CS 423
Operating System Design: Systems Review

Professor Adam Bates
Fall 2016
Goals for Today

• **Learning Objective:**
  • Review the prerequisite skills needed to be successful in this course
  • I.E., make sure you’re all in the right place : - )
  • If something in this lecture is unclear to you, review ASAP: [http://www.lysator.liu.se/c/bwk-tutor.html](http://www.lysator.liu.se/c/bwk-tutor.html)

**Reminder:** Please put away devices at the start of class
Your Teaching Assistants!

Saad Hussain

Bo Teng

Yisong Yue
System Calls

Function Calls

Caller and callee are in the same Process
- Same user
- Same “domain of trust”

System Calls
System Calls

Function Calls

- fnCall()
- Caller and callee are in the same Process
  - Same user
  - Same “domain of trust”

System Calls

- sysCall()
- OS is trusted; user is not.
- OS has super-privileges; user does not
- Must take measures to prevent abuse
Example System Calls?
Example System Calls?

Example:

getuid()   //get the user ID
fork()     //create a child process
exec()     //executing a program
Example System Calls?

Example:
- getuid() //get the user ID
- fork() //create a child process
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Don’t confuse system calls with stdlib calls

Differences?
- Is printf() a system call?
- Is rand() a system call?
Each system call has analogous procedure calls from the standard I/O library:

<table>
<thead>
<tr>
<th>System Call</th>
<th>Standard I/O call</th>
</tr>
</thead>
<tbody>
<tr>
<td>open</td>
<td>fopen</td>
</tr>
<tr>
<td>close</td>
<td>fclose</td>
</tr>
<tr>
<td>read/write</td>
<td>getchar/putchar</td>
</tr>
<tr>
<td></td>
<td>getc/putc</td>
</tr>
<tr>
<td></td>
<td>fgetc/fputc</td>
</tr>
<tr>
<td></td>
<td>fread/fwrite</td>
</tr>
<tr>
<td></td>
<td>gets/puts</td>
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<tr>
<td></td>
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<tr>
<td></td>
<td>scanf/printf</td>
</tr>
<tr>
<td></td>
<td>fscanf/fprintf</td>
</tr>
<tr>
<td>lseek</td>
<td>fseek</td>
</tr>
</tbody>
</table>
Processes

- Possible process states
  - Running (occupy CPU)
  - Blocked
  - Ready (does not occupy CPU)
  - Other states: suspended, terminated

1. Process blocks for input
2. Scheduler picks another process
3. Scheduler picks this process
4. Input becomes available
Processes

Possible process states
- Running (occupy CPU)
- Blocked
- Ready (does not occupy CPU)
- Other states: suspended, terminated

Question: in a single processor machine, how many processes can be in the running state?
Creating a Process

• What UNIX call creates a process?
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  - `fork()` duplicates a process so that instead of one process you get two.
  - The new process and the old process both continue in parallel from the statement that follows the `fork()`
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  ▪ How can you tell the two processes apart?
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    ▪ `fork()` returns
      ▪ 0 if child
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      ▪ Child’s PID if parent process
  ▪ If the parent code changes a global variable, will the child see the change?
    ▪ Nope! On fork, child gets new program counter, stack, file descriptors, heap, globals, pid!
• What if we need the child process to execute different code than the parent process?
What if we need the child process to execute different code than the parent process?

- Exec function allows child process to execute code that is different from that of parent
- Exec family of functions provides a facility for overlaying the process image of the calling process with a new image.
- Exec functions return -1 and sets errno if unsuccessful
• What is the difference between a thread and a process?
• What is the difference between a thread and a process?
  ▪ Both provided independent execution sequences, but...
  ▪ Each process has its own memory space
    ▪ *Remember how child processes can’t see changes to parent’s global variable?*
  ▪ Threads run in a shared memory space
Threads vs. Processes

• What is POSIX?
• How do you create a POSIX thread?
Threads vs. Processes

- What is POSIX?
- How do you create a POSIX thread?

<table>
<thead>
<tr>
<th>POSIX function</th>
<th>description</th>
</tr>
</thead>
<tbody>
<tr>
<td>pthread_create</td>
<td>create a thread</td>
</tr>
<tr>
<td>pthread_detach</td>
<td>set thread to release resources</td>
</tr>
<tr>
<td>pthread_equal</td>
<td>test two thread IDs for equality</td>
</tr>
<tr>
<td>pthread_exit</td>
<td>exit a thread without exiting process</td>
</tr>
<tr>
<td>pthread_kill</td>
<td>send a signal to a thread</td>
</tr>
<tr>
<td>pthread_join</td>
<td>wait for a thread</td>
</tr>
<tr>
<td>pthread_self</td>
<td>find out own thread ID</td>
</tr>
</tbody>
</table>
Threads: Lightweight Proc’s

- (a) Three processes each with one thread
- (b) One process with three threads
What is the difference between kernel and user threads? Pros and Cons?
What is the difference between kernel and user threads? Pros and cons?

