

# The Internet of Things and Life beyond Linux

Embedded Linux Conference Europe 2016

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# Overview

- 1 Introduction
- 2 IoT vs. Linux: Conceptual Differences
- 3 IoT OSes: Properties
- 4 Development with RTEMS
  - Application Style
  - Building RTEMS systems
  - Example: Networked Appliance with Dynamic Language

# Outline

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# Introduction

## Target Audience

- Linux is your standard development target
- Your embedded boards come with Linux/Android
- Open Source is default choice
- “Standard embedded engineer”

## TA Check

- *Linux application development?*
- *Embedded Linux system development?*
- *Deeply embedded systems development?*

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# Internet of Things: What is it about?

## Internet of Things

- Wireless sensor networks, home control
- Ubiquitous connectivity
  - Novel communication approaches (non-IP mesh networks)
  - Not covered in this presentation
- 2020: 25-30 billion devices
- Hardware costs *extremely* important



# Hardware for IoT I

## Infinite Ressources

- Supermarket class smartphone: 2GiB RAM, 2-4 cores
- Raspberry Pi: 1GiB RAM, 4 cores

## Deeply Embedded: Cortex-M class

- NXP:  $\approx$  200 devices, TI:  $\approx$  400 devices
- On-Board memory, 100s of KiB
- Too large for bare metal programming, too small for Linux
- Available during the last 20 years
- Likely not going away any time soon

# Hardware for IoT II

	Networked Node	Embedded Cntrl.	Embedded Comp.	Embedded Server
ARM offerings	M0/M0+/M3/M4	M4/7,A9,R4/5/7	ARM A9/A35,R7	ARM A53/A72
Intel offerings	Quark MCU	Quark SoC	Atom	Core, Xeon
Architecture, clock	32-bit, <500 MHz	32-bit, <1 GHz	32/64-bit, <2 GHz	64-bit, >2 GHz
non-volatile storage	MiBs	GiBs	GiBs	TiBs
RAM	< 8 MiB	< 1 GiB	< 4 GiB	> 4 GiB
HW ref. platform	Arduino class board	RPI class board	SoC-FPGA (Zync,...)	Industrial PC
application examples	Sensor, field device	control systems	special purpose & server based controllers	
	PLC, IoT node		gateways	multi-purpose controllers

# Shrinking Linux?

## Network maintainer's point of view

*What parts would you remove to get the foot print down for a 2MB single purpose machine?*

I wouldn't use Linux, end of story.

Maybe two decades ago, but not now, those days are over.

(Response to net diet patch series)

## Alternatives

### Linux Weltanschauung

*“Linux has a lot more longevity and generality than most embedded OSes. Most such OSes are proprietary. All of them lack the range of capabilities, drivers, and general level of code quality and review found in Linux. Most have far smaller communities (or no communities at all).”*

[tiny.wiki.kernel.org/faq](http://tiny.wiki.kernel.org/faq)

## Weltanschauung and Veracity

- Many parts of Linux: Very high quality
- Tremendous complexity. Necessary?
- “Corner Cases” like real-time: Community?

## Consequences I

### Perception

*“A growing kernel makes it hard for the people who are trying to build tiny systems, forcing them to go to a proprietary real-time operating system instead.”*

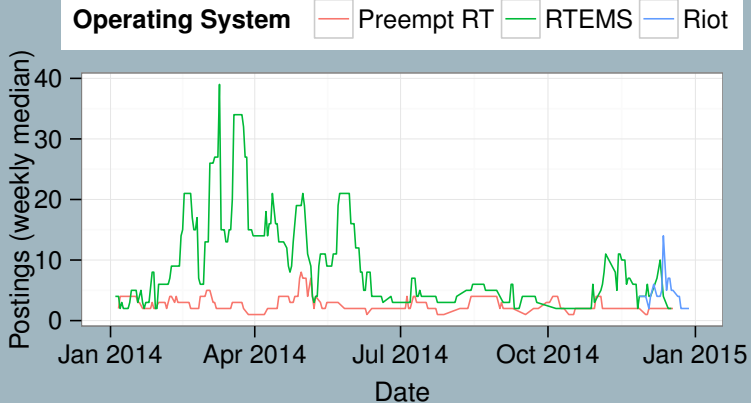
lwn.net

### Alternative RTOSes

- RTEMS, eCos, Contiki, RIOT, mbed, FreeRTOS, uclinux, threadX. . .
- ⟨Favourite proprietary OS⟩

## Consequences II

No communities at all?



