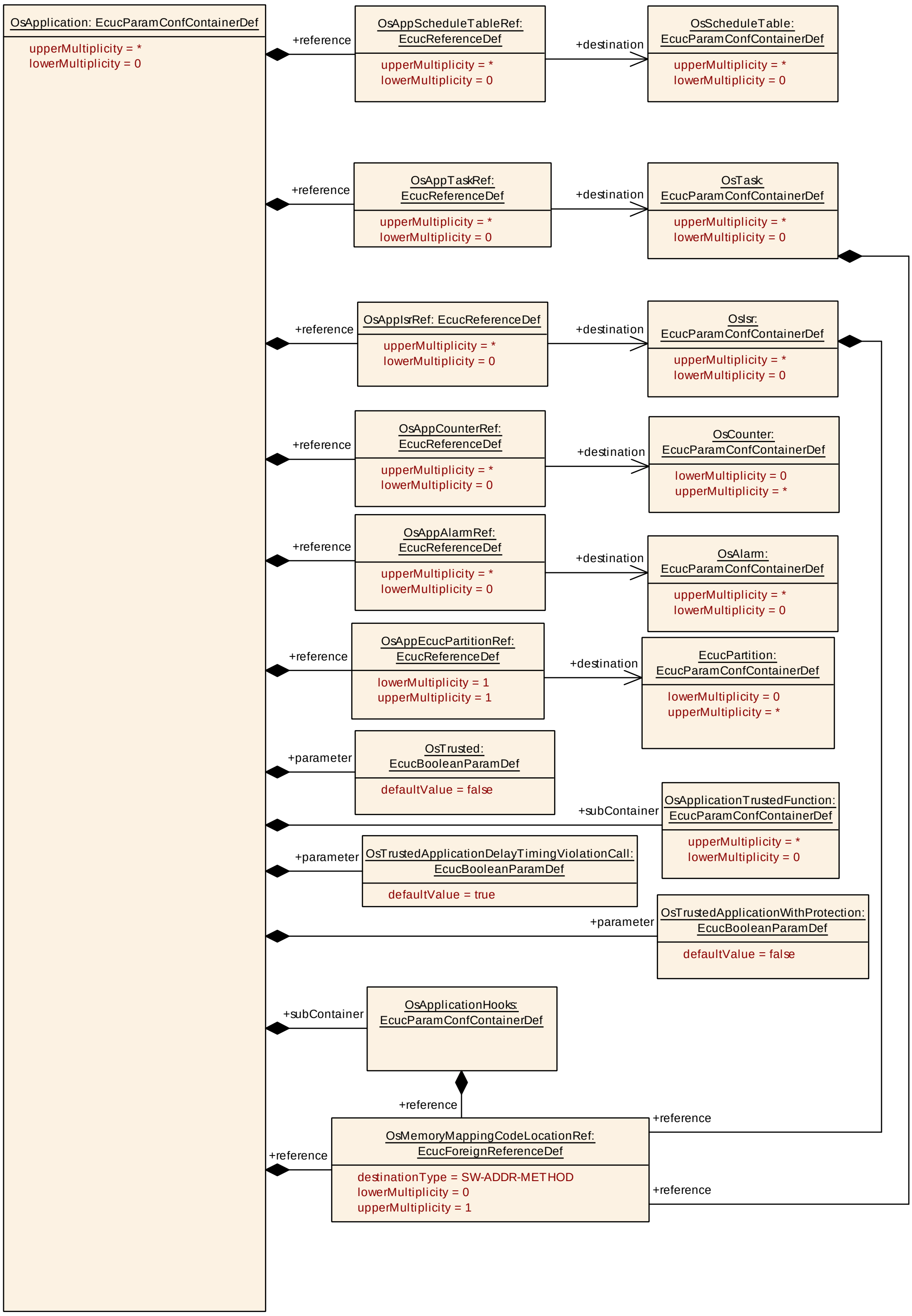

Figure 10.3: OsApplication configuration overview

10.2.10 OsApplicationHooks

[ECUC_Os_00020] Definition of EcucParamConfContainerDef OsApplicationHooks ⌈

Container Name	OsApplicationHooks
Parent Container	OsApplication
Description	Container to structure the OS-Application-specific hooks
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsAppErrorHook	1	[ECUC_Os_00213]
OsAppShutdownHook	1	[ECUC_Os_00125]
OsAppStartupHook	1	[ECUC_Os_00124]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00402]

No Included Containers

⌋

[ECUC_Os_00213] Definition of EcucBooleanParamDef OsAppErrorHook ⌈

Parameter Name	OsAppErrorHook		
Parent Container	OsApplicationHooks		
Description	Select the OS-Application error hook. true: Hook is called false: Hook is not called		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	Pre-compile time	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 3 and 4.		

⌋

[ECUC_Os_00125] Definition of EcucBooleanParamDef OsAppShutdownHook ⌈

Parameter Name	OsAppShutdownHook
Parent Container	OsApplicationHooks
Description	Select the OS-Application specific shutdown hook for the OS-Application. true: Hook is called false: Hook is not called

▽

△

Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 3 and 4.		

⌋

[ECUC_Os_00124] Definition of EcucBooleanParamDef OsAppStartupHook ⌈

Parameter Name	OsAppStartupHook		
Parent Container	OsApplicationHooks		
Description	Select the OS-Application specific startup hook for the OS-Application. true: Hook is called false: Hook is not called		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 3 and 4.		

⌋

For parameter table [ECUC_Os_00402] OsMemoryMappingCodeLocationRef, see definition below container OsApplication.

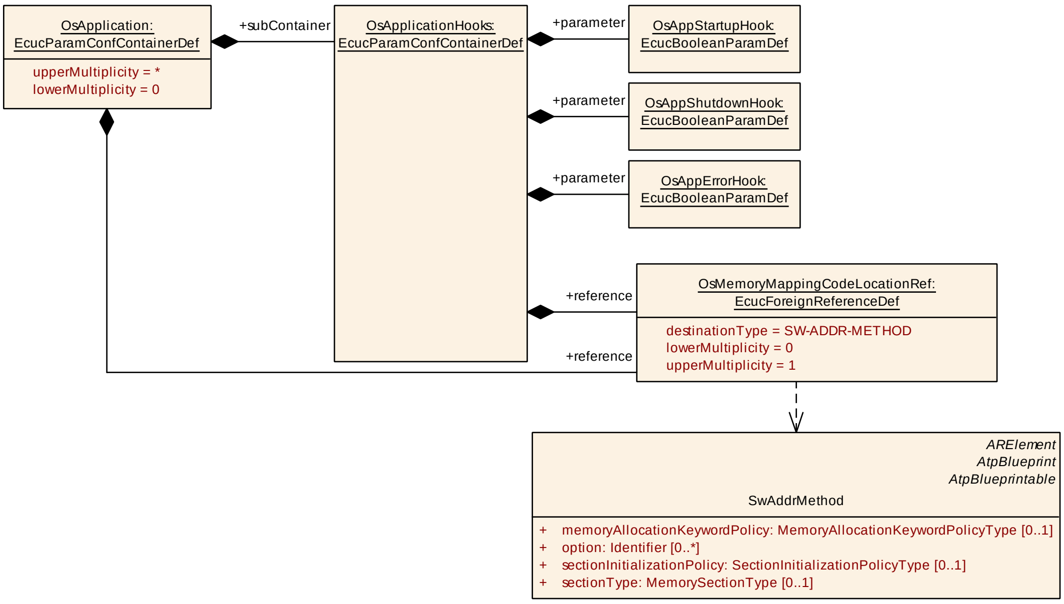

Figure 10.4: OsApplicationHooks configuration overview

10.2.11 OsApplicationTrustedFunction

[ECUC_Os_00021] Definition of EcucParamConfContainerDef OsApplication TrustedFunction ⌈

Container Name	OsApplicationTrustedFunction
Parent Container	OsApplication
Description	Container to structure the configuration parameters of trusted functions
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsTrustedFunctionName	1	[ECUC_Os_00254]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00408]

No Included Containers

⌋

[ECUC_Os_00254] Definition of EcucFunctionNameDef OsTrustedFunctionName ⌈

Parameter Name	OsTrustedFunctionName		
Parent Container	OsApplicationTrustedFunction		
Description	Trusted function (as part of a trusted OS-Application) available to other OS-Applications. This also supersedes the ISO 17356-6 attribute TRUSTED in APPLICATION because the optionality of this parameter is describing that already.		
Multiplicity	1		
Type	EcucFunctionNameDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 3 and 4 and in trusted OS-Applications.		

⌋

[ECUC_Os_00408] Definition of EcucForeignReferenceDef OsMemoryMappingCodeLocationRef ⌈

Parameter Name	OsMemoryMappingCodeLocationRef		
Parent Container	OsApplicationTrustedFunction		
Description	Reference to the memory mapping containing details about the section where the code is placed.		
Multiplicity	0..1		
Type	Foreign reference to SW-ADDR-METHOD		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

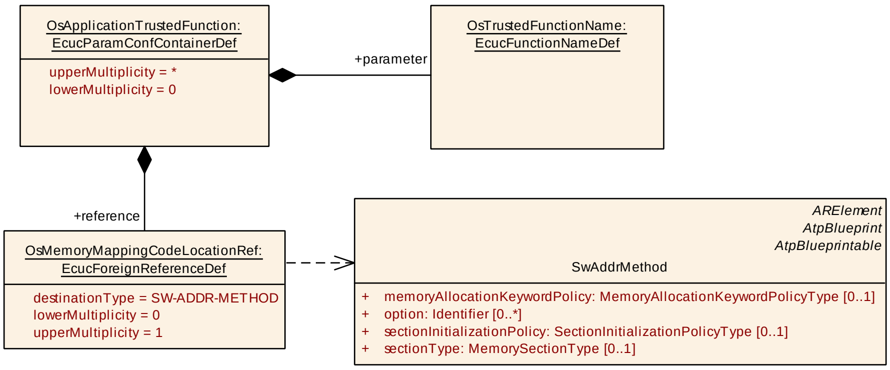

Figure 10.5: OsApplicationTrustedFunction configuration overview

10.2.12 OsAppMode

[ECUC_Os_00022] Definition of EcucParamConfContainerDef OsAppMode ⌈

Container Name	OsAppMode
Parent Container	Os
Description	OsAppMode is the object used to define ISO 17356-3 properties for an ISO 17356-3 application mode. No standard attributes are defined for AppMode. In a CPU, at least one AppMode object has to be defined. [source: ISO 17356-6] An OsAppMode called OSDEFAULTAPPMODE must always be there for ISO 17356 compatibility.
Configuration Parameters	

No Included Parameters

No Included Containers

⌋

10.2.13 OsCounter

[ECUC_Os_00026] Definition of EcucParamConfContainerDef OsCounter ⌈

Container Name	OsCounter
Parent Container	Os
Description	Configuration information for the counters that belong to the OsApplication.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsCounterMaxAllowedValue	1	[ECUC_Os_00027]
OsCounterMinCycle	1	[ECUC_Os_00028]
OsCounterTicksPerBase	1	[ECUC_Os_00029]
OsCounterType	1	[ECUC_Os_00255]
OsSecondsPerTick	0..1	[ECUC_Os_00030]
OsCounterAccessingApplication	0..*	[ECUC_Os_00031]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsDriver	0..1	This Container contains the information who will drive the counter. This configuration is only valid if the counter has Os CounterType set to HARDWARE. If the container does not exist (multiplicity=0) the timer is managed by the OS internally (OSINTERNAL). If the container exists the OS can use the GPT interface to manage the timer. The user have to supply the GPT channel. If the counter is driven by some other (external to the OS) source (like a TPU for example) this must be described as a vendor specific extension.
OsTimeConstant	0..*	Allows the user to define constants which can be e.g. used to compare time values with timer tick values. A time value will be converted to a timer tick value during generation and can later on accessed via the OsConstName. The conversation is done by rounding time values to the nearest fitting tick value.

⌋

[ECUC_Os_00027] Definition of EcucIntegerParamDef OsCounterMaxAllowedValue ⌈

Parameter Name	OsCounterMaxAllowedValue		
Parent Container	OsCounter		
Description	Maximum possible allowed value of the system counter in ticks.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	1 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00028] Definition of EcucIntegerParamDef OsCounterMinCycle ⌈

Parameter Name	OsCounterMinCycle		
Parent Container	OsCounter		
Description	The MINCYCLE attribute specifies the minimum allowed number of counter ticks for a cyclic alarm linked to the counter.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	1 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00029] Definition of EcucIntegerParamDef OsCounterTicksPerBase ⌈

Parameter Name	OsCounterTicksPerBase		
Parent Container	OsCounter		
Description	The TICKSPERBASE attribute specifies the number of ticks required to reach a counterspecific unit. The interpretation is implementation-specific.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	1 .. 4294967295		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00255] Definition of EcucEnumerationParamDef OsCounterType ⌈

Parameter Name	OsCounterType	
Parent Container	OsCounter	
Description	This parameter contains the natural type or unit of the counter.	
Multiplicity	1	
Type	EcucEnumerationParamDef	
Range	HARDWARE	This counter is driven by some hardware e.g. a hardware timer unit.
	SOFTWARE	The counter is driven by some software which calls the IncrementCounter service.

▽

△

Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00030] Definition of EcucFloatParamDef OsSecondsPerTick ⌈

Parameter Name	OsSecondsPerTick		
Parent Container	OsCounter		
Description	Time of one counter tick in seconds.		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00031] Definition of EcucReferenceDef OsCounterAccessingApplication ⌈

Parameter Name	OsCounterAccessingApplication		
Parent Container	OsCounter		
Description	Reference to applications which have an access to this object.		
Multiplicity	0..*		
Type	Reference to OsApplication		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	

▽

△

Scope / Dependency	scope: local

⌋

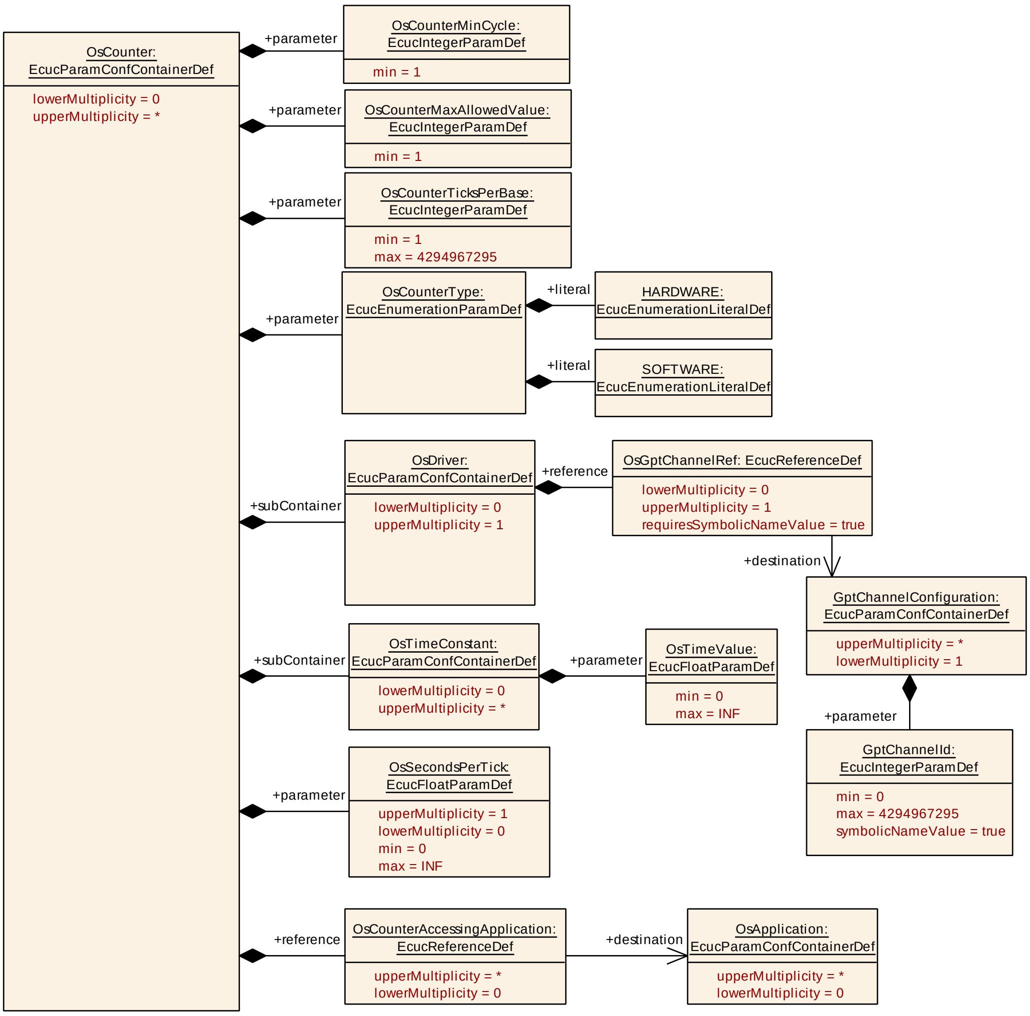

Figure 10.6: OsCounter configuration overview

10.2.14 OsEvent

[ECUC_Os_00033] Definition of EcucParamConfContainerDef OsEvent ⌈

Container Name	OsEvent
Parent Container	Os
Description	Representation of OS events in the configuration context. Adopted from the ISO 17356-6 specification.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsEventMask	0..1	[ECUC_Os_00034]

No Included Containers

⌋

[ECUC_Os_00034] Definition of EcucIntegerParamDef OsEventMask ⌈

Parameter Name	OsEventMask		
Parent Container	OsEvent		
Description	If event mask would be set to AUTO in OIL, this parameter should be omitted here.		
Multiplicity	0..1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.2.15 OsDriver

[ECUC_Os_00371] Definition of EcucParamConfContainerDef OsDriver ⌈

Container Name	OsDriver
Parent Container	OsCounter
Description	This Container contains the information who will drive the counter. This configuration is only valid if the counter has OsCounterType set to HARDWARE. If the container does not exist (multiplicity=0) the timer is managed by the OS internally (OSINTERNAL). If the container exists the OS can use the GPT interface to manage the timer. The user have to supply the GPT channel. If the counter is driven by some other (external to the OS) source (like a TPU for example) this must be described as a vendor specific extension.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsGptChannelRef	0..1	[ECUC_Os_00032]

No Included Containers

⌋

[ECUC_Os_00032] Definition of EcucReferenceDef OsGptChannelRef ⌈

Parameter Name	OsGptChannelRef		
Parent Container	OsDriver		
Description	Reference to the GPT channel.		
Multiplicity	0..1		
Type	Symbolic name reference to GptChannelConfiguration		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.2.16 OsHooks

[ECUC_Os_00035] Definition of EcucParamConfContainerDef OsHooks ⌈

Container Name	OsHooks
Parent Container	OsOS
Description	Container to structure all hooks belonging to the OS
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsErrorHook	1	[ECUC_Os_00036]
OsPostTaskHook	1	[ECUC_Os_00037]
OsPreTaskHook	1	[ECUC_Os_00038]
OsProtectionHook	0..1	[ECUC_Os_00214]
OsShutdownHook	1	[ECUC_Os_00039]
OsStartupHook	1	[ECUC_Os_00040]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00402]

No Included Containers

⌋

[ECUC_Os_00036] Definition of EcucBooleanParamDef OsErrorHook ⌈

Parameter Name	OsErrorHook		
Parent Container	OsHooks		
Description	Error hook as defined by ISO 17356 true: Hook is called false: Hook is not called		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00037] Definition of EcucBooleanParamDef OsPostTaskHook ⌈

Parameter Name	OsPostTaskHook		
Parent Container	OsHooks		
Description	Post-task hook as defined by ISO 17356 true: Hook is called false: Hook is not called		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00038] Definition of EcucBooleanParamDef OsPreTaskHook ⌈

Parameter Name	OsPreTaskHook
Parent Container	OsHooks
Description	Pre-task hook as defined by ISO 17356 true: Hook is called false: Hook is not called
Multiplicity	1
Type	EcucBooleanParamDef

▽

△

Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00214] Definition of EcucBooleanParamDef OsProtectionHook ⌈

Parameter Name	OsProtectionHook		
Parent Container	OsHooks		
Description	Switch to enable/disable the call to the (user supplied) protection hook. true: Protection hook is called on protection error false: Protection hook is not called		
Multiplicity	0..1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2,3 and 4		

⌋

[ECUC_Os_00039] Definition of EcucBooleanParamDef OsShutdownHook ⌈

Parameter Name	OsShutdownHook		
Parent Container	OsHooks		
Description	Shutdown hook as defined by ISO 17356 true: Hook is called false: Hook is not called		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00040] Definition of EcucBooleanParamDef OsStartupHook ⌈

Parameter Name	OsStartupHook		
Parent Container	OsHooks		
Description	Startup hook as defined by ISO 17356 true: Hook is called false: Hook is not called		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

For parameter table [ECUC_Os_00402] OsMemoryMappingCodeLocationRef, see definition below container OsApplication.