Kernel thread packages
- Each thread can make blocking I/O calls
- Can run concurrently on multiple processors

Threads in User-level
- Fast context switch
- Customized scheduling
M:N model multiplexes N user-level threads onto M kernel-level threads

Good idea? Bad Idea?
Processes and threads can be preempted at arbitrary times, which may generate problems.

Example: What is the execution outcome of the following two threads (initially x=0)?

Thread 1:
- Read X
- Add 1
- Write X

Thread 2:
- Read X
- Add 1
- Write X

How do we account for this?
Critical Regions/Sections

Process {
    while (true) {
        ENTER CRITICAL SECTION
        Access shared variables;
        LEAVE CRITICAL SECTION
        Do other work
    }
}
Mutex

- Simplest and most efficient thread synchronization mechanism
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- A special variable that can be either in
  - **locked state**: a distinguished thread that holds or owns the mutex; or
  - **unlocked state**: no thread holds the mutex
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- When several threads compete for a mutex, the losers block at that call
  - The mutex also has a queue of threads that are waiting to hold the mutex.
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- POSIX does not require that this queue be accessed FIFO.
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- When several threads compete for a mutex, the losers block at that call
  - The mutex also has a queue of threads that are waiting to hold the mutex.
- POSIX does not require that this queue be accessed FIFO.
- Helpful note — Mutex is short for “Mutual Exclusion”
POSIX Mutex Functions

- **int pthread_mutex_init**(pthread_mutex_t *restrict mutex, const pthread_mutexattr_t *restrict attr);
  - Also see  PTHREAD_MUTEX_INITIALIZER
- **int pthread_mutex_destroy**(pthread_mutex_t *mutex);
- **int pthread_mutex_lock**(pthread_mutex_t *mutex);
- **int pthread_mutex_trylock**(pthread_mutex_t *mutex);
- **int pthread_mutex_unlock**(pthread_mutex_t *mutex);
void wait (semaphore_t *sp) 
   if (sp->value > 0) sp->value--; 
   else { 
      <Add this process to sp->list>
      <block>
   }

void signal (semaphore_t *sp) 
   if (sp->list != NULL) 
      <remove a process from sp->list, 
      put it in ready state>
   else sp->value++;
Pseudocode for a blocking implementation of semaphores:

```c
void wait (semaphore_t *sp)
    if (sp->value > 0) sp->value--;
    else {
        <Add this process to sp->list>
        <block>
    }

void signal (semaphore_t *sp)
    if (sp->list != NULL)
        <remove a process from sp->list, put it in ready state>
    else sp->value++;
```
Basic scheduling algorithms
  - FIFO (FCFS)
  - Shortest job first
  - Round Robin
  - Priority Scheduling
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- Priority Scheduling

What is an optimal algorithm in the sense of maximizing the number of jobs finished?
Scheduling

- Basic scheduling algorithms
  - FIFO (FCFS)
  - Shortest job first
  - Round Robin
  - Priority Scheduling

- What is an optimal algorithm in the sense of meeting the most deadlines (of real time tasks)?
• **Non-preemptive scheduling:**
  - The running process keeps the CPU until it *voluntarily* gives up the CPU
    - process exits
    - switches to blocked state
    - 1 and 4 only (no 3)

• **Preemptive scheduling:**
  - The running process can be interrupted and must release the CPU (can be *forced* to give up CPU)
• What is a signal in UNIX/Linux?
Signals

• What is a signal in UNIX/Linux?
  ▪ A way for one process to send a notification to another
  ▪ A signal can be “caught”, “ignored”, or “blocked”
What is a signal in UNIX/Linux?

