


Advanced Operating Systems
MS degree in Computer Engineering
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Kernel level task management

1. Advanced/scalable task management schemes
2. (Multi-core) CPU scheduling approaches
3. Automatic concurrency managers
4. Binding to the Linux architecture

Tasks vs processes/threads

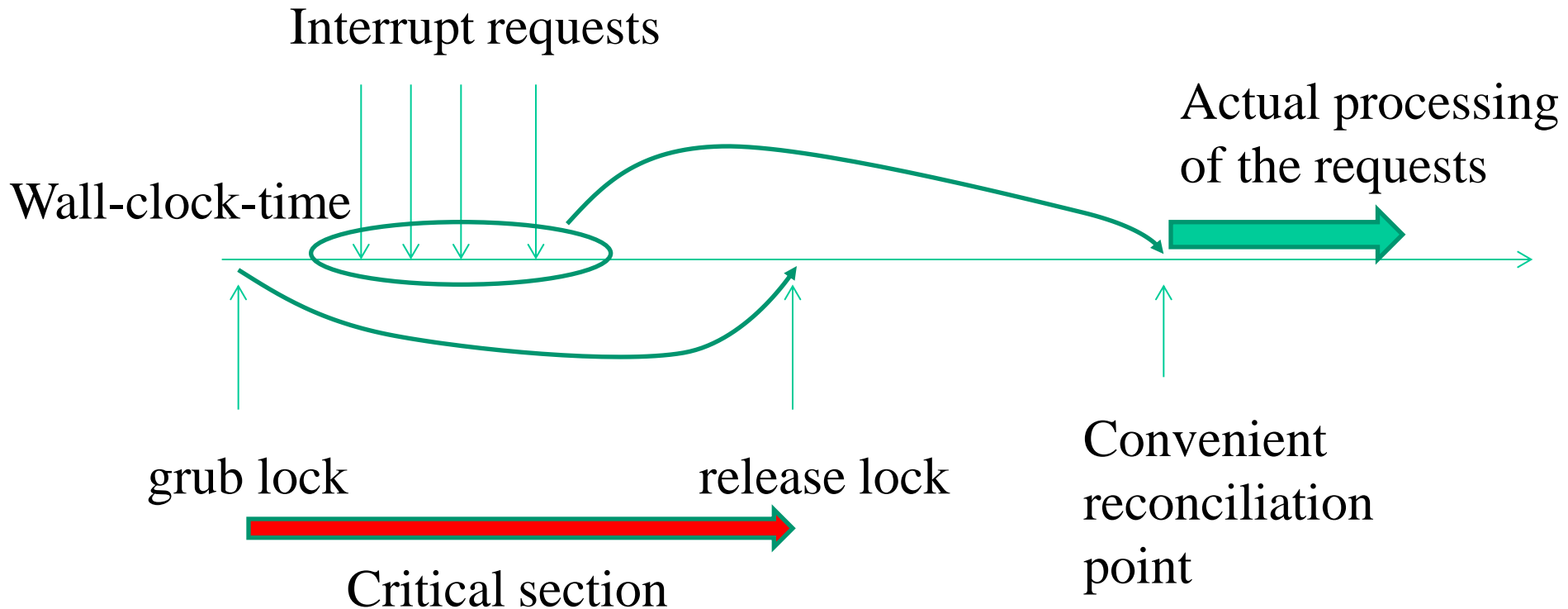
- Types of traces
 - User mode process/thread
 - Kernel mode process/thread
 - Interrupt management
- Non-determinism
 - Due to nesting of user/kernel mode traces and interrupt management traces
- Performance
 - Non-determinism may give rise to inefficiency whenever the evolution of the traces is tightly coupled (like on SMP and multi-core machines)
 - **Timing expectations for critical sections can be altered**

Design methodologies

Temporal reconciliation

- Interrupt management traces get nested into (mapped onto) process/thread traces according to temporal shift (**work deferring**)
- This mapping can lead to aggregating the management of the events within the system (many-to-one aggregation)
- Priority based scheduling mechanisms are required in order not to induce starvation, or to correctly manage different levels of criticality

An example timeline for work deferring



Reconciliation points

Guarantees

- “Eventually”

Conventional support

- Returning from syscall
 - This involves application level technology
- Context-switch
 - This involves idle-process technology
- Reconciliation in process-context
 - This involves kernel-thread technology

The historical concept: top/bottom half programming

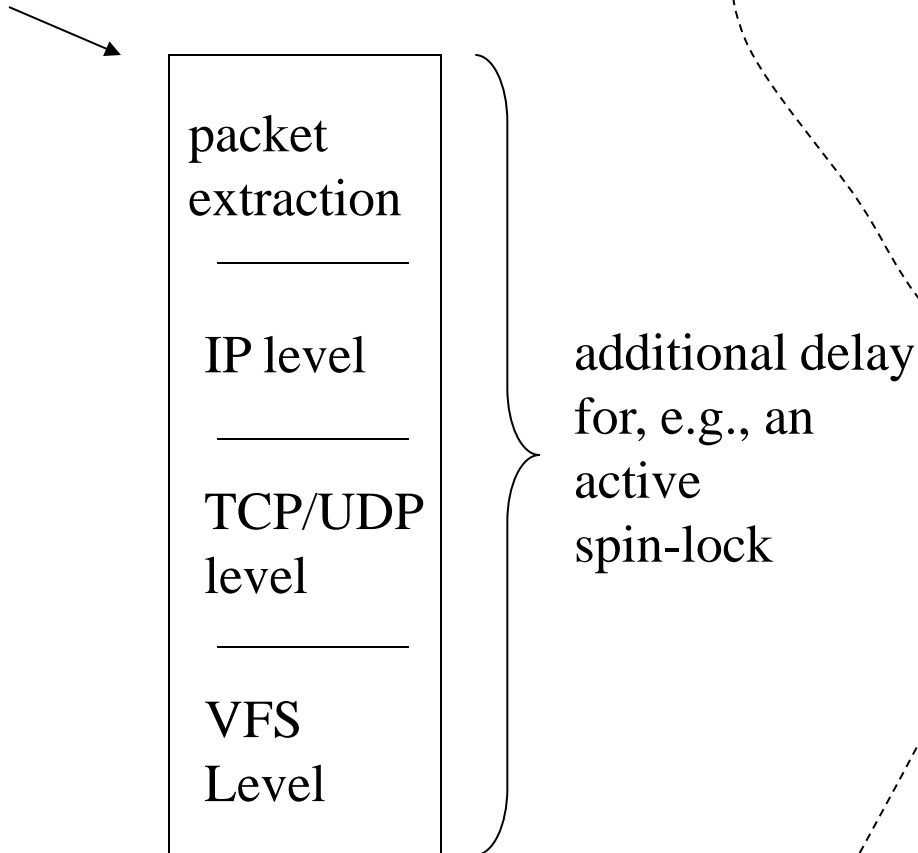
- The management of tasks associated with the interrupts typically occurs via a two-level logic: top half e bottom half
- The top-half level takes care of executing a minimal amount of work which is needed to allow later finalization of the whole interrupt management
- The top-half code portion is typically (but not manadatorily) handled according to a non-interruptible (hence non-preemptable) scheme
- The finalization of the work takes place via the bottom-half level
- The top-half takes care of scheduling the bottom-half task, e.g., by queuing a record into a proper data structure

- The difference between top-half and bottom-half comes out because of
 - ✓ the need to manage events in a timely manner,
 - ✓ while avoiding to lock resources right upon the event occurrence
- Otherwise, we may incur the risk of delaying critical actions (**e.g. spinlock-release**) interrupted due to the event occurrence
- At worst we might even incur deadlocks when a slow interrupt management is hit by the activation of another one that needs the same resources

