

embOS

Real-Time Operating System

CPU & Compiler specifics for
Renesas RX using Renesas
CCRX compiler and e2Studio

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Manual versions

This manual describes the current software version. If you find an error in the manual or a problem in the software, please inform us and we will try to assist you as soon as possible. Contact us for further information on topics or functions that are not yet documented.

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Software	Revision	Date	By	Description
5.18.0.0	0	230327	MC	New software version.
5.16.1.0	0	220310	MM	New software version.
5.14.0.0	0	210805	MM	New software version.
5.12.0.0	0	201014	MM	New software version.
5.10.2.0	0	200921	MM	New software version.
5.06	0	190918	TS	New software version.
5.02a	0	180719	TS	New software version.
4.24	0	160808	RH	Chapter "SEGGER RTT and SystemView" added.
4.16	0	160226	RH	General manual update.
4.12	0	150826	TS	New software version.
4.10a	0	150519	TS	New software version.
4.06b	0	150326	SC	New software version.
4.02a	0	141103	TS	New software version.
4.00	0	140702	TS	New software version and RXv2 library description added.
3.88	0	130320	AW	Description of e2studio project added.

About this document

Assumptions

This document assumes that you already have a solid knowledge of the following:

- The software tools used for building your application (assembler, linker, C compiler).
- The C programming language.
- The target processor.
- DOS command line.

If you feel that your knowledge of C is not sufficient, we recommend "C: A Reference Manual by Harbison and Steele" (ISBN 0--13--089592X). This book provides a complete description of the C language, the run-time libraries, and a style of C programming that emphasizes correctness, portability, and maintainability.

How to use this manual

This manual explains all the functions and macros that the product offers. It assumes you have a working knowledge of the C language. Knowledge of assembly programming is not required.

Typographic conventions for syntax

This manual uses the following typographic conventions:

Style	Used for
Body	Body text.
Keyword	Text that you enter at the command prompt or that appears on the display (that is system functions, file- or pathnames).
<i>Parameter</i>	Parameters in API functions.
Sample	Sample code in program examples.
<i>Sample comment</i>	Comments in program examples.
<i>Reference</i>	Reference to chapters, sections, tables and figures or other documents.
GUIElement	Buttons, dialog boxes, menu names, menu commands.
Emphasis	Very important sections.

Table of contents

1	Using embOS	9
1.1	Installation	10
1.2	Using Renesas e2 studio	11
1.3	First Steps	13
1.4	The example application OS_StartLEDBlink.c	14
1.5	Stepping through the sample application	15
2	Build your own application	19
2.1	Introduction	20
2.2	Required files for an embOS	20
2.3	Change library mode	20
2.4	Select another CPU	20
3	Libraries	21
3.1	Naming conventions for prebuilt libraries	22
4	CPU and compiler specifics	23
4.1	Memory models	24
5	Stacks	25
5.1	Stack pointers	26
5.2	Task stack	26
5.3	System stack	26
5.4	Interrupt stack	26
6	Interrupts	27
6.1	What happens when an interrupt occurs?	28
6.2	Defining interrupt handlers in C	28
6.3	Interrupt priorities	29
6.4	Interrupt handling	29
6.4.1	API functions	29
6.4.1.1	OS_INT_SetPriorityThreshold()	30
6.4.2	Zero latency interrupts	30
6.4.3	embOS interrupts	30
6.5	Interrupt nesting	32
6.6	Interrupt-stack switching	32
6.7	Fast interrupt, RX specific	32
6.8	Non maskable interrupt, NMI	32

6.9	Using Register Bank Save Function with RXv3 core	32
7	RTT and SystemView	34
7.1	SEGGER Real Time Transfer	35
7.2	SEGGER SystemView	35
8	Technical data	36
8.1	Resource Usage	37

Chapter 1

Using embOS

1.1 Installation

This chapter describes how to start with embOS. You should follow these steps to become familiar with embOS.

embOS is shipped as a zip-file in electronic form.

To install it, proceed as follows:

Extract the zip-file to any folder of your choice, preserving the directory structure of this file. Keep all files in their respective sub directories. Make sure the files are not read only after copying.

Note

The BSP projects at `/Start/BoardSupport/<DeviceManufacturer>/<Device>` assume that the `/Start/Lib` and `/Start/Inc` folders are located relative to the BSP folder. If you copy a BSP folder to another location, you will need to adjust these paths in the project.

Assuming that you are using an IDE to develop your application, no further installation steps are required. You will find many prepared sample start projects, which you should use and modify to write your application. So follow the instructions of section *First Steps* on page 13.

You should do this even if you do not intend to use the IDE for your application development to become familiar with embOS.

If you do not or do not want to work with the IDE, you should: Copy either all or only the library-file that you need to your work-directory. The advantage is that when switching to an updated version of embOS later in a project, you do not affect older projects that use embOS, too. embOS does in no way rely on an IDE, it may be used without the IDE using batch files or a make utility without any problem.

1.2 Using Renesas e2 studio

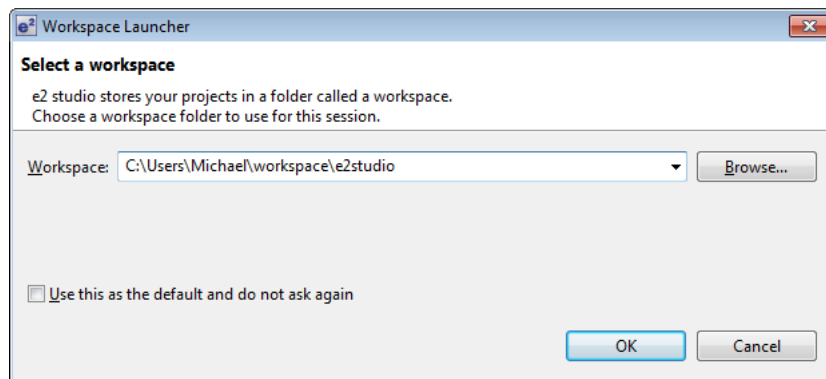
The start projects are based on e2 studio and include the necessary project files for Renesas e2 studio.

To get your new application running, you should proceed as follows:

- Create a work directory for your application, for example `C:\embOS`
- Copy the whole folder `Start` which is part of your embOS distribution into your work directory.
- Start Renesas e2 studio and select and create a workspace.
- Import the sample start project into the workspace.
- Build the start project
- Run the application using e2 studio HardwareDebug configuration using the E1 emulator for downloading and debugging.