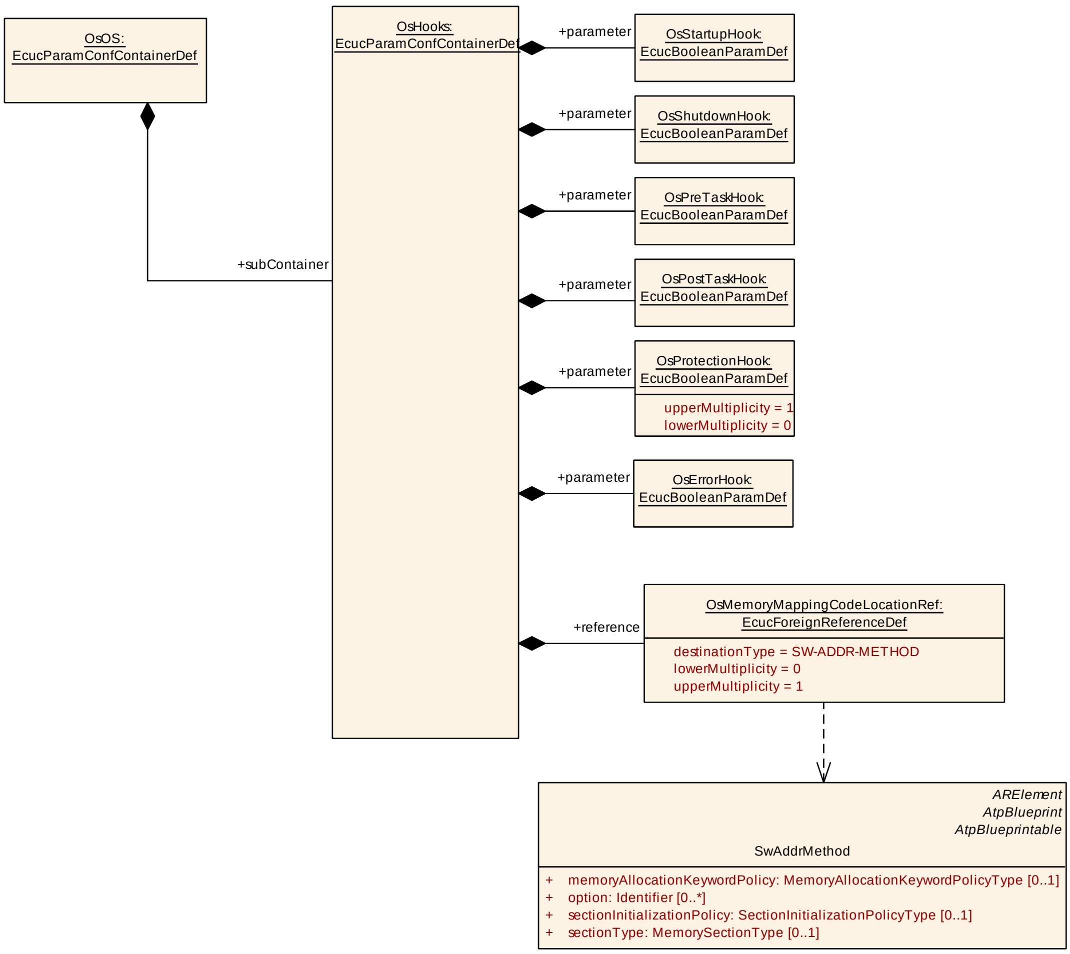

Figure 10.7: OsHooks configuration overview

10.2.17 OsIsr

[ECUC_Os_00041] Definition of EcucParamConfContainerDef OsIsr ⌈

Container Name	OsIsr
Parent Container	Os
Description	The OsIsr container represents an ISO 17356 interrupt service routine.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsIsrCategory	1	[ECUC_Os_00042]
OsIsrPeriod	0..1	[ECUC_Os_00403]
OsIsrResourceRef	0..*	[ECUC_Os_00043]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00402]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsIsrTimingProtection	0..1	This container contains all parameters which are related to timing protection If the container exists, the timing protection is used for this interrupt. If the container does not exist, the interrupt is not supervised regarding timing violations.

⌋

[ECUC_Os_00042] Definition of EcucEnumerationParamDef OsIsrCategory ⌈

Parameter Name	OsIsrCategory		
Parent Container	OsIsr		
Description	This attribute specifies the category of this ISR.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	CATEGORY_1	Interrupt is of category 1	
	CATEGORY_2	Interrupt is of category 2	
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00403] Definition of EcucFloatParamDef OsIsrPeriod ⌈

Parameter Name	OsIsrPeriod		
Parent Container	OsIsr		
Description	This parameter specifies the period in seconds of this ISR in case of a cyclically triggered interrupt. If this parameter is not given the interrupt can be activated sporadicly or cyclically with a unknown period value. This value is information, e.g. for time base calculations in the RTE in case Timing Events are mapped onto this OsIsr. Be aware, that this parameter is not supposed to be relevant for the OS! It's the responsibility of the integrator to ensure the activation of the ISR according the configured period. This information is given as part of the OS configuration to support configuration work flows using a fixed set of OsIsrs.		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[-INF .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00043] Definition of EcucReferenceDef OsIsrResourceRef ⌈

Parameter Name	OsIsrResourceRef		
Parent Container	OsIsr		
Description	This reference defines the resources accessed by this ISR.		
Multiplicity	0..*		
Type	Reference to OsResource		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

For parameter table [ECUC_Os_00402] OsMemoryMappingCodeLocationRef, see definition below container OsApplication.

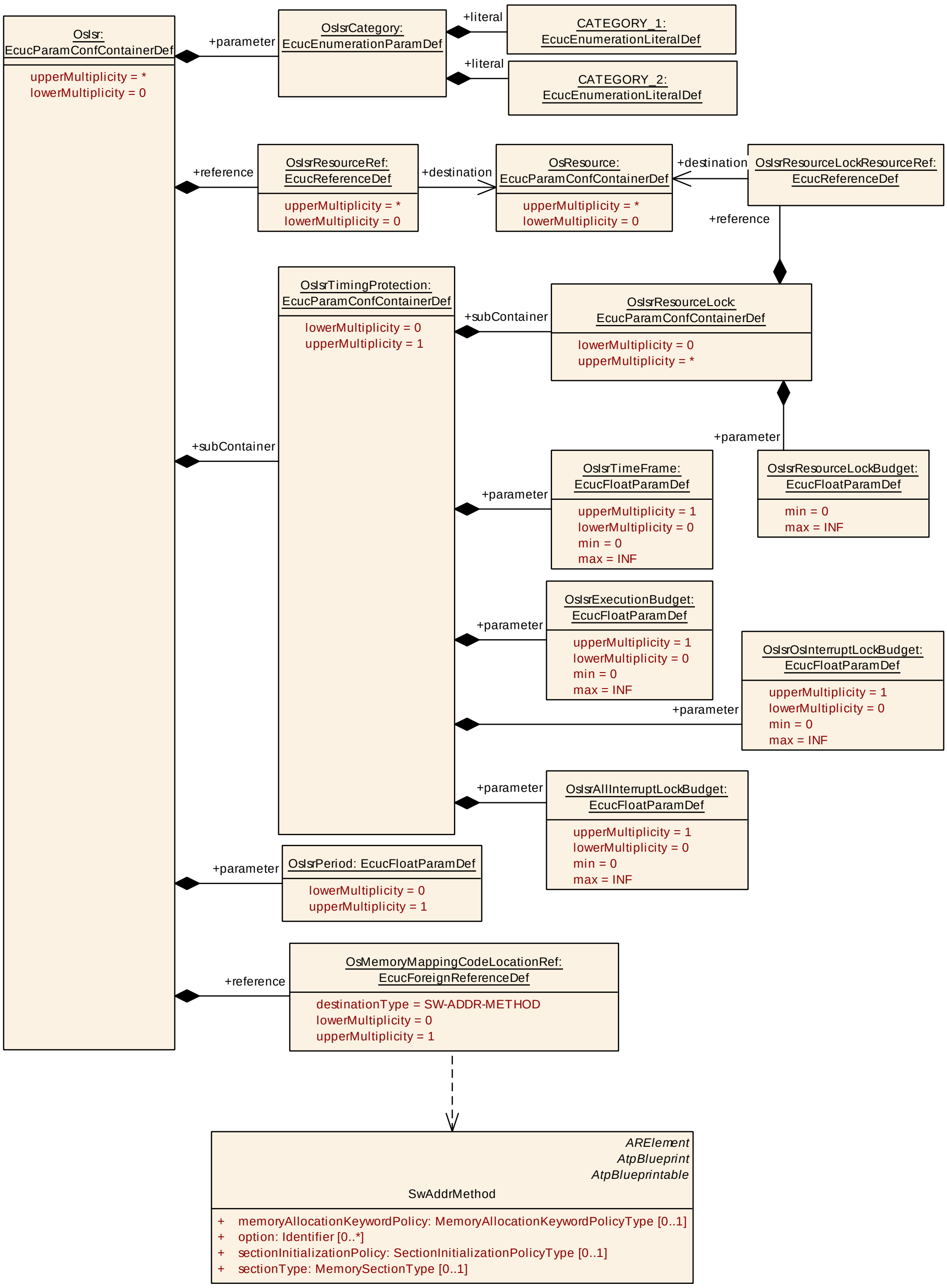

Figure 10.8: OsIsr configuration overview

10.2.18 OsIsrResourceLock

[ECUC_Os_00388] Definition of EcucParamConfContainerDef OsIsrResourceLock ⌈

Container Name	OsIsrResourceLock
Parent Container	OsIsrTimingProtection
Description	This container contains a list of times the interrupt uses resources.
Configuration Parameters	

Included Parameters		
Parameter Name	Multiplicity	ECUC ID
OsIsrResourceLockBudget	1	[ECUC_Os_00389]
OsIsrResourceLockResourceRef	1	[ECUC_Os_00390]

No Included Containers

⌋

[ECUC_Os_00389] Definition of EcucFloatParamDef OsIsrResourceLockBudget ⌈

Parameter Name	OsIsrResourceLockBudget		
Parent Container	OsIsrResourceLock		
Description	This parameter contains the maximum time the interrupt is allowed to hold the given resource (in seconds).		
Multiplicity	1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00390] Definition of EcucReferenceDef OsIsrResourceLockResourceRef ⌈

Parameter Name	OsIsrResourceLockResourceRef		
Parent Container	OsIsrResourceLock		
Description	Reference to the resource the locking time is depending on		
Multiplicity	1		
Type	Reference to OsResource		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	

▽

△

Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4

⌋

10.2.19 OsIsrTimingProtection

[ECUC_Os_00326] Definition of EcucParamConfContainerDef OsIsrTimingProtection ⌈

Container Name	OsIsrTimingProtection
Parent Container	OsIsr
Description	This container contains all parameters which are related to timing protection If the container exists, the timing protection is used for this interrupt. If the container does not exist, the interrupt is not supervised regarding timing violations.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsIsrAllInterruptLockBudget	0..1	[ECUC_Os_00229]
OsIsrExecutionBudget	0..1	[ECUC_Os_00222]
OsIsrOsInterruptLockBudget	0..1	[ECUC_Os_00387]
OsIsrTimeFrame	0..1	[ECUC_Os_00223]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsIsrResourceLock	0..*	This container contains a list of times the interrupt uses resources.

⌋

[ECUC_Os_00229] Definition of EcucFloatParamDef OsIsrAllInterruptLockBudget ⌈

Parameter Name	OsIsrAllInterruptLockBudget	
Parent Container	OsIsrTimingProtection	
Description	This parameter contains the maximum time for which the ISR is allowed to lock all interrupts (via SuspendAllInterrupts() or DisableAllInterrupts()) (in seconds).	
Multiplicity	0..1	
Type	EcucFloatParamDef	
Range	[0 .. INF]	
Default value	–	
Post-Build Variant Multiplicity	false	

▽

△

Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00222] Definition of EcucFloatParamDef OsIsrExecutionBudget ⌈

Parameter Name	OsIsrExecutionBudget		
Parent Container	OsIsrTimingProtection		
Description	The parameter contains the maximum allowed execution time of the interrupt (in seconds).		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00387] Definition of EcucFloatParamDef OsIsrOsInterruptLockBudget ⌈

Parameter Name	OsIsrOsInterruptLockBudget	
Parent Container	OsIsrTimingProtection	
Description	This parameter contains the maximum time for which the ISR is allowed to lock all Category 2 interrupts (via SuspendOSInterrupts()) (in seconds).	
Multiplicity	0..1	
Type	EcucFloatParamDef	
Range	[0 .. INF]	
Default value	–	

▽

△

Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00223] Definition of EcucFloatParamDef OsIsrTimeFrame ⌈

Parameter Name	OsIsrTimeFrame		
Parent Container	OsIsrTimingProtection		
Description	This parameter contains the minimum inter-arrival time between successive interrupts (in seconds).		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

10.2.20 OsOS

[ECUC_Os_00044] Definition of EcucParamConfContainerDef OsOS ⌈

Container Name	OsOS
Parent Container	Os
Description	OS is the object used to define ISO 17356-3 properties for an ISO 17356 application. Per CPU exactly one OS object has to be defined.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsLockTrustedFunctionCall	1	[ECUC_Os_00410]
OsNumberOfCores	0..1	[ECUC_Os_01019]
OsScalabilityClass	0..1	[ECUC_Os_00259]
OsStackMonitoring	1	[ECUC_Os_00307]
OsStatus	1	[ECUC_Os_00046]
OsUseArti	1	[ECUC_Os_00406]
OsUseGetServiceId	1	[ECUC_Os_00047]
OsUseParameterAccess	1	[ECUC_Os_00048]
OsUseResScheduler	1	[ECUC_Os_00049]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsHooks	1	Container to structure all hooks belonging to the OS

⌋

[ECUC_Os_00410] Definition of EcucBooleanParamDef OsLockTrustedFunctionCall ⌈

Parameter Name	OsLockTrustedFunctionCall		
Parent Container	OsOS		
Description	The OsLockTrustedFunctionCall attribute defines whether the OS locks preemption while a trusted function call is ongoing.		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	true		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_01019] Definition of EcucIntegerParamDef OsNumberOfCores ⌈

Parameter Name	OsNumberOfCores	
Parent Container	OsOS	
Description	Maximum number of cores that are controlled by the OS. The OS uses the value internally. It depends on the ECU HW.	
Multiplicity	0..1	
Type	EcucIntegerParamDef	
Range	1 .. 65535	
Default value	–	
Post-Build Variant Multiplicity	false	

▽

△

Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00259] Definition of EcucEnumerationParamDef OsScalabilityClass ⌈

Parameter Name	OsScalabilityClass		
Parent Container	OsOS		
Description	A scalability class for each System Object "OS" has to be selected. In order to customize the operating system to the needs of the user and to take full advantage of the processor features the operating system can be scaled according to the scalability classes. If the scalability class is omitted this translates to the OIL AUTO mechanism.		
Multiplicity	0..1		
Type	EcucEnumerationParamDef		
Range	SC1	–	
	SC2	–	
	SC3	–	
	SC4	–	
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00307] Definition of EcucBooleanParamDef OsStackMonitoring ⌈

Parameter Name	OsStackMonitoring		
Parent Container	OsOS		
Description	Select stack monitoring of Tasks/Category 2 ISRs true: Stacks are monitored false: Stacks are not monitored		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	

▽

△

	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00046] Definition of EcucEnumerationParamDef OsStatus ⌈

Parameter Name	OsStatus		
Parent Container	OsOS		
Description	The Status attribute specifies whether a system with standard or extended status has to be used. Automatic assignment is not supported for this attribute.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	EXTENDED	–	
	STANDARD	–	
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00406] Definition of EcucBooleanParamDef OsUseArti ⌈

Parameter Name	OsUseArti		
Parent Container	OsOS		
Description	The OsUseArti attribute defines whether the OS uses and calls ARTI hooks. This includes also the generation of related ARTI artifacts by the generator.		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00047] Definition of EcucBooleanParamDef OsUseGetServiceId ⌈

Parameter Name	OsUseGetServiceId
Parent Container	OsOS
Description	As defined by ISO 17356
Multiplicity	1

▽

△

Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00048] Definition of EcucBooleanParamDef OsUseParameterAccess ⌈

Parameter Name	OsUseParameterAccess		
Parent Container	OsOS		
Description	As defined by ISO 17356		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00049] Definition of EcucBooleanParamDef OsUseResScheduler ⌈

Parameter Name	OsUseResScheduler		
Parent Container	OsOS		
Description	The OsUseResScheduler attribute defines whether the resource RES_SCHEDULER is used within the application.		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	true		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

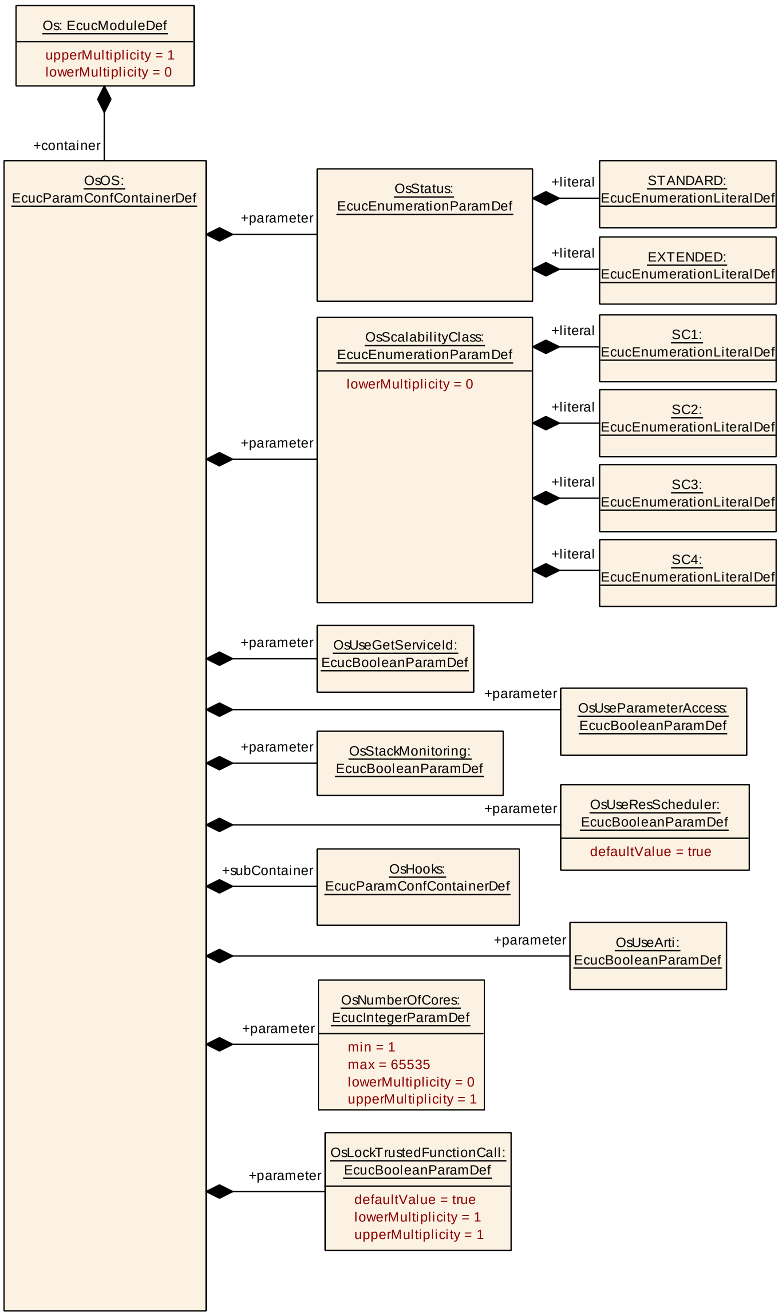

Figure 10.9: OsOs configuration overview

10.2.21 OsPeripheralArea

[ECUC_Os_00397] Definition of EcucParamConfContainerDef OsPeripheralArea
⌈

Container Name	OsPeripheralArea		
Parent Container	Os		
Description	Container to structure the configuration parameters of one peripheral area. The container short name can be used to access this area.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsPeripheralAreaEndAddress	1	[ECUC_Os_00400]
OsPeripheralAreaId	1	[ECUC_Os_00398]
OsPeripheralAreaStartAddress	1	[ECUC_Os_00399]
OsPeripheralAreaAccessingApplication	0..*	[ECUC_Os_00401]

No Included Containers

⌋

[ECUC_Os_00400] Definition of EcucIntegerParamDef OsPeripheralAreaEndAddress ⌈

Parameter Name	OsPeripheralAreaEndAddress		
Parent Container	OsPeripheralArea		
Description	Last valid address of a peripheral area.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00398] Definition of EcucIntegerParamDef OsPeripheralAreaId ⌈

Parameter Name	OsPeripheralAreaId
Parent Container	OsPeripheralArea
Description	Id of peripheral area.
Multiplicity	1
Type	EcucIntegerParamDef (Symbolic Name generated for this parameter)

▽

△

Range	0 .. 18446744073709551615	
Default value	–	
Post-Build Variant Value	false	
Scope / Dependency	scope: local	

⌋

[ECUC_Os_00399] Definition of EcucIntegerParamDef OsPeripheralAreaStartAddress ⌈

Parameter Name	OsPeripheralAreaStartAddress		
Parent Container	OsPeripheralArea		
Description	First valid address of a peripheral area.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Multiplicity	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00401] Definition of EcucReferenceDef OsPeripheralAreaAccessing Application ⌈

Parameter Name	OsPeripheralAreaAccessingApplication
Parent Container	OsPeripheralArea
Description	Reference to application which have access to this object.
Multiplicity	0..*
Type	Reference to OsApplication
Post-Build Variant Multiplicity	false
Post-Build Variant Value	false
Scope / Dependency	scope: local

⌋

10.2.22 OsResource

[ECUC_Os_00252] Definition of EcucParamConfContainerDef OsResource ⌈

Container Name	OsResource
Parent Container	Os
Description	An OsResource object is used to co-ordinate the concurrent access by tasks and ISRs to a shared resource, e.g. the scheduler, any program sequence, memory or any hardware area.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsResourceProperty	1	[ECUC_Os_00050]
OsResourceAccessingApplication	0..*	[ECUC_Os_00051]
OsResourceLinkedResourceRef	0..1	[ECUC_Os_00052]

No Included Containers

⌋

[ECUC_Os_00050] Definition of EcucEnumerationParamDef OsResourceProperty ⌈

Parameter Name	OsResourceProperty		
Parent Container	OsResource		
Description	This specifies the type of the resource.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	INTERNAL	The resource is an internal resource.	
	LINKED	The resource is a linked resource (a second name for a existing resource).	
	STANDARD	The resource is a standard resource.	
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00051] Definition of EcucReferenceDef OsResourceAccessingApplication ⌈

Parameter Name	OsResourceAccessingApplication
Parent Container	OsResource
Description	Reference to applications which have an access to this object.
Multiplicity	0..*
Type	Reference to OsApplication
Post-Build Variant Multiplicity	false

▽

△

Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00052] Definition of EcucReferenceDef OsResourceLinkedResourceRef ⌈

Parameter Name	OsResourceLinkedResourceRef		
Parent Container	OsResource		
Description	The link to the resource. Must be valid if OsResourceProperty is LINKED. If OsResourceProperty is not LINKED the value is ignored.		
Multiplicity	0..1		
Type	Reference to OsResource		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

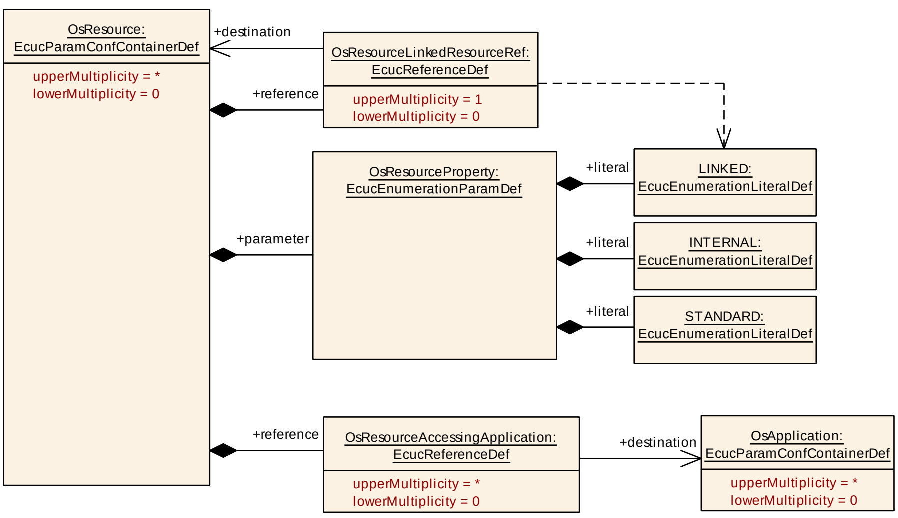

Figure 10.10: OsResource configuration overview

10.2.23 OsScheduleTable

[ECUC_Os_00141] Definition of EcucParamConfContainerDef OsScheduleTable
⌈

Container Name	OsScheduleTable
Parent Container	Os
Description	An OsScheduleTable addresses the synchronization issue by providing an encapsulation of a statically defined set of alarms that cannot be modified at runtime.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsScheduleTableDuration	1	[ECUC_Os_00053]
OsScheduleTableRepeating	1	[ECUC_Os_00144]
OsScheduleTableCounterRef	1	[ECUC_Os_00145]
OsSchTblAccessingApplication	0..*	[ECUC_Os_00054]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsScheduleTableAutostart	0..1	This container specifies if and how the schedule table is started on startup of the Operating System. The options to start a schedule table correspond to the API calls to start schedule tables during runtime.
OsScheduleTableExpiryPoint	1..*	The point on a Schedule Table at which the OS activates tasks and/or sets events
OsScheduleTableSync	0..1	This container specifies the synchronization parameters of the schedule table.