One example: sockets

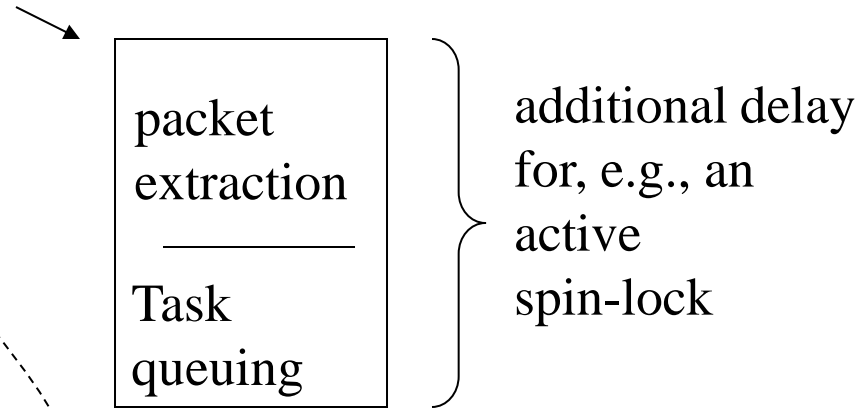
no top/bottom half

interrupt from network device

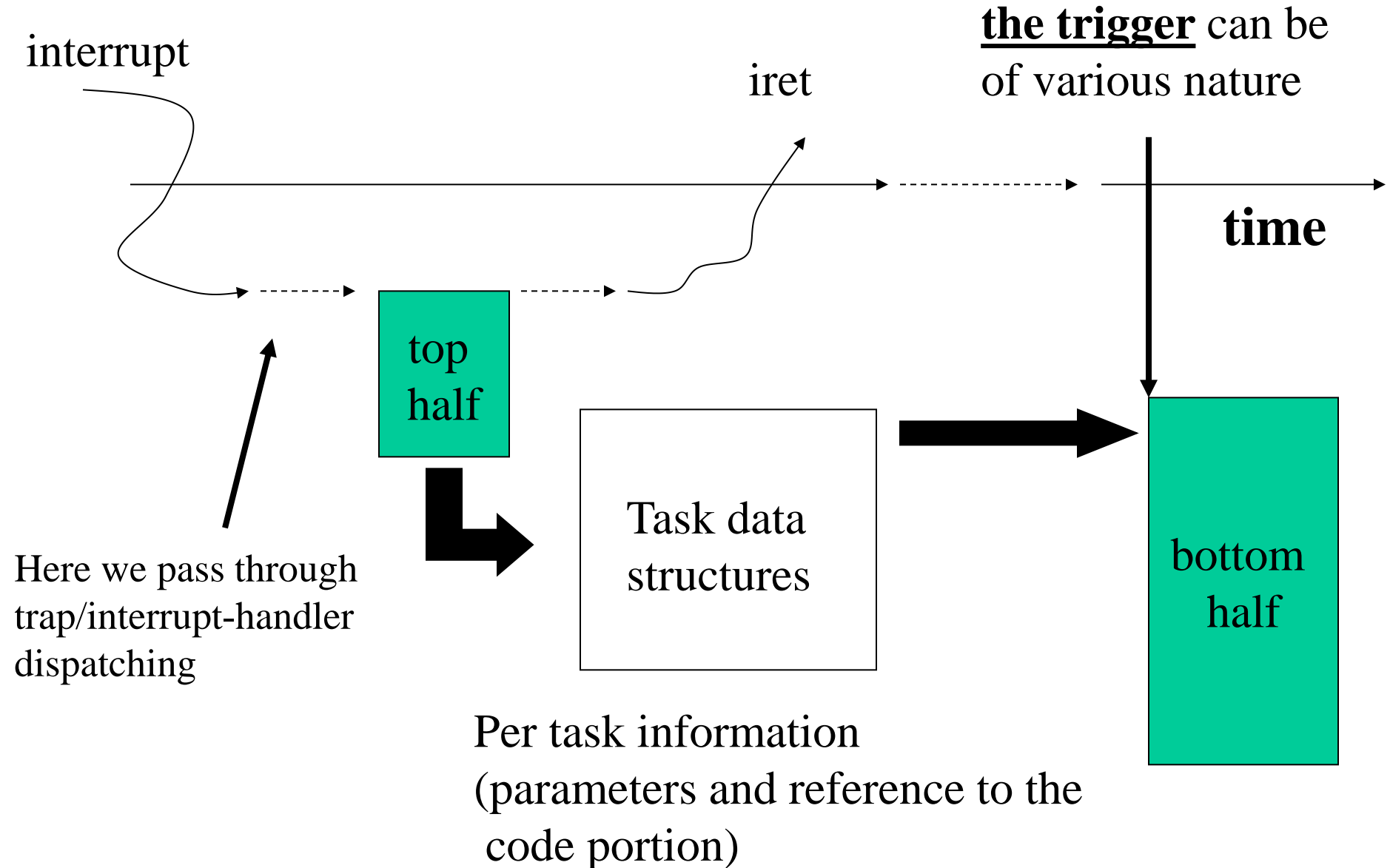


top/bottom half

interrupt from network device

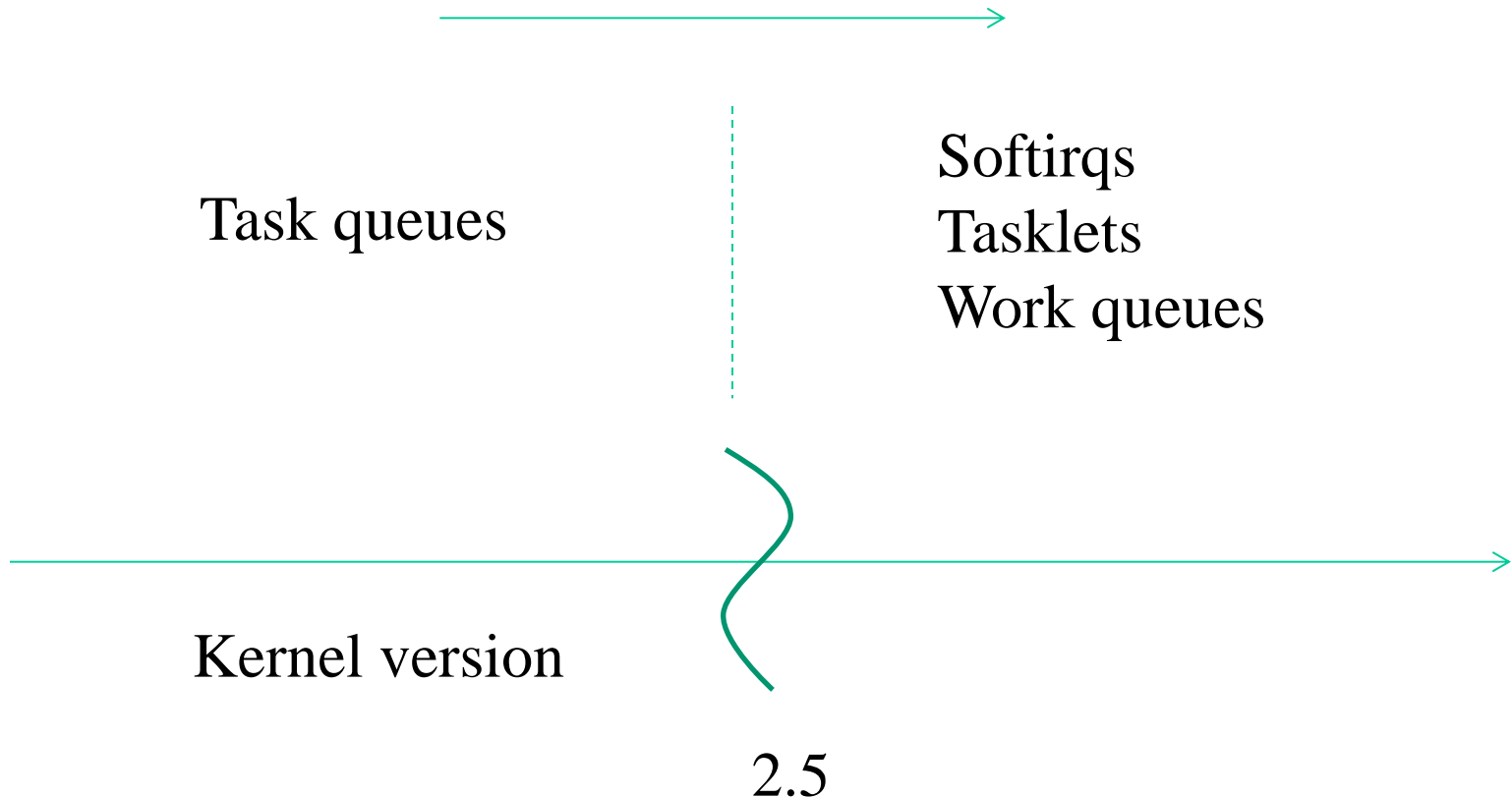


The historical architectural concept: bottom-half queues



Historical evolution in LINUX

Improved orientation to SMP/multi-core and automation
(concepts that relevant to every operating system kernel so we can
take the LINUX instances as archetypal solutions)



Let's start from task queues

- task-queues are queuing structures, which can be associated with variable names
- LINUX (ref. kernel 2.2) already declared a given amount of **predefined task-queues**, having the following names

➤ `tq_immediate`

(tasks to be executed upon timer-interrupt or syscall return)

➤ `tq_timer`

(tasks to be executed upon timer-interrupt)

➤ `tq_schedule`

(task to be executed in process context)

Task queues data structures

- Additional task queues can be declared using the macro `DECLARE_TASK_QUEUE (queuename)` which is defined in `include/linux/tqueue.h` – this macro also initializes the task-queue as empty
- The structure of a task is defined in `include/linux/tqueue.h`

```
struct tq_struct {  
    struct tq_struct *next; /*linked list of active bh's*/  
    int sync; /* must be initialized to zero */  
    void (*routine)(void *); /* function to call */  
    void *data; /* argument to function */  
}
```

Task management API

- The queuing function has prototype `int queue_task(struct tq_struct *task, task_queue *list)`, where `list` is the address of the target task-queue structure
- This function is used to only register the task, not to execute it
- The task flushing (execution) function for all the tasks currently kept by a task queue is `void run_task_queue(task_queue *list)`
- When invoked, unlinking and actual execution of the tasks takes place
- For the `tq_schedule` task-queue there exists a proper queuing function offered by the kernel with prototype `int schedule_task(struct tq_struct *task)`
- **The return value of any queuing function is non-zero if the task is not already registered within the queue** (the check is done by exploiting the `sync` field, which gets set to 1 when the task is queued)

Task management details

- Non-predefined task-queues need to be flushed via an explicit call to **the function** `run_task_queue(...)`
- Pre-defined task-queues are automatically handled (flushed) by the kernel
- Anyway, pre-defined queues can be used for inserting tasks that may differ from those natively inserted by the standard kernel image
- **Note**: upon inserting a task into the `tq_immediate` queue, a call to `void mark_bh(IMMEDIATE_BH)` needs to be made, which is used to set the data structures in such a way to indicate that this is not empty
- This needs to be done in relation to legacy management rules

Bottom-half occurrences with task queues

Timely flushing of the bottom halves requires

- Invokation by the scheduler
- Invokation upon entering and/or exiting system calls

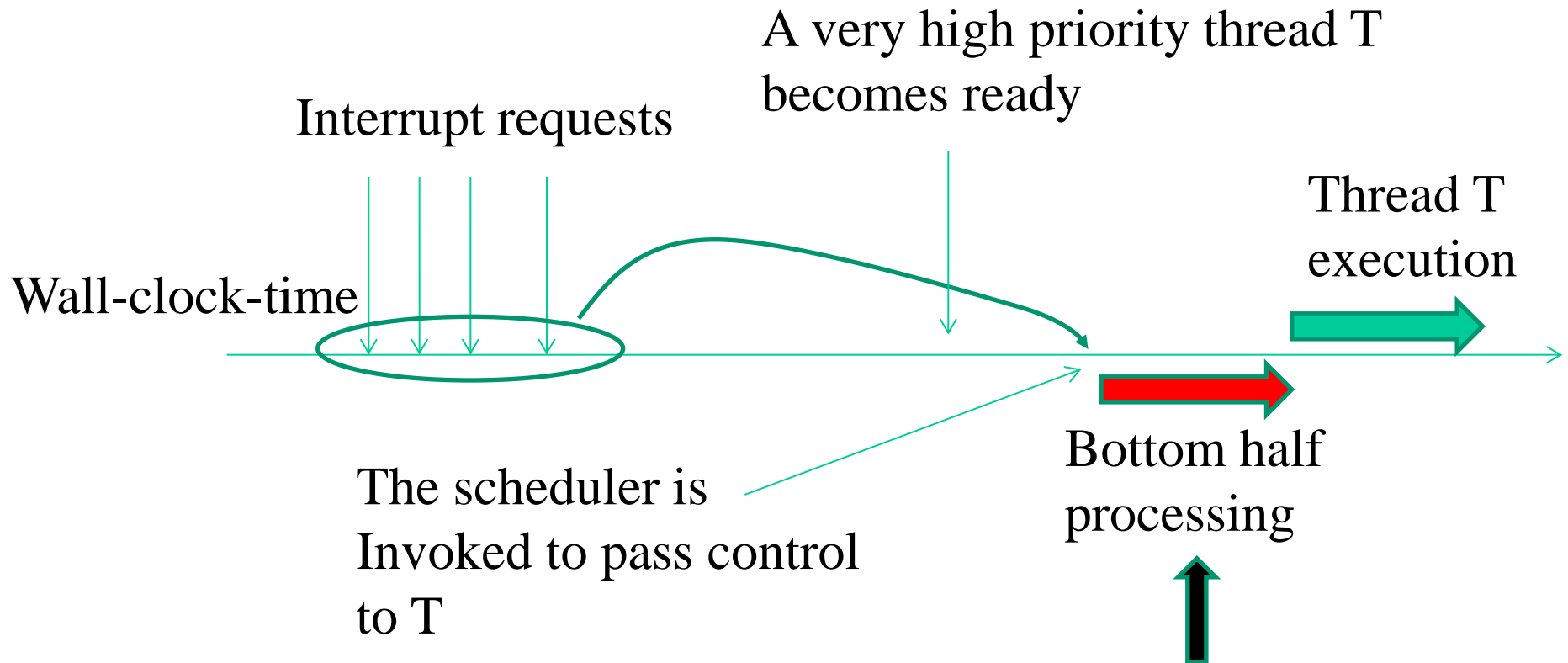
The Linux kernel (up to 2.5) invokes **do_bottom_half()**

- within `schedule()`
- from `ret_from_sys_call()`

Be careful: the bottom half execution context

- Even though bottom half tasks can be executed in process context, the actual context for the thread while running them should look like “interrupt”
- No blocking service invocation in any bottom half function!!