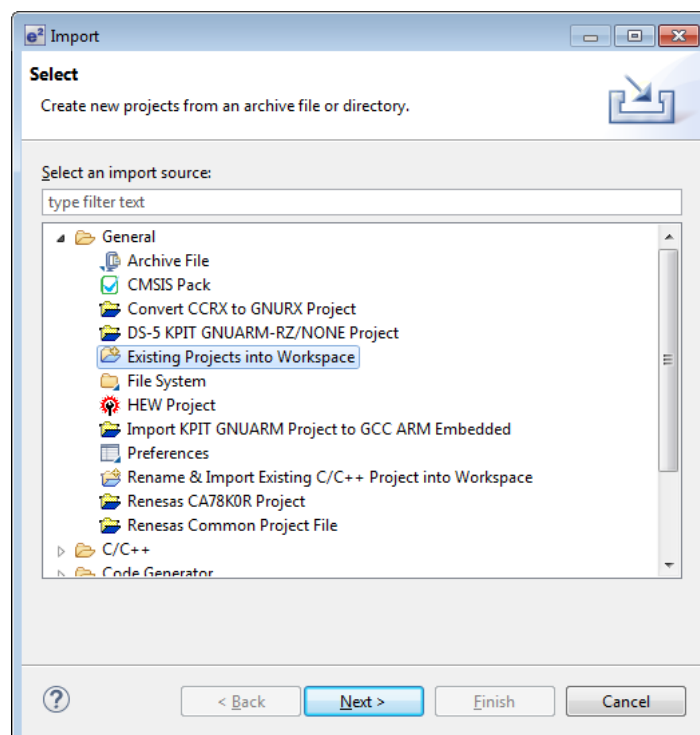
Start Renesas e2 studio and in the Workspace Launcher click `Browse...` to select the workspace. If the Workspace Launcher is not shown on startup, select it by menu `File -> Switch Workspace`.

Select the workspace directory `C:\workspace` or any other folder of your choice:



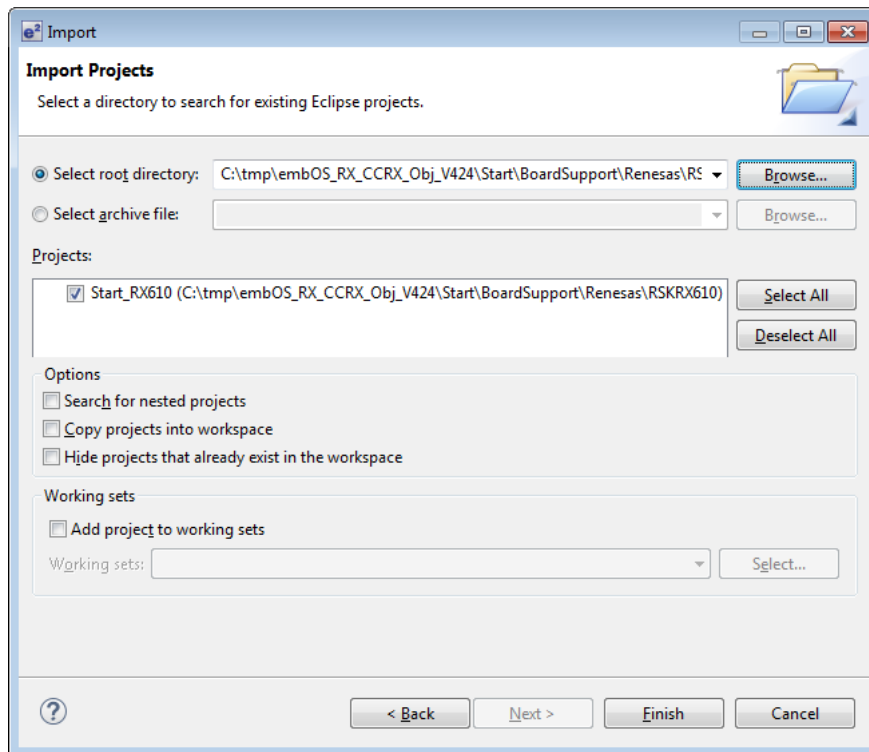
The workspace will then be created in the selected folder.

Now import the sample start project from one board support folder. Choose menu `File -> Import` and in the Import dialog select `General -> Existing Projects into Workspace`.



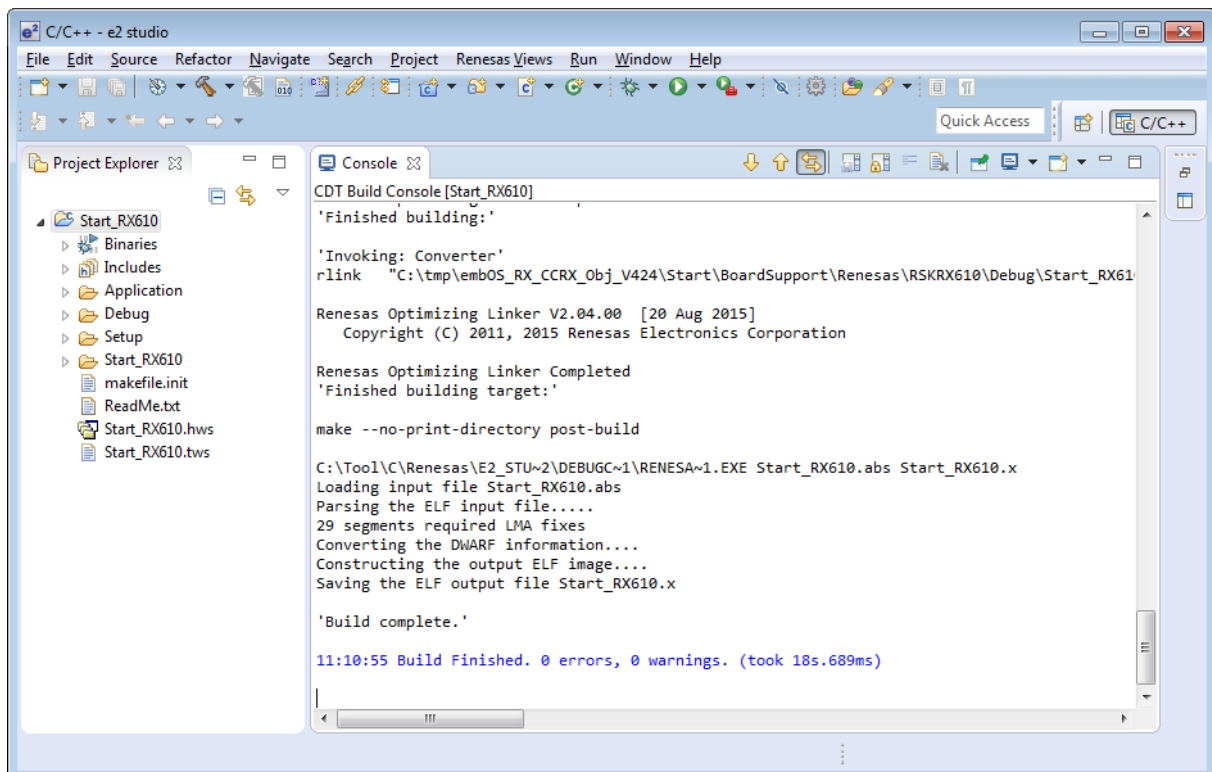
Press Next, the Import Projects dialog shows up.

Press Browse... and select Start\BoardSupport\ or any project subfolder as the root directory for the project to import:



Do **not** select the Copy projects into workspace option.

Refresh the project and build it:



For latest information you may read the ReadMe.txt file which is part of every start project.

