

MARTe2-components - User story #791

Patch RealTimeThreadSynchronisation (from FAT-tools)

08.04.2021 10:48 - André Neto

Status:	Closed	Start date:	08.04.2021
Priority:	Normal	Due date:	
Assignee:		% Done:	0%
Category:		Estimated time:	0.00 hour
Target version:		Spent time:	0.00 hour
Git branch (link):		SVN commit (link/?p=rev):	
Git merge to develop (link):			
Description https://vcis-gitlab.f4e.europa.eu/aneto/MARTe2-components/-/compare/develop...DiagnosticCrio#7a207f5396f3fa5829e59b3540bd26d5f8c4adf2 https://vcis-gitlab.f4e.europa.eu/aneto/MARTe2-components/-/compare/develop...DiagnosticCrio#cd58b8f0074f034650fc3e38232ad9231912a2e8 https://vcis-gitlab.f4e.europa.eu/aneto/MARTe2-components/-/compare/develop...DiagnosticCrio#1c31d0a2143af387864edc09064342a62f5f45d4 https://vcis-gitlab.f4e.europa.eu/aneto/MARTe2-components/-/compare/develop...DiagnosticCrio#a491e4d7097658d4b4cd9b967d7f8dce251c4bcf See also: #779			

History

#1 - 08.04.2021 10:48 - André Neto

- Subject changed from Patch RealTimeThreadAsyncBridge (from FAT-tools) to Patch RealTimeThreadSynchronisation (from FAT-tools)

#2 - 12.04.2021 17:08 - André Neto

- Status changed from Code: Impl to Closed

If the parameter WaitForNext is set to 1, the synchronisation thread will first reset and then wait on the event semaphore. This can be useful if cycles were lost and the thread should wait for the next synchronisation cycle. The default behaviour (WaitForNext=0) is to first wait and then reset the semaphore and, as a consequence, if the semaphore had already been posted, it will not wait.

Merged with develop at 3b45257e8716e9b68c35a35704f23fdff838818e

#3 - 12.04.2021 17:09 - André Neto

- Description updated