Limitations of task queues: the actual timeline



Thread T is delayed by the whole time require to process all the standing bottom halves

Limitations of task queues: more general aspects

- Nesting of bottom halves on a single thread leads to
 - ✓ The impossibility to exploit multiple CPU-cores for interrupt (bottom half) management
 - ✓ The impossibility to optimize locality of operations and data accesses
 - ✓ Unsuitability for heavy interrupt load
 - ✓ Unsuitability for scaled up hardware parallelism

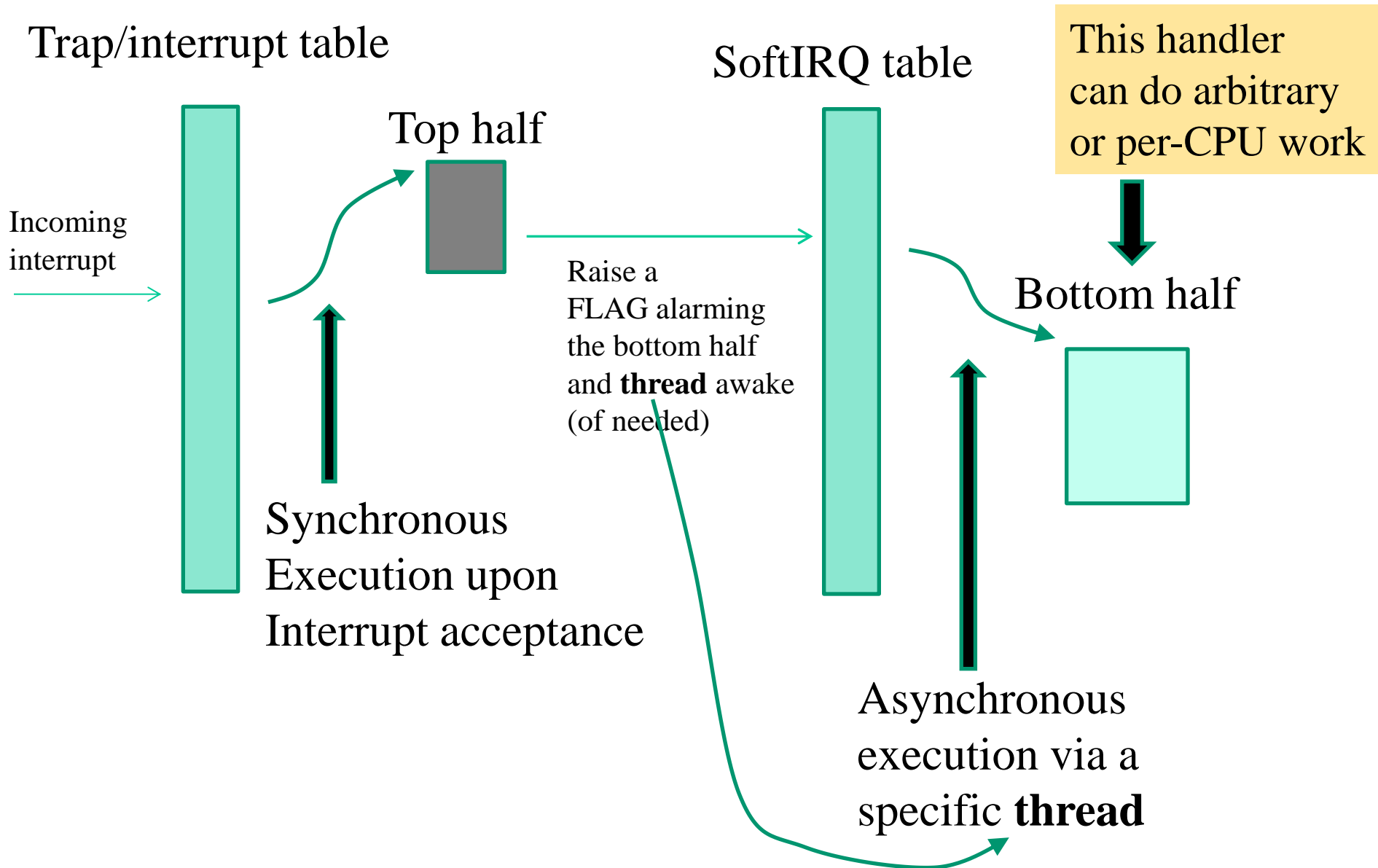
Parallelism vs interrupts vs device drivers

- Interrupts can be also be raised by software
- This is the scenario of drivers for logical (not physical) devices
- So interrupt drivers may be requested to handle a load that may grow with the number of running threads
- Clearly, the actual workload can be a function of the number of available CPU-cores
- Overall, we need:
 - ✓ More scalability and locality
 - ✓ More flexibility
 - ✓ Reactiveness and predictability

SoftIRQ architectures

- The top half is further reduced
- It does not necessarily queue the bottom half, so it can be even more responsive
- Bottom halves can therefore be already present somewhere
- They can be seen as actual interrupt handlers triggered via software (by the top half)
- The queuing concept is still there for on demand usage, if required (e.g. for programmability of new bottom halves)
- Queues of tasks are not queues of bottom halves, **they are queues of bottom half input data**

The architectural scheme



LINUX SoftIRQs (kernels later than 2.5)

- The SoftIRQ table is an array of `NR_SOFTIRQS` entries, each of which is set to identify a `struct softirq_action`
- The entries are associated with different types/priorities of handlers, the set is:

```
enum {    HI_SOFTIRQ=0,  
          TIMER_SOFTIRQ,  
          NET_TX_SOFTIRQ,  
          NET_RX_SOFTIRQ,  
          BLOCK_SOFTIRQ,  
          BLOCK_IOPOLL_SOFTIRQ,  
          TASKLET_SOFTIRQ,  
          SCHED_SOFTIRQ,  
          HRTIMER_SOFTIRQ,  
          RCU_SOFTIRQ,  
          NR_SOFTIRQS }
```

High priority
queued stuff

Stuff to do on timers or
reschedules

Normal priority
queued stuff

Who does the softIRQ work

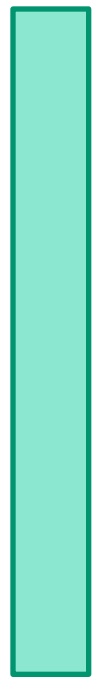
- The `ksoftirq` daemon (multiple threads with CPU affinity)
- This is typically listed as `ksoftirq[n]` where 'n' is the CPU-core it is affine with
- Once awoken, the threads look at the softIRQ table to inspect if some entry is flagged
- In the positive case the thread runs the softIRQ handler
- We can also build a mask telling that a thread awoken on a CPU-core X will not process the handler associated with a given softIRQ
- So we can create affinity between softIRQs and CPU-cores
- On the other hand, affinity can be based on groups of CPU-core IDs so we can distribute the SoftIRQ load across the CPU-cores

Overall advantages from softIRQs

- Multithread execution of bottom half tasks
- Bottom half execution not synchronous with respect to specific threads (e.g. upon rescheduling a very high priority thread)
- Binding of task execution to CPU-cores if required (e.g. locality on NUMA machines)
- Ability to still queue tasks to be done (see the `HI_SOFTIRQ` and `TASKLET_SOFTIRQ` types)

Actual management of queued tasks: normal and high priority tasklets

SoftIRQ table



HI_SOFTIRQ

`void tasklet_action(struct softirq_action *a)`



Access to per-CPU
queues of tasks

TASKLET_SOFTIRQ

● → ● → ● High priority

● → ● Normal priority

Tasklet representation and API

- The tasklet is a data structure used for keeping track of a specific task, related to the execution of a specific function internal to the kernel
- The function can accept a single pointer as the parameter, namely an unsigned long, and must return void
- Tasklets can be instantiated by exploiting the following macros defined in include/linux/interrupt.h:
 - DECLARE_TASKLET(tasklet, function, data)
 - DECLARE_TASKLET_DISABLED(tasklet, function, data)
- name is the tasklet identifier, function is the name of the function associated with the tasklet and data is the parameter to be passed to the function
- If instantiation is disabled, then the task will not be executed until an explicit enabling will take place

- tasklet enabling/disabling functions are

```
tasklet_enable(struct tasklet_struct *tasklet)
```

```
tasklet_disable(struct tasklet_struct *tasklet)
```

```
tasklet_disable_nosynch(struct tasklet_struct *tasklet)
```

- the functions scheduling the tasklet are

```
void tasklet_schedule(struct tasklet_struct *tasklet)
```

```
void tasklet_hi_schedule(struct tasklet_struct  
    *tasklet)
```

```
void tasklet_hi_schedule_first(struct tasklet_struct  
    *tasklet)
```

- **NOTE:**

➤ Subsequent reschedule of a same tasklet may result in a single execution, depending on whether the tasklet was already flushed or not

The tasklet init function

```
void tasklet_init(struct tasklet_struct *t, void
(*func) (unsigned long), unsigned long data) {

    t->next = NULL;

    t->state = 0;

    atomic_set(&t->count, 0); ← This enables/disables
                                the tasklet

    t->func = func;

    t->data = data;

}
```

Important note

- A tasklet that is already queued and is not active still stands in the pending tasklet list, up to its enabling and then processing
- This is clearly important when we implement, e.g., device drivers with tasklets in LINUX modules and we want to unmount the module for any reason
- In other words we must be very careful that queue linkage is not broken upon the unmount

Tasklets' recap

- Tasklets related tasks are performed via specific kernel threads (CPU-affinity can work here when logging the tasklet)
- If the tasklet has already been scheduled on a different CPU-core, it will not be moved to another CPU-core if it's still pending (generic softirqs can instead be processed by different CPU-cores)
- Tasklets have schedule level similar to the one of `tq_schedule`
- The main difference is that the thread actual context should be an “interrupt-context” – thus with no-sleep phases within the tasklet (an issue already pointed to)

Finally: work queues

- Kernel 2.5.41 fully replaced the task queue with the work queue
- Users (e.g. drivers) of `tq_immediate` should normally switch to tasklets
- Users of `tq_timer` should use timers directly
- If these interfaces are inappropriate, the `schedule_work()` interface can be used
- This interface queues the work to the kernel “events” (multithreaded) daemon, which executes it in process context


... work queues continued

- Interrupts are enabled while the work queues are being run (except if the same work to be done disables them)
- Functions called from a work queue may call blocking operations, but this is discouraged as it prevents other users from running (an issue already pointed to)
- The above point is anyhow tackled by more recent variants of work queues as we shall see