1.3 First Steps

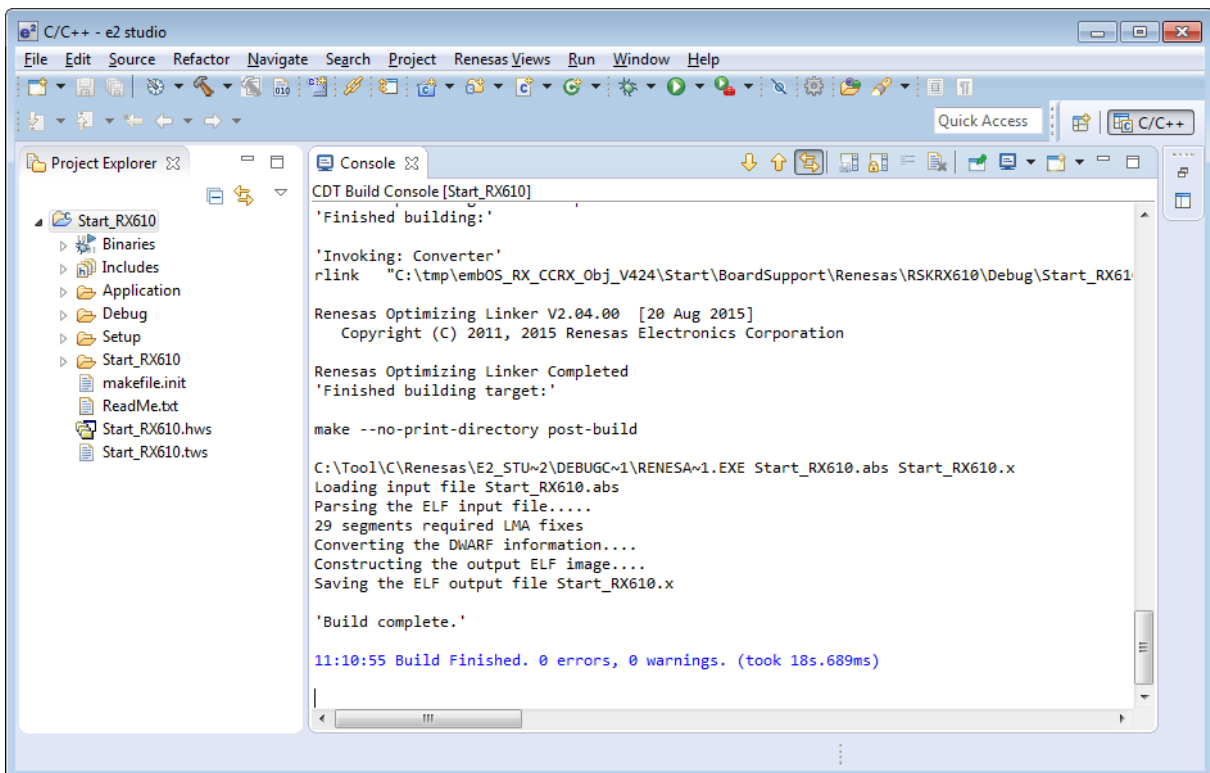
After installation of embOS you can create your first multitasking application. You have received several ready to go sample start workspaces and projects and every other files needed in the subfolder `Start`. It is a good idea to use one of them as a starting point for all of your applications. The subfolder `BoardSupport` contains the workspaces and projects which are located in manufacturer- and CPU-specific subfolders.

To start with, you may use any project from `BoardSupport` subfolder.

To get your new application running, you should proceed as follows:

- Create a work directory for your application, for example `c:\work`.
- Copy the whole folder `Start` which is part of your embOS distribution into your work directory.
- Clear the read-only attribute of all files in the new `Start` folder.
- Open one sample workspace/project in `Start\BoardSupport\<DeviceManufacturer>\<CPU>` with your IDE (for example, by double clicking it).
- Build the project. It should be built without any error or warning messages.

After generating the project of your choice, the screen should look like this:



For additional information you should open the `ReadMe.txt` file which is part of every specific project. The `ReadMe` file describes the different configurations of the project and gives additional information about specific hardware settings of the supported eval boards, if required.

1.4 The example application OS_StartLEDBlink.c

The following is a printout of the example application OS_StartLEDBlink.c. It is a good starting point for your application. (Note that the file actually shipped with your port of embOS may look slightly different from this one.)

What happens is easy to see:

After initialization of embOS two tasks are created and started. The two tasks are activated and execute until they run into the delay, then suspend for the specified time and continue execution.

```

/*****
*                               SEGGER Microcontroller GmbH                               *
*                               The Embedded Experts                                   *
*****/

----- END-OF-HEADER -----
File      : OS_StartLEDBlink.c
Purpose   : embOS sample program running two simple tasks, each toggling
            a LED of the target hardware (as configured in BSP.c).
*/

#include "RTOS.h"
#include "BSP.h"

static OS_STACKPTR int StackHP[128], StackLP[128]; // Task stacks
static OS_TASK      TCBHP, TCBLP;                 // Task control blocks

static void HPTask(void) {
    while (1) {
        BSP_ToggleLED(0);
        OS_TASK_Delay(50);
    }
}

static void LPTask(void) {
    while (1) {
        BSP_ToggleLED(1);
        OS_TASK_Delay(200);
    }
}

/*****
*
*      main()
*/
int main(void) {
    OS_Init(); // Initialize embOS
    OS_Inithw(); // Initialize required hardware
    BSP_Init(); // Initialize LED ports
    OS_TASK_CREATE(&TCBHP, "HP Task", 100, HPTask, StackHP);
    OS_TASK_CREATE(&TCBLP, "LP Task", 50, LPTask, StackLP);
    OS_Start(); // Start embOS
    return 0;
}

/***** End of file *****/