- A way for one process to send a notification to another
- A signal can be “caught”, “ignored”, or “blocked”

- Signal is **generated** when the event that causes it occurs.
- Signal is **delivered** when a process receives it.
- The **lifetime** of a signal is the interval between its generation and delivery.
- Signal that is generated but not delivered is **pending**.
- Process **catches** signal if it executes a **signal handler** when the signal is delivered.
- Alternatively, a process can **ignore** a signal when it is delivered, that is to take no action.
- Process can temporarily prevent signal from being delivered by **blocking** it.
- **Signal Mask** contains the set of signals currently blocked.
## POSIX-required Signals

<table>
<thead>
<tr>
<th>Signal</th>
<th>Description</th>
<th>default action</th>
</tr>
</thead>
<tbody>
<tr>
<td>SIGABRT</td>
<td>process abort</td>
<td>implementation dependent</td>
</tr>
<tr>
<td>SIGALRM</td>
<td>alarm clock</td>
<td>abnormal termination</td>
</tr>
<tr>
<td>SIGBUS</td>
<td>access undefined part of memory object</td>
<td>implementation dependent</td>
</tr>
<tr>
<td>SIGCHLD</td>
<td>child terminated, stopped or continued</td>
<td>ignore</td>
</tr>
<tr>
<td>SIGILL</td>
<td>invalid hardware instruction</td>
<td>implementation dependent</td>
</tr>
<tr>
<td>SIGINT</td>
<td>interactive attention signal (usually ctrl-C)</td>
<td>abnormal termination</td>
</tr>
<tr>
<td>SIGKILL</td>
<td>terminated (cannot be caught or ignored)</td>
<td>abnormal termination</td>
</tr>
</tbody>
</table>

*Not an exhaustive list*
# POSIX-required Signals*

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<tbody>
<tr>
<td>SIGSEGV</td>
<td>Invalid memory reference</td>
<td>implementation dependent</td>
</tr>
<tr>
<td>SIGSTOP</td>
<td>Execution stopped</td>
<td>stop</td>
</tr>
<tr>
<td>SIGTERM</td>
<td>termination</td>
<td>Abnormal termination</td>
</tr>
<tr>
<td>SIGTSTP</td>
<td>Terminal stop</td>
<td>stop</td>
</tr>
<tr>
<td>SIGTIN</td>
<td>Background process attempting read</td>
<td>stop</td>
</tr>
<tr>
<td>SIGTOU</td>
<td>Background process attempting write</td>
<td>stop</td>
</tr>
<tr>
<td>SIGURG</td>
<td>High bandwidth data available on socket</td>
<td>ignore</td>
</tr>
<tr>
<td>SIGUSR1</td>
<td>User-defined signal 1</td>
<td>abnormal termination</td>
</tr>
</tbody>
</table>
How can you send a signal to a process from the command line?
User-generated Signals

- How can you send a signal to a process from the command line?
- `kill` 😢
User-generated Signals

- How can you send a signal to a process from the command line?
- `kill`
- `kill -l` will list the signals the system understands
- `kill [-signal] pid` will send a signal to a process.
  - The optional argument may be a name or a number (default is SIGTERM).
- To unconditionally kill a process, use:
  - `kill -9 pid` which is `kill -SIGKILL pid`.
Signal Masks
A process can temporarily prevent a signal from being delivered by blocking it.
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**Signal Mask** contains a set of signals currently blocked.
Signal Masks

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- **Important!** Blocking a signal is different from ignoring signal. Why?
Signal Masks
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**Important!** Blocking a signal is different from ignoring signal. Why?

- When a process blocks a signal, the OS does not deliver signal until the process unblocks the signal
  - A **blocked** signal is not delivered to a process until it is unblocked.
A process can temporarily prevent a signal from being delivered by blocking it.

Signal Mask contains a set of signals currently blocked.

**Important!** Blocking a signal is different from ignoring signal. Why?

When a process blocks a signal, the OS does not deliver signal until the process unblocks the signal
- A **blocked** signal is not delivered to a process until it is unblocked.

When a process ignores signal, signal is delivered and the process handles it by throwing it away.
Deadlocks
When do deadlocks occur (hint: 4 preconditions)?
Deadlocks

When do deadlocks occur (hint: 4 preconditions)?

- Mutual exclusion
- Hold and wait condition
- No preemption condition
- Circular wait condition
Deadlocks

Resource Allocation Graphs

- resource R assigned to process A
- process B is requesting/waiting for resource S
- process C and D are in deadlock over resources T and U
Strategies for Dealing with Deadlocks

- shouting
- detection and recovery
- dynamic avoidance (at run-time)
- prevention (by offline design)
  - by negating one of the four necessary conditions
• make sure you have a working understanding of other systems programming issues, e.g.:
  • dynamic avoidance (at run-time)
  • prevention (by offline design)
    • memory management
    • working with files
    • I/O