Work queues basic interface (default queues)

```
schedule_work(struct work_struct *work)
schedule_work_on(int cpu,
                  struct work_struct *work)
```

```
INIT_WORK(&var_name, function-pointer, &data);
```



Additional APIs can be used to create custom work queues and to manage them



```
struct workqueue_struct *create_workqueue(const  
char *name);
```

```
struct workqueue_struct  
    *create_singlethread_workqueue(const char  
*name);
```

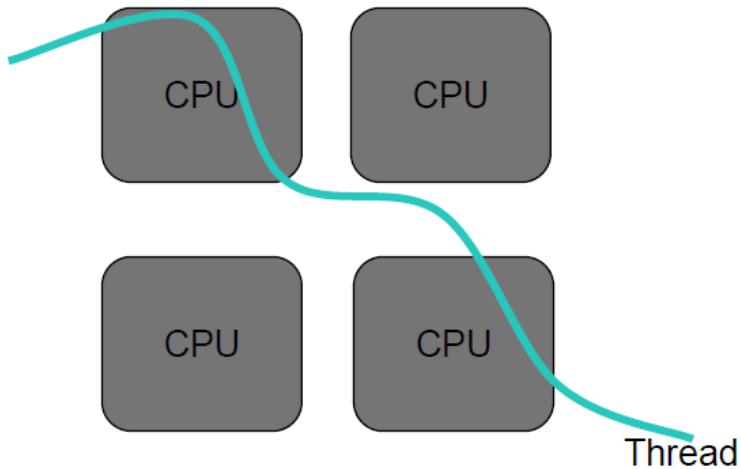
Both create a `workqueue_struct` (with one entry per processor)
The second provides the support for flushing the queue via a
single worker thread (and no affinity of jobs)

```
void destroy_workqueue(struct workqueue_struct  
*queue);
```

This eliminates the queue

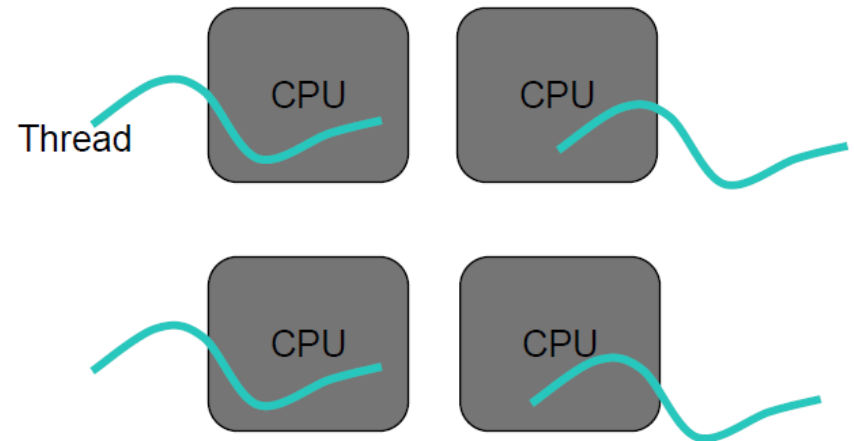
Actual scheme

Single threaded workqueue



A single threaded workqueue had one worker thread system-wide.

Multi threaded workqueue



A multi threaded workqueue had one thread per CPU.

```
int queue_work(struct workqueue_struct *queue,  
               struct work_struct *work);
```

```
int queue_delayed_work(struct workqueue_struct *queue,  
                      struct work_struct *work, unsigned long delay);
```

Both queue a job - the second with timing information

```
int cancel_delayed_work(struct work_struct *work);
```

This cancels a pending job

```
void flush_workqueue(struct workqueue_struct *queue);
```

This runs any job

Work queue issues

→ **Proliferation of kernel threads** The original version of workqueues could, on a large system, run the kernel out of process IDs before user space ever gets a chance to run

→ **Deadlocks** Workqueues could also be subject to deadlocks if resource usage is not handled very carefully

→ **Unnecessary context switches** Workqueue threads contend with each other for the CPU, causing more context switches than are really necessary

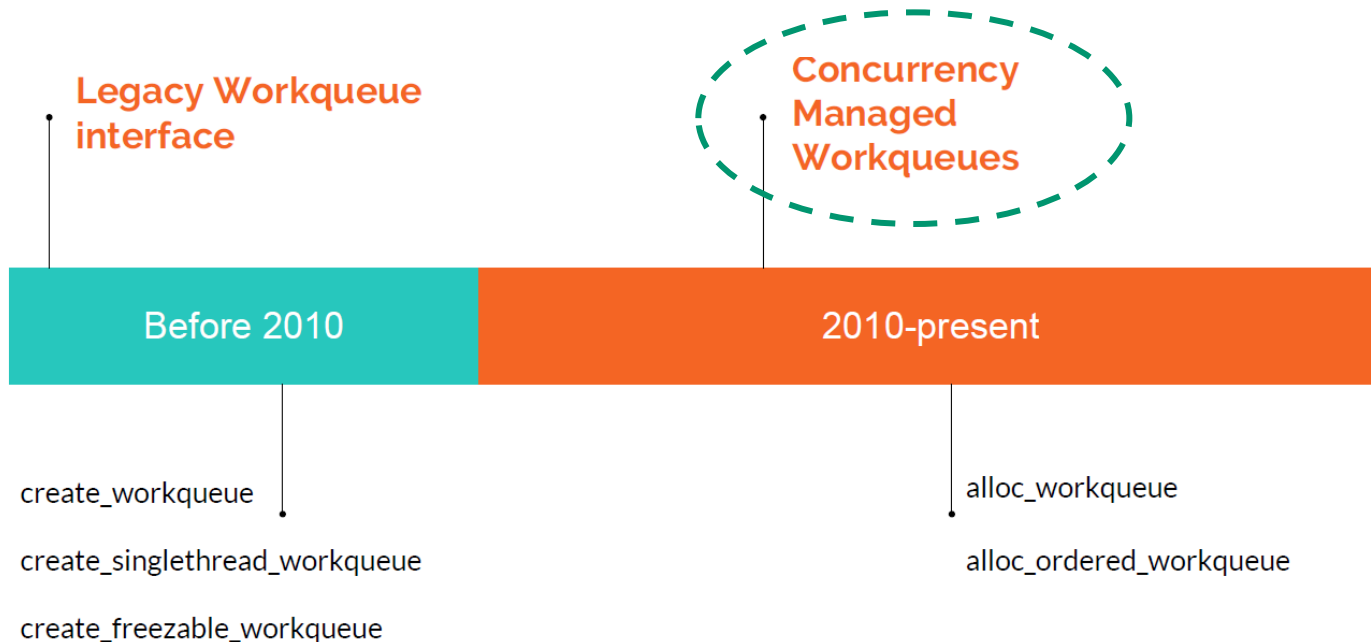
Interface and functionality evolution

Due to its development history, there currently are two sets of interfaces to create workqueues.

- **Older:**

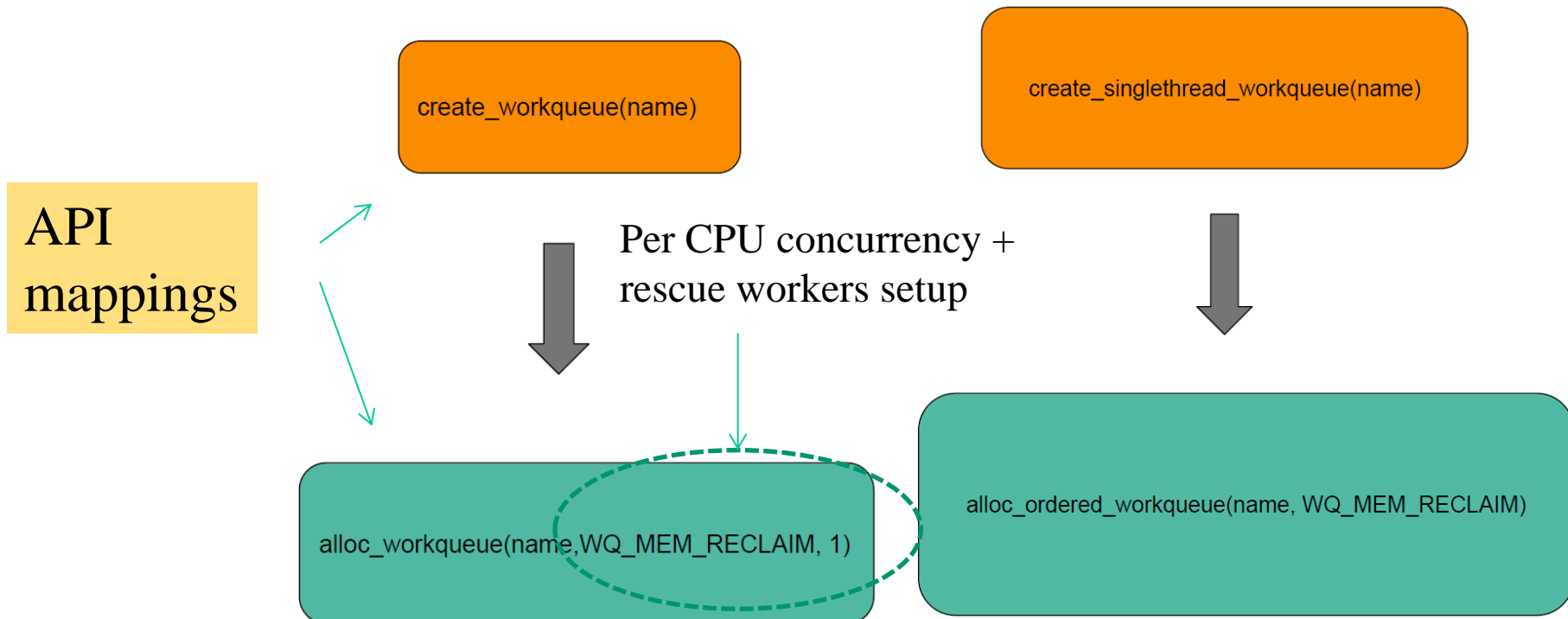
`create[_singlethread|_freezable]_workqueue()`