■ Biased, naturally: Specific feature vs. complete OS

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# $\Delta$ (IoT, Linux): Address Spaces & Execution

Kernel+User//Syscalls//Threads vs. processes//Stacks

# $\Delta$ (IoT, Linux): Scheduling

RT scheduling//determinism//scheduling choices//pre-computed schedules//time vs. event based

# $\Delta$ (IoT, Linux): Building Appliances

App packaging//highly configurable kernels

## IoT vs. Linux: Legal Caveats

### IoT vs. Linux: Legal Caveats

- Linux: Transition Kernel  $\Leftrightarrow$  Userland: *license barrier*
- IoT: Kernel + “Userland” in single address space
- Code (statically) linked together
- Some licenses: Implications on payload code, up to inheriting OS license!

# IoT vs. Linux: Commonalities


























## IoT and Linux: Commonalities

- Toolchain (Cross Building), Build System, Version Control
- Debugging Mechanisms
- Standard C/C++ programming techniques
- Non-system libraries: Custom API
  - POSIX is overrated!
  - IoT system libraries: Yet another library. . .

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# High-Level Comparison

System	POSIX	Maturity	VM	Archs	Drivers	Ressources	Docs
FreeRTOS	✗		✓				
RTEMS	✓		✗				
<i>μ</i> clinux	✓		✗				
mbed	✗		✗				
Zephyr	✗		✗				

# RTEMS

## RTEMS – Real-Time Executive for Multiprocessor Systems

- Extensive support for CPU architectures
- Comprehensive board support
- Commercial Vendors involved in development
- POSIX/Berkeley sockets support
- FreeBSD and LWIP networking stacks
- MPU, but no MMU support



- `www.rtems.org`
- $\approx 250\text{KiB}$



# FreeRTOS

## FreeRTOS

- Virtual address space support
- Dynamic task creation
- Very small community
- Multiple TCP/IP stacks; Berkeley sockets API



- `www.freertos.org`
- A few KiB onwards

# mbed

## mbed

- Restricted to ARM targets (Cortex-M)
- Ease of use for (first-time) developers:  
Web-based dev environment
- Very easy deployment of applications (w/  
suitable HW)
  - Upload binary to mass storage device
  - HW target support required (mbed HDK)
- High level C++ SDK

ARM<sup>®</sup>mbed<sup>™</sup>

- [www.mbed.org](http://www.mbed.org)
- ≈ 512 KiB

# Zephyr

## Zephyr

- Linux Foundation Community Project
- Build system and programming style very similar to Linux kernel
- Nano- and Microkernel with different APIs/capabilities
  - Nanokernel: Single task + ISR + fibres (non-preemptive; cooperative multitasking)
  - Microkernel: Multiple tasks (+ ISR + fibres); preemptive multitasking

**ARM**<sup>®</sup>mbed™

- `www.zephyrproject.org`
- A few KiB onwards

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# RTEMS example application I

```
#include <stdio.h>
#include <stdlib.h>

void *POSIX_Init(
    void *argument
)
{
    print("Hello ,_world");
    exit(0);
}

/* configuration information */

#include <bsp.h>

#define CONFIGURE_APPLICATION_NEEDS_CONSOLE_DRIVER

#define CONFIGURE_POSIX_INIT_THREAD_TABLE
#define CONFIGURE_MAXIMUM_POSIX_THREADS 1

#define CONFIGURE_INIT
#include <rtems/confdefs.h>
```

# Building RTEMS systems

## Building a complete *system*

- 1 Download sources (links: see published slides)
- 2 Define target environment
- 3 Define build environment details

## Technical Details

```
wget http://url/of/component.tar.bz2
```

# Building RTEMS systems

## Building a complete *system*

- 1 Download sources (links: see published slides)
- 2 Define target environment
- 3 Define build environment details

## Technical Details

```
export ARCH=arm
export BSP=raspberrypi
```

# Building RTEMS systems

## Building a complete *system*

- 1 Download sources (links: see published slides)
- 2 Define target environment
- 3 Define build environment details

## Technical Details

```
export ARCH=arm
export BSP=stm32f4
```



# Building RTEMS systems

## Building a complete *system*

- 1 Download sources (links: see published slides)
- 2 Define target environment
- 3 Define build environment details

## Technical Details

```
export ARCH=i386  
export BSP=pc386
```

# Building RTEMS systems

## Building a complete *system*

- 1 Download sources (links: see published slides)
- 2 Define target environment
- 3 Define build environment details