```

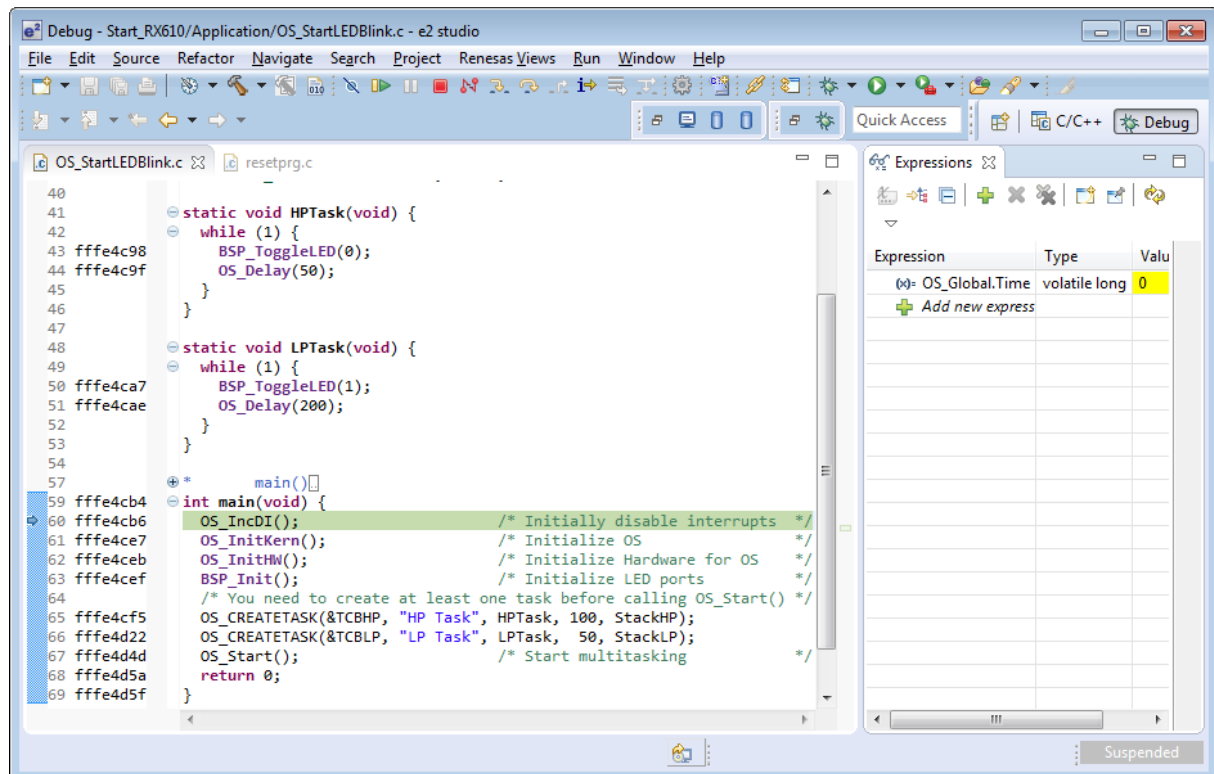
1.5 Stepping through the sample application

When starting the debugger, you will see the `main()` function (see example screenshot below). The `main()` function appears as long as project option `Run to main` is selected, which it is enabled by default. Now you can step through the program.

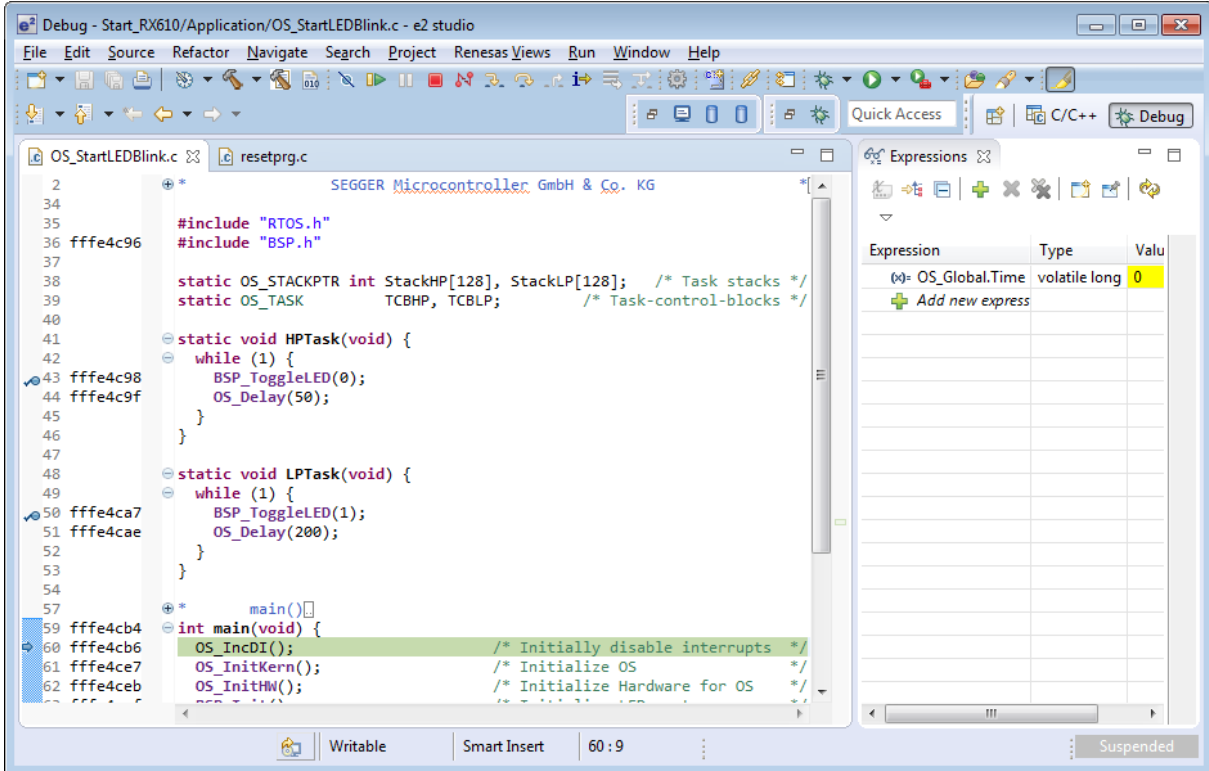
`OS_Init()` is part of the `embOS` library and written in assembler; you can therefore only step into it in disassembly mode. It initializes the relevant OS variables.

`OS_InitHW()` is part of `RTOSInit.c` and therefore part of your application. Its primary purpose is to initialize the hardware required to generate the system tick interrupt for `embOS`. Step through it to see what is done.

`OS_Start()` should be the last line in `main()`, because it starts multitasking and does not return.