- **Newer:** `alloc[_ordered]_workqueue()`



Concurrency managed work queues

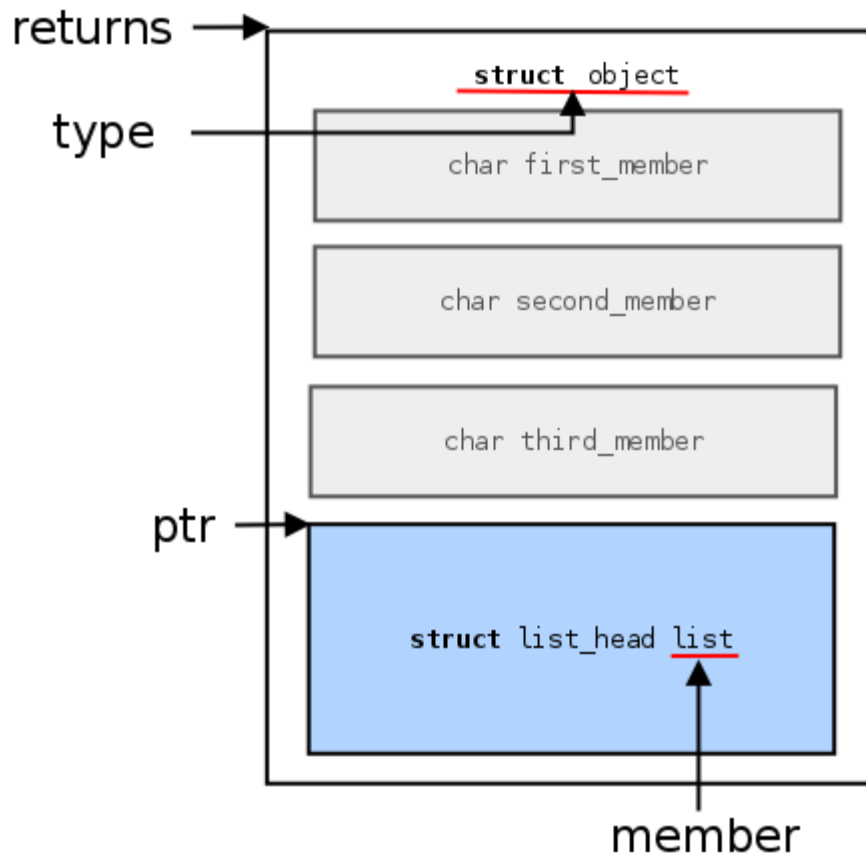
- Uses per-CPU unified worker pools shared by all work queues to provide flexible levels of concurrency on demand without wasting a lot of resources
- Automatically regulates worker pool and level of concurrency so that the users don't need to worry about such details



Managing dynamic memory with (not only) work queues

`container_of(ptr, type, member)`

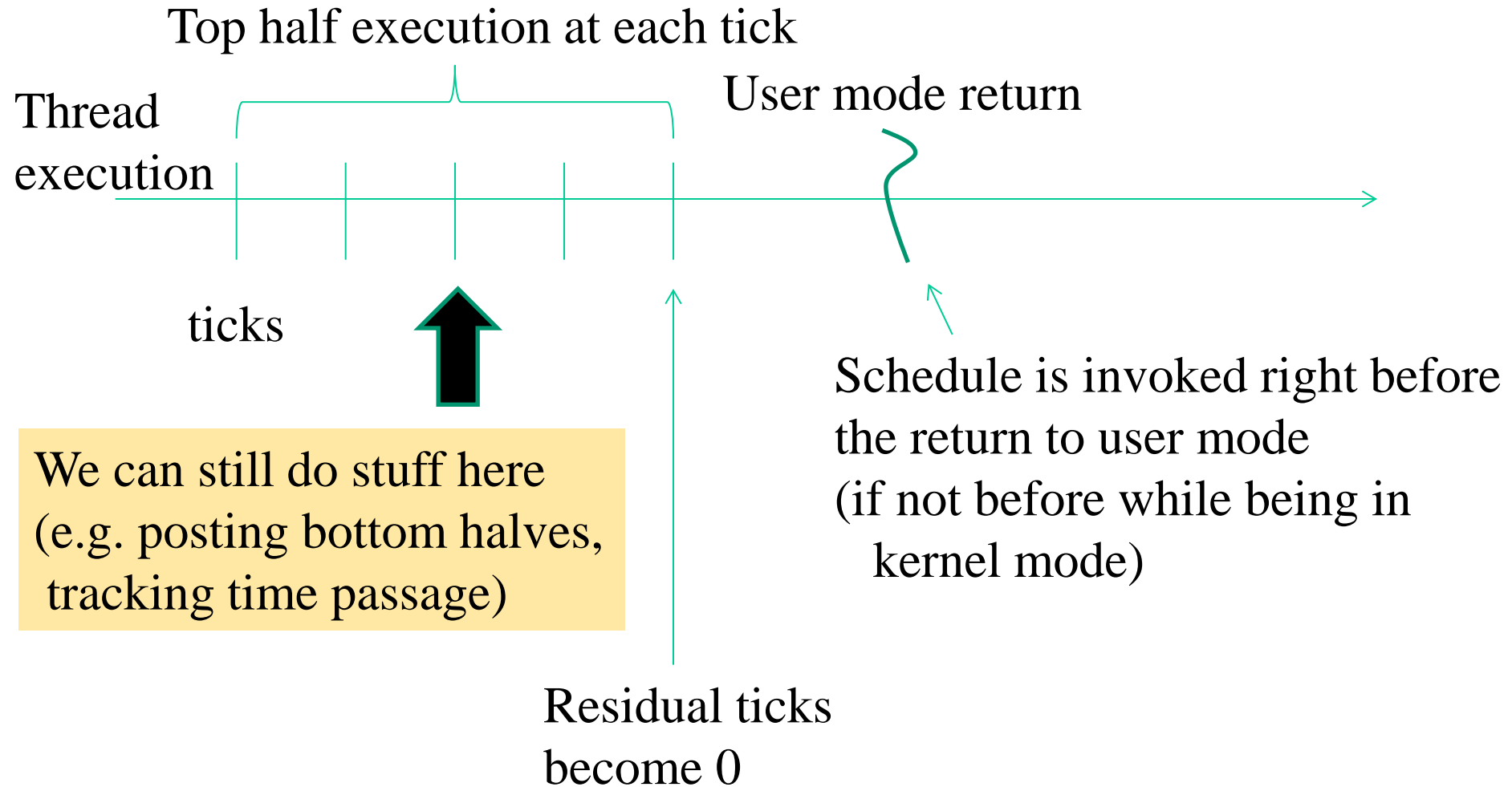
illustrated explanation



Interrupts vs passage of time vs CPU-scheduling

- The unsuitability of processing interrupts immediately (upon their asynchronous arrival) still stands there for TIMER interrupts
- Although we have historically abstracted a context switch off the CPU caused by the time-quantum expiration as an asynchronous event, this is not generally true
- What changes asynchronously is the condition that tells to the kernel software if we need to call the CPU scheduler (synchronously at some point along execution in kernel mode)
- Overall, timing vs CPU reschedules are still managed according to a top/bottom half scheme
- **NOTE: this is not true for preemption not linked to time passage, as we shall see**

A scheme for timer interrupts vs CPU reschedules



Could the disabling of the timer interrupt on demand be still effective?

- Clearly no!!
- If we disable timer interrupts while running a kernel block of code that absolutely needs not to be preempted by the timer we loose the possibility to schedule bottom halves along time passage
- We also loose the possibility to control timings at fine grain, which is fundamental on a multi-core system
- A CPU-core can in fact at fine grain interact with the others
- Switching off timer interrupts was an old style approach for atomicity of kernel actions on single-core CPUs

LINUX timer interrupts: the top half

- The top half of the timer interrupt handler executes the following actions
 - **Flags the task-queue** `tq_timer` as ready for flushing (old style)
 - Increments the global variable `volatile unsigned long jiffies`, which takes into account **the number of** ticks elapsed since interrupts' enabling
 - Does some minimal time-passage related work
 - **It checks whether the CPU scheduler needs to be activated**, and in the positive case flags the `need_resched` variable/bit within the TCB (Thread Control Block) of the current thread
- **NOTE AGAIN: time passage is not the unique means for preempting threads in LINUX, as we shall see**

Effects of raising `need_resched`

- Upon finalizing any kernel level work (e.g. a system call) the `need_resched` variable/bit within the TCB of the current process gets checked (recall this may have been set by the top-half of the timer interrupt)
- In case of positive check, the actual scheduler module gets activated
- It corresponds to the `schedule()` function, defined in `kernel/sched.c` (or `/kernel/sched/core.c` in more recent versions)

Timer-interrupt top-half module (old style)

defined in `linux/kernel/timer.c`

```
void do_timer(struct pt_regs *regs)
{
    (*(unsigned long *)&jiffies)++;
    #ifndef CONFIG_SMP
        /* SMP process accounting uses
           the local APIC timer */

        update_process_times(user_mode(regs)) ;
    #endif
    mark_bh(TIMER_BH) ;
    if (TQ_ACTIVE(tq_timer))
        mark_bh(TQUEUE_BH) ;
}
```

Timer-interrupt bottom-half module (old style)

- definito in `linux/kernel/timer.c`

```
void timer_bh(void)
{
    update_times();
    run_timer_list();
}
```

- Where the `run_timer_list()` function takes care of any timer-related action

Kernel 3 example (kernel 4 is quite similar in structure)

```
931 __visible void __irq_entry smp_apic_timer_interrupt(struct pt_regs *regs)
932 {
933     struct pt_regs *old_regs = set_irq_regs(regs);
934
935     /*
936      * NOTE! We'd better ACK the irq immediately,
937      * because timer handling can be slow.
938      *
939      * update_process_times() expects us to have done irq_enter().
940      * Besides, if we don't timer interrupts ignore the global
941      * interrupt lock, which is the WrongThing (tm) to do.
942      */
943     entering_ack_irq();
944     local_apic_timer_interrupt();
945     exiting_irq();
946
947     set_irq_regs(old_regs);
948 }
```

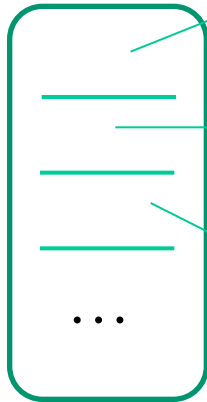

The role of TCBs in common operating systems

- A TCB is a data structure mostly keeping information related to
 - ✓ Schedulability and execution flow control (so scheduler/context specific information)
 - ✓ Linkage with subsystems external to the scheduling one (via linkage to metadata)
 - ✓ Cross thread information sharing: Multiple TBCs can link to the same external metadata (as for multiple threads within a same process)

An example

If and how the CPU scheduling logic should treat this thread

TCB



How the kernel should manage memory and its accesses by this thread (just to tell, do you remember the mem-policy concept?)