⌋

[ECUC_Os_00053] Definition of EcucIntegerParamDef OsScheduleTableDuration
⌈

Parameter Name	OsScheduleTableDuration		
Parent Container	OsScheduleTable		
Description	This parameter defines the modulus of the schedule table (in ticks).		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00144] Definition of EcucBooleanParamDef OsScheduleTableRepeating ⌈

Parameter Name	OsScheduleTableRepeating		
Parent Container	OsScheduleTable		
Description	true: first expiry point on the schedule table shall be processed at final expiry point delay ticks after the final expiry point is processed. false: the schedule table processing stops when the final expiry point is processed.		
Multiplicity	1		
Type	EcucBooleanParamDef		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00145] Definition of EcucReferenceDef OsScheduleTableCounterRef ⌈

Parameter Name	OsScheduleTableCounterRef		
Parent Container	OsScheduleTable		
Description	This parameter contains a reference to the counter which drives the schedule table.		
Multiplicity	1		
Type	Reference to OsCounter		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00054] Definition of EcucReferenceDef OsSchTblAccessingApplication ⌈

Parameter Name	OsSchTblAccessingApplication		
Parent Container	OsScheduleTable		
Description	Reference to applications which have an access to this object.		
Multiplicity	0..*		
Type	Reference to OsApplication		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	

▽

△

	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

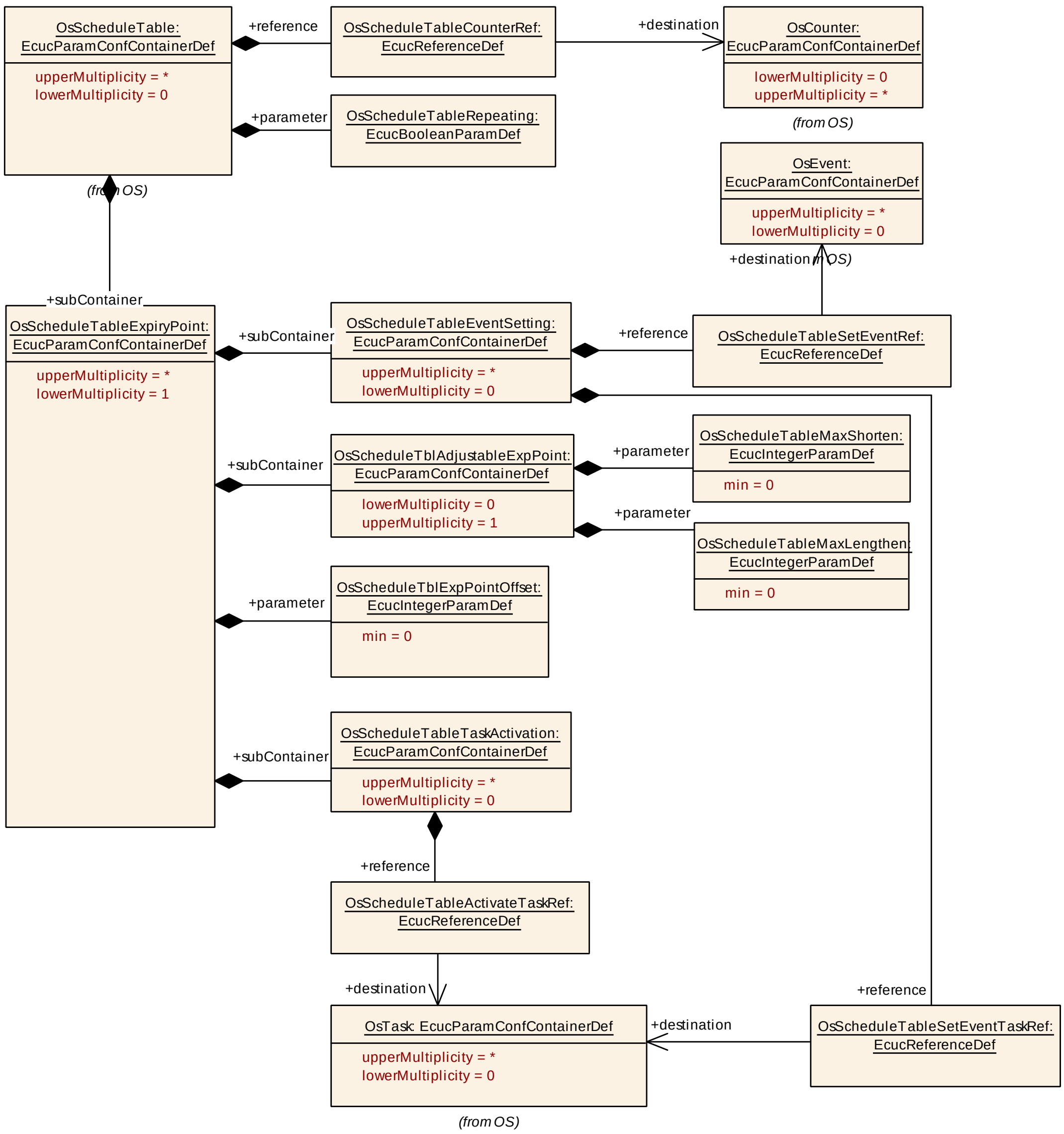

Figure 10.11: OsScheduleTable configuration overview (part 1)

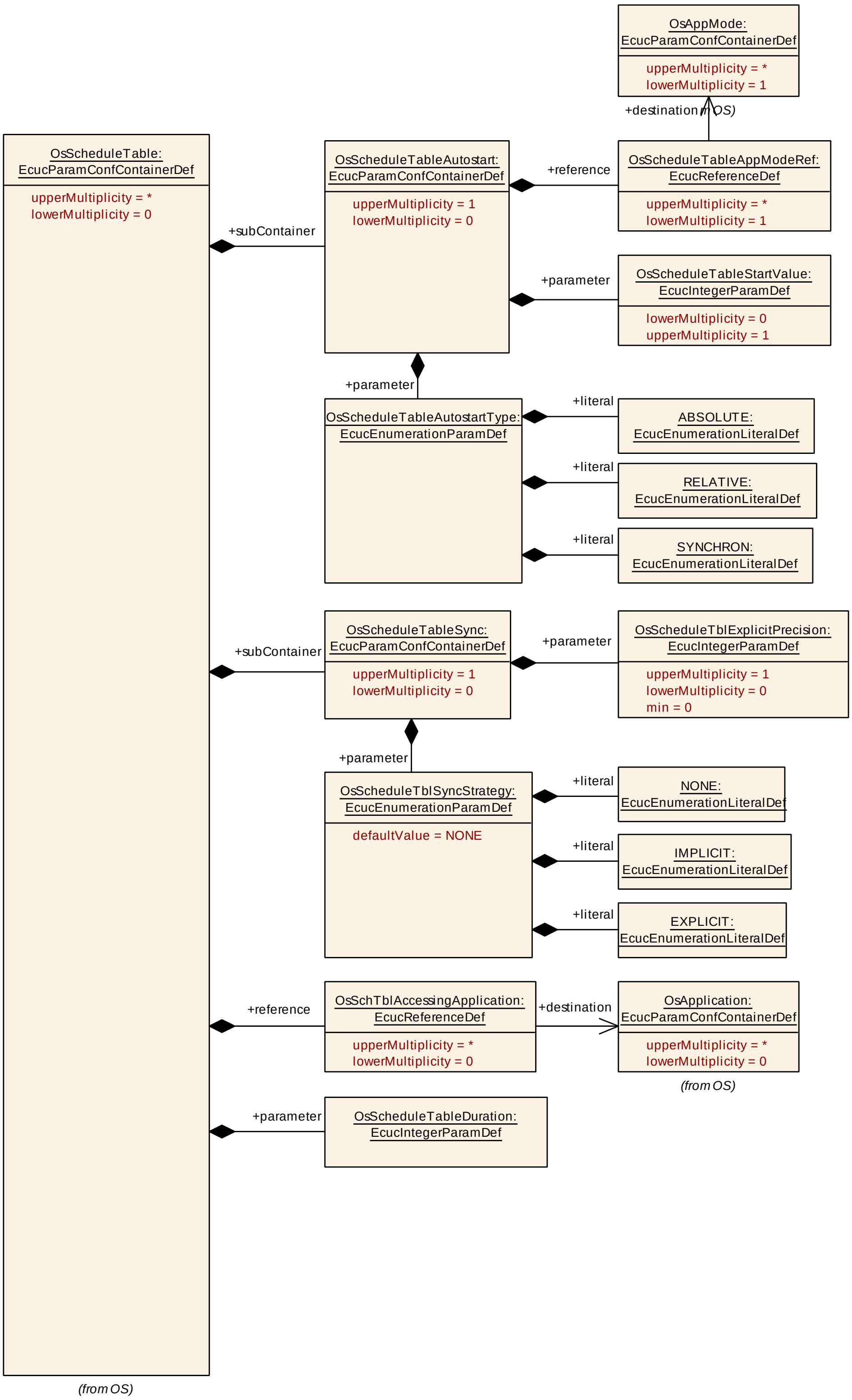

Figure 10.12: OsScheduleTable configuration overview (part 2)

10.2.24 OsScheduleTableAutostart

[ECUC_Os_00335] Definition of EcucParamConfContainerDef OsScheduleTable Autostart ⌈

Container Name	OsScheduleTableAutostart
Parent Container	OsScheduleTable
Description	This container specifies if and how the schedule table is started on startup of the Operating System. The options to start a schedule table correspond to the API calls to start schedule tables during runtime.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsScheduleTableAutostartType	1	[ECUC_Os_00056]
OsScheduleTableStartValue	0..1	[ECUC_Os_00057]
OsScheduleTableAppModeRef	1..*	[ECUC_Os_00058]

No Included Containers

⌋

[ECUC_Os_00056] Definition of EcucEnumerationParamDef OsScheduleTable AutostartType ⌈

Parameter Name	OsScheduleTableAutostartType		
Parent Container	OsScheduleTableAutostart		
Description	This specifies the type of the autostart for the schedule table.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	ABSOLUTE	The schedule table is started during startup with the StartScheduleTableAbs() service.	
	RELATIVE	The schedule table is started during startup with the StartScheduleTableRel() service.	
	SYNCHRON	The schedule table is started during startup with the StartScheduleTableSynchron() service.	
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00057] Definition of EcucIntegerParamDef OsScheduleTableStartValue ⌈

Parameter Name	OsScheduleTableStartValue		
Parent Container	OsScheduleTableAutostart		
Description	Absolute autostart tick value when the schedule table starts. Only used if the OsScheduleTableAutostartType is ABSOLUTE. Relative offset in ticks when the schedule table starts. Only used if the OsScheduleTableAutostartType is RELATIVE.		
Multiplicity	0..1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00058] Definition of EcucReferenceDef OsScheduleTableAppModeRef ⌈

Parameter Name	OsScheduleTableAppModeRef		
Parent Container	OsScheduleTableAutostart		
Description	Reference in which application modes the schedule table should be started during startup		
Multiplicity	1..*		
Type	Reference to OsAppMode		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.2.25 OsScheduleTableEventSetting

[ECUC_Os_00059] Definition of EcucParamConfContainerDef OsScheduleTableEventSetting ⌈

Container Name	OsScheduleTableEventSetting
Parent Container	OsScheduleTableExpiryPoint
Description	Event that is triggered by that schedule table.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsScheduleTableSetEventRef	1	[ECUC_Os_00060]
OsScheduleTableSetEventTaskRef	1	[ECUC_Os_00061]

No Included Containers

⌋

[ECUC_Os_00060] Definition of EcucReferenceDef OsScheduleTableSetEventRef ⌈

Parameter Name	OsScheduleTableSetEventRef		
Parent Container	OsScheduleTableEventSetting		
Description	Reference to event that will be set by action		
Multiplicity	1		
Type	Reference to OsEvent		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00061] Definition of EcucReferenceDef OsScheduleTableSetEventTaskRef ⌈

Parameter Name	OsScheduleTableSetEventTaskRef		
Parent Container	OsScheduleTableEventSetting		
Description	–		
Multiplicity	1		
Type	Reference to OsTask		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants

▽

△

	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.2.26 OsScheduleTableExpiryPoint

[ECUC_Os_00143] Definition of EcucParamConfContainerDef OsScheduleTableExpiryPoint ⌈

Container Name	OsScheduleTableExpiryPoint
Parent Container	OsScheduleTable
Description	The point on a Schedule Table at which the OS activates tasks and/or sets events
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsScheduleTblExpPointOffset	1	[ECUC_Os_00062]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsScheduleTableEventSetting	0..*	Event that is triggered by that schedule table.
OsScheduleTableTaskActivation	0..*	Task that is triggered by that schedule table.
OsScheduleTblAdjustableExpPoint	0..1	Adjustable expiry point

⌋

[ECUC_Os_00062] Definition of EcucIntegerParamDef OsScheduleTblExpPointOffset ⌈

Parameter Name	OsScheduleTblExpPointOffset		
Parent Container	OsScheduleTableExpiryPoint		
Description	The offset from zero (in ticks) at which the expiry point is to be processed.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	

▽

△

Scope / Dependency	

⌋

10.2.27 OsScheduleTableTaskActivation

[ECUC_Os_00066] Definition of EcucParamConfContainerDef OsScheduleTableTaskActivation ⌈

Container Name	OsScheduleTableTaskActivation
Parent Container	OsScheduleTableExpiryPoint
Description	Task that is triggered by that schedule table.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsScheduleTableActivateTaskRef	1	[ECUC_Os_00067]

No Included Containers

⌋

[ECUC_Os_00067] Definition of EcucReferenceDef OsScheduleTableActivateTaskRef ⌈

Parameter Name	OsScheduleTableActivateTaskRef		
Parent Container	OsScheduleTableTaskActivation		
Description	Reference to task that will be activated by action		
Multiplicity	1		
Type	Reference to OsTask		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.2.28 OsScheduleTblAdjustableExpPoint

[ECUC_Os_00068] Definition of EcucParamConfContainerDef OsScheduleTblAdjustableExpPoint ⌈

Container Name	OsScheduleTblAdjustableExpPoint
Parent Container	OsScheduleTableExpiryPoint
Description	Adjustable expiry point
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsScheduleTableMaxLengthen	1	[ECUC_Os_00069]
OsScheduleTableMaxShorten	1	[ECUC_Os_00070]

No Included Containers

⌋

[ECUC_Os_00069] Definition of EcucIntegerParamDef OsScheduleTableMaxLengthen ⌈

Parameter Name	OsScheduleTableMaxLengthen		
Parent Container	OsScheduleTblAdjustableExpPoint		
Description	The maximum positive adjustment that can be made to the expiry point offset (in ticks).		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00070] Definition of EcucIntegerParamDef OsScheduleTableMaxShorten ⌈

Parameter Name	OsScheduleTableMaxShorten
Parent Container	OsScheduleTblAdjustableExpPoint
Description	The maximum negative adjustment that can be made to the expiry point offset (in ticks).
Multiplicity	1
Type	EcucIntegerParamDef

▽

△

Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.2.29 OsScheduleTableSync

[ECUC_Os_00063] Definition of EcucParamConfContainerDef OsScheduleTableSync ⌈

Container Name	OsScheduleTableSync
Parent Container	OsScheduleTable
Description	This container specifies the synchronization parameters of the schedule table.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsScheduleTblExplicitPrecision	0..1	[ECUC_Os_00064]
OsScheduleTblSyncStrategy	1	[ECUC_Os_00065]

No Included Containers

⌋

[ECUC_Os_00064] Definition of EcucIntegerParamDef OsScheduleTblExplicitPrecision ⌈

Parameter Name	OsScheduleTblExplicitPrecision		
Parent Container	OsScheduleTableSync		
Description	This configuration is only valid if the explicit synchronization is used.		
Multiplicity	0..1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	

▽

△

	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00065] Definition of EcucEnumerationParamDef OsScheduleTblSyncStrategy ⌈

Parameter Name	OsScheduleTblSyncStrategy		
Parent Container	OsScheduleTableSync		
Description	AUTOSAR OS provides support for synchronization in two ways: explicit and implicit.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	EXPLICIT	The schedule table is driven by an OS counter but processing needs to be synchronized with a different counter which is not an OS counter object.	
	IMPLICIT	The counter driving the schedule table is the counter with which synchronisation is required.	
	NONE	No support for synchronisation.	
Default value	NONE		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.2.30 OsSpinlock

[ECUC_Os_00258] Definition of EcucParamConfContainerDef OsSpinlock ⌈

Container Name	OsSpinlock
Parent Container	Os
Description	An OsSpinlock object is used to co-ordinate concurrent access by TASKs/ISR2s on different cores to a shared resource.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsSpinlockLockMethod	1	[ECUC_Os_01038]
OsSpinlockAccessingApplication	1..*	[ECUC_Os_01021]
OsSpinlockSuccessor	0..1	[ECUC_Os_01022]

No Included Containers

⌋

[ECUC_Os_01038] Definition of EcucEnumerationParamDef OsSpinlockLockMethod ⌈

Parameter Name	OsSpinlockLockMethod		
Parent Container	OsSpinlock		
Description	Lock method which is used when a spinlock is taken. Note that it is possible that a user (e.g. a Task) might hold more than one spinlock. In this case the last lock taken is forced to use at least a lock methode which locks as strong as the current one.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	LOCK_ALL_INTERRUPTS	–	
	LOCK_CAT2_INTERRUPTS	–	
	LOCK_NOTHING	–	
	LOCK_WITH_RES_SCHEDULER	–	
Default value	LOCK_NOTHING		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_01021] Definition of EcucReferenceDef OsSpinlockAccessingApplication ⌈

Parameter Name	OsSpinlockAccessingApplication		
Parent Container	OsSpinlock		
Description	Reference to OsApplications that have an access to this object.		
Multiplicity	1..*		
Type	Reference to OsApplication		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	

▽

△

Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_01022] Definition of EcucReferenceDef OsSpinlockSuccessor ⌈

Parameter Name	OsSpinlockSuccessor		
Parent Container	OsSpinlock		
Description	Reference to OsApplications that have an access to this object. To check whether a spinlock can be occupied (in a nested way) without any danger of deadlock, a linked list of spinlocks can be defined. A spinlock can only be occupied in the order of the linked list. It is allowed to skip a spinlock. If no linked list is specified, spinlocks cannot be nested.		
Multiplicity	0..1		
Type	Reference to OsSpinlock		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

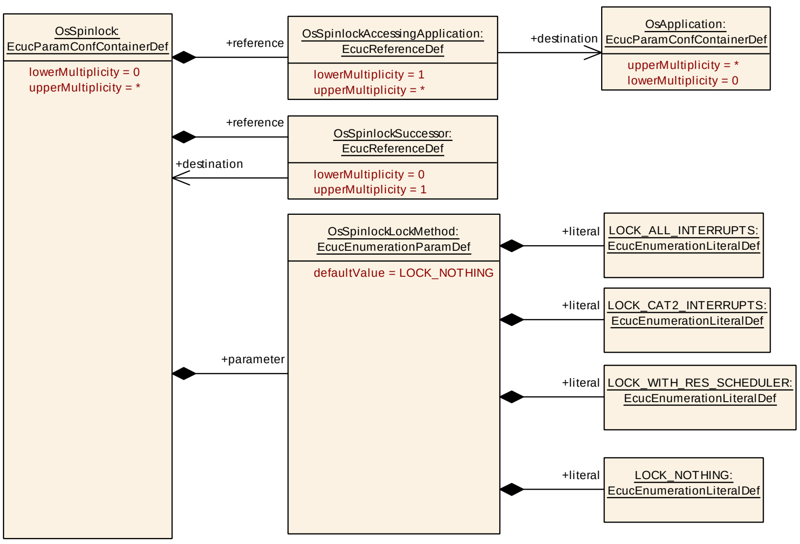

Figure 10.13: OsSpinlock configuration overview

10.2.31 OsTask

[ECUC_Os_00073] Definition of EcucParamConfContainerDef OsTask ⌈

Container Name	OsTask
Parent Container	Os
Description	This container represents an ISO 17356 task.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsTaskActivation	1	[ECUC_Os_00074]
OsTaskPeriod	0..1	[ECUC_Os_00404]
OsTaskPriority	1	[ECUC_Os_00075]
OsTaskSchedule	1	[ECUC_Os_00076]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00402]
OsTaskAccessingApplication	0..*	[ECUC_Os_00077]
OsTaskEventRef	0..*	[ECUC_Os_00078]
OsTaskResourceRef	0..*	[ECUC_Os_00079]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsTaskAutostart	0..1	This container determines whether the task is activated during the system start-up procedure or not for some specific application modes. If the task shall be activated during the system start-up, this container is present and holds the references to the application modes in which the task is auto-started.
OsTaskTimingProtection	0..1	This container contains all parameters regarding timing protection of the task.