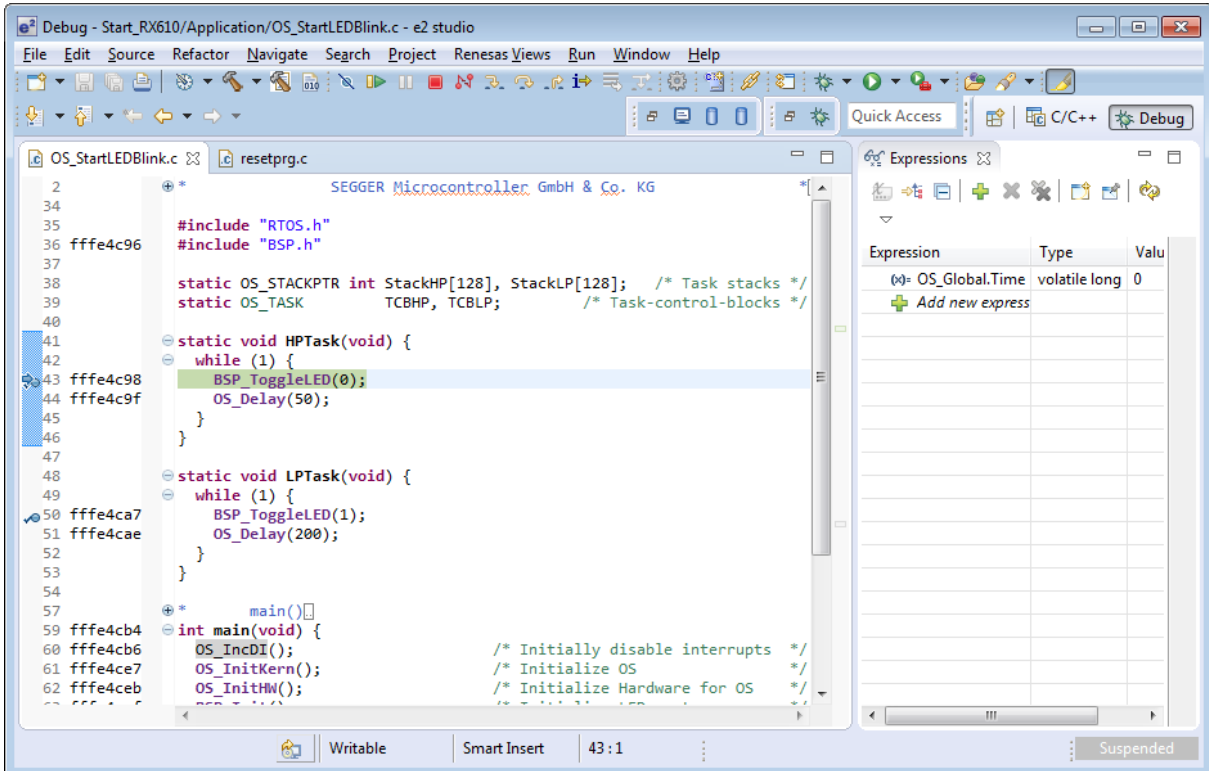


Before you step into `OS_Start()`, you should set two breakpoints in the two tasks as shown below.

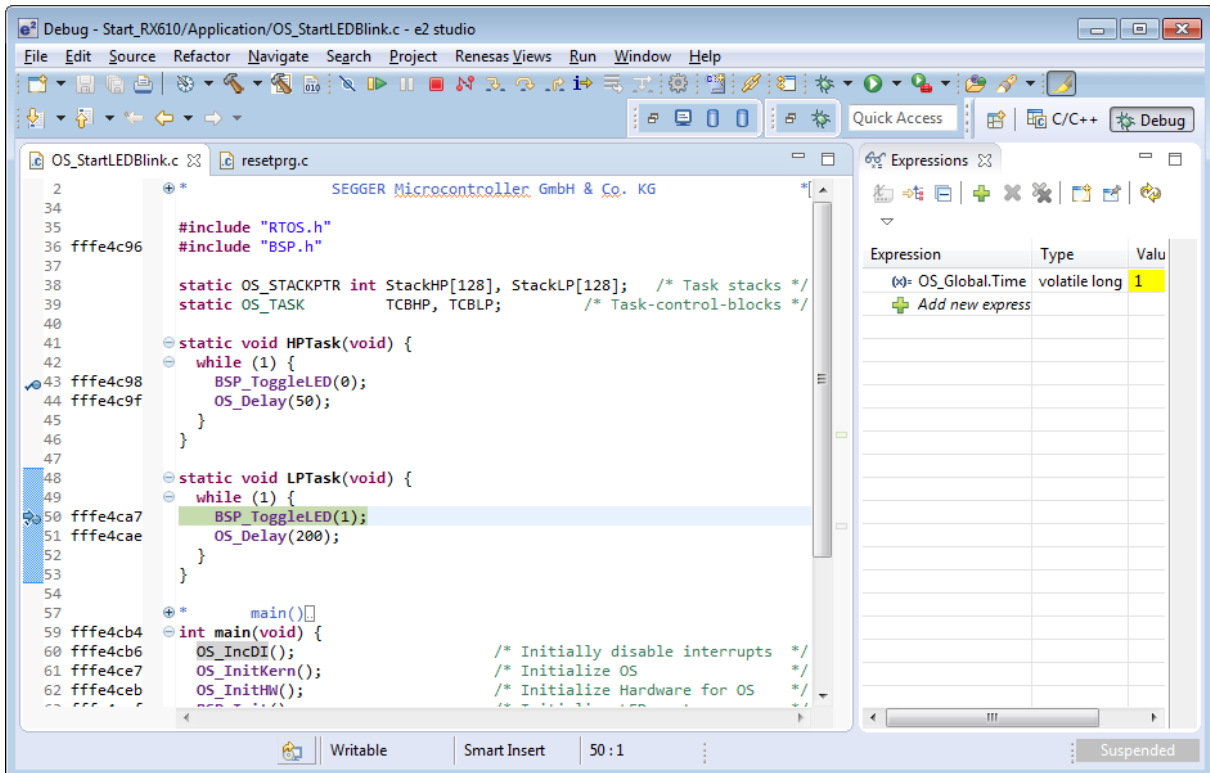


As `OS_Start()` is part of the embOS library, you can step through it in disassembly mode only.

Click GO, step over `OS_Start()`, or step into `OS_Start()` in disassembly mode until you reach the highest priority task.

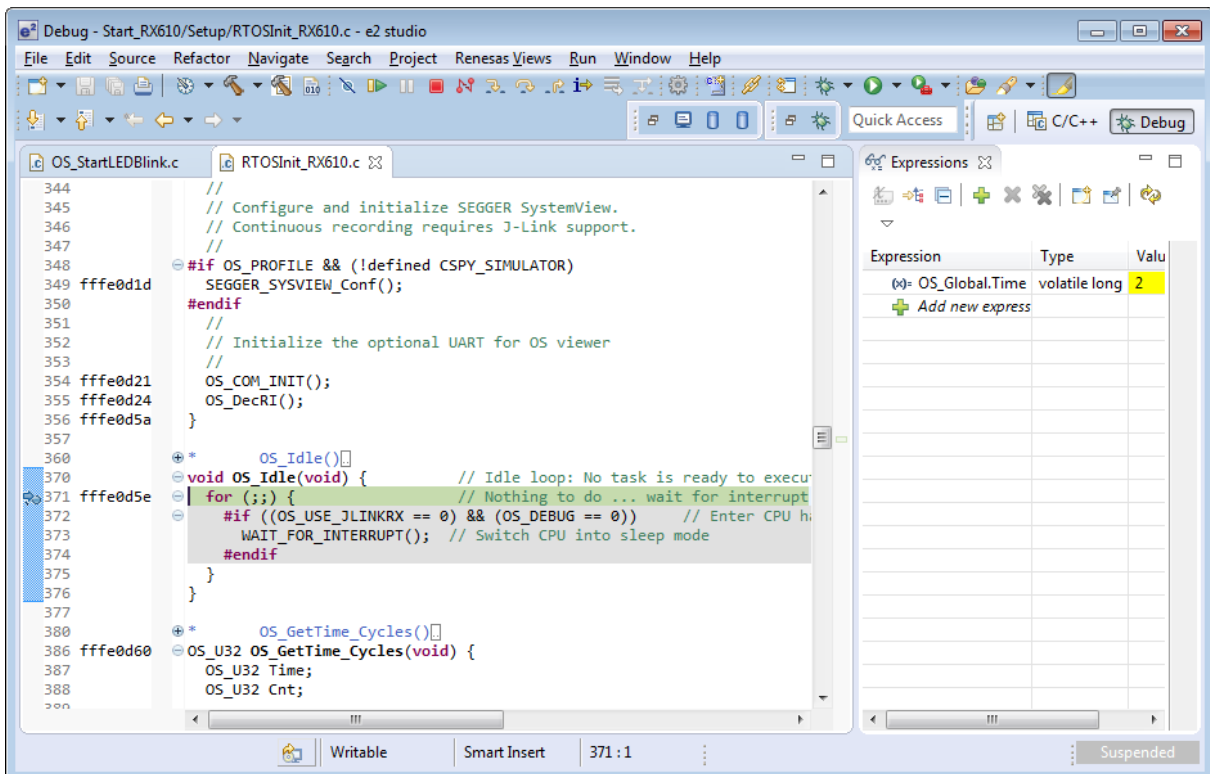


If you continue stepping, you will arrive at the task that has lower priority:



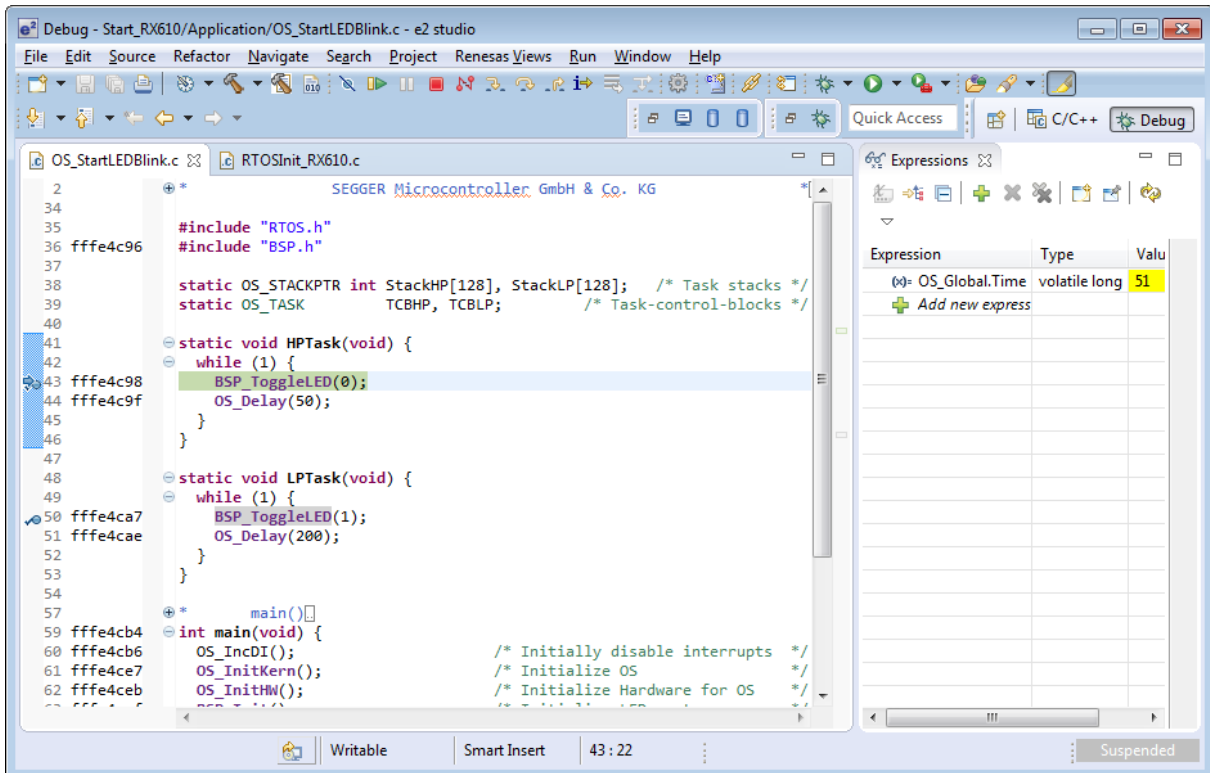
Continue to step through the program, there is no other task ready for execution. embOS will therefore start the idle-loop, which is an endless loop always executed if there is nothing else to do (no task is ready, no interrupt routine or timer executing).

You will arrive there when you step into the `OS_Task_Delay()` function in disassembly mode. `OS_Idle()` is part of `RTOSInit.c`. You may also set a breakpoint there before stepping over the delay in `LPTask()`.



If you set a breakpoint in one or both of our tasks, you will see that they continue execution after the given delay.

As can be seen by the value of embOS timer variable `OS_Global.Time`, shown in the Watch window, `HPTask()` continues operation after expiration of the delay.



Chapter 2

Build your own application

2.1 Introduction

This chapter provides all information to set up your own embOS project. To build your own application, you should always start with one of the supplied sample workspaces and projects. Therefore, select an embOS workspace as described in chapter *First Steps* on page 13 and modify the project to fit your needs. Using an embOS start project as starting point has the advantage that all necessary files are included and all settings for the project are already done.

2.2 Required files for an embOS

To build an application using embOS, the following files from your embOS distribution are required and have to be included in your project:

- **RTOS.h** from the directory `.\Start\Inc`. This header file declares all embOS API functions and data types and has to be included in any source file using embOS functions.
- **RTOSInit*.c** from one target specific `.\Start\BoardSupport\ subfolder. It contains hardware-dependent initialization code for embOS. It initializes the system timer interrupt but can also initialize or set up the interrupt controller, clocks and PLLs, the memory protection unit and its translation table, caches and so on.`
- **OS_Error.c** from one target specific subfolder `.\Start\BoardSupport\. The error handler is used only if a debug library is used in your project.`
- One **embOS library** from the subfolder `.\Start\Lib`.
- Additional CPU and compiler specific files may be required according to CPU.

When you decide to write your own startup code or use a low level `init()` function, ensure that non-initialized variables are initialized with zero, according to C standard. This is required for some embOS internal variables. Your `main()` function has to initialize embOS by calling `OS_Init()` and `OS_InitHW()` prior to any other embOS functions that are called.

2.3 Change library mode

For your application you might want to choose another library. For debugging and program development you should always use an embOS debug library. For your final application you may wish to use an embOS release library or a stack check library.

Therefore you have to select or replace the embOS library in your project or target:

- If your selected library is already available in your project, just select the appropriate project configuration.
- To add a library, you may add the library to the existing Lib group. Exclude all other libraries from your build, delete unused libraries or remove them from the configuration.
- Check and set the appropriate `OS_LIBMODE_*` define as preprocessor option and/or modify the `OS_Config.h` file accordingly.

2.4 Select another CPU

embOS contains CPU-specific code for various CPUs. Manufacturer- and CPU-specific sample start workspaces and projects are located in the subfolders of the `.\Start\BoardSupport` directory. To select a CPU which is already supported, just select the appropriate workspace from a CPU-specific folder.