How the kernel should manage VFS services on behalf of this thread

```
struct ... {  
    ...  
    ...  
}
```

The scheduling part: CPU-dispatchability

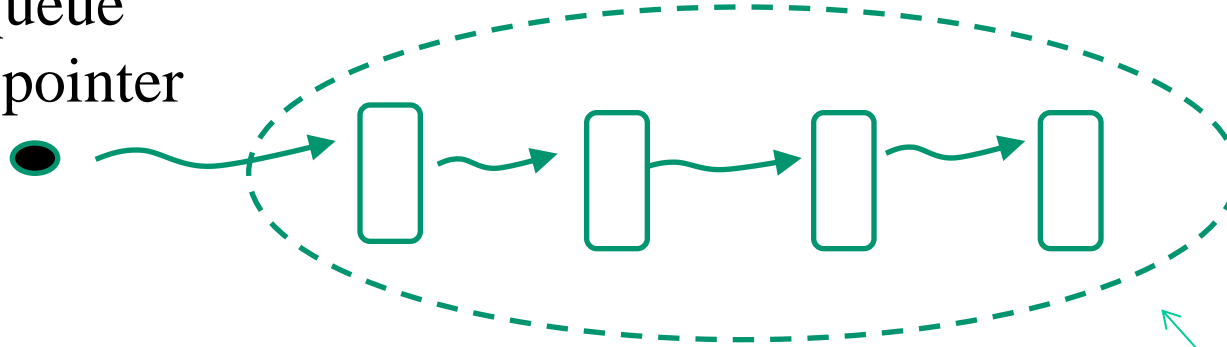
- The TCB tells at any time whether the thread can be CPU-dispatched
- But what s the real meaning of “CPU-dispatchability” ?
- Its means that the scheduler logic (so the corresponding block of code) can decide to pick the CPU-snapshot (context) kept by the TBC and install it on CPU
- CPU-schedulability is not decided by the scheduler logic, rather by other entities (e.g. an interrupt handler)
- So the scheduler logic is simply a selector of currently CPU-dispatchable threads

The scheduling part: run/wait queues

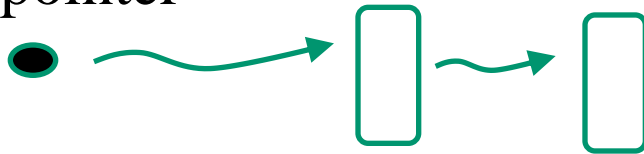
- A thread is CPU-schedulable if its TCB is included into a specific data structure (generally a list)
- This is typically referred to as the **runqueue**
- The scheduler logic selects threads based on ``scans'' of the runqueue
- All the non CPU-schedulable threads are kept on aside data structures (again lists) which are not looked at by the scheduling logic
- These are typically referred to as **waitqueues**

A scheme

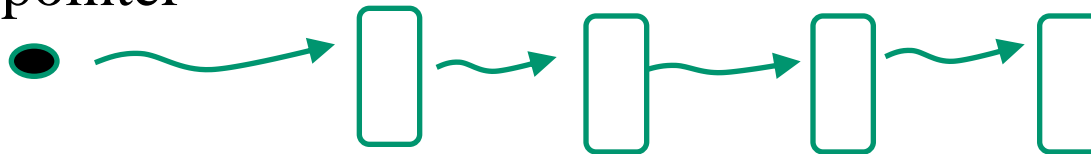
Runqueue
head pointer



Waitqueue A
head pointer



Waitqueue B
head pointer



The scheduler logic only
looks at these TCBs

Scheduler logic vs blocking services

- Clearly the scheduler logic is run on a CPU-core within the context of some generic thread A
- When we end executing the logic the CPU-core can have switched to the context of another thread B
- When thread A is running a blocking service in kernel mode it will synchronously invoke the scheduler logic, but its TCB is currently present on the runqueue
- How to exclude the TCB of thread A from the scheduler selection process?

Sleep/wait kernel services

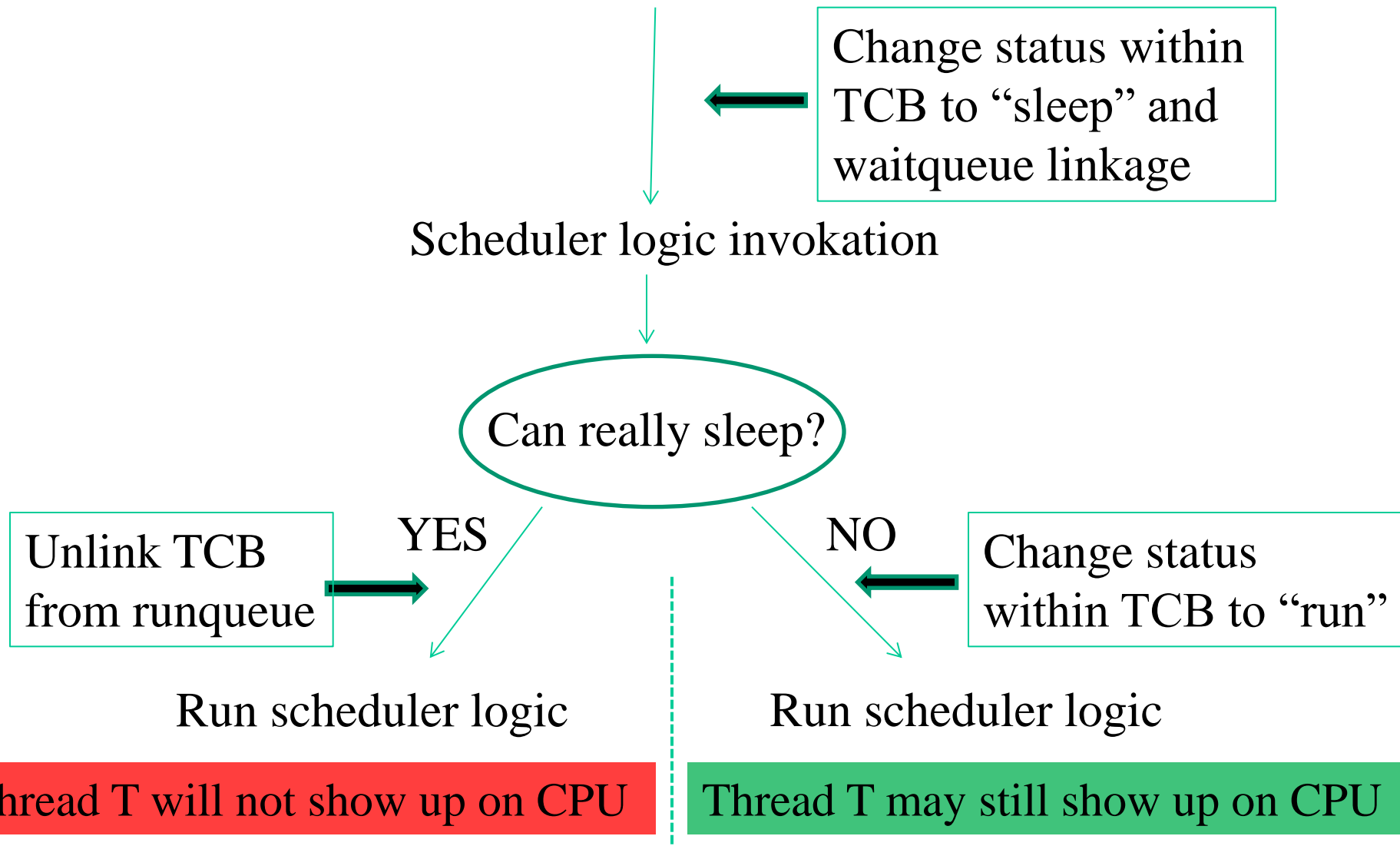
- A blocking service typically relies on well structured kernel level sleep/wait services (and related API)
- These services exploit TCB information to drive, in combination with the scheduler logic, the actual behavior of the service-invoking thread
- Possible outcomes of the invocation of these services:
 - ✓ The TCB of the invoking thread is removed from the runqueue by the scheduler logic before the actual selection of the next thread to run is performed – **the block takes place**
 - ✓ The TCB of the invoking thread still stands on the runqueue during the selection of the next thread to be run – **the block does not take place**

Where does the TCB of a thread invoking a sleep/wait service stand?

- No way, it needs to stand onto some waitqueue
- Well structuring of sleep/wait services is in fact based on an API where we need to pass the ID of some waitqueue in input
- Overall steps of a sleep/wait service:
 1. Link of the TCB of the invoking thread to some waitqueue
 2. Flag the thread as “sleep”
 3. Call the scheduler logic (will really sleep?)
 4. Unlink the TCB of the invoking thread from the wait waitque

Sleep/wait service timeline

sleep/wait API invocation by thread T



Additional features

- **Unlinkage from the waitqueue**
 - ✓ Done by the same thread that was linked upon being rescheduled
- **Relinkage to the runqueue**
 - ✓ Done by other threads when running whatever piece of kernel code such as
 - Synchronously invoked services (e.g. `sys_kill`)
 - Top/botton halves

Actual context switch

- It involves saving into the TCB the CPU context of the switched off the CPU thread
- It involves restoring from the TCB the CPU context of the CPU-dispatched thread
- One core point in changing the CPU context is related to the unique kernel level ``private'' memory each thread has
- This is the kernel level stack
- In most kernel implementations we say that we switch the context when we install a value on the stack pointer

LINUX thread control blocks

- The structure of Linux process control blocks is defined in `include/linux/sched.h` as `struct task_struct`

- The main fields (ref 2.6 kernel) are

- **`volatile long state`**
- **`struct mm_struct *mm`**
- **`pid_t pid`**
- **`pid_t pgrp`**
- **`struct fs_struct *fs`**
- **`struct files_struct *files`**
- **`struct signal_struct *sig`**
- **`volatile long need_resched`**
- **`struct thread_struct thread`** /* CPU-specific state of this task - *TSS* */
- **`long counter`**
- **`long nice`**
- **`unsigned long policy`** /*CPU scheduling info*/

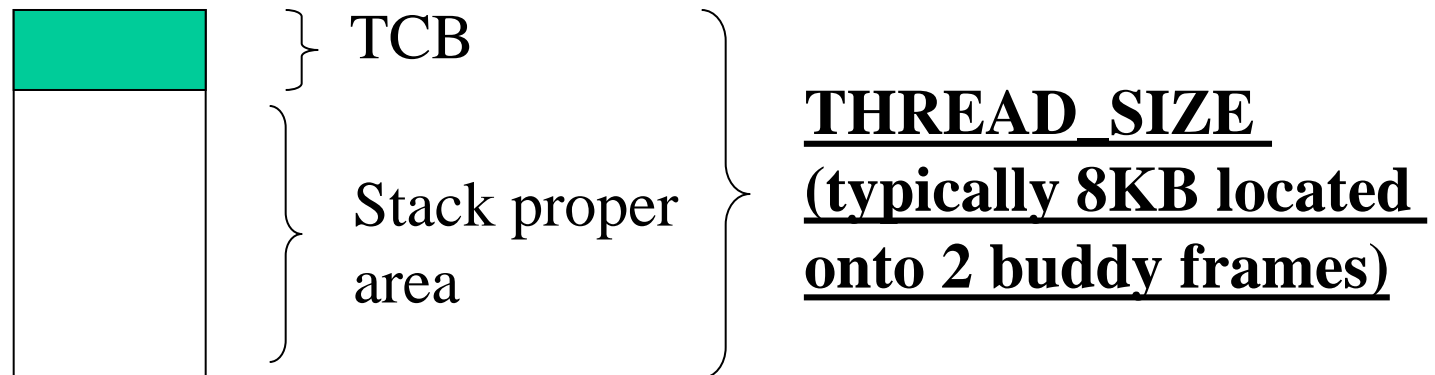
synchronous and asynchronous modifications

More modern kernel versions (3.xx or 4.xx)

- A few info is compacted into bitmasks
 - ✓ e.g. `need_resched` has become a single bit into a bit
- The compacted info can be easily accessed via specific macros/APIs
- More field have been added to reflect new capabilities, e.g., in the Posix specification or LINUX internals
- The main fields are still there, such as
 - `state`
 - `pid`
 - `tgid` (the thread group ID – actual PID)
 - ...