⌋

[ECUC_Os_00074] Definition of EcucIntegerParamDef OsTaskActivation ⌈

Parameter Name	OsTaskActivation		
Parent Container	OsTask		
Description	This attribute defines the maximum number of queued activation requests for the task. A value equal to "1" means that at any time only a single activation is permitted for this task. Note that the value must be a natural number starting at 1.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	1 .. 4294967295		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	

▽

△

Scope / Dependency	scope: local		

⌋

[ECUC_Os_00404] Definition of EcucFloatParamDef OsTaskPeriod ⌈

Parameter Name	OsTaskPeriod		
Parent Container	OsTask		
Description	This parameter specifies the period in seconds of this task in case of a cyclically activated task. If this parameter is not given the task can be activated sporadicly or cyclically with a unknown period value. This value is information, e.g. for time base calculations in the RTE in case Timing Events are mapped onto this OsTask.Be aware, that this parameter is not supposed to be relevant for the OS! This information is given as part of the OS configuration to support configuration work flows using a fixed set of OsTasks.		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[-INF .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_00075] Definition of EcucIntegerParamDef OsTaskPriority ⌈

Parameter Name	OsTaskPriority		
Parent Container	OsTask		
Description	The priority of a task is defined by the value of this attribute. This value has to be understood as a relative value, i.e. the values show only the relative ordering of the tasks. ISO 17356-3 defines the lowest priority as zero (0); larger values correspond to higher priorities.		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 4294967295		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	

▽

△

	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00076] Definition of EcucEnumerationParamDef OsTaskSchedule ⌈

Parameter Name	OsTaskSchedule		
Parent Container	OsTask		
Description	The OsTaskSchedule attribute defines the preemptability of the task. If this attribute is set to NON, no internal resources may be assigned to this task.		
Multiplicity	1		
Type	EcucEnumerationParamDef		
Range	FULL	Task is preemptable.	
	NON	Task is not preemptable.	
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

For parameter table [ECUC_Os_00402] OsMemoryMappingCodeLocationRef, see definition below container OsApplication.

[ECUC_Os_00077] Definition of EcucReferenceDef OsTaskAccessingApplication ⌈

Parameter Name	OsTaskAccessingApplication		
Parent Container	OsTask		
Description	Reference to applications which have an access to this object.		
Multiplicity	0..*		
Type	Reference to OsApplication		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00078] Definition of EcucReferenceDef OsTaskEventRef ⌈

Parameter Name	OsTaskEventRef		
Parent Container	OsTask		
Description	This reference defines the list of events the extended task may react on.		
Multiplicity	0..*		
Type	Reference to OsEvent		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00079] Definition of EcucReferenceDef OsTaskResourceRef ⌈

Parameter Name	OsTaskResourceRef		
Parent Container	OsTask		
Description	This reference defines a list of resources accessed by this task.		
Multiplicity	0..*		
Type	Reference to OsResource		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

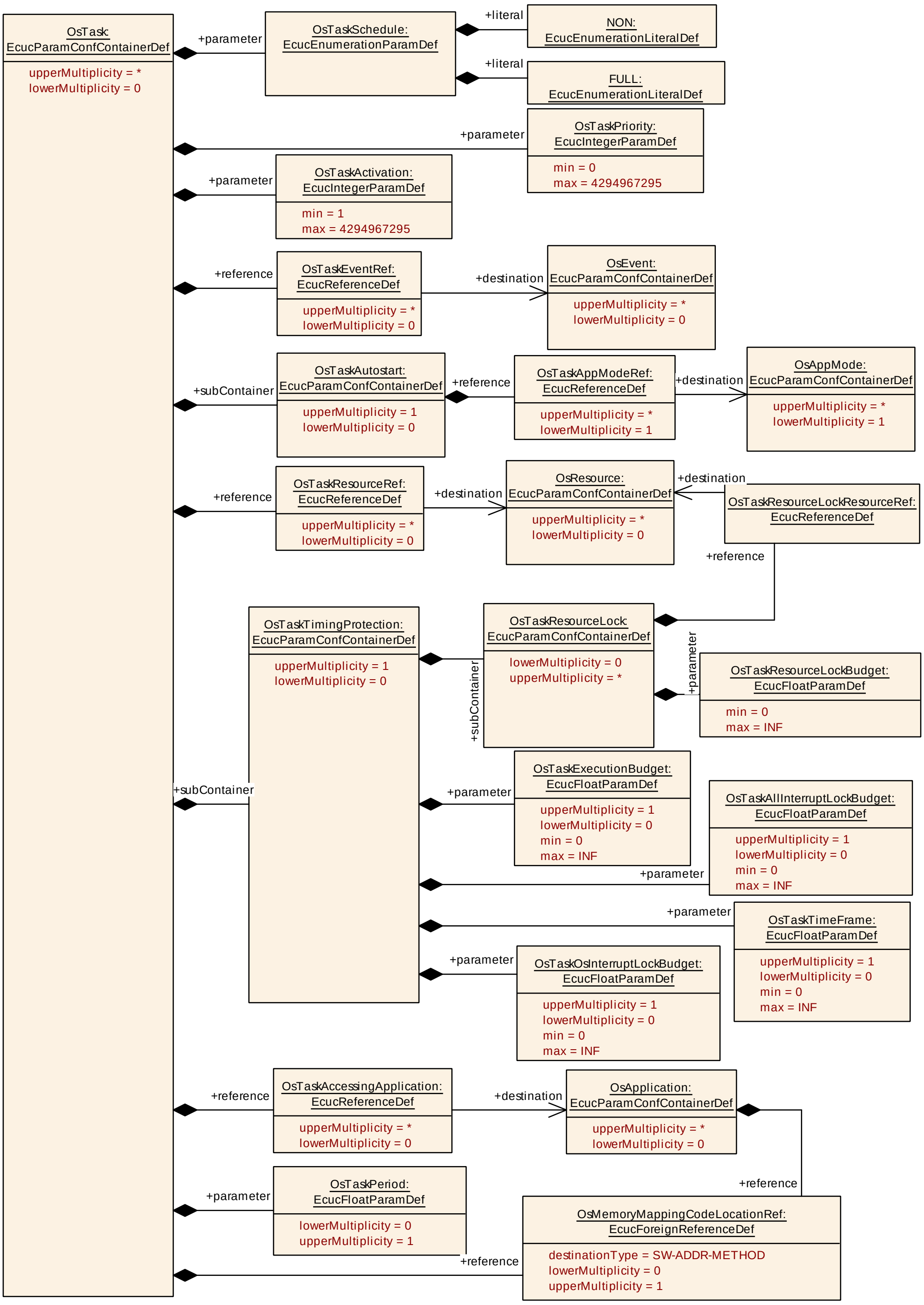

Figure 10.14: OsTask configuration overview

10.2.32 OsTaskAutostart

[ECUC_Os_00080] Definition of EcucParamConfContainerDef OsTaskAutostart ⌈

Container Name	OsTaskAutostart	
Parent Container	OsTask	
Description	This container determines whether the task is activated during the system start-up procedure or not for some specific application modes. If the task shall be activated during the system start-up, this container is present and holds the references to the application modes in which the task is auto-started.	
Configuration Parameters		

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsTaskAppModeRef	1..*	[ECUC_Os_00081]

No Included Containers

⌋

[ECUC_Os_00081] Definition of EcucReferenceDef OsTaskAppModeRef ⌈

Parameter Name	OsTaskAppModeRef		
Parent Container	OsTaskAutostart		
Description	Reference to application modes in which that task is activated on startup of the OS		
Multiplicity	1..*		
Type	Reference to OsAppMode		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency			

⌋

10.2.33 OsTaskResourceLock

[ECUC_Os_00082] Definition of EcucParamConfContainerDef OsTaskResourceLock ⌈

Container Name	OsTaskResourceLock
Parent Container	OsTaskTimingProtection
Description	This container contains the worst case time between getting and releasing a given resource (in seconds).
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsTaskResourceLockBudget	1	[ECUC_Os_00083]
OsTaskResourceLockResourceRef	1	[ECUC_Os_00084]

No Included Containers

⌋

[ECUC_Os_00083] Definition of EcucFloatParamDef OsTaskResourceLockBudget ⌈

Parameter Name	OsTaskResourceLockBudget		
Parent Container	OsTaskResourceLock		
Description	This parameter contains the maximum time the task is allowed to lock the resource (in seconds)		
Multiplicity	1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00084] Definition of EcucReferenceDef OsTaskResourceLockResourceRef ⌈

Parameter Name	OsTaskResourceLockResourceRef		
Parent Container	OsTaskResourceLock		
Description	Reference to the resource used by the task		
Multiplicity	1		
Type	Reference to OsResource		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

10.2.34 OsTaskTimingProtection

[ECUC_Os_00325] Definition of EcucParamConfContainerDef OsTaskTimingProtection ⌈

Container Name	OsTaskTimingProtection
Parent Container	OsTask
Description	This container contains all parameters regarding timing protection of the task.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsTaskAllInterruptLockBudget	0..1	[ECUC_Os_00085]
OsTaskExecutionBudget	0..1	[ECUC_Os_00185]
OsTaskOsInterruptLockBudget	0..1	[ECUC_Os_00086]
OsTaskTimeFrame	0..1	[ECUC_Os_00391]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsTaskResourceLock	0..*	This container contains the worst case time between getting and releasing a given resource (in seconds).

⌋

[ECUC_Os_00085] Definition of EcucFloatParamDef OsTaskAllInterruptLockBudget ⌈

Parameter Name	OsTaskAllInterruptLockBudget		
Parent Container	OsTaskTimingProtection		
Description	This parameter contains the maximum time for which the task is allowed to lock all interrupts (via SuspendAllInterrupts() or DisableAllInterrupts()) (in seconds).		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00185] Definition of EcucFloatParamDef OsTaskExecutionBudget ⌈

Parameter Name	OsTaskExecutionBudget		
Parent Container	OsTaskTimingProtection		
Description	This parameter contains the maximum allowed execution time of the task (in seconds).		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00086] Definition of EcucFloatParamDef OsTaskOsInterruptLockBudget ⌈

Parameter Name	OsTaskOsInterruptLockBudget		
Parent Container	OsTaskTimingProtection		
Description	This parameter contains the maximum time for which the task is allowed to lock all Category 2 interrupts (via SuspendOSInterrupts()) (in seconds).		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Required for scalability class 2 and 4		

⌋

[ECUC_Os_00391] Definition of EcucFloatParamDef OsTaskTimeFrame ⌈

Parameter Name	OsTaskTimeFrame		
Parent Container	OsTaskTimingProtection		
Description	The minimum inter-arrival time between activations and/or releases of a task (in seconds).		
Multiplicity	0..1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU dependency: Only available in scalability class 2 and 4		

⌋

10.2.35 OsTimeConstant

[ECUC_Os_00386] Definition of EcucParamConfContainerDef OsTimeConstant ⌈

Container Name	OsTimeConstant
Parent Container	OsCounter
Description	Allows the user to define constants which can be e.g. used to compare time values with timer tick values. A time value will be converted to a timer tick value during generation and can later on accessed via the OsConstName. The conversation is done by rounding time values to the nearest fitting tick value.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsTimeValue	1	[ECUC_Os_00002]

No Included Containers

⌋

[ECUC_Os_00002] Definition of EcucFloatParamDef OsTimeValue ⌈

Parameter Name	OsTimeValue		
Parent Container	OsTimeConstant		
Description	This parameter contains the value of the constant in seconds.		
Multiplicity	1		
Type	EcucFloatParamDef		
Range	[0 .. INF]		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.3 Containers and configuration parameter extensions of the IOC

This section describes the content of the IOC Configuration Description that is needed for the generation of the IOC API.

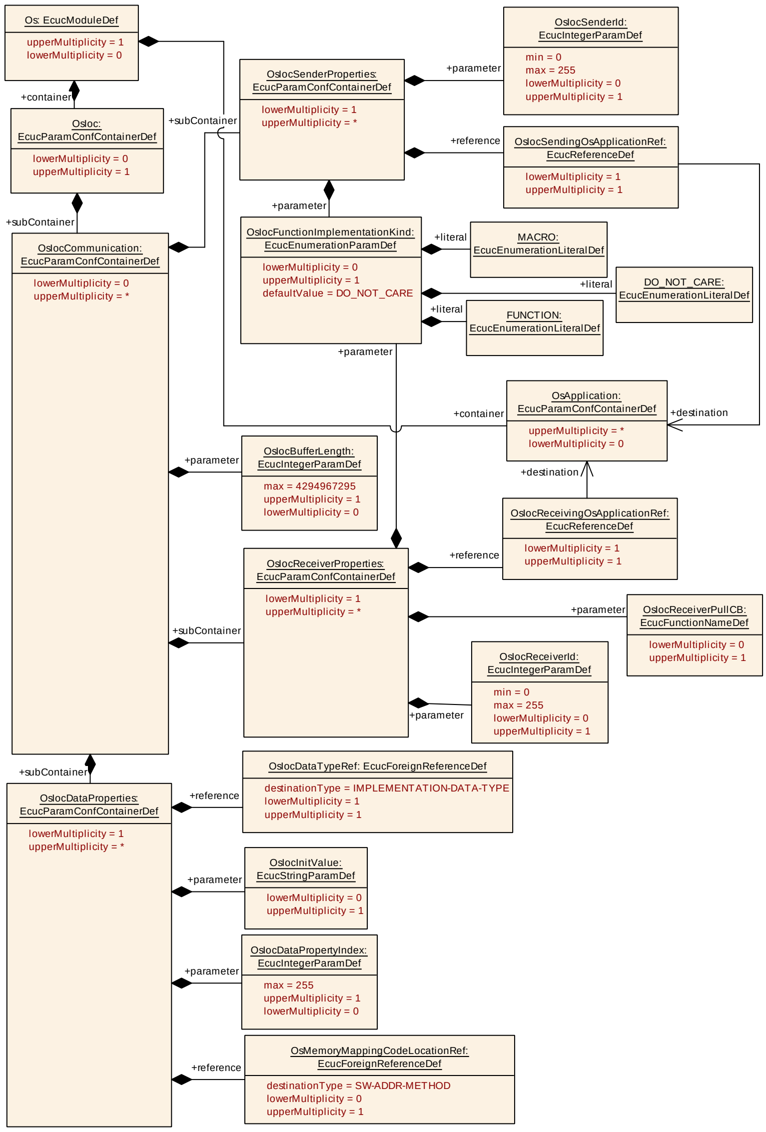

Figure 10.15: OsIoc configuration overview

10.3.1 OsIoc

[ECUC_Os_01000] Definition of EcucParamConfContainerDef OsIoc ⌈

Container Name	OsIoc
Parent Container	Os
Description	Configuration of the IOC (Inter OS Application Communicator).
Configuration Parameters	

No Included Parameters

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsIocCommunication	0..*	Representation of a 1:1 or N:1 or N:M (unqueued only) communication between software parts located in different OS-Applications that are bound to the same or to different cores. The name shall begin with the name of the sending software service and be followed by a unique identifier delivered by the sending software service. In the case of RTE as user attention shall be paid on the fact that uniqueness for identifier names has to be reached over ports, data elements, object instances and maybe additional identification properties (E.g. Case 1:N mapping to 1:1). Example: • <NameSpace>_UniqueID

⌋

10.3.2 OsIocCommunication

[ECUC_Os_01003] Definition of EcucParamConfContainerDef OsIocCommunication ⌈

Container Name	OsIocCommunication
Parent Container	OsIoc
Description	Representation of a 1:1 or N:1 or N:M (unqueued only) communication between software parts located in different OS-Applications that are bound to the same or to different cores. The name shall begin with the name of the sending software service and be followed by a unique identifier delivered by the sending software service. In the case of RTE as user attention shall be paid on the fact that uniqueness for identifier names has to be reached over ports, data elements, object instances and maybe additional identification properties (E.g. Case 1:N mapping to 1:1). Example: • <NameSpace>_UniqueID
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsIocBufferLength	0..1	[ECUC_Os_01001]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
OsIocDataProperties	1..*	Data properties of the data to be transferred on the IOC communication channel.
OsIocReceiverProperties	1..*	Representation of receiver properties for one communication. For each OsIocCommunication one (1:1) or many receivers (N:M) have to be defined. This container should be instantiated within an OsIocCommunication.
OsIocSenderProperties	1..*	Representation of sender properties for one communication. For each OsIocCommunication one (1:1) or many senders (N:1 or N:M) have to be defined. Multiplicity > 1 (N:1 or N:M communication) is only allowed for Multiplicity of OsIocDataType Ref = 1. This container should be instantiated within an OsIoc Communication.

⌋

[ECUC_Os_01001] Definition of EcucIntegerParamDef OsIocBufferLength ⌈

Parameter Name	OsIocBufferLength		
Parent Container	OsIocCommunication		
Description	This attribute defines the size of the IOC internal queue to be allocated for a queued communication. This configuration information shall allow the optimization of the needed memory for communications requiring buffers within the RTE and within the IOC.		
Multiplicity	0..1		
Type	EcucIntegerParamDef		
Range	0 .. 4294967295		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.3.3 OsIocSenderProperties

[ECUC_Os_01015] Definition of EcucParamConfContainerDef OsIocSenderProperties ⌈

Container Name	OsIocSenderProperties
Parent Container	OsIocCommunication
Description	Representation of sender properties for one communication. For each OsIoc Communication one (1:1) or many senders (N:1 or N:M) have to be defined. Multiplicity > 1 (N:1 or N:M communication) is only allowed for Multiplicity of OsIocDataTypeRef = 1. This container should be instantiated within an OsIocCommunication.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsIocFunctionImplementationKind	0..1	[ECUC_Os_01036]
OsIocSenderId	0..1	[ECUC_Os_01016]
OsIocSendingOsApplicationRef	1	[ECUC_Os_01014]

No Included Containers

⌋

For parameter table [ECUC_Os_01036] OsIocFunctionImplementationKind, see definition below container OsIocReceiverProperties.

[ECUC_Os_01016] Definition of EcucIntegerParamDef OsIocSenderId ⌈

Parameter Name	OsIocSenderId		
Parent Container	OsIocSenderProperties		
Description	Representation of a sender in a N:1 or N:M communication to distinguish between senders. This parameter does not exist in 1:1 communication.		
Multiplicity	0..1		
Type	EcucIntegerParamDef		
Range	0 .. 255		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_01014] Definition of EcucReferenceDef OsIocSendingOsApplicationRef ⌈

Parameter Name	OsIocSendingOsApplicationRef		
Parent Container	OsIocSenderProperties		
Description	This attribute is a reference to the sending OS-Application instance defined in the configuration file of the OS. This information shall allows the generator to get additional information necessary for the code generation like: • The protection properties of the communicating OS-Applications to find out which protection boundaries have to be crossed. • The core identifiers to find out if an intra or an inter core communication has to be realized • Interrupt details in case of cross core notification to realize over IRQs		
Multiplicity	1		
Type	Reference to OsApplication		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	

▽

△

	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.3.4 OsIocReceiverProperties

[ECUC_Os_01017] Definition of EcucParamConfContainerDef OsIocReceiverProperties ⌈

Container Name	OsIocReceiverProperties
Parent Container	OsIocCommunication
Description	Representation of receiver properties for one communication. For each OsIocCommunication one (1:1) or many receivers (N:M) have to be defined. This container should be instantiated within an OsIocCommunication.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsIocFunctionImplementationKind	0..1	[ECUC_Os_01036]
OsIocReceiverId	0..1	[ECUC_Os_00407]
OsIocReceiverPullCB	0..1	[ECUC_Os_01010]
OsIocReceivingOsApplicationRef	1	[ECUC_Os_01012]

No Included Containers

⌋

[ECUC_Os_01036] Definition of EcucEnumerationParamDef OsIocFunctionImplementationKind ⌈

Parameter Name	OsIocFunctionImplementationKind	
Parent Container	OsIocReceiverProperties, OsIocSenderProperties	
Description	This parameter is used to select whether this communication is implemented as a macro or as a function.	
Multiplicity	0..1	
Type	EcucEnumerationParamDef	
Range	DO_NOT_CARE	It is not defined whether a macro or a function is used.
	FUNCTION	Communication is implemented as a function
	MACRO	Communication is implemented as a macro
Default value	DO_NOT_CARE	
Post-Build Variant Multiplicity	false	

▽

△

Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00407] Definition of EcucIntegerParamDef OsIocReceiverId ⌈

Parameter Name	OsIocReceiverId		
Parent Container	OsIocReceiverProperties		
Description	Representation of a receiver in a N:M communication to distinguish between receivers. This parameter does not exist in 1:1 or N:1 communication.		
Multiplicity	0..1		
Type	EcucIntegerParamDef		
Range	0 .. 255		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Os_01010] Definition of EcucFunctionNameDef OsIocReceiverPullCB ⌈

Parameter Name	OsIocReceiverPullCB
Parent Container	OsIocReceiverProperties
Description	This attribute defines the name of a callback function that the IOC shall call on the receiving core for each data reception. In case of non existence of this attribute no ReceiverPullCB notification shall be applied by the IOC. The name of the function shall begin with the name of the receiving module, followed with a callback name and followed by the IocId. Example: void RTE_ReceiverPullCB_RTE25 (void). If this attribute does not exist, it means that no ReceiverPullCB shall be called (No notification from IOC is required). If this attribute exists the IOC shall call the callback function on the receiving core.
Multiplicity	0..1

▽

△

Type	EcucFunctionNameDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_01012] Definition of EcucReferenceDef OsIocReceivingOsApplicationRef ⌈

Parameter Name	OsIocReceivingOsApplicationRef		
Parent Container	OsIocReceiverProperties		
Description	This attribute is a reference to the receiving OsApplication instance defined in the configuration file of the OS. This information allows for the generator to get additional information necessary for the code generation like: • The protection properties of the communicating OsApplications to find out which protections have to be crossed • The core identifiers to find out if an intra or an inter core communication has to be realized • Interrupt details in case of cross core notification to realize over IRQs		
Multiplicity	1		
Type	Reference to OsApplication		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.3.5 OsIocDataProperties

[ECUC_Os_01023] Definition of EcucParamConfContainerDef OsIocDataProperties ⌈

Container Name	OsIocDataProperties
Parent Container	OsIocCommunication
Description	Data properties of the data to be transferred on the IOC communication channel.
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
OsIocDataPropertyIndex	0..1	[ECUC_Os_01035]
OsIocInitValue	0..1	[ECUC_Os_01024]
OsIocDataTypeRef	1	[ECUC_Os_01005]
OsMemoryMappingCodeLocationRef	0..1	[ECUC_Os_00405]

No Included Containers

⌋

[ECUC_Os_01035] Definition of EcucIntegerParamDef OsIocDataPropertyIndex ⌈

Parameter Name	OsIocDataPropertyIndex		
Parent Container	OsIocDataProperties		
Description	This parameter is used to define in which order the data is send, e.g. whether IocSend Group(A,B) or IocSendGroup(B,A) shall be used.		
Multiplicity	0..1		
Type	EcucIntegerParamDef		
Range	0 .. 255		
Default value	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_01024] Definition of EcucStringParamDef OsIocInitValue ⌈

Parameter Name	OsIocInitValue
Parent Container	OsIocDataProperties
Description	Initial Value for the data to be transferred on the IOC communication channel.
Multiplicity	0..1
Type	EcucStringParamDef

▽

△

Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_01005] Definition of EcucForeignReferenceDef OsIocDataTypeRef ⌈

Parameter Name	OsIocDataTypeRef		
Parent Container	OsIocDataProperties		
Description	This is the type of the data to be transferred on the IOC communication channel. This attribute is necessary to generate the parameter type of the Ioc functions. Additionally this information should be used to compute the data size for necessary data copy operations within the Ioc module. If more than one attribute is defined, the IOC generator should generate an IocXxx Group function (Xxx= CHOICE [Send, Receive, Write, Read]). N:1 or N:M communication (Multiplicity of OsIocSenderProperties > 1) is only allowed for multiplicity of OsIocDataTypeRef = 1		
Multiplicity	1		
Type	Foreign reference to IMPLEMENTATION-DATA-TYPE		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Os_00405] Definition of EcucForeignReferenceDef OsMemoryMappingCodeLocationRef ⌈

Parameter Name	OsMemoryMappingCodeLocationRef
Parent Container	OsIocDataProperties
Description	Reference to the memory mapping containing details about the section where the IOC buffer is placed.
Multiplicity	0..1
Type	Foreign reference to SW-ADDR-METHOD
Post-Build Variant Multiplicity	false
Post-Build Variant Value	false

▽

△

Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4 Containers and configuration parameters for ARTI

This section describes the structure (containers) and the parameters of ARTI objects related to the OS configuration. ARTI objects are defined by the MOD_ARTI model.