If your CPU is currently not supported, examine all `RTOSInit.c` files in the CPU-specific subfolders and select one which almost fits your CPU. You may have to modify `OS_InitHW()`, the interrupt service routines for the embOS system tick timer and the low level initialization.

Chapter 3

Libraries

3.1 Naming conventions for prebuilt libraries

embOS is shipped with different pre-built libraries with different combinations of features. The libraries are named as follows:

```
Rtos<Architecture>_<Endianness><LibMode>.lib
```

Parameter	Meaning	Values
<code>Architecture</code>	Specifies the RX core.	Rx : RXv1 core Rxv2: RXv2 core Rxv3: RXv3 core
<code>Endianness</code>	Byte order	B : Big endian L : Little endian
<code>LibMode</code>	Specifies the library mode	XR : Extreme Release R : Release S : Stack check SP : Stack check + profiling D : Debug DP : Debug + profiling + stack check DT : Debug + profiling + stack check + trace

Example

`RtosRX_LDP.lib` is the library for an RX CPU, little endian mode with debug and profiling support.

Chapter 4

CPU and compiler specifics

4.1 Memory models

The Renesas CCRX compiler provides only one memory model.

Chapter 5

Stacks

5.1 Stack pointers

RX CPUs have two stack pointers, the user stack pointer (USP) and the interrupt stack pointer (ISP). The U-flag in the PSW register selects which stack pointer is used. During execution of tasks, software timers or the embOS scheduler, the U-flag is set and the USP is used. When an interrupt occurs, the U-flag is cleared and the ISP is used. On interrupt exit, the stack pointer is switched to the previous stack pointer.

5.2 Task stack

Each task uses its individual stack. The stack pointer is initialized and set every time a task is activated by the scheduler. The stack size required for a task is the sum of the used stack of all routines and the basic stack size.

The basic stack size is the size of memory required to store the registers of the CPU plus the stack size required by calling embOS routines. For the Renesas RX CPUs, the minimum basic task stack size is about 44 bytes. Because any function call uses some amount of stack, the task stack size has to be large enough to handle these calls. We recommend at least 128 bytes stack as a start.

5.3 System stack

The system stack is the stack that is used by embOS for the scheduler and software timers. When `OS_Init()` is called, embOS switches to the user stack pointer and uses its stack as the system stack. The minimum system stack size required by embOS is about 128 bytes (stack check & profiling build). However, since the system stack is also used by the application before the start of multitasking, and because software timers also use the system stack, the actual stack requirements depend on the application.

The size of the system stack can be configured with the `#pragma stacksize su` statement in the `stackset.h` file in the BSP specific `Setup\` folder. We recommend a minimum stack size of 256 bytes for the system stack.

5.4 Interrupt stack

Additional software stack switching in interrupts as for other CPUs is not necessary for the RX. If an interrupt occurs, the RX clears the U-flag and switches automatically to the ISP. The ISP is active during the entire ISR (interrupt service routine). This way, the interrupt does not use the stack of the task and the size of the task stack does not have to be increased for interrupt routines.

The size of the interrupt stack can be configured with the `#pragma stacksize si` statement in the `stackset.h` file in the CPU specific `Setup\` folder. We recommend at least a minimum of 256 bytes the interrupt stack.

Chapter 6

Interrupts

6.1 What happens when an interrupt occurs?

- The CPU receives an interrupt request.
- As soon as interrupts are enabled and the interrupt priority level (IPL) of the CPU is lower than the IPL of the interrupt, the interrupt is accepted.
- The CPU switches to the Interrupt stack.
- The CPU saves the PC and flag register on the interrupt stack.
- The CPU disables all further interrupts.
- The CPU sets its IPL to the IPL of the accepted interrupt.
- The CPU jumps to the address specified in the vector table for the interrupt service routine (ISR).
- ISR: Saves registers.
- ISR: User-defined functionality is executed.
- ISR: Restores registers.
- ISR: Executes RTE command, restoring PC, Flag register and switching back to the user stack.

For details, refer to the Renesas hard- and software manuals.

6.2 Defining interrupt handlers in C

Interrupt handlers for Renesas RX cores are written as normal C-functions which do not take parameters and do not return any value. Routines defined with the keyword `#pragma INTERRUPT` automatically save & restore the registers they modify and return with RTE.

For a detailed description on how to define an interrupt routine in "C", refer to the Renesas CCRX C-Compiler User's manual.

For details how to write interrupt handlers using embOS functions, refer to the embOS generic manual.

For details about interrupt priorities, refer to chapter *Interrupt priorities* on page 29.

Note

Interrupts that use embOS API must not specify `enable`, as this might lead to severe problems. If nestable interrupts are desired, then `OS_INT_EnterNestable()` can be used. This embOS API function ensures that interrupts are nestable. For zero latency interrupts `enable` can be used.

Example

Simple interrupt routine:

```
//  
// Interrupt handler NOT using embOS functions  
//  
#pragma INTERRUPT IntHandlerTimer(vect=104);  
void IntHandlerTimer(void) {  
    IntCnt++;  
}  
//  
// Interrupt function using embOS functions  
//  
#pragma interrupt (OS_ISR_Tick(vect=OS_TIMER_VECT))  
void OS_ISR_Tick(void) {  
    OS_INT_EnterNestable();  
    OS_TICK_Handle();  
    OS_INT_LeaveNestable();  
}
```

6.3 Interrupt priorities

RX CPUs can have up to 16 IPLs (interrupt priority levels) reaching from 0 to 15. While most RX CPUs have 16 priority levels implemented, the RX610 CPUs only support 8 priority levels from 0 to 7.

6.4 Interrupt handling

For the Renesas RX CPU embOS delivers following functions to handle interrupts.

6.4.1 API functions

Routine	Description	main	Task	ISR	SW Timer
<code>OS_INT_SetPriorityThreshold()</code>	Sets the interrupt priority limit for zero latency interrupts.	•	•	•	•

6.4.1.1 OS_INT_SetPriorityThreshold()

Description

Sets the interrupt priority limit for zero latency interrupts.

Prototype

```
void OS_INT_SetPriorityThreshold(OS_UINT Priority);
```

Parameters

Parameter	Description
Priority	The highest value usable as priority for embOS interrupts. All interrupts with higher priority are never disabled by embOS. Valid range: $1 \leq \text{Priority} \leq 7$ for RX610 CPUs. $1 \leq \text{Priority} \leq 15$ for other RX CPUs.

Additional information

The interrupt priority limit for zero latency interrupts is set to 4 by default. This means, all interrupts with higher priority than 4 (i.e. from 5 up to the maximum CPU specific priority) will never be disabled by embOS. To disable zero latency interrupts at all, the priority limit may be set to the highest interrupt priority supported by the CPU, which is 7 for the RX610 series and 15 for other RX CPUs.

To modify the default priority limit, `OS_INT_SetPriorityThreshold()` should be called before embOS was started. In the sample start projects, `OS_INT_SetPriorityThreshold()` is not called. The start projects use the default zero latency interrupt priority limit.

Any interrupts running above the zero latency interrupt priority limit must not call any embOS function.