TCB allocation: the case before kernel 2.6

- TCBs are allocated dynamically, whenever requested
- The memory area for the TCB is reserved within the top portion of the kernel level stack of the associated process
- This occurs also for the IDLE PROCESS, hence the kernel stack for this process has base at the address `&init_task+8192`, where `init_task` is the address of the IDLE PROCESS TCB



Implications of the encapsulation of TCB into the stack area

- A single memory allocation request is enough for making per-thread core memory areas available (see `_get_free_pages()`)
- However, TCB size and stack size need to be scaled up in a correlated manner
- This is a limitation when considering that buddy allocation entails buffers with sizes that are powers of 2 times the size of one page
- The growth of the TCB size may lead to
 - ✓ Buffer overflow risks, if the stack size is not rescaled
 - ✓ Memory fragmentation, if the stack size is rescaled

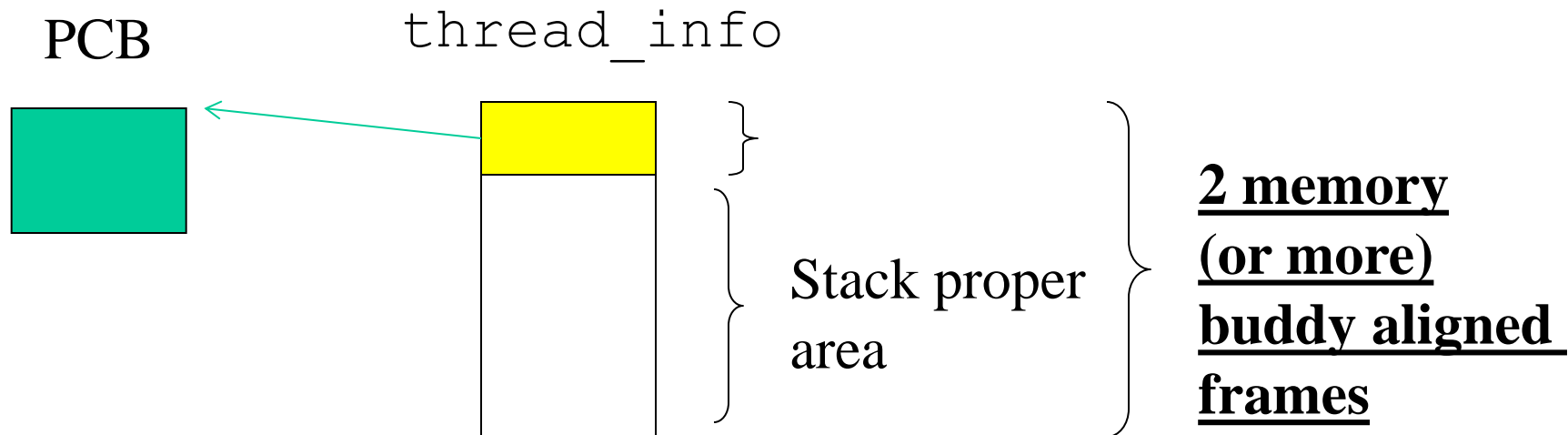
Actual declaration of the kernel level stack data structure

Kernel 2.4.37 example

```
522 union task_union {  
523     struct task_struct task;  
524     unsigned long stack[INIT_TASK_SIZE/sizeof(long)];  
525 };
```


PCB allocation: since kernel 2.6 up to 4.8

- The memory area for the PCB is reserved outside the top portion of the kernel level stack of the associated process
- At the top portion we find a so called `thread_info` data structure
- This is used as an indirection data structure for getting the memory position of the actual PCB
- This allows for improved memory usage with large PCBs



Actual declaration of the kernel level **thread_info** data structure

Kernel 3.19 example

```
26 struct thread_info {
27     struct task_struct *task;          /* main task structure */
28     struct exec_domain *exec_domain;    /* execution domain */
29     __u32 flags;                        /* low level flags */
30     __u32 status; /* thread synchronous flags */
31     __u32 cpu; /* current CPU */
32     int saved_preempt_count;
33     mm_segment_t addr_limit;
34     struct restart_block restart_block;
35     void __user *sysenter_return;
36     unsigned int sig_on_uaccess_error:1;
37     unsigned int uaccess_err:1; /* uaccess failed */
38 };
```

Kernel 4 thread size on x86-64

```
#define THREAD_SIZE_ORDER 2  
#define THREAD_SIZE (PAGE_SIZE << THREAD_SIZE_ORDER)
```



Here we get 16KB

Defined in [arch/x86/include/asm/page_64_types.h](#)
for x86-64

The `current` MACRO

- The macro `current` is used to return the memory address of the TCB of the currently running process/thread (namely the pointer to the corresponding `struct task_struct`)
- This macro performs computation based on the value of the stack pointer (up to kernel 4.8), by exploiting that the stack is aligned to the couple (or higher order) of pages/frames in memory
- This also means that a change of the kernel stack implies a change in the outcome from this macro (and hence in the address of the PCB of the running thread)

Actual computation by current

Old style

Masking of the stack pointer value so to discard the less significant bits that are used to displace into the stack

New style

Masking of the stack pointer value so to discard the less significant bits that are used to displace into the stack

Indirection to the task filed of `thread_info`

More flexibility and isolation: virtually mapped stacks

- Typically we only need logical memory contiguousness for the stack
- On the other hand stack overflow is a serious problem for kernel corruption, especially under attack scenarios
- One approach is to rely on `vmalloc()` for creating a stack allocator
- The advantage is that surrounding pages to the stack area can be set as unmapped
- How do we cope with computation of the address of the TCB under arbitrary positioning of the kernel stack
- The approach taken since kernel 4.9 is to rely on per-cpu-memory on CPUs that support segmentation (e.g. x86)

current on kernel 4.9 or later versions for x86 machines

```
DECLARE_PER_CPU(struct task_struct *, current_task);

static __always_inline struct task_struct
    *get_current(void) {
    return this_cpu_read_stable(current_task);
}
```

Runqueue (2.4 style)

- In `kernel/sched.c` we find the following initialization of an array of pointers to `task_struct`

```
struct task_struct * init_tasks[NR_CPUS]
= {&init_task, }
```

- Starting from the TCB of the IDLE PROCESS we can find a list of TCBs associated with ready-to-run threads
- The addresses of the first and the last TCBs within the list are also kept via the static variable `runqueue_head` of type `struct list_head`

```
struct list_head{struct list_head
*prev, *next; }
```
- The TCB list gets scanned by the `schedule()` function whenever we need to determine the next thread to be dispatched

Waitqueues (2.4 style)

- TCBs can be arranged into lists called wait-queues
- TCBs currently kept within any wait-queue are not scanned by the scheduler module
- We can declare a wait-queue by relying on the macro `DECLARE_WAIT_QUEUE_HEAD(queue)` which is defined in `include/linux/wait.h`
- The following main functions defined in `kernel/sched.c` allow queuing and de-queuing operations into/from wait queues
 - `void interruptible_sleep_on(wait_queue_head_t *q)`
The TCB is no more scanned by the scheduler until it is dequeued or a signal kills the process/thread
 - `void sleep_on(wait_queue_head_t *q)`
Like the above semantic, but signals are don't care events

➤ `void interruptible_sleep_on_timeout(wait_queue_head_t *q, long timeout)`

Dequeuing will occur by timeout or by signaling

➤ `void sleep_on_timeout(wait_queue_head_t *q, long timeout)`

Dequeuing will only occur by timeout

Non selective

➤ `void wake_up(wait_queue_head_t *q)`

Reinstalls onto the ready-to-run queue all the PCBs currently kept by the wait queue `q`

➤ `void wake_up_interruptible(wait_queue_head_t *q)`

Reinstalls onto the ready-to-run queue the PCBs currently kept by the wait queue `q`, which were queued as “interruptible”

(too) Selective

➤ `wake_up_process(struct task_struct * p)`

Reinstalls onto the ready-to-run queue the process whose PCB is pointed by `p`

Thread states

- The state field within the TCB keeps track of the current state of the process/thread
- The set of possible values are defined as follows in `include/linux/sched.h`
 - `#define TASK_RUNNING` 0
 - `#define TASK_INTERRUPTIBLE` 1
 - `#define TASK_UNINTERRUPTIBLE` 2
 - `#define TASK_ZOMBIE` 4
 - `#define TASK_STOPPED` 8
- All the TCBs recorded within the run-queue keep the value `TASK_RUNNING`
- The two values `TASK_INTERRUPTIBLE` and `TASK_UNINTERRUPTIBLE` discriminate the wakeup conditions from any waitqueue