For a detailed description of the referenced ARTI parameters, please see chapter 10 of [8]. Also refer to application note 12.7 of this document.

[SWS_Os_00859]

Upstream requirements: RS_Arti_00001, RS_Arti_00002, RS_Arti_00003, RS_Arti_00005, RS_Arti_00007, RS_Arti_00011, RS_Arti_00012, RS_Arti_00014, RS_Arti_00016, RS_Arti_00018, RS_Arti_00022, RS_Arti_00023, RS_Arti_00004, RS_Arti_00009

⌈The configuration items `ArtiHardware` and `ArtiOs` and their related subcontainers contain the parameters to configure ARTI objects.⌋

10.4.1 ArtiHardware

[ECUC_Arti_00061] Definition of EcucParamConfContainerDef ArtiHardware ⌈

Container Name	ArtiHardware		
Parent Container	Arti		
Description	The ArtiHardware container contains ARTI extensions to the EcucHardware module.		
Post-Build Variant Multiplicity	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Configuration Parameters			

No Included Parameters

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
ArtiHardwareCoreClass	0..1	Contains the layout of an ARTI "Core" object, extending the Ecuc CoreDefinition.
ArtiHardwareCoreInstance	0..*	Description: Represents an instance of an ARTI "Core" object, extending the EcucCoreDefinition. When using ARTI for debugging or hardware based tracing, this is mandatory (i.e. multiplicity 1..*), else optional.

⌋

```
<ECUC-MODULE-CONFIGURATION-VALUES>
<SHORT-NAME>Vendor1ArtiHardware</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-MODULE-DEF">
/AUTOSAR/Arti/ArtiHardware</DEFINITION-REF>
<CONTAINERS>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiCoreClass</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiHardware/ArtiHardwareCoreClass</DEFINITION-REF>
<...>
</ECUC-CONTAINER-VALUE>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiCore0</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiHardware/ArtiHardwareCoreInstance</DEFINITION-REF>
<...>
</ECUC-CONTAINER-VALUE>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiCore1</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiHardware/ArtiHardwareCoreInstance</DEFINITION-REF>
<...>
</ECUC-CONTAINER-VALUE>
</CONTAINERS>
</ECUC-MODULE-CONFIGURATION-VALUES>
```

10.4.2 ArtiHardwareCoreClass

[ECUC_Arti_00062] Definition of EcucParamConfContainerDef ArtiHardwareCoreClass ⌈

Container Name	ArtiHardwareCoreClass		
Parent Container	ArtiHardware		
Description	Contains the layout of an ARTI "Core" object, extending the EcucCoreDefinition.		
Post-Build Variant Multiplicity	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	

▽

△

	Post-build time	X	VARIANT-POST-BUILD
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiHardwareCoreClassCurrentApplicationRef	0..1	[ECUC_Arti_00054]
ArtiHardwareCoreClassCurrentIsrRef	0..1	[ECUC_Arti_00056]
ArtiHardwareCoreClassCurrentTaskRef	1	[ECUC_Arti_00058]
ArtiHardwareCoreClassGenericComponentRef	0..1	[ECUC_Arti_00064]
ArtiHardwareCoreClassLastErrorRef	0..1	[ECUC_Arti_00066]
ArtiHardwareClassRunningTaskPriorityRef	0..1	[ECUC_Arti_00094]

No Included Containers

⌋

[ECUC_Arti_00054] Definition of EcucReferenceDef ArtiHardwareCoreClassCurrentApplicationRef ⌈

Parameter Name	ArtiHardwareCoreClassCurrentApplicationRef		
Parent Container	ArtiHardwareCoreClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiCurrentApplicationInstance parameter.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00056] Definition of EcucReferenceDef ArtiHardwareCoreClassCurrentIsrRef ⌈

Parameter Name	ArtiHardwareCoreClassCurrentIsrRef
Parent Container	ArtiHardwareCoreClass
Description	Refers to the ArtiObjectClassParameter that defines the ArtiCurrentIsrInstance parameter.
Multiplicity	0..1

▽

△

Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Value	true		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00058] Definition of EcucReferenceDef ArtiHardwareCoreClassCurrentTaskRef ⌈

Parameter Name	ArtiHardwareCoreClassCurrentTaskRef		
Parent Container	ArtiHardwareCoreClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiCurrentTaskInstance parameter.		
Multiplicity	1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Value	true		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00064] Definition of EcucReferenceDef ArtiHardwareCoreClassGenericComponentRef ⌈

Parameter Name	ArtiHardwareCoreClassGenericComponentRef		
Parent Container	ArtiHardwareCoreClass		
Description	Refers to an ArtiGenericComponentClass that extends the core description.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00066] Definition of EcucReferenceDef ArtiHardwareCoreClassLastErrorRef ⌈

Parameter Name	ArtiHardwareCoreClassLastErrorRef		
Parent Container	ArtiHardwareCoreClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiLastErrorInstance parameter.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00094] Definition of EcucReferenceDef ArtiHardwareCoreClassRunningTaskPriorityRef ⌈

Parameter Name	ArtiHardwareCoreClassRunningTaskPriorityRef		
Parent Container	ArtiHardwareCoreClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiHwCoreInstanceRunningTaskPriority parameter. This attribute specifies how to evaluate the current priority of the task referred by RUNNINGTASK. The current priority can be different from the static task priority as a result of priority ceiling protocol. This attribute differs from ArtiCurrentTask->ArtiOsTaskClassPriority as here is a single variable while in multiple tasks there is a single variable per task.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

```
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiCoreClass</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">/AUTOSAR/Arti/
ArtiHardware/ArtiHardwareCoreClass</DEFINITION-REF>
<REFERENCE-VALUES>
<ECUC-REFERENCE-VALUE>
```

```
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiHardware/ArtiHardwareCoreClass/
ArtiHardwareCoreClassCurrentApplicationRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiObjectClassParameter_ArtiHwCore_CurrentApplication
</VALUE-REF>
</ECUC-REFERENCE-VALUE>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiHardware/ArtiHardwareCoreClass/
ArtiHardwareCoreClassCurrentTaskRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiObjectClassParameter_ArtiHwCore_CurrentTask</VALUE-REF>
</ECUC-REFERENCE-VALUE>
</REFERENCE-VALUES>
</ECUC-CONTAINER-VALUE>
```

10.4.3 ArtiHardwareCoreInstance

[ECUC_Arti_00063] Definition of EcucParamConfContainerDef ArtiHardwareCoreInstance ⌈

Container Name	ArtiHardwareCoreInstance		
Parent Container	ArtiHardware		
Description	Description: Represents an instance of an ARTI "Core" object, extending the EcucCore Definition. When using ARTI for debugging or hardware based tracing, this is mandatory (i.e. multiplicity 1..*), else optional.		
Post-Build Variant Multiplicity	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiHardwareCoreInstanceCoreId	1	[ECUC_Arti_00091]
ArtiHardwareCoreInstanceCurrentApplicationRef	1	[ECUC_Arti_00055]
ArtiHardwareCoreInstanceCurrentIsrRef	0..1	[ECUC_Arti_00057]
ArtiHardwareCoreInstanceCurrentTaskRef	1	[ECUC_Arti_00059]
ArtiHardwareCoreInstanceEcucCoreRef	1	[ECUC_Arti_00060]
ArtiHardwareCoreInstanceGenericComponentRef	0..1	[ECUC_Arti_00065]
ArtiHardwareCoreInstanceLastErrorRef	0..1	[ECUC_Arti_00067]
ArtiHardwareCoreInstanceRunningTaskPriorityRef	0..1	[ECUC_Arti_00095]
ArtiHardwareCoreInstanceValidRef	0..1	[ECUC_Arti_00096]

No Included Containers

⌋

[ECUC_Arti_00091] Definition of EcucIntegerParamDef ArtiHardwareCoreInstanceCoreId ⌈

Parameter Name	ArtiHardwareCoreInstanceCoreId		
Parent Container	ArtiHardwareCoreInstance		
Description	This parameter represents the "CoreID" as given by the OS, returned by GetCoreID().		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	true		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00055] Definition of EcucReferenceDef ArtiHardwareCoreInstance CurrentApplicationRef ⌈

Parameter Name	ArtiHardwareCoreInstanceCurrentApplicationRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current application" that is running on this core.		
Multiplicity	1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Value	true		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00057] Definition of EcucReferenceDef ArtiHardwareCoreInstance CurrentIsrRef ⌈

Parameter Name	ArtiHardwareCoreInstanceCurrentIsrRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current ISR" that is running on this core.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE

▽

△

	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00059] Definition of EcucReferenceDef ArtiHardwareCoreInstanceCurrentTaskRef ⌈

Parameter Name	ArtiHardwareCoreInstanceCurrentTaskRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current task" that is running on this core.		
Multiplicity	1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Value	true		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00060] Definition of EcucReferenceDef ArtiHardwareCoreInstanceEcucCoreRef ⌈

Parameter Name	ArtiHardwareCoreInstanceEcucCoreRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to the EcucCoreDefinition of this core.		
Multiplicity	1		
Type	Reference to EcucCoreDefinition		
Post-Build Variant Value	true		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00065] Definition of EcucReferenceDef ArtiHardwareCoreInstanceGenericComponentRef ⌈

Parameter Name	ArtiHardwareCoreInstanceGenericComponentRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to an ArtiGenericComponentInstance that extends a core.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00067] Definition of EcucReferenceDef ArtiHardwareCoreInstanceLastErrorRef ⌈

Parameter Name	ArtiHardwareCoreInstanceLastErrorRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "last error" that happened on this core.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00095] Definition of EcucReferenceDef ArtiHardwareCoreInstanceRunningTaskPriorityRef ⌈

Parameter Name	ArtiHardwareCoreInstanceRunningTaskPriorityRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "running task priority" that is on this core.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	true		
Post-Build Variant Value	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	–	
	Post-build time	X	VARIANT-POST-BUILD
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00096] Definition of EcucReferenceDef ArtiHardwareCoreInstanceValidRef ⌈

Parameter Name	ArtiHardwareCoreInstanceValidRef		
Parent Container	ArtiHardwareCoreInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this ArtiHwCoreInstance. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

```
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiCore0</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">/AUTOSAR/Arti/
ArtiHardware/ArtiHardwareCoreInstance</DEFINITION-REF>
<REFERENCE-VALUES>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
```

```
ArtiHardware/ArtiHardwareCoreInstance/
ArtiHardwareCoreInstanceCurrentApplicationRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiObjectInstanceParameter_CurrentApplicationOnCore0
</VALUE-REF>
</ECUC-REFERENCE-VALUE>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiHardware/ArtiHardwareCoreInstance/
ArtiHardwareInstanceCurrentTaskRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiObjectInstanceParameter_CurrentTaskOnCore0</VALUE-REF>
</ECUC-REFERENCE-VALUE>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiHardware/ArtiHardwareCoreInstance/
ArtiHardwareCoreInstanceEcucCoreRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">
/Vendor1/Vendor1EcucEcuC/Hardware/Core0</VALUE-REF>
</ECUC-REFERENCE-VALUE>
</REFERENCE-VALUES>
</ECUC-CONTAINER-VALUE>
```

10.4.4 ArtiOs

[ECUC_Arti_00071] Definition of EcucParamConfContainerDef ArtiOs ⌈

Container Name	ArtiOs		
Parent Container	Arti		
Description	The ArtiOs container contains ARTI extensions to the EcucDefs/Os module.		
Post-Build Variant Multiplicity	true		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsGenericComponentRef	0..*	[ECUC_Arti_00178]

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
ArtiOsAlarmClass	0..1	Contains the layout of an ArtiOsAlarm object.
ArtiOsAlarmInstance	0..*	Represents an instance of an ArtiOsAlarm object, extending the EcuC OsTaskAlarm.
ArtiOsClass	0..1	Contains the layout of an ARTI "Os" object, extending the EcuC OsOS.
ArtiOsContextClass	0..1	Contains the layout of an ARTI "OsContext" object.

⌋

△

Included Containers		
Container Name	**Multiplicity**	**Scope / Dependency**
ArtiOsContextInstance	0..*	Represents an instance of an "ArtiContext" object.
ArtiOsInstance	0..1	Represents an instance of an ARTI "Os" object, extending the EcuC OsOS.
ArtiOsIsrClass	0..1	Contains the layout of an ARTI "OsIsr" object, extending the Ecu C OsIsr.
ArtiOsIsrInstance	0..*	Represents an instance of an ARTI "OsIsr" object, extending the EcuC OsIsr.
ArtiOsMessageContainerClass	0..1	Contains the layout of an ARTI "OsMessageContainer" object. The "OsMessageContainer" object represents an existing combination of OSEK messages.
ArtiOsMessageContainerInstance	0..*	Represents an instance of an "ArtiMessageContainer" object.
ArtiOsResourceClass	0..1	Contains the layout of an ArtiOsResource object. The ArtiOs Resource object represents an OSEK resource.
ArtiOsResourceInstance	0..*	Represents an instance of an ArtiOsResource object.
ArtiOsScheduleTableClass	0..1	Contains the layout of an ArtiOsScheduleTable object.
ArtiOsScheduleTableInstance	0..*	Represents an instance of an ArtiOsScheduleTable object, extending the EcuC OsScheduleTable.
ArtiOsSpinlockClass	0..1	Contains the layout of an ArtiOsSpinlock object.
ArtiOsSpinlockInstance	0..*	Represents an instance of an ArtiOsSpinlock object, extending the EcuC OsSpinlock.
ArtiOsStackClass	0..1	Contains the layout of an ArtiOsStack object. The ArtiOsStack object defines the memory area of any stack in the system.
ArtiOsStackInstance	0..*	Represents an instance of an ArtiOsStack object.
ArtiOsTaskClass	0..1	Contains the layout of an ARTI "OsTask" object, extending the EcuC OsTask.
ArtiOsTaskInstance	0..*	Represents an instance of an ARTI "OsTask" object, extending the EcuC OsTask.

⌋

[ECUC_Arti_00178] Definition of EcucReferenceDef ArtiOsGenericComponentRef ⌈

Parameter Name	ArtiOsGenericComponentRef		
Parent Container	ArtiOs		
Description	Refers to an ArtiGenericComponentClass that relates to the OS.		
Multiplicity	0..*		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	

▽

△

Scope / Dependency	scope: ECU

⌋

```
<ECUC-MODULE-CONFIGURATION-VALUES>
<SHORT-NAME>Vendor1ArtiOs</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-MODULE-DEF">
/AUTOSAR/Arti/ArtiOs</DEFINITION-REF>
<CONTAINERS>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsClass_Conf</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiOs/ArtiOsClass</DEFINITION-REF>
<...>
</ECUC-CONTAINER-VALUE>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsInstance_Conf</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiOs/ArtiOsInstance</DEFINITION-REF>
<...>
</ECUC-CONTAINER-VALUE>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsTaskClass_Conf</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiOs/ArtiOsTaskClass</DEFINITION-REF>
</ECUC-CONTAINER-VALUE>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsTaskInstance_TaskHighPriority</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiOs/ArtiOsTaskInstance</DEFINITION-REF>
<...>
</ECUC-CONTAINER-VALUE>
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsTaskInstance_TaskLowPriority</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">
/AUTOSAR/Arti/ArtiOs/ArtiOsTaskInstance</DEFINITION-REF>
<...>
</ECUC-CONTAINER-VALUE>
</CONTAINERS>
</ECUC-MODULE-CONFIGURATION-VALUES>
```

10.4.5 ArtiOsAlarmClass

[ECUC_Arti_00108] Definition of EcucParamConfContainerDef ArtiOsAlarmClass ⌈

Container Name	ArtiOsAlarmClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ArtiOsAlarm object.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	Multiplicity	ECUC ID
ArtiOsAlarmClassGenericComponentClassRef	0..1	[ECUC_Arti_00110]
ArtiOsAlarmClassStateRef	0..1	[ECUC_Arti_00111]

No Included Containers

⌋

[ECUC_Arti_00110] Definition of EcucReferenceDef ArtiOsAlarmClassGenericComponentClassRef ⌈

Parameter Name	ArtiOsAlarmClassGenericComponentClassRef		
Parent Container	ArtiOsAlarmClass		
Description	Refers to an ArtiGenericComponentClass that extends the ArtiOsAlarmClass.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00111] Definition of EcucReferenceDef ArtiOsAlarmClassStateRef ⌈

Parameter Name	ArtiOsAlarmClassStateRef
Parent Container	ArtiOsAlarmClass
Description	Refers to the ArtiObjectClassParameter that declares the attribute ArtiOsAlarmStateRef in ArtiOsAlarmInstances. This attribute specifies if an alarm is "RUNNING" or "STOPPED". The refered ArtiObjectClassParameter does include the mapping from integer to human readable "RUNNING" or "STOPPED".
Multiplicity	0..1

▽

△

Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.6 ArtiOsAlarmInstance

[ECUC_Arti_00109] Definition of EcucParamConfContainerDef ArtiOsAlarmInstance ⌈

Container Name	ArtiOsAlarmInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an ArtiOsAlarm object, extending the EcuC OsTaskAlarm.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsAlarmInstanceAction	0..1	[ECUC_Arti_00112]
ArtiOsAlarmInstanceCounter	0..1	[ECUC_Arti_00113]
ArtiOsAlarmInstanceAlarmTimeRef	0..1	[ECUC_Arti_00156]
ArtiOsAlarmInstanceCycleTimeRef	0..1	[ECUC_Arti_00114]
ArtiOsAlarmInstanceEcuCRef	0..1	[ECUC_Arti_00115]
ArtiOsAlarmInstanceGenericComponentInstanceRef	0..1	[ECUC_Arti_00116]
ArtiOsAlarmInstanceStateRef	0..1	[ECUC_Arti_00117]
ArtiOsAlarmInstanceValidRef	0..1	[ECUC_Arti_00118]

No Included Containers

⌋

[ECUC_Arti_00112] Definition of EcucStringParamDef ArtiOsAlarmInstanceAction ⌈

Parameter Name	ArtiOsAlarmInstanceAction		
Parent Container	ArtiOsAlarmInstance		
Description	This attribute provides a string with a description of the action when the alarm expires, e.g. "ActivateTask TaskA".		
Multiplicity	0..1		
Type	EcucStringParamDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00113] Definition of EcucStringParamDef ArtiOsAlarmInstance Counter ⌈

Parameter Name	ArtiOsAlarmInstanceCounter		
Parent Container	ArtiOsAlarmInstance		
Description	This attribute provides a string containing the name of the counter used by this alarm.		
Multiplicity	0..1		
Type	EcucStringParamDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00156] Definition of EcucReferenceDef ArtiOsAlarmInstanceAlarmTimeRef ⌈

Parameter Name	ArtiOsAlarmInstanceAlarmTimeRef		
Parent Container	ArtiOsAlarmInstance		
Description	This attribute specifies how to evaluate the time until the alarm expires next. The time should be represented in seconds.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00114] Definition of EcucReferenceDef ArtiOsAlarmInstanceCycleTimeRef ⌈

Parameter Name	ArtiOsAlarmInstanceCycleTimeRef		
Parent Container	ArtiOsAlarmInstance		
Description	This attribute specifies how to evaluate the cycle time for cyclic alarms. The value of "cycle time" is 0 for non-cyclic alarms. The time should be represendet in seconds.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00115] Definition of EcucReferenceDef ArtiOsAlarmInstanceEcuCRef ⌈

Parameter Name	ArtiOsAlarmInstanceEcuCRef		
Parent Container	ArtiOsAlarmInstance		
Description	Refers to an EcuC OsAlarm that is beeing extended.		
Multiplicity	0..1		
Type	Reference to OsAlarm		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00116] Definition of EcucReferenceDef ArtiOsAlarmInstanceGenericComponentInstanceRef ⌈

Parameter Name	ArtiOsAlarmInstanceGenericComponentInstanceRef		
Parent Container	ArtiOsAlarmInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the ArtiOsAlarmInstance.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00117] Definition of EcucReferenceDef ArtiOsAlarmInstanceStateRef ⌈

Parameter Name	ArtiOsAlarmInstanceStateRef		
Parent Container	ArtiOsAlarmInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "state" of this alarm. The result then is mapped with the typemap of the ArtiOsAlarmStateRef of the ArtiOsAlarmClass.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00118] Definition of EcucReferenceDef ArtiOsAlarmInstanceValidRef ⌈

Parameter Name	ArtiOsAlarmInstanceValidRef		
Parent Container	ArtiOsAlarmInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this alarm. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.7 ArtiOsClass

[ECUC_Arti_00074] Definition of EcucParamConfContainerDef ArtiOsClass ⌈

Container Name	ArtiOsClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ARTI "Os" object, extending the EcuC OsOS.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	Multiplicity	ECUC ID
ArtiOsClassAppModeRef	1	[ECUC_Arti_00072]
ArtiOsClassGenericComponentRef	0..1	[ECUC_Arti_00076]
ArtiOsClassServiceTraceRef	0..1	[ECUC_Arti_00097]

No Included Containers

⌋

[ECUC_Arti_00072] Definition of EcucReferenceDef ArtiOsClassAppModeRef ⌈

Parameter Name	ArtiOsClassAppModeRef		
Parent Container	ArtiOsClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiOsAppModeInstance parameter.		
Multiplicity	1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Value	false		
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00076] Definition of EcucReferenceDef ArtiOsClassGenericComponentRef ⌈

Parameter Name	ArtiOsClassGenericComponentRef		
Parent Container	ArtiOsClass		
Description	Refers to an ArtiGenericComponentClass that extends the OS description.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE

▽

△

	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00097] Definition of EcucReferenceDef ArtiOsClassServiceTraceRef