Note that the maximum allowed parameter is device dependent. The function will not check whether the device specific limit is exceeded. It is the users responsibility not to use a value above 7 for CPUs which do not support more than 8 priority levels.

6.4.2 Zero latency interrupts

Instead of disabling interrupts when embOS enters a critical section, the processor's IPL is increased. This prevents the execution of interrupts with an IPL lower or equal to the current IPL of the processor. All interrupts with IPL higher than the IPL threshold that embOS uses to disable interrupt are called *zero latency interrupts*.

Zero latency interrupts are never disabled by embOS.

The IPL of the processor can be increased by calling `OS_INT_Disable()`, which sets the current IPL to the IPL threshold. Initially, the IPL threshold is set to 4, but may be modified during system initialization by a call of the function `OS_INT_SetPriorityThreshold()`. Therefore, by default all interrupts with IPL 5 and greater are zero latency interrupts and can still be processed. You must not execute any embOS function from within an interrupt running on high priority.

6.4.3 embOS interrupts

Any interrupt handler using embOS API functions has to run with IPLs from 1 to the current IPL threshold. These embOS interrupt handlers have to start with a call of `OS_INT_Enter()` or `OS_INT_EnterNestable()` and must end with a call of `OS_INT_Leave()` or `OS_INT_LeaveNestable()`. Interrupt handlers running at low priorities, i.e. with priorities from 1 to the current IPL threshold, which are not calling any embOS API function are allowed, but must not re-enable interrupts!

Note

The IPL threshold between embOS interrupts and zero latency interrupts is initially set to 4, but can be changed at runtime by a call to `OS_INT_SetPriorityThreshold()`.

6.5 Interrupt nesting

The Renesas RX CPU uses a priority controlled interrupt scheduling which allows preemption and nesting of interrupts. Interrupts and exceptions with a higher priority may preempt an interrupt handler with lower priority when interrupts are enabled during execution of the interrupt service routine.

An interrupt handler calling embOS functions has to start with a call of `OS_INT_Enter()` or `OS_INT_EnterNestable()` to inform embOS that an interrupt handler is running. Using `OS_INT_EnterNestable()` enables interrupts in the interrupt handler and thus allows nesting of interrupts.

6.6 Interrupt-stack switching

Since the RX CPUs have a separate stack pointer for interrupts, there is no need for explicit software stack-switching in an interrupt routine. The routines `OS_INT_EnterIntStack()` and `OS_INT_LeaveIntStack()` are supplied for source code compatibility to other processors only and have no functionality.

6.7 Fast interrupt, RX specific

The RX CPU supports a “Fast interrupt” mode which is described in the hardware manual. The fast interrupt may be used for special purposes, but must not call any embOS function.

6.8 Non maskable interrupt, NMI

The RX CPU supports a non maskable interrupt which is described in the hardware manual. The NMI may be used for special purposes, but must not call any embOS function.

6.9 Using Register Bank Save Function with RXv3 core

Except in some products, the RXv3 CPU provides collective saving and restoring of CPU registers. In order to perform fast collective saving and restoring of CPU registers, the RXv3 CPU provides dedicated save register banks and instructions for using these banks. Using these save register banks, it is possible to perform fast register saving at the beginning of interrupt handlers, and high-speed register restoring at the end of interrupt handlers. The save register banks can only be accessed with the `SAVE` instruction and `RSTR` instruction. Each of these banks is used to save and restore the values of the following CPU registers: all general purpose registers (R1 to R15) except for R0, the USP, the FPSW, and the accumulators (ACC0, ACC1).

The pragma directive `bank=` can be used with an interrupt function to save the values of registers to the specified register bank at the start of the interrupt, and restore them again afterward. The `SAVE` and `RSTR` instructions will be used.

The `bank=` interrupt specification can be used with any embOS or zero latency interrupt.

Example

```
//  
// Interrupt function using bank pragma directive  
//  
#pragma interrupt (OS_ISR_Tick(vect=28,bank=1))  
static void OS_ISR_Tick(void) {  
    OS_INT_EnterNestable(); // Inform embOS that interrupt code is running  
    OS_Tick_Handle();  
}
```



```
OS_INT_LeaveNestable();  
}
```

Chapter 7

RTT and SystemView

7.1 SEGGER Real Time Transfer

With SEGGER's Real Time Transfer (RTT) it is possible to output information from the target microcontroller as well as sending input to the application at a very high speed without affecting the target's real time behavior. SEGGER RTT can be used with any J-Link model and any supported target processor which allows background memory access.

RTT is included with many embOS start projects. These projects are by default configured to use RTT for debug output. Some IDEs, such as SEGGER Embedded Studio, support RTT and display RTT output directly within the IDE. In case the used IDE does not support RTT, SEGGER's J-Link RTT Viewer, J-Link RTT Client, and J-Link RTT Logger may be used instead to visualize your application's debug output.

For more information on SEGGER Real Time Transfer, refer to [segger.com/jlink-rtt](https://www.segger.com/jlink-rtt).

7.2 SEGGER SystemView

SEGGER SystemView is a real-time recording and visualization tool to gain a deep understanding of the runtime behavior of an application, going far beyond what debuggers are offering. The SystemView module collects and formats the monitor data and passes it to RTT.

SystemView is included with many embOS start projects. These projects are by default configured to use SystemView in debug builds. The associated PC visualization application, SystemView, is not shipped with embOS. Instead, the most recent version of that application is available for download from our website.

SystemView is initialized by calling `SEGGER_SYSVIEW_Conf()` on the target microcontroller. This call is performed within `OS_InitHW()` of the respective `RTOSInit*.c` file. As soon as this function was called, the connection of the SystemView desktop application to the target can be started. In order to remove SystemView from the target application, remove the `SEGGER_SYSVIEW_Conf()` call, the `SEGGER_SYSVIEW.h` include directive as well as any other reference to `SEGGER_SYSVIEW_*` like `SEGGER_SYSVIEW_TickCnt`.

For more information on SEGGER SystemView and the download of the SystemView desktop application, refer to [segger.com/systemview](https://www.segger.com/systemview).

Note

SystemView uses embOS timing API to get at start the current system time. This requires that `OS_TIME_ConfigSysTimer()` was called before `SEGGER_SYSVIEW_Start()` is called or the SystemView PC application is started.

Chapter 8

Technical data

8.1 Resource Usage

The memory requirements of embOS (RAM and ROM) differs depending on the used features, CPU, compiler, and library model. The following values are measured using embOS library mode `OS_LIBMODE_XR`.

Module	Memory type	Memory requirements
embOS kernel	ROM	~1700 bytes
embOS kernel	RAM	~140 bytes
Task control block	RAM	36 bytes
Software timer	RAM	20 bytes
Task event	RAM	0 bytes
Event object	RAM	16 bytes
Mutex	RAM	16 bytes
Semaphore	RAM	8 bytes
RWLock	RAM	28 bytes
Mailbox	RAM	24 bytes
Queue	RAM	32 bytes
Watchdog	RAM	12 bytes
Fixed Block Size Memory Pool	RAM	32 bytes