Wait vs run queues

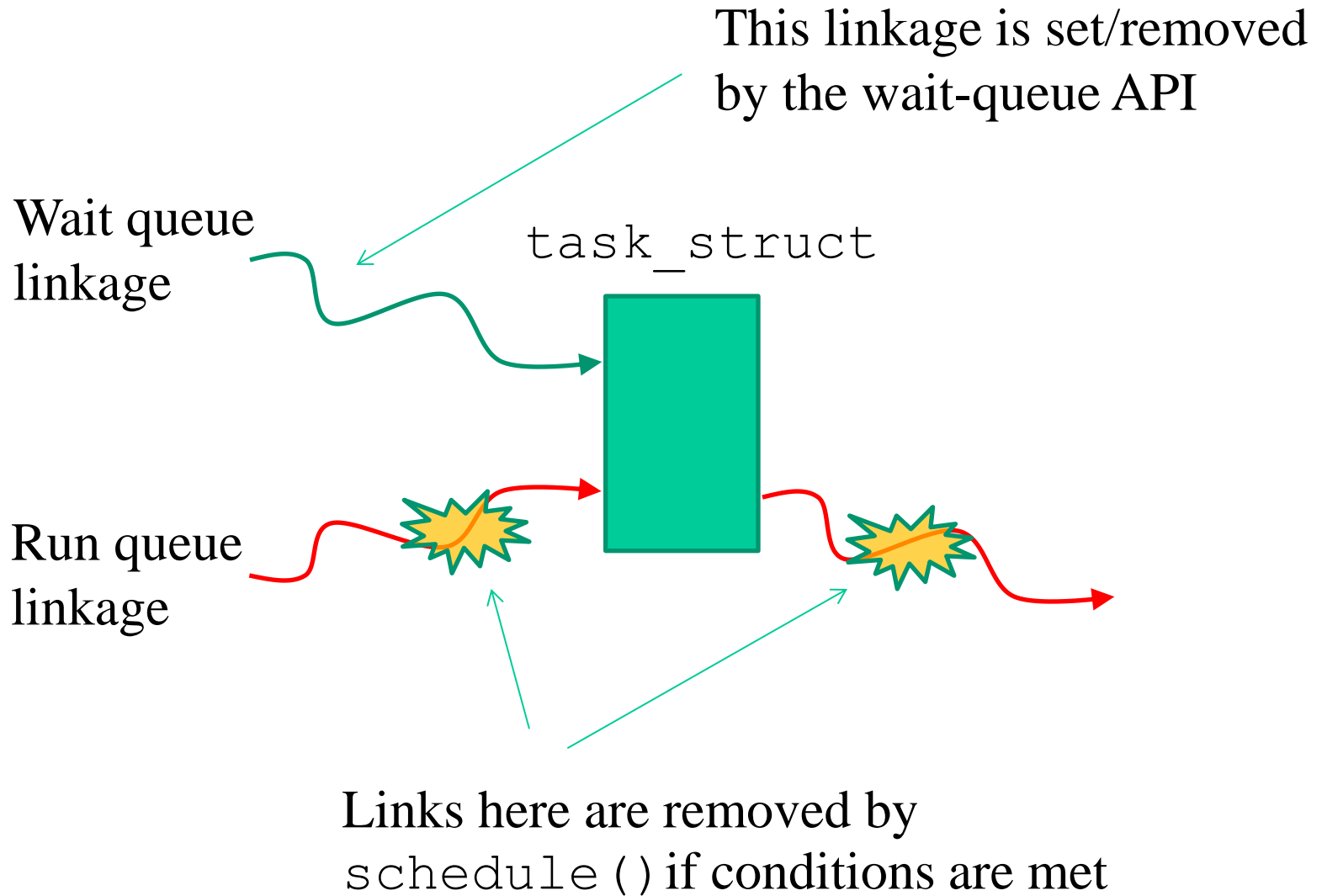
- as hinted, sleep functions for wait queues also manage the unlinking from the wait queue upon returning from the schedule operation

```
#define SLEEP_ON_HEAD \
    wq_write_lock_irqsave(&q->lock, flags); \
    __add_wait_queue(q, &wait); \
    wq_write_unlock(&q->lock);

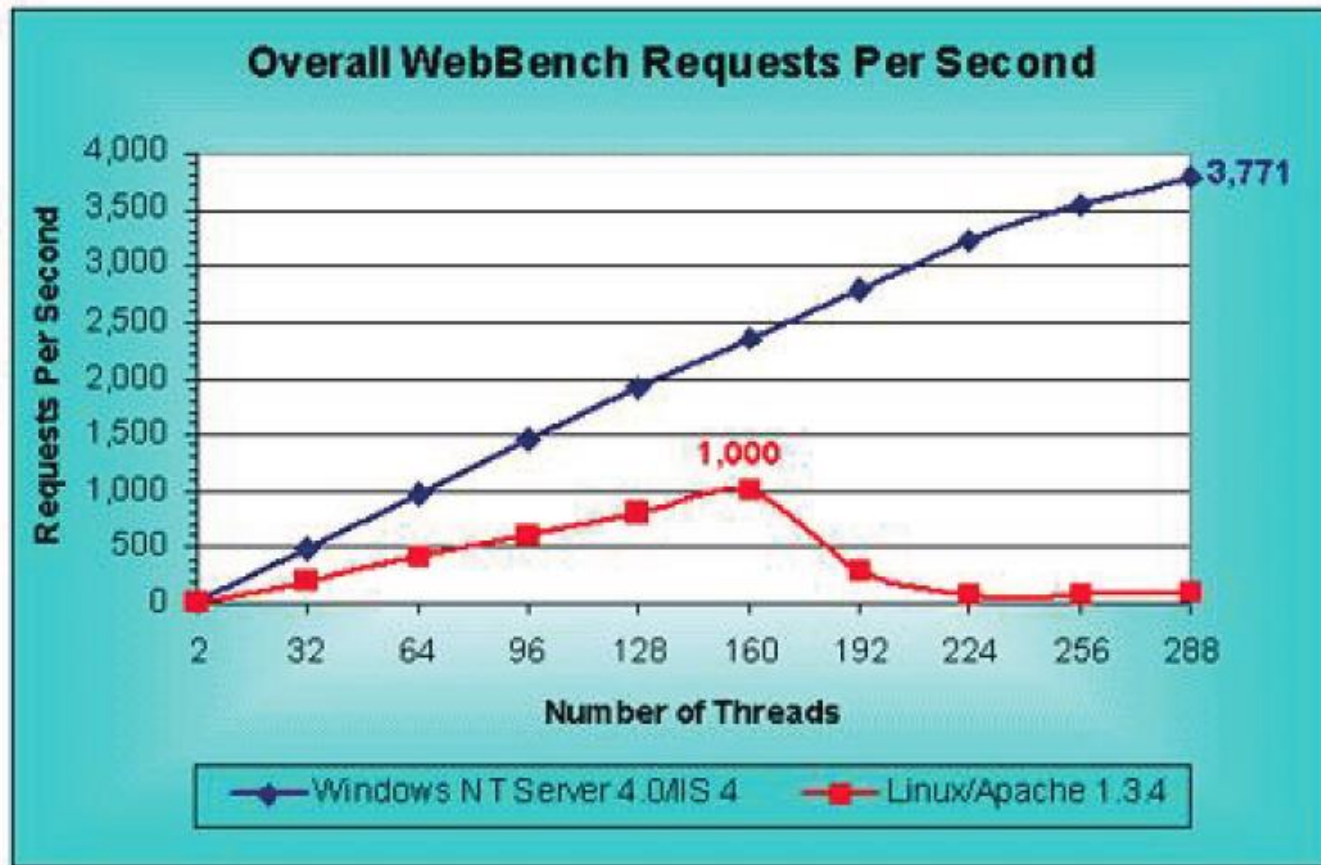
#define SLEEP_ON_TAIL \
    wq_write_lock_irq(&q->lock); \
    __remove_wait_queue(q, &wait); \
    wq_write_unlock_irqrestore(&q->lock, flags);

void interruptible_sleep_on(wait_queue_head_t *q) {
    SLEEP_ON_VAR
    current->state = TASK_INTERRUPTIBLE;
    SLEEP_ON_HEAD
    schedule();
    SLEEP_ON_TAIL
}
```

TCB linkage dynamics



Thundering herd effect



Taken from 1999 Mindcraft study on Web and File Server Comparison

The new style: wait event queues

- They allow to drive thread awake via conditions
- The conditions for a same queue can be different for different threads
- This allows for selective awakes depending on what condition is actually fired
- The scheme is based on polling the conditions upon awake, and on consequent re-sleep

Conditional waits –one example

Name

`wait_event_interruptible` — sleep until a condition gets true

Synopsis

```
wait_event_interruptible (wq,  
                        condition);
```

Arguments

wq

the waitqueue to wait on

condition

a C expression for the event to wait for

Description

The process is put to sleep (TASK_INTERRUPTIBLE) until the *condition* evaluates to true or a signal is received. The *condition* is checked each time the waitqueue *wq* is woken up.

`wake_up` has to be called after changing any variable that could change the result of the wait condition.

The function will return `-ERESTARTSYS` if it was interrupted by a signal and 0 if *condition* evaluated to true.

Wider (not exhaustive) conditional wait queue API

```
wait_event( wq, condition )
```

```
wait_event_timeout( wq, condition, timeout )
```

```
wait_event_freezable( wq, condition )
```

```
wait_event_command( wq, condition, pre-command,  
                    post-command)
```

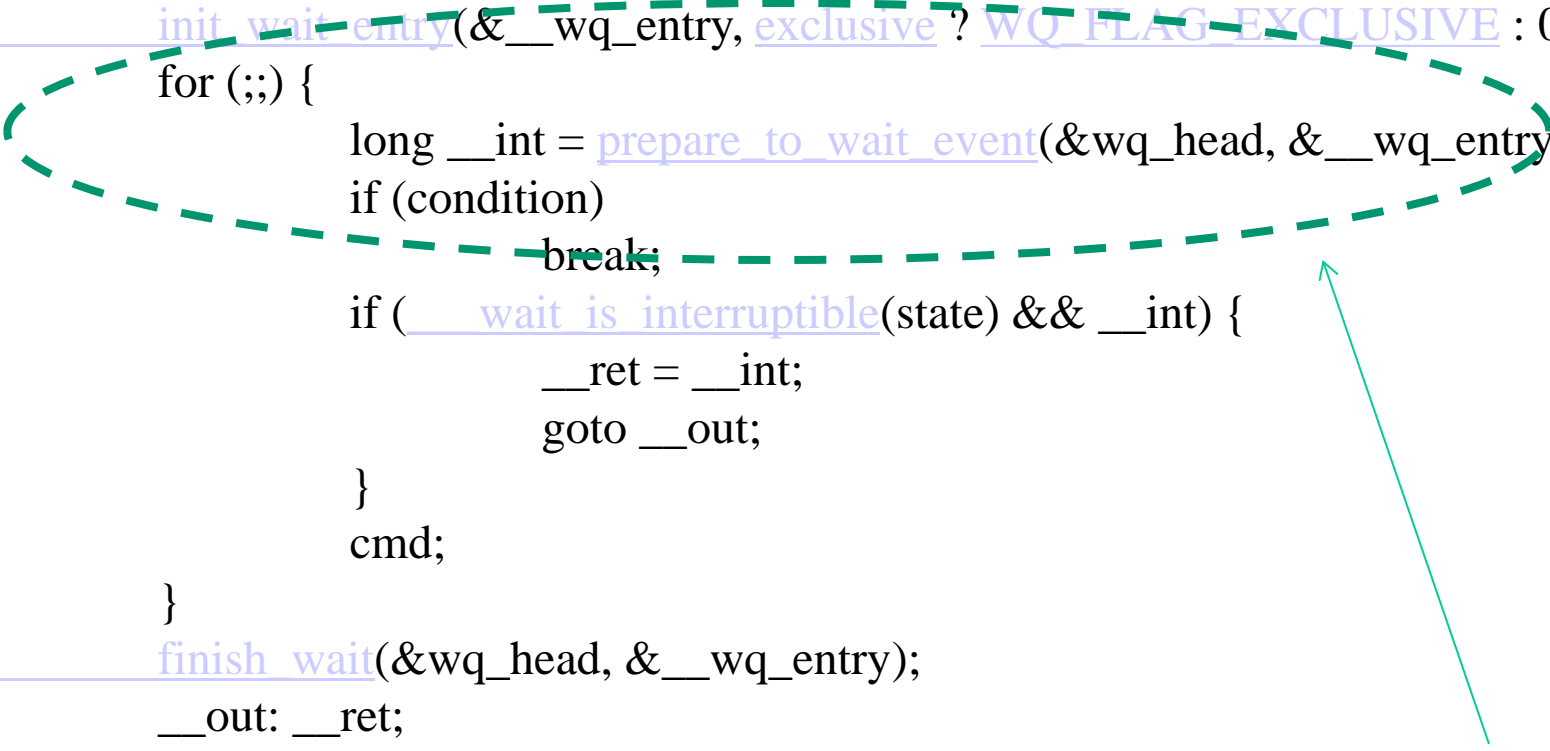
```
wait_on_bit( unsigned long * word, int bit,  
             unsigned mode)
```

```
wait_on_bit_timeout( unsigned long * word, int bit,  
                    unsigned mode, unsigned long timeout)
```

```
wake_up_bit( void* word, int bit)
```