⌈

Parameter Name	ArtiOsClassServiceTraceRef		
Parent Container	ArtiOsClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiOsInstanceServiceTrace parameter. This attribute indicates the entry or exit of a service routine and the ID of this service routine. The value of this attribute must be evaluated from one single memory location.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

```
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsClass_Conf</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsClass</DEFINITION-REF>
<REFERENCE-VALUES>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsClass/ArtiOsClassAppModeRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiObjectClassParameter_ArtiOs_OsAppMode</VALUE-REF>
</ECUC-REFERENCE-VALUE>
</REFERENCE-VALUES>
</ECUC-CONTAINER-VALUE>
```

10.4.8 ArtiOsContextClass

[ECUC_Arti_00119] Definition of EcucParamConfContainerDef ArtiOsContextClass ⌈

Container Name	ArtiOsContextClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ARTI "OsContext" object.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsContextClassGenericComponentClassRef	0..1	[ECUC_Arti_00121]

No Included Containers

⌋

[ECUC_Arti_00121] Definition of EcucReferenceDef ArtiOsContextClassGenericComponentClassRef ⌈

Parameter Name	ArtiOsContextClassGenericComponentClassRef		
Parent Container	ArtiOsContextClass		
Description	Refers to an ArtiGenericComponentClass that extends the ArtiOsContextClass.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.9 ArtiOsContextInstance

[ECUC_Arti_00120] Definition of EcucParamConfContainerDef ArtiOsContextInstance ⌈

Container Name	ArtiOsContextInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an "ArtiContext" object.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsContextInstanceAddressRef	0..1	[ECUC_Arti_00122]
ArtiOsContextInstanceGenericComponentInstanceRef	0..1	[ECUC_Arti_00123]
ArtiOsContextInstanceSizeRef	0..1	[ECUC_Arti_00124]
ArtiOsContextInstanceValidRef	0..1	[ECUC_Arti_00125]

No Included Containers

⌋

[ECUC_Arti_00122] Definition of EcucReferenceDef ArtiOsContextInstanceAddressRef ⌈

Parameter Name	ArtiOsContextInstanceAddressRef		
Parent Container	ArtiOsContextInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "address" of this context.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00123] Definition of EcucReferenceDef ArtiOsContextInstance GenericComponentInstanceRef ⌈

Parameter Name	ArtiOsContextInstanceGenericComponentInstanceRef		
Parent Container	ArtiOsContextInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the ArtiOsContext.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00124] Definition of EcucReferenceDef ArtiOsContextInstanceSize Ref ⌈

Parameter Name	ArtiOsContextInstanceSizeRef		
Parent Container	ArtiOsContextInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "size" of this context.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00125] Definition of EcucReferenceDef ArtiOsContextInstanceValidRef ⌈

Parameter Name	ArtiOsContextInstanceValidRef		
Parent Container	ArtiOsContextInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this context. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.10 ArtiOsInstance

[ECUC_Arti_00080] Definition of EcucParamConfContainerDef ArtiOsInstance ⌈

Container Name	ArtiOsInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an ARTI "Os" object, extending the EcuC OsOS.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsInstanceAppModeRef	1	[ECUC_Arti_00073]
ArtiOsInstanceEcucRef	1	[ECUC_Arti_00075]
ArtiOsInstanceGenericComponentRef	0..1	[ECUC_Arti_00078]
ArtiOsInstanceHookRef	0..*	[ECUC_Arti_00079]
ArtiOsInstanceServiceTraceRef	0..1	[ECUC_Arti_00098]
ArtiOsInstanceValidRef	0..1	[ECUC_Arti_00099]

No Included Containers

⌋

[ECUC_Arti_00073] Definition of EcucReferenceDef ArtiOsInstanceAppModeRef ⌈

Parameter Name	ArtiOsInstanceAppModeRef		
Parent Container	ArtiOsInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "application mode" of this OS.		
Multiplicity	1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00075] Definition of EcucReferenceDef ArtiOsInstanceEcucRef ⌈

Parameter Name	ArtiOsInstanceEcucRef		
Parent Container	ArtiOsInstance		
Description	Refers to the EcucDefs/Os/OsOS of this OS.		
Multiplicity	1		
Type	Reference to OsOS		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00078] Definition of EcucReferenceDef ArtiOsInstanceGenericComponentRef ⌈

Parameter Name	ArtiOsInstanceGenericComponentRef		
Parent Container	ArtiOsInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the OS.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	

▽

△

Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00079] Definition of EcucReferenceDef ArtiOsInstanceHookRef ⌈

Parameter Name	ArtiOsInstanceHookRef		
Parent Container	ArtiOsInstance		
Description	Refers to a hook defined in the OS.		
Multiplicity	0..*		
Type	Reference to ArtiHook		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00098] Definition of EcucReferenceDef ArtiOsInstanceServiceTraceRef ⌈

Parameter Name	ArtiOsInstanceServiceTraceRef		
Parent Container	ArtiOsInstance		
Description	Refers to a hook defined in the OS.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00099] Definition of EcucReferenceDef ArtiOsInstanceValidRef ⌈

Parameter Name	ArtiOsInstanceValidRef		
Parent Container	ArtiOsInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this ArtiOsInstance. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

```
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsInstance_Conf</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsInstance</DEFINITION-REF>
<REFERENCE-VALUES>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsInstance/ArtiOsInstanceAppModeRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiObjectInstanceParameter_OsAppMode</VALUE-REF>
</ECUC-REFERENCE-VALUE>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsInstance/ArtiOsInstanceEcucRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1EcucOs/
Vendor1Os</VALUE-REF>
</ECUC-REFERENCE-VALUE>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsInstance/ArtiOsInstanceHookRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiHook_ArtiOs_TaskStart</VALUE-REF>
</ECUC-REFERENCE-VALUE>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsInstance/ArtiOsInstanceHookRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1Arti/
ArtiHook_ArtiOs_TaskStop</VALUE-REF>
</ECUC-REFERENCE-VALUE>
</REFERENCE-VALUES>
</ECUC-CONTAINER-VALUE>
```

10.4.11 ArtiOsIsrClass

[ECUC_Arti_00081] Definition of EcucParamConfContainerDef ArtiOsIsrClass ⌈

Container Name	ArtiOsIsrClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ARTI "OsIsr" object, extending the EcuC OsIsr.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsIsrClassGenericComponentRef	0..1	[ECUC_Arti_00084]

No Included Containers

⌋

[ECUC_Arti_00084] Definition of EcucReferenceDef ArtiOsIsrClassGenericComponentRef ⌈

Parameter Name	ArtiOsIsrClassGenericComponentRef		
Parent Container	ArtiOsIsrClass		
Description	Refers to an optional ArtiGenericComponentClass that extends the OsIsr with additional parameters.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.12 ArtiOsIsrInstance

[ECUC_Arti_00086] Definition of EcucParamConfContainerDef ArtiOsIsrInstance
⌈

Container Name	ArtiOsIsrInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an ARTI "OsIsr" object, extending the EcuC OsIsr.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsIsrInstanceCategory	0..1	[ECUC_Arti_00174]
ArtiOsIsrInstanceFunction	0..1	[ECUC_Arti_00083]
ArtiOsIsrInstanceId	1	[ECUC_Arti_00093]
ArtiOsIsrInstanceEcucRef	0..1	[ECUC_Arti_00082]
ArtiOsIsrInstanceGenericComponentRef	0..1	[ECUC_Arti_00085]
ArtiOsIsrInstanceTimingProtectionLastTimeFrameRef	0..1	[ECUC_Arti_00211]
ArtiOsIsrInstanceTimingProtectionUsedBudgetRef	0..1	[ECUC_Arti_00212]
ArtiOsIsrInstanceValidRef	0..1	[ECUC_Arti_00157]

No Included Containers

⌋

[ECUC_Arti_00174] Definition of EcucEnumerationParamDef ArtiOsIsrInstance Category ⌈

Parameter Name	ArtiOsIsrInstanceCategory		
Parent Container	ArtiOsIsrInstance		
Description	Specifies category of this ISR. If omitted the instance is related to a CATEGORY_2.		
Multiplicity	0..1		
Type	EcucEnumerationParamDef		
Range	CATEGORY_1	–	
	CATEGORY_2	–	
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	

▽

△

	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00083] Definition of EcucFunctionNameDef ArtiOsIsrInstanceFunction ⌈

Parameter Name	ArtiOsIsrInstanceFunction		
Parent Container	ArtiOsIsrInstance		
Description	This parameter represents the C function name of the ISR routine.		
Multiplicity	0..1		
Type	EcucFunctionNameDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00093] Definition of EcucIntegerParamDef ArtiOsIsrInstanceId ⌈

Parameter Name	ArtiOsIsrInstanceId		
Parent Container	ArtiOsIsrInstance		
Description	This parameter represents the "ISRID" as given by the OS, returned by GetISRID().		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00082] Definition of EcucReferenceDef ArtiOsIsrInstanceEcucRef ⌈

Parameter Name	ArtiOsIsrInstanceEcucRef		
Parent Container	ArtiOsIsrInstance		
Description	Refers to the EcucDefs/Os/OsIsr of this ISR.		
Multiplicity	0..1		
Type	Reference to OsIsr		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00085] Definition of EcucReferenceDef ArtiOsIsrInstanceGenericComponentRef ⌈

Parameter Name	ArtiOsIsrInstanceGenericComponentRef		
Parent Container	ArtiOsIsrInstance		
Description	Refers to an optional ArtiGenericComponentInstance that extends this OsIsr with additional parameters.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00211] Definition of EcucReferenceDef ArtiOsIsrInstanceTimingProtectionLastTimeFrameRef ⌈

Parameter Name	ArtiOsIsrInstanceTimingProtectionLastTimeFrameRef
Parent Container	ArtiOsIsrInstance
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the last time frame related to the OsIsr/OsIsrTimingProtection configuration.

▽

△

Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00212] Definition of EcucReferenceDef ArtiOsIsrInstanceTimingProtectionUsedBudgetRef ⌈

Parameter Name	ArtiOsIsrInstanceTimingProtectionUsedBudgetRef		
Parent Container	ArtiOsIsrInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the used budget related to the OsIsr/OsIsrTimingProtection configuration.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00157] Definition of EcucReferenceDef ArtiOsIsrInstanceValidRef ⌈

Parameter Name	ArtiOsIsrInstanceValidRef
Parent Container	ArtiOsIsrInstance
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this ArtiOsIsrInstance. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).
Multiplicity	0..1
Type	Reference to ArtiObjectInstanceParameter
Post-Build Variant Multiplicity	false
Post-Build Variant Value	false

▽

△

Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.13 ArtiOsMessageContainerClass

[ECUC_Arti_00126] Definition of EcucParamConfContainerDef ArtiOsMessageContainerClass ⌈

Container Name	ArtiOsMessageContainerClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ARTI "OsMessageContainer" object. The "OsMessage Container" object represents an existing combination of OSEK messages.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsMessageContainerClassGenericComponentClass Ref	0..1	[ECUC_Arti_00128]

No Included Containers

⌋

[ECUC_Arti_00128] Definition of EcucReferenceDef ArtiOsMessageContainerClassGenericComponentClassRef ⌈

Parameter Name	ArtiOsMessageContainerClassGenericComponentClassRef
Parent Container	ArtiOsMessageContainerClass
Description	Refers to an ArtiGenericComponentClass that extends the ArtiOsMessageContainer Class.
Multiplicity	0..1
Type	Reference to ArtiGenericComponentClass

▽

△

Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.14 ArtiOsMessageContainerInstance

[ECUC_Arti_00127] Definition of EcucParamConfContainerDef ArtiOsMessageContainerInstance ⌈

Container Name	ArtiOsMessageContainerInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an "ArtiMessageContainer" object.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsMessageContainerInstanceMsgName	0..1	[ECUC_Arti_00129]
ArtiOsMessageContainerInstanceMsgType	0..1	[ECUC_Arti_00130]
ArtiOsMessageContainerInstanceFirstElementRef	0..1	[ECUC_Arti_00131]
ArtiOsMessageContainerInstanceGenericComponentInstanceRef	0..1	[ECUC_Arti_00132]
ArtiOsMessageContainerInstanceQueueCountRef	0..1	[ECUC_Arti_00133]
ArtiOsMessageContainerInstanceQueueSizeRef	0..1	[ECUC_Arti_00134]
ArtiOsMessageContainerInstanceValidRef	0..1	[ECUC_Arti_00135]

No Included Containers

⌋

[ECUC_Arti_00129] Definition of EcucStringParamDef ArtiOsMessageContainerInstanceMsgName ⌈

Parameter Name	ArtiOsMessageContainerInstanceMsgName		
Parent Container	ArtiOsMessageContainerInstance		
Description	This attribute provides the name of the message as defined in OIL file.		
Multiplicity	0..1		
Type	EcucStringParamDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00130] Definition of EcucStringParamDef ArtiOsMessageContainerInstanceMsgType ⌈

Parameter Name	ArtiOsMessageContainerInstanceMsgType		
Parent Container	ArtiOsMessageContainerInstance		
Description	This attribute provides the type of the message.		
Multiplicity	0..1		
Type	EcucStringParamDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00131] Definition of EcucReferenceDef ArtiOsMessageContainerInstanceFirstElementRef ⌈

Parameter Name	ArtiOsMessageContainerInstanceFirstElementRef		
Parent Container	ArtiOsMessageContainerInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "firstelement" of this "ArtiOsMessageContainer". This attribute provides the formula for evaluation of address of first valid message. This message will be received next. If no message is in the queue the value is zero.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00132] Definition of EcucReferenceDef ArtiOsMessageContainerInstanceGenericComponentInstanceRef ⌈

Parameter Name	ArtiOsMessageContainerInstanceGenericComponentInstanceRef		
Parent Container	ArtiOsMessageContainerInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the ArtiOsMessageContainer Instance.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00133] Definition of EcucReferenceDef ArtiOsMessageContainerInstanceQueueCountRef ⌈

Parameter Name	ArtiOsMessageContainerInstanceQueueCountRef		
Parent Container	ArtiOsMessageContainerInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "queuecount" of this "ArtiOsMessageContainer". This attribute provides the number of valid messages in the queue and "1" for unqueued messages.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00134] Definition of EcucReferenceDef ArtiOsMessageContainerInstanceQueueSizeRef ⌈

Parameter Name	ArtiOsMessageContainerInstanceQueueSizeRef		
Parent Container	ArtiOsMessageContainerInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "queuesize" of this "ArtiOsMessageContainer". This attribute provides the size of the queue for queued messages and "1" for unqueued messages.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00135] Definition of EcucReferenceDef ArtiOsMessageContainerInstanceValidRef ⌈

Parameter Name	ArtiOsMessageContainerInstanceValidRef		
Parent Container	ArtiOsMessageContainerInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this ArtiOsMessageContainerInstance. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.15 ArtiOsResourceClass

[ECUC_Arti_00136] Definition of EcucParamConfContainerDef ArtiOsResourceClass ⌈

Container Name	ArtiOsResourceClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ArtiOsResource object. The ArtiOsResource object represents an OSEK resource.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsResourceClassGenericComponentClassRef	0..1	[ECUC_Arti_00138]
ArtiOsResourceClassLockerRef	0..1	[ECUC_Arti_00139]
ArtiOsResourceClassStateRef	0..1	[ECUC_Arti_00140]

No Included Containers

⌋

[ECUC_Arti_00138] Definition of EcucReferenceDef ArtiOsResourceClass GenericComponentClassRef ⌈

Parameter Name	ArtiOsResourceClassGenericComponentClassRef		
Parent Container	ArtiOsResourceClass		
Description	Refers to an ArtiGenericComponentClass that extends the ArtiOsResourceClass.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00139] Definition of EcucReferenceDef ArtiOsResourceClassLocker Ref ⌈

Parameter Name	ArtiOsResourceClassLockerRef		
Parent Container	ArtiOsResourceClass		
Description	Refers to the ArtiObjectClassParameter that declares the attribute ArtiOsResource LockerRef in ArtiOsResourceInstances. This attribute indicates the locking ArtiOsTask Instance or ArtiOsIsrInstance.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00140] Definition of EcucReferenceDef ArtiOsResourceClassStateRef ⌈

Parameter Name	ArtiOsResourceClassStateRef		
Parent Container	ArtiOsResourceClass		
Description	Refers to the ArtiObjectClassParameter that declares the attribute ArtiOsResourceStateRef in ArtiOsResourceInstances. This attribute represents the state of a resource ("LOCKED"/"UNLOCKED"). The ArtiObjectClassParameter does include the mapping from integer to human readable "LOCKED" or "UNLOCKED".		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.16 ArtiOsResourceInstance

[ECUC_Arti_00137] Definition of EcucParamConfContainerDef ArtiOsResourceInstance ⌈

Container Name	ArtiOsResourceInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an ArtiOsResource object.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsResourceInstancePriority	0..1	[ECUC_Arti_00141]
ArtiOsResourceInstanceEcuCRef	0..1	[ECUC_Arti_00142]
ArtiOsResourceInstanceGenericComponentInstanceRef	0..1	[ECUC_Arti_00143]
ArtiOsResourceInstanceLockerRef	0..1	[ECUC_Arti_00145]
ArtiOsResourceInstanceStateRef	0..1	[ECUC_Arti_00144]
ArtiOsResourceInstanceValidRef	0..1	[ECUC_Arti_00146]

No Included Containers

⌋

[ECUC_Arti_00141] Definition of EcucStringParamDef ArtiOsResourceInstance Priority ⌈

Parameter Name	ArtiOsResourceInstancePriority		
Parent Container	ArtiOsResourceInstance		
Description	This attribute has two components that state: that the RESOURCE is used by TASKs only or by TASKs and ISRs, and the priority that will be used when locking the RESOURCE.		
Multiplicity	0..1		
Type	EcucStringParamDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00142] Definition of EcucReferenceDef ArtiOsResourceInstanceEcuCRef ⌈

Parameter Name	ArtiOsResourceInstanceEcuCRef		
Parent Container	ArtiOsResourceInstance		
Description	Refers to an EcuC OsResource that is beeing extended.		
Multiplicity	0..1		
Type	Reference to OsResource		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00143] Definition of EcucReferenceDef ArtiOsResourceInstance GenericComponentInstanceRef ⌈

Parameter Name	ArtiOsResourceInstanceGenericComponentInstanceRef		
Parent Container	ArtiOsResourceInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the ArtiOsResourceInstance.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00145] Definition of EcucReferenceDef ArtiOsResourceInstance LockerRef ⌈

Parameter Name	ArtiOsResourceInstanceLockerRef		
Parent Container	ArtiOsResourceInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "locker" of this ArtiOsResource.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00144] Definition of EcucReferenceDef ArtiOsResourceInstance StateRef ⌈

Parameter Name	ArtiOsResourceInstanceStateRef
Parent Container	ArtiOsResourceInstance
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "state" of this ArtiOsResource.

▽

△

Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00146] Definition of EcucReferenceDef ArtiOsResourceInstanceValidRef ⌈

Parameter Name	ArtiOsResourceInstanceValidRef		
Parent Container	ArtiOsResourceInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this ArtiOsResourceInstance. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.17 ArtiOsScheduleTableClass

[ECUC_Arti_00182] Definition of EcucParamConfContainerDef ArtiOsScheduleTableClass ⌈

Container Name	ArtiOsScheduleTableClass
Parent Container	ArtiOs
Description	Contains the layout of an ArtiOsScheduleTable object.
Post-Build Variant Multiplicity	false
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsScheduleTableClassCurrentStateRef	0..1	[ECUC_Arti_00184]
ArtiOsScheduleTableClassGenericComponentClassRef	0..1	[ECUC_Arti_00183]

No Included Containers

⌋

[ECUC_Arti_00184] Definition of EcucReferenceDef ArtiOsScheduleTableClassCurrentStateRef ⌈

Parameter Name	ArtiOsScheduleTableClassCurrentStateRef		
Parent Container	ArtiOsScheduleTableClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiCurrentScheduleTableStateInstance parameter including the state mapping.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00183] Definition of EcucReferenceDef ArtiOsScheduleTableClassGenericComponentClassRef ⌈

Parameter Name	ArtiOsScheduleTableClassGenericComponentClassRef
Parent Container	ArtiOsScheduleTableClass
Description	Refers to an ArtiGenericComponentClass that extends the ArtiOsScheduleTableClass.
Multiplicity	0..1
Type	Reference to ArtiGenericComponentClass
Post-Build Variant Multiplicity	false
Post-Build Variant Value	false

▽

△

Multiplicity Configuration Class	Pre-compile time	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.4.18 ArtiOsScheduleTableInstance

[ECUC_Arti_00185] Definition of EcucParamConfContainerDef ArtiOsScheduleTableInstance ⌈

Container Name	ArtiOsScheduleTableInstance
Parent Container	ArtiOs
Description	Represents an instance of an ArtiOsScheduleTable object, extending the EcuC Os ScheduleTable.
Post-Build Variant Multiplicity	false
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsScheduleTableInstanceCoreRef	0..1	[ECUC_Arti_00186]
ArtiOsScheduleTableInstanceCounterValueRef	0..1	[ECUC_Arti_00187]
ArtiOsScheduleTableInstanceCurrentStateRef	0..1	[ECUC_Arti_00188]
ArtiOsScheduleTableInstanceEcucRef	0..1	[ECUC_Arti_00189]
ArtiOsScheduleTableInstanceExpiryTimeRef	0..1	[ECUC_Arti_00190]
ArtiOsScheduleTableInstanceGenericComponentInstanceRef	0..1	[ECUC_Arti_00191]
ArtiOsScheduleTableInstanceNextEventRef	0..1	[ECUC_Arti_00224]
ArtiOsScheduleTableInstanceNextExpiryPointRef	0..1	[ECUC_Arti_00192]
ArtiOsScheduleTableInstanceNextScheduleTableRef	0..1	[ECUC_Arti_00193]

No Included Containers

⌋

[ECUC_Arti_00186] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceCoreRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceCoreRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to the ArtiHardwareCoreInstance on which this OsScheduleTable runs.		
Multiplicity	0..1		
Type	Reference to ArtiHardwareCoreInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00187] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceCounterValueRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceCounterValueRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the absolute counter value.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00188] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceCurrentStateRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceCurrentStateRef
Parent Container	ArtiOsScheduleTableInstance
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current state" of this OsScheduleTable.