## Technical Details

```
export TARGET=${ARCH}-rtems4.11
export TOOLDIR=${HOME}/rtems-bin
export JOBS=8
export PATH=${TOOLDIR}/bin:${PATH}
export RTEMS_MAKEFILE_PATH=\
    ${TOOLDIR}/rtems/bsps/4.11/${ARCH}-rtems4.11/${BSP}
export RTEMS_ROOT=${TOOLDIR}/rtems/bsps/4.11/share/rtems4.11/
```

# Building RTEMS systems

## Building a complete *system*

- 1 Build binutils
- 2 Build the initial C compiler/standard C library/final C compiler
- 3 Build the RTEMS kernel

## Technical Details

```
mkdir binutils-build; cd binutils-build
../binutils-version/configure --target=${TARGET} \
                             --prefix=${TOOLDIR}
make -j${JOBS} && make install
```

# Building RTEMS systems

## Building a complete *system*

- 1 Build binutils
- 2 Build the initial C compiler/standard C library/final C compiler
- 3 Build the RTEMS kernel

## Technical Details

```
mkdir gcc-build; cd gcc-build
../gcc-4.9.1/configure --target=${TARGET} --without-headers \  
                    --with-gnu-as --with-newlib \  
                    --enable-threads --prefix=${TOOLDIR} \  
                    --enable-languages="c,c++"
make all-gcc -j${JOBS} && make install-gcc
```

# Building RTEMS systems

## Building a complete *system*

- 1 Build binutils
- 2 Build the initial C compiler/standard C library/final C compiler
- 3 Build the RTEMS kernel

## Technical Details

```
mkdir newlib-build; cd newlib-build  
../newlib/configure --target=${TARGET} --prefix=${TOOLDIR}  
make -j${JOBS} && make install
```

# Building RTEMS systems

## Building a complete *system*

- 1 Build binutils
- 2 Build the initial C compiler/standard C library/final C compiler
- 3 Build the RTEMS kernel

## Technical Details

```
cd gccbuild
../gcc-4.9.1/configure --target=${TARGET} --with-gnu-as \
                      --with-newlib --enable-threads \
                      --enable-languages="c,c++" \
                      --prefix=${TOOLDIR}
make -j${JOBS} && make install
```

# Building RTEMS systems

## Building a complete *system*

- 1 Build binutils
- 2 Build the initial C compiler/standard C library/final C compiler
- 3 Build the RTEMS kernel

## Technical Details

```
cd rtems; ./bootstrap
cd ../; mkdir rtems-build; cd rtems-build
../rtems/configure --target=${ARCH}-rtems4.11 \
                  --enable-rtemsbsp=${BSP} \
                  --enable-networking --enable-posix \
                  --prefix=${TOOLDIR}/rtems/bsps/4.11
make && make install
```

## Building the payload application

### Building the payload application

- Collect application sources (libraries: separate build, of course)
- Makefile templates: `rtems/make/Template`
- Build process delivers binaries in `o-optimized/`
  - `file.exe`: ELF executable. Symbol information, sections etc.
  - `file.ralf`: *RTEMS Application Loadable File*. “Core dump” of the binary. (`≈ objdump -O binary`) – execute on *raw* hardware (debugger, flash tool, bootloader)



## Running pc386 inside qemu

### System in emulated machine

```
qemu-system-i386 -no-reboot -serial stdio -monitor null \  
-nographic -m 2 \  
-append "--console=com1" \  
-s -kernel file.exe
```

## Running pc386 inside qemu

### System in emulated machine + debugging

```
qemu-system-i386 -no-reboot -serial stdio -monitor null \  
    -nographic -m 2 \  
    -append "--console=com1" \  
    -s -kernel file.exe
```

- gdb file.elf
- (gdb) target remote localhost:1234
- ...as easy as debugging a simple Linux userland application

## Running pc386 inside qemu

### System in emulated machine + debugging + networking

```
qemu-system-i386 -no-reboot -serial stdio -monitor null \  
-nographic -m 4 \  
-append "--console=com1 --ne2k-irq=9" \  
-device ne2k.isa,netdev=usernet \  
-netdev user,id=usernet \  
-redir tcp:24742::24742 \  
-s -kernel file.exe
```

## Networked appliance with dynamic language

### Requirements

- Payload: No deeply embedded experts required
  - Port lua to device (essentially: adapt `Makefile`)
  - Run standard C applications (RT etc.) in parallel
- Standard networking (configuration option!)
- Linux-like interactive development
- Works well with  $\approx 0.5$  MiB of RAM
- See link in published slides

# Thanks for your interest!