▽

△

Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00189] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceEcucRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceEcucRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to an EcuC OsScheduleTable that is beeing extended.		
Multiplicity	0..1		
Type	Reference to OsScheduleTable		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00190] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceExpiryTimeRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceExpiryTimeRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the expiry time.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants

▽

△

	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00191] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceGenericComponentInstanceRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceGenericComponentInstanceRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the ArtiOsScheduleTable Instance.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00224] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceNextEventRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceNextEventRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "next event".		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	

▽

△

Scope / Dependency	scope: local

⌋

[ECUC_Arti_00192] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceNextExpiryPointRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceNextExpiryPointRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "next expiry point".		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00193] Definition of EcucReferenceDef ArtiOsScheduleTableInstanceNextScheduleTableRef ⌈

Parameter Name	ArtiOsScheduleTableInstanceNextScheduleTableRef		
Parent Container	ArtiOsScheduleTableInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "next schedule table".		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.4.19 ArtiOsSpinlockClass

[ECUC_Arti_00194] Definition of EcucParamConfContainerDef ArtiOsSpinlockClass ⌈

Container Name	ArtiOsSpinlockClass
Parent Container	ArtiOs
Description	Contains the layout of an ArtiOsSpinlock object.
Post-Build Variant Multiplicity	false
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsScheduleTableClassGenericComponentClassRef	0..1	[ECUC_Arti_00195]
ArtiOsSpinlockClassCurrentOwnerTypeRef	0..1	[ECUC_Arti_00197]
ArtiOsSpinlockClassCurrentStateRef	0..1	[ECUC_Arti_00196]

No Included Containers

⌋

[ECUC_Arti_00195] Definition of EcucReferenceDef ArtiOsScheduleTableClassGenericComponentClassRef ⌈

Parameter Name	ArtiOsScheduleTableClassGenericComponentClassRef		
Parent Container	ArtiOsSpinlockClass		
Description	Refers to an ArtiGenericComponentClass that extends the ArtiOsSpinlockClass.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00197] Definition of EcucReferenceDef ArtiOsSpinlockClassCurrentOwnerTypeRef ⌈

Parameter Name	ArtiOsSpinlockClassCurrentOwnerTypeRef		
Parent Container	ArtiOsSpinlockClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiCurrentSpinlockOwnerTypeInstance parameter including the type mapping.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00196] Definition of EcucReferenceDef ArtiOsSpinlockClassCurrentStateRef ⌈

Parameter Name	ArtiOsSpinlockClassCurrentStateRef		
Parent Container	ArtiOsSpinlockClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiCurrentSpinlockStateInstance parameter including the state mapping.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.4.20 ArtiOsSpinlockInstance

[ECUC_Arti_00198] Definition of EcucParamConfContainerDef ArtiOsSpinlockInstance ⌈

Container Name	ArtiOsSpinlockInstance
Parent Container	ArtiOs
Description	Represents an instance of an ArtiOsSpinlock object, extending the EcuC OsSpinlock.
Post-Build Variant Multiplicity	false
Configuration Parameters	

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsSpinlockInstanceCurrentOwnerRef	0..1	[ECUC_Arti_00199]
ArtiOsSpinlockInstanceCurrentOwnerTypeRef	0..1	[ECUC_Arti_00200]
ArtiOsSpinlockInstanceCurrentStateRef	0..1	[ECUC_Arti_00201]
ArtiOsSpinlockInstanceEcuCRef	0..1	[ECUC_Arti_00202]
ArtiOsSpinlockInstanceGenericComponentInstanceRef	0..1	[ECUC_Arti_00203]
ArtiOsSpinlockInstanceLockingCoreRef	0..1	[ECUC_Arti_00204]

No Included Containers

⌋

[ECUC_Arti_00199] Definition of EcucReferenceDef ArtiOsSpinlockInstanceCurrentOwnerRef ⌈

Parameter Name	ArtiOsSpinlockInstanceCurrentOwnerRef		
Parent Container	ArtiOsSpinlockInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the owner ID (task or ISR2).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00200] Definition of EcucReferenceDef ArtiOsSpinlockInstanceCurrentOwnerTypeRef ⌈

Parameter Name	ArtiOsSpinlockInstanceCurrentOwnerTypeRef		
Parent Container	ArtiOsSpinlockInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current owner type" of this OsSpinlock.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00201] Definition of EcucReferenceDef ArtiOsSpinlockInstanceCurrentStateRef ⌈

Parameter Name	ArtiOsSpinlockInstanceCurrentStateRef		
Parent Container	ArtiOsSpinlockInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current state" of this OsSpinlock.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00202] Definition of EcucReferenceDef ArtiOsSpinlockInstanceEcuCRef ⌈

Parameter Name	ArtiOsSpinlockInstanceEcuCRef		
Parent Container	ArtiOsSpinlockInstance		
Description	Refers to an EcuC OsSpinlock that is beeing extended.		
Multiplicity	0..1		
Type	Reference to OsSpinlock		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00203] Definition of EcucReferenceDef ArtiOsSpinlockInstanceGenericComponentInstanceRef ⌈

Parameter Name	ArtiOsSpinlockInstanceGenericComponentInstanceRef		
Parent Container	ArtiOsSpinlockInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the ArtiOsSpinlockInstance.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00204] Definition of EcucReferenceDef ArtiOsSpinlockInstanceLockingCoreRef ⌈

Parameter Name	ArtiOsSpinlockInstanceLockingCoreRef		
Parent Container	ArtiOsSpinlockInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the current locking core.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

10.4.21 ArtiOsStackClass

[ECUC_Arti_00147] Definition of EcucParamConfContainerDef ArtiOsStackClass ⌈

Container Name	ArtiOsStackClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ArtiOsStack object. The ArtiOsStack object defines the memory area of any stack in the system.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	Multiplicity	ECUC ID
ArtiOsStackClassGenericComponentClassRef	0..1	[ECUC_Arti_00149]

No Included Containers

⌋

[ECUC_Arti_00149] Definition of EcucReferenceDef ArtiOsStackClassGenericComponentClassRef ⌈

Parameter Name	ArtiOsStackClassGenericComponentClassRef		
Parent Container	ArtiOsStackClass		
Description	Refers to an ArtiGenericComponentClass that extends the ArtiOsStackClass.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.22 ArtiOsStackInstance

[ECUC_Arti_00148] Definition of EcucParamConfContainerDef ArtiOsStackInstance ⌈

Container Name	ArtiOsStackInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an ArtiOsStack object.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsStackInstanceDirection	0..1	[ECUC_Arti_00150]
ArtiOsStackInstanceBaseAddressRef	0..1	[ECUC_Arti_00151]
ArtiOsStackInstanceFillPatternRef	0..1	[ECUC_Arti_00152]
ArtiOsStackInstanceGenericComponentInstanceRef	0..1	[ECUC_Arti_00153]
ArtiOsStackInstanceSizeRef	0..1	[ECUC_Arti_00154]
ArtiOsStackInstanceValidRef	0..1	[ECUC_Arti_00155]

No Included Containers

⌋

[ECUC_Arti_00150] Definition of EcucStringParamDef ArtiOsStackInstanceDirection ⌈

Parameter Name	ArtiOsStackInstanceDirection		
Parent Container	ArtiOsStackInstance		
Description	This attribute specifies the direction of stack growth and may have either "UP" or "DOWN" as its value. UP means growing from lower to higher addresses. DOWN means growing from higher addresses to lower addresses.		
Multiplicity	0..1		
Type	EcucStringParamDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00151] Definition of EcucReferenceDef ArtiOsStackInstanceBaseAddressRef ⌈

Parameter Name	ArtiOsStackInstanceBaseAddressRef		
Parent Container	ArtiOsStackInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "baseaddress" of this ArtiOsStack. This attribute specifies the lowest address of stack memory area, regardless of the stack direction.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00152] Definition of EcucReferenceDef ArtiOsStackInstanceFillPatternRef ⌈

Parameter Name	ArtiOsStackInstanceFillPatternRef		
Parent Container	ArtiOsStackInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "fillpattern" of this ArtiOsStack. If the operating system fills the stack during initialisation, this attribute specifies with which pattern the stack area is initialised. This allows the debugger to evaluate the maximum stack usage. For "stackdirection" "DOWN" the pattern starts at "baseaddress". For "stackdirection" "UP" the pattern starts at "baseaddress" + "size". If no pattern is used, this attribute must be omitted.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00153] Definition of EcucReferenceDef ArtiOsStackInstanceGenericComponentInstanceRef ⌈

Parameter Name	ArtiOsStackInstanceGenericComponentInstanceRef		
Parent Container	ArtiOsStackInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the ArtiOsStackInstance.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00154] Definition of EcucReferenceDef ArtiOsStackInstanceSizeRef ⌈

Parameter Name	ArtiOsStackInstanceSizeRef		
Parent Container	ArtiOsStackInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "size" of this ArtiOsStack. This attribute represents the size (in bytes) of the memory area allocated for stack.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00155] Definition of EcucReferenceDef ArtiOsStackInstanceValidRef ⌈

Parameter Name	ArtiOsStackInstanceValidRef		
Parent Container	ArtiOsStackInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this ArtiOsStackInstance. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

10.4.23 ArtiOsTaskClass

[ECUC_Arti_00087] Definition of EcucParamConfContainerDef ArtiOsTaskClass ⌈

Container Name	ArtiOsTaskClass		
Parent Container	ArtiOs		
Description	Contains the layout of an ARTI "OsTask" object, extending the EcuC OsTask.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsTaskClassClassGenericComponentRef	0..1	[ECUC_Arti_00077]
ArtiOsTaskClassContextRef	0..1	[ECUC_Arti_00100]
ArtiOsTaskClassCurrentTaskStateRef	0..1	[ECUC_Arti_00068]
ArtiOsTaskClassPriorityRef	0..1	[ECUC_Arti_00101]
ArtiOsTaskClassStackRef	0..1	[ECUC_Arti_00102]

No Included Containers

⌋

[ECUC_Arti_00077] Definition of EcucReferenceDef ArtiOsTaskClassClass GenericComponentRef ⌈

Parameter Name	ArtiOsTaskClassClassGenericComponentRef		
Parent Container	ArtiOsTaskClass		
Description	Refers to an ArtiGenericComponentClass that extends the OsTask.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentClass		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00100] Definition of EcucReferenceDef ArtiOsTaskClassContextRef ⌈

Parameter Name	ArtiOsTaskClassContextRef		
Parent Container	ArtiOsTaskClass		
Description	ArtiOsTaskContextRef in ArtiOsTaskInstances. This attribute contains a reference to the context object that the task is currently using.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00068] Definition of EcucReferenceDef ArtiOsTaskClassCurrentTaskStateRef ⌈

Parameter Name	ArtiOsTaskClassCurrentTaskStateRef		
Parent Container	ArtiOsTaskClass		
Description	Refers to the ArtiObjectClassParameter that defines the ArtiCurrentTaskStateInstance parameter including the task state mapping.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00101] Definition of EcucReferenceDef ArtiOsTaskClassPriorityRef ⌈

Parameter Name	ArtiOsTaskClassPriorityRef		
Parent Container	ArtiOsTaskClass		
Description	Refers to the ArtiObjectClassParameter that declares the attribute ArtiOsTaskPriorityRef in ArtiOsTaskInstances. This attribute represents the current priority of the TASK object. The current priority can be different from the static task priority as a result of priority ceiling protocol. The priority displayed is the priority as defined in the OsTask.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00102] Definition of EcucReferenceDef ArtiOsTaskClassStackRef ⌈

Parameter Name	ArtiOsTaskClassStackRef		
Parent Container	ArtiOsTaskClass		
Description	Refers to the ArtiObjectClassParameter that declares the attribute ArtiOsTaskStackRef in ArtiOsTaskInstances. This attribute contains a reference to the stack object that the task is currently using.		
Multiplicity	0..1		
Type	Reference to ArtiObjectClassParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

```
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsTaskClass_Conf</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsTaskClass</DEFINITION-REF>
<REFERENCE-VALUES>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsTaskClass/
```

```
ArtiOsTaskClassGenericComponentRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1ArtiGeneric/
ArtiGenericComponentClass_Vendor1Task</VALUE-REF>
</ECUC-REFERENCE-VALUE>
</REFERENCE-VALUES>
</ECUC-CONTAINER-VALUE>
```

10.4.24 ArtiOsTaskInstance

[ECUC_Arti_00090] Definition of EcucParamConfContainerDef ArtiOsTaskInstance ⌈

Container Name	ArtiOsTaskInstance		
Parent Container	ArtiOs		
Description	Represents an instance of an ARTI "OsTask" object, extending the EcuC OsTask.		
Post-Build Variant Multiplicity	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Configuration Parameters			

Included Parameters		
Parameter Name	**Multiplicity**	**ECUC ID**
ArtiOsTaskInstanceFunction	0..1	[ECUC_Arti_00089]
ArtiOsTaskInstanceId	1	[ECUC_Arti_00092]
ArtiOsTaskInstanceContextRef	0..1	[ECUC_Arti_00104]
ArtiOsTaskInstanceCurrentActivationsRef	0..1	[ECUC_Arti_00105]
ArtiOsTaskInstanceCurrentTaskStateRef	0..1	[ECUC_Arti_00069]
ArtiOsTaskInstanceEcucRef	1	[ECUC_Arti_00088]
ArtiOsTaskInstanceGenericComponentRef	0..1	[ECUC_Arti_00070]
ArtiOsTaskInstancePriorityRef	0..1	[ECUC_Arti_00106]
ArtiOsTaskInstanceStackRef	0..1	[ECUC_Arti_00107]
ArtiOsTaskInstanceTimingProtectionLastTimeFrameRef	0..1	[ECUC_Arti_00214]
ArtiOsTaskInstanceTimingProtectionUsedBudgetRef	0..1	[ECUC_Arti_00213]
ArtiOsTaskInstanceValidRef	0..1	[ECUC_Arti_00103]

No Included Containers

⌋

[ECUC_Arti_00089] Definition of EcucFunctionNameDef ArtiOsTaskInstance Function ⌈

Parameter Name	ArtiOsTaskInstanceFunction		
Parent Container	ArtiOsTaskInstance		
Description	This parameter represents the C function name of the task body.		
Multiplicity	0..1		
Type	EcucFunctionNameDef		
Default value	–		
Regular Expression	–		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00092] Definition of EcucIntegerParamDef ArtiOsTaskInstanceId ⌈

Parameter Name	ArtiOsTaskInstanceId		
Parent Container	ArtiOsTaskInstance		
Description	This parameter represents the "TaskID" as given by the OSEK OS, returned by Get TaskID().		
Multiplicity	1		
Type	EcucIntegerParamDef		
Range	0 .. 18446744073709551615		
Default value	–		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00104] Definition of EcucReferenceDef ArtiOsTaskInstanceContext Ref ⌈

Parameter Name	ArtiOsTaskInstanceContextRef
Parent Container	ArtiOsTaskInstance
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the ArtiOs Context of this ArtiOsTask.
Multiplicity	0..1

▽

△

Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00105] Definition of EcucReferenceDef ArtiOsTaskInstanceCurrentActivationsRef ⌈

Parameter Name	ArtiOsTaskInstanceCurrentActivationsRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current activations" of this task. This attribute specifies the number of current activations for the task.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00069] Definition of EcucReferenceDef ArtiOsTaskInstanceCurrentTaskStateRef ⌈

Parameter Name	ArtiOsTaskInstanceCurrentTaskStateRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "current state" of this task.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE

▽

△

	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00088] Definition of EcucReferenceDef ArtiOsTaskInstanceEcucRef ⌈

Parameter Name	ArtiOsTaskInstanceEcucRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the OsTask.		
Multiplicity	1		
Type	Reference to OsTask		
Post-Build Variant Value	false		
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00070] Definition of EcucReferenceDef ArtiOsTaskInstanceGenericComponentRef ⌈

Parameter Name	ArtiOsTaskInstanceGenericComponentRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to an ArtiGenericComponentInstance that extends the OsTask.		
Multiplicity	0..1		
Type	Reference to ArtiGenericComponentInstance		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00106] Definition of EcucReferenceDef ArtiOsTaskInstancePriorityRef ⌈

Parameter Name	ArtiOsTaskInstancePriorityRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "task priority" of this task.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00107] Definition of EcucReferenceDef ArtiOsTaskInstanceStackRef ⌈

Parameter Name	ArtiOsTaskInstanceStackRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the ArtiOs Stack of this ArtiOsTask.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

[ECUC_Arti_00214] Definition of EcucReferenceDef ArtiOsTaskInstanceTimingProtectionLastTimeFrameRef ⌈

Parameter Name	ArtiOsTaskInstanceTimingProtectionLastTimeFrameRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the last time frame related to the OsTask/OsTaskTimingProtection configuration.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00213] Definition of EcucReferenceDef ArtiOsTaskInstanceTimingProtectionUsedBudgetRef ⌈

Parameter Name	ArtiOsTaskInstanceTimingProtectionUsedBudgetRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the used budget related to the OsTask/OsTaskTimingProtection configuration.		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Value Configuration Class	**Pre-compile time**	X	All Variants
	Link time	–	
	Post-build time	–	
Scope / Dependency	scope: local		

⌋

[ECUC_Arti_00103] Definition of EcucReferenceDef ArtiOsTaskInstanceValidRef ⌈

Parameter Name	ArtiOsTaskInstanceValidRef		
Parent Container	ArtiOsTaskInstance		
Description	Refers to the ArtiObjectInstanceParameter that contains the evaluation for the "validity" of this ArtiOsTaskInstance. Every object declaration may contain a VALID attribute telling the debugger whether the object's attributes are currently valid. It may have an integer type of any size. Its possible values are 0 (invalid) and non zero (object is valid).		
Multiplicity	0..1		
Type	Reference to ArtiObjectInstanceParameter		
Post-Build Variant Multiplicity	false		
Post-Build Variant Value	false		
Multiplicity Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Value Configuration Class	Pre-compile time	X	VARIANT-PRE-COMPILE
	Link time	X	VARIANT-LINK-TIME
	Post-build time	–	
Scope / Dependency	scope: ECU		

⌋

```
<ECUC-CONTAINER-VALUE>
<SHORT-NAME>ArtiOsTaskInstance_TaskHighPriority</SHORT-NAME>
<DEFINITION-REF DEST="ECUC-PARAM-CONF-CONTAINER-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsTaskInstance</DEFINITION-REF>
<REFERENCE-VALUES>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsTaskInstance/
ArtiOsTaskInstanceGenericComponentRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1ArtiGeneric/
ArtiGenericComponentInstance_TaskHighPriority</VALUE-REF>
</ECUC-REFERENCE-VALUE>
<ECUC-REFERENCE-VALUE>
<DEFINITION-REF DEST="ECUC-REFERENCE-DEF">/AUTOSAR/Arti/
ArtiOs/ArtiOsTaskInstance/
ArtiOsTaskInstanceEcucRef</DEFINITION-REF>
<VALUE-REF DEST="ECUC-CONTAINER-VALUE">/Vendor1/Vendor1EcucOs/
TaskHighPriority</VALUE-REF>
</ECUC-REFERENCE-VALUE>
</REFERENCE-VALUES>
</ECUC-CONTAINER-VALUE>
```

10.5 Published Information

For details refer to the chapter 10.3 “Published Information” in [4].

11 Generation of the OS

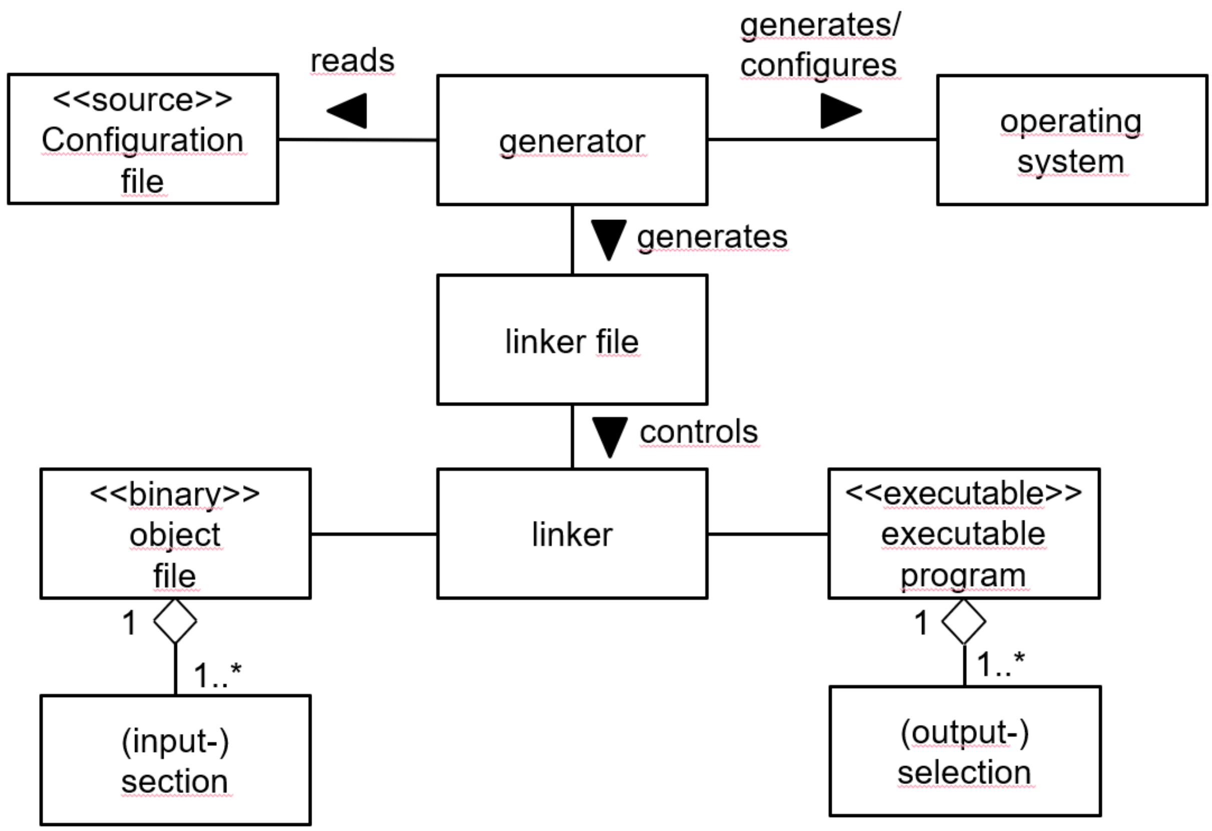

Figure 11.1: Generation activities

11.1 Read in configuration

[SWS_Os_00172] ⌈The generator shall provide the user the ability of reading the information of a selectable configuration file.⌋

11.2 Consistency check

The conistency check can issue warnings or errors. Warnings mean that the generation is completed successfully, only indicating a not advisable configuration. Errors mean that the generation is not performed.

[SWS_Os_00173] ⌈The generator shall provide the user the ability of performing a consistency check of the current configuration.⌋

[SWS_Os_00050] ⌈If service protection is required and OsStatus is not equal to EXTENDED (all the associated error handling is provided), the consistency check shall issue an error.⌋

[SWS_Os_00045] ⌈If timing protection is configured together with OSEK OS Category 1 interrupts, the consistency check shall issue a warning.⌋

[SWS_Os_00562] ⌈If timing protection is configured together with OsPreTaskHook or OsPostTaskHook the consistency check shall issue a warning.⌋

[SWS_Os_00320] ⌈If configured attributes do not match the configured scalability class (e.g. defining an execution time budget in Tasks or Category 2 ISRs and selected scalability class is 1) the consistency check shall issue a warning.⌋

[SWS_Os_00311] ⌈If OsScalabilityClass is SC3 or SC4, or system is Multi-Core, AND a Task OR Category 2 ISR OR Counters OR Alarms OR ScheduleTables does not belong to exactly one OS-Application the consistency check shall issue an error.⌋

[SWS_Os_00361] ⌈If OsScalabilityClass is SC3 or SC4, or system is Multi-Core, AND a Category 1 ISR does not belong to exactly one trusted OS-Application the consistency check shall issue an error⌋

[SWS_Os_00177] ⌈If OsScalabilityClass is SC3 or SC4, or system is Multi-Core, AND an interrupt source that is used by the OS is assigned to an OS-Application, the consistency check shall issue an error.⌋

[SWS_Os_00303] ⌈If OsAlarmIncrementCounter is configured as action on alarm expiry AND the alarm is driven directly or indirectly (a cyclic chain of alarm actions with OsAlarmIncrementCounter) by that Counter, the consistency check shall issue a warning.⌋

[SWS_Os_00328] ⌈If OsStatus is STANDARD and OsScalabilityClass is SC3 or SC4 the consistency check shall issue an error.⌋

[SWS_Os_00343] ⌈If OsScalabilityClass is SC3 or SC4, or system is Multi-Core, AND a Task is referenced within a ScheduleTable object AND the OS-Application of the ScheduleTable has no access to the Task, the consistency check shall issue an error.⌋

[SWS_Os_00344] ⌈If OsScalabilityClass is SC3 or SC4, or system is Multi-Core, AND a Task is referenced within an alarm object AND the OS-Application of the alarm has no access to the Task, the consistency check shall issue an error.⌋

[SWS_Os_00440] ⌈If a ScheduleTable has OsScheduleTblSyncStrategy = IMPLICIT and the OsCounterMaxAllowedValue+1 of the associated Counter is not equal to the duration of the ScheduleTable then the consitency check shall issue an error.⌋

[SWS_Os_00461] ⌈If OsScalabilityClass is SC2, SC3 or SC4 AND Alarm Callbacks are configured the conistency check shall isuue an error.⌋

[SWS_Os_00850] ⌈If OsUseResScheduler is TRUE AND the configuration contains a resource called RES_SCHEDULER, the generation tool shall ignore the configured RES_SCHEDULER.⌋

11.3 Generating operating system

[SWS_Os_00179] ⌈If the consistency check of the read-in configuration file has not run free of errors, the generator shall not generate/configure the operating system.⌋

[SWS_Os_00336]

Upstream requirements: SRS_Os_11019

⌈The generator shall generate a relocatable memory section containing the interrupt vector table.⌋

[SWS_Os_00370] ⌈The generator shall print out information about timers used internally by the OS during generation (e.g. on console, list file).⌋

[SWS_Os_00393] ⌈The generator shall create conversation macros to convert counter ticks (given as argument) into real time. The format of the macro is OS_TICKS2 <Unit>_<Counter>(ticks) whereas <Unit> is one of NS (nanoseconds), US (microseconds), MS (milliseconds) or SEC (seconds) and <Counter> is the name of the Counter; E.g. OS_TICKS2MS_MyCounter())⌋

[SWS_Os_00815]

Upstream requirements: SRS_BSW_00351

⌈The OS code shall wrap each declaration of Task, ISR, trusted functions, alarm callbacks and hook functions with the Memory Mapping Allocation Keywords macros.

```
#define OS_START_SEC_<sadm>
#include "Os_MemMap.h"

< Task, ISR, trusted functions or hook functions declaration>

#define OS_STOP_SEC_<sadm>
#include "Os_MemMap.h"
```

where <sadm> is the shortName of the SwAddrMethod if configured (e.g. in `OsMemoryMappingCodeLocationRef`).⌋

12 Application Notes

12.1 Hooks

In OSEK OS, PreTask & PostTask Hooks run at the level of the OS with unrestricted access rights and therefore must be trusted. It is strongly recommended that these hook routines are only used during debugging and are not used in a final product.

When an OS-Application is killed the shutdown and startup hooks of the OS-Application are not called.

All application-specific hook functions (startup, shutdown and error) must return (blocking or endless loops are not acceptable).

12.2 Providing Trusted Functions

Address checking shall be done before data is accessed. Special care must be taken if parameters passed by reference point to the stack space of a Task or interrupt, because this address space might no longer belong to the Task or interrupt when the address is used.

The following code fragment shows an example how a trusted function is called and how the checks should be done.

```
struct parameter_struct {type1 name1, type2 name2, StatusType
    return_value};

/* This service is called by the user and uses a trusted function */
StatusType system_service( type1 parameter1, type2 parameter2)
{
    /* store parameters in a structure (parameter1 and parameter2) */
    struct parameter_struct local_struct;
    local_struct.name1 = parameter1;
    local_struct.name2 = parameter2;
    /* call CallTrustedFunction with appropriate index and
     * pointer to structure */
    if(CallTrustedFunction(SYSTEM_SERVICE_INDEX, &local_struct) != E_OK
       )
        return(FUNCTION_DOES_NOT_EXIST);
    return(local_struct.return_value);
}

/* The CallTrustedFunction() service switches to the privileged
 * mode. Note that the example is only a fragment! */
StatusType CallTrustedFunction( TrustedFunctionIndexType ix,
    TrustedFunctionParameterRefType ref)
{
    /* check for legal service index and return error if necessary */
    if(ix > MAX_SYSTEM_SERVICE)
        return(E_OS_SERVICEID);
    /* some implementation specific magic happens: the processor is
```

```
     * set to privileged mode */

    /* indirectly call target function based on the index */
    (*(system-service_list[ix]))(ix, ref);
    /* some implementation specific magic happens: the processor is
     * set to non-privileged mode */

   return(E_OK);
}


/* This part of the system service is called by
 * CallTrustedFunction() */
void TRUSTED_system_service_part2 (TrustedFunctionIndexType a,
    parameter_struct *local_struct)
{
    TaskRefType task;
    type1 parameter1;
    type2 parameter2;
    if (GetTaskID(&task) != E_OK)
        task = INVALID_TASK;
        /* get parameters out of the structure (parameter1 and
         * parameter2) */
    parameter1 = local_struct.name1;
    parameter2 = local_struct.name2;
    /* check the parameters if necessary */
    /* example is for parameter1 being an address and parameter2
     * being a size */
    /* example only for system_service called from tasks */
    if(GetISRID()!=INVALID_ISR)
    {
        /* error: not callable from ISR */
        local_struct.return_value = E_OS_ACCESS;
    }
    else if(OSMEMORY_IS_WRITEABLE(CheckTaskMemoryAccess(task,parameter1
        ,parameter2)))
    {
        /* system_service_part3() is now the function as it
         * would be if directly called in a non-protected
         * environment */
        local_struct.return_value = system_service_part3(parameter1,
            parameter2);
    }
    else
    {
    /* error handling */
        local_struct.return_value = E_OS_ACCESS;
    }
}
```

Note: Since the service of `CallTrustedFunction` is very generic, it is needed to define a stub-interface which does the packing and unpacking of the arguments (as the example show). Depending on the implementation the stub interface may be (partly) generated by the generation tool.

12.3 Software Components and OS-Applications

Trusted OS-Applications can be permitted access to IO space. As software components can not be allowed direct access to the hardware, software components can not be trusted OS-Applications because this would violate this protection feature. The configuration process must ensure that this is the case.

The AUTOSAR Virtual Function Bus (VFB) specification places no restrictions on how runnables from software components are mapped to OS `Task`s. However, the protection mechanisms in AUTOSAR OS apply only to OS managed objects. This means that all runnables in a `Task`:

- Are not protected from each other at runtime
- Share the same protection boundary

If runnables need to be protected they must therefore be allocated to different `Task`s and those `Task`s protected accordingly.

A simple rule can suffice:

"When allocating runnables to `Task`s, only allocate runnables from the same software component into the same `Task`."

If multiple software components from the same application are to reside on the same processor, then, assuming protection is required between applications (or parts thereof) on the same processor, this rule could be modified to relax the scope of protection to the application:

"When allocating runnables to `Task`s, only allocate runnables from the same application into the same `Task`."

12.4 Global Time Synchronization

The OS currently assumes that the global time synchronization is done by the user (unless implicit synchronization is used). This allows maximum flexibility regarding the time source. For synchronization with e.g. FlexRay some glue code may be necessary which transfer the information from the time source to the OS.

12.5 Working with FlexRay

`ScheduleTable`s in the AUTOSAR OS may be synchronized with a global (network) time provided by FlexRay in essentially two ways:

- Using the FlexRay interface's services for controlling timer interrupts related to global time to provide a "hardware" counter tick source to drive the processing of a `ScheduleTable` (implicit synchronization)

- Using the FlexRay interface's service for accessing the current global time and passing this into the OS through the SyncScheduleTable OS service call

This section looks at the second option only.

In FlexRay time is presented as a tuple of a Cycle and a MacrotickOffset within the cycle. Cycle is an 8-bit value and MacrotickOffset is a 16-bit value.

In AUTOSAR OS a ScheduleTable is associated with an underlying Counter that has a notion of ticks. It is therefore possible to synchronize with either the Cycle or the tuple of Cycle/MacrotickOffset to give the resolution of synchronization required by the application.

If Cycle only resolution is required then an OS Counter object should be configured to have a OsCounterMaxAllowedValue equal to the maximum number of Cycles. If Cycle/MacrotickOffset is required then an OS Counter object should be configured with a OsCounterMaxAllowedValue of the maximum number of Cycles multiplied by the MacrotickOffset. This provides the OS with a time base against which a ScheduleTable can be synchronized.

Synchronization between the OS and an external global time source is provided by telling the OS the global time through the SyncScheduleTable service call. This call takes a scalar parameter of TickType so to interface this to FlexRay's representation of time a small conversion needs to be done. The following example assumes a Cycle of 255 with 65535 Macroticks per Cycle. TickType is at least 24-bits wide.

```
#define OSTIME(x) (TickType)(x);

FrIf_GetGlobalTime(Controller, &Cycle, &Macrotick);

SyncScheduleTable(Tbl, ((OSTIME(Cycle)<<16)+(OSTIME(Macrotick))));
```

Telling the ScheduleTable that GlobalTime can be done when the application detects that the FlexRay controller has lost synchronization with the network (by polling the controller sync status). The following code indicates how this can be used to force an associated ScheduleTable into the SCHEDULETABLE_RUNNING state from the SCHEDULETABLE_RUNNING_AND_SYNCHRONOUS state.

```
Fr_SyncStateType CurrentSyncStatus;

if (FrIf_GetSyncState(Controller, &CurrentSyncStatus) == E_OK) {

    if (CurrentSyncStatus == FR_ASYNC ) {
        SetScheduleTableAsync(Table);
    }

}
```

Of course, other actions are possible here, like stopping the ScheduleTable, as best fits user requirements.

12.6 Migration from OIL to XML

This version of the AUTOSAR OS specification does not directly support the configuration via OIL. The support for OIL was dropped in favour of XML because XML is the standard configuration language in AUTOSAR and is essential if configuration data has to be imported / exported from / to other AUTOSAR modules or between different tools during development.

Since OIL and XML are both ASCII formats a tool vendor may offer a possibility to import (old) OIL files and to store them as (AUTOSAR OS) XML files. Currently all known vendors support at least the import of existing OIL configurations.

Note that for showing conformance to the OSEK OS specification, each OSEK OS vendor must support OIL. This means that practically each AUTOSAR OS vendor will offer some sort of import of OIL configurations - at least to show the OSEK OS conformance.

12.7 Debug support

For the AUTOSAR OS the following information may be useful for users and should be considert for debug support (and may be published, e.g. in the BSWMD):

- General information about how to retrieve the current (active) `Task` or `ISR` and their (current) priority and (current) stack.
- For `ISR`s: Information about the name of interrupts, their mapping to the `ISR` identifier, the associated hardware and the used stack(s).
- For `Task`s: Information about the name of the `Task`, its identifier, the task state, the possible priorities, the event mask (if its an extended `Task`), the OS-Application to whom the `Task` belongs (if existant) and the used stack.
- For `Resource`s: Information about the name of the `Resource`, its mapping to the identifier, its priority and the current owner (the `Task`/`ISR` which currently holds the `Resource`)
- For `Alarm`s: Information about the name of the `Alarm`, its mapping to the identifier, the `Counter` to whom it belong, the action which is executed on expiry and the current state (running or stopped). In running state the next expiry in ticks and the possible cycle time shall be also published.
- For `Counter`s: Information about the name of the `Counter`, its mapping to the identifier, its associated alarms and the current counter value.
- For `SchduleTable`s: Information about the name of the `ScheduleTable`, its mapping to the identifier, its current state and the next expiry point (if the table is running).

- For OS-Applications: Information about the name of the OS-Application, its mapping to the identifier, its current state and the memory sections assigned to it (if memory protection is used).

ARTI implements mechanisms to retrieve the described information (see [8]).

User documentation should contain information about the implemeted debug features.

12.8 Integration hints for peripheral protection

Peripheral protection requires configuration on the core level usually conditioned by a supervisor access. For this reason the task of the peripheral protection is assigned to the OS module.

Peripheral protection may be implemented in two ways

- using MPU

- using dedicated peripheral protection units of the target MCU.

When using the memory protection unit, it is reasonable if two or more protected region descriptors are available for peripheral protection mechanism. The region descriptors shall be programmed to allow access to those peripherals the current OS-Application shall work with. The defined regions shall cover all memory mapped configuration registers for the periphiherals to be protected. The advantage of using the MPU is that the configuration is the same as for memory protection. One of the disadvantages of this method is that it could be impossilbe to cover all peripheral control registers with available MPU region descriptors. The number of such descriptors is typically low.

Beware that using this method may have implication to the linker file of the project software configuration.

Second method is using a dedicated register protection schema. This method shall allow to precisely select peripherals for every OS Application. However the number of peripherals may make the register protection implementation rather bulky. Therefore it is advisable to reduce the number of protected peripherals to a reasonable value.

For both methods the configuration shall be placed into custom OS Application properties. The configuration shall be active when a `Task` (or `ISR`) of a particular OS Application is running.

12.9 Termination of OS-Applications

Inconsistencies may occur when an `OsApplication` is terminated, depending on its state at the termination.

- A notification from an asynchronous job started before the termination of `OsApplication` can occur afterwards.

- An asynchronous memory read or write started before the termination of OsApplication can occur afterwards and may cause data inconsistency.
- A requested mode or state to another OsApplication (e.g. from a SW-C to A BSW) can lead to unsynchronized state machines.

Therefore special care needs to be taken by developers to avoid such inconsistencies and guaranty a correct behavior. This is especially true if an OS-Application is forcible terminated.

13 AUTOSAR Service implemented by the OS

13.1 Scope of this Chapter

This chapter is an addition to the specification of the Operating System. Whereas the other parts of the specification define the behavior and the C-interfaces of the OS module, this chapter formally specifies the corresponding AUTOSAR Service in terms of the SWC Template. The interfaces described here will be visible on the VFB and are used by the RTE generator to create the glue code between the application software (SWC) and the OS.

13.1.1 Package

The following definitions are interpreted to be in

`ARPackage AUTOSAR/Services/Os`

13.2 Overview

The AUTOSAR Operating System is normally not used directly by SWCs. Even the other BSW modules which are below the RTE are using the BSW Scheduler to have access to OS services. The BSW Scheduler of course uses the OS to implement its features, e.g. critical sections.

Nevertheless there is one case where it makes sense to allow SWCs access to services of the OS:

- Timer services

Since the number of timers in an ECU is limited it make sense to share these units across several SWCs. The functionality of the timer services of the OS which are offered to the SWCs are:

- A service to get the current value of a - hardware or software - `Counter`
- A service which calculates the time difference between the current timer value and a given (previouls read) timer value
- Both services will return real time values instead of ticks. This limits the access to the services to those counters which are counting time. Other counters e.g. counting errors or angles are not accessible.

13.3 Specification of the Ports and Port Interfaces

The detailed port interface can be found in chapter 8.8.

The notation of possible error codes resulting from server calls follows the approach in the meta-model. It is a matter of the RTE specification [9], how those error codes will be passed via the actual API.

14 Outlook on Memory Protection Configuration

As stated before, memory protection configuration is not standardized yet. Nevertheless it seems helpful to contribute a recommendation in this chapter, how the configuration might work.

14.1 Configuration Approach

Both, SW-Components and BSW modules, map code and variables to dedicated, disjoined memory sections (see meta-class *ObjectFileSection* in chapter 7.3 of *Software Component Template* [[10]], Version 2.0.1, and *module specific sections* in chapter 8.2 of *Specification of Memory Mapping* [[11]], Version 1.0.1).

This essential precondition (avoid an inseparable conglomeration of variables in the default section) can be used to support configuration of memory protection domains:

- The generator can save for each OS-Application a (processor-specific) maximum number of output sections for data in a file (to be used in the linker file).
- The generator can uniquely identify the address spaces of the data output sections with symbols using the naming convention (see *memory allocation keywords* `_STOP_SEC_VAR` and `_START_SEC_VAR` for start and stop symbols) in the specification mentioned above.

The input data sections in the object files of an OS-Application can then be assigned to the output sections (with potential tool support). Usually, this is one segment for global data, and one segment for code.

To archieve portability, the user shall group all variables belonging to a private data section (`Task`/`ISR` or OS-Application) in separate files.

A Not applicable requirements

[SWS_Os_NA_00767]

Upstream requirements: SRS_BSW_00344, SRS_BSW_00404, SRS_BSW_00405, SRS_BSW_00170, SRS_BSW_00419, SRS_BSW_00383, SRS_BSW_00384, SRS_BSW_00375, SRS_BSW_00406, SRS_BSW_00168, SRS_BSW_00407, SRS_BSW_00423, SRS_BSW_00337, SRS_BSW_00369, SRS_BSW_00339, SRS_BSW_00422, SRS_BSW_00417, SRS_BSW_00409, SRS_BSW_00385, SRS_BSW_00386, SRS_BSW_00437, SRS_BSW_00388, SRS_BSW_00389, SRS_BSW_00390, SRS_BSW_00392, SRS_BSW_00393, SRS_BSW_00394, SRS_BSW_00395, SRS_BSW_00396, SRS_BSW_00399, SRS_BSW_00403, SRS_BSW_00416, SRS_BSW_00425, SRS_BSW_00432, SRS_BSW_00452, SRS_BSW_00458, SRS_BSW_00461, SRS_BSW_00466, SRS_BSW_00469, SRS_BSW_00470, SRS_BSW_00471, SRS_BSW_00472, SRS_BSW_00478, SRS_BSW_00490, SRS_BSW_00492, RS_Arti_00008, RS_Arti_00025, RS_Arti_00039, RS_Arti_00040, RS_Arti_00041, RS_Arti_00042, RS_Arti_04085, RS_Arti_04086, RS_Arti_04087, RS_Arti_04089, RS_Arti_04090, RS_Arti_04101, RS_Arti_04143, RS_Arti_04145, RS_Arti_00038, RS_Arti_00028, RS_Arti_00035, RS_Arti_00036, RS_Arti_00037

⌈These requirements are not applicable to this specification.⌋

B History of Constraints and Specification Items

B.1 Differences between R23-11 and R24-11

B.1.1 Added Specification Items in R24-11

[ECUC_Arti_00182] [ECUC_Arti_00183] [ECUC_Arti_00184] [ECUC_Arti_00185] [ECUC_Arti_00186] [ECUC_Arti_00187] [ECUC_Arti_00188] [ECUC_Arti_00189] [ECUC_Arti_00190] [ECUC_Arti_00191] [ECUC_Arti_00192] [ECUC_Arti_00193] [ECUC_Arti_00194] [ECUC_Arti_00195] [ECUC_Arti_00196] [ECUC_Arti_00197] [ECUC_Arti_00198] [ECUC_Arti_00199] [ECUC_Arti_00200] [ECUC_Arti_00201] [ECUC_Arti_00202] [ECUC_Arti_00203] [ECUC_Arti_00204] [ECUC_Arti_00211] [ECUC_Arti_00212] [ECUC_Arti_00213] [ECUC_Arti_00214] [ECUC_Arti_00224] [ECUC_Os_00410] [SWS_Os_00863] [SWS_Os_91028]

B.1.2 Changed Specification Items in R24-11

[ECUC_Arti_00071] [ECUC_Arti_00086] [ECUC_Arti_00090] [ECUC_Os_00044] [ECUC_Os_00114] [SWS_Os_00106] [SWS_Os_00244] [SWS_Os_00258] [SWS_Os_00287] [SWS_Os_00364] [SWS_Os_00467] [SWS_Os_00502] [SWS_Os_00506] [SWS_Os_00538] [SWS_Os_00563] [SWS_Os_00773] [SWS_Os_00784] [SWS_Os_00787] [SWS_Os_00788] [SWS_Os_91026]

B.1.3 Deleted Specification Items in R24-11

[ECUC_Os_00120] [SWS_Os_00111] [SWS_Os_00365] [SWS_Os_00459] [SWS_Os_00497] [SWS_Os_00498] [SWS_Os_00501] [SWS_Os_00503] [SWS_Os_00508] [SWS_Os_00547] [SWS_Os_00548] [SWS_Os_00555] [SWS_Os_00557] [SWS_Os_00564] [SWS_Os_91029]

B.1.4 Added Constraints in R24-11

none

B.1.5 Changed Constraints in R24-11

none

B.1.6 Deleted Constraints in R24-11

none

B.2 Differences between R22-11 and R23-11

B.2.1 Added Specification Items in R23-11

[SWS_Os_00859] [SWS_Os_00860] [SWS_Os_00861] [SWS_Os_00862] [SWS_Os_91034]

B.2.2 Changed Specification Items in R23-11

[SWS_Os_00261] [SWS_Os_00287] [SWS_Os_00548] [SWS_Os_00566] [SWS_Os_00573] [SWS_Os_00675] [SWS_Os_00798] [SWS_Os_00820] [SWS_Os_00822] [SWS_Os_00826] [SWS_Os_91025]

B.2.3 Deleted Specification Items in R23-11

[SWS_Os_00821] [SWS_Os_00823]

B.2.4 Added Constraints in R23-11

[SWS_Os_CONSTR_00001] [SWS_Os_CONSTR_00002]

B.2.5 Changed Constraints in R23-11

none

B.2.6 Deleted Constraints in R23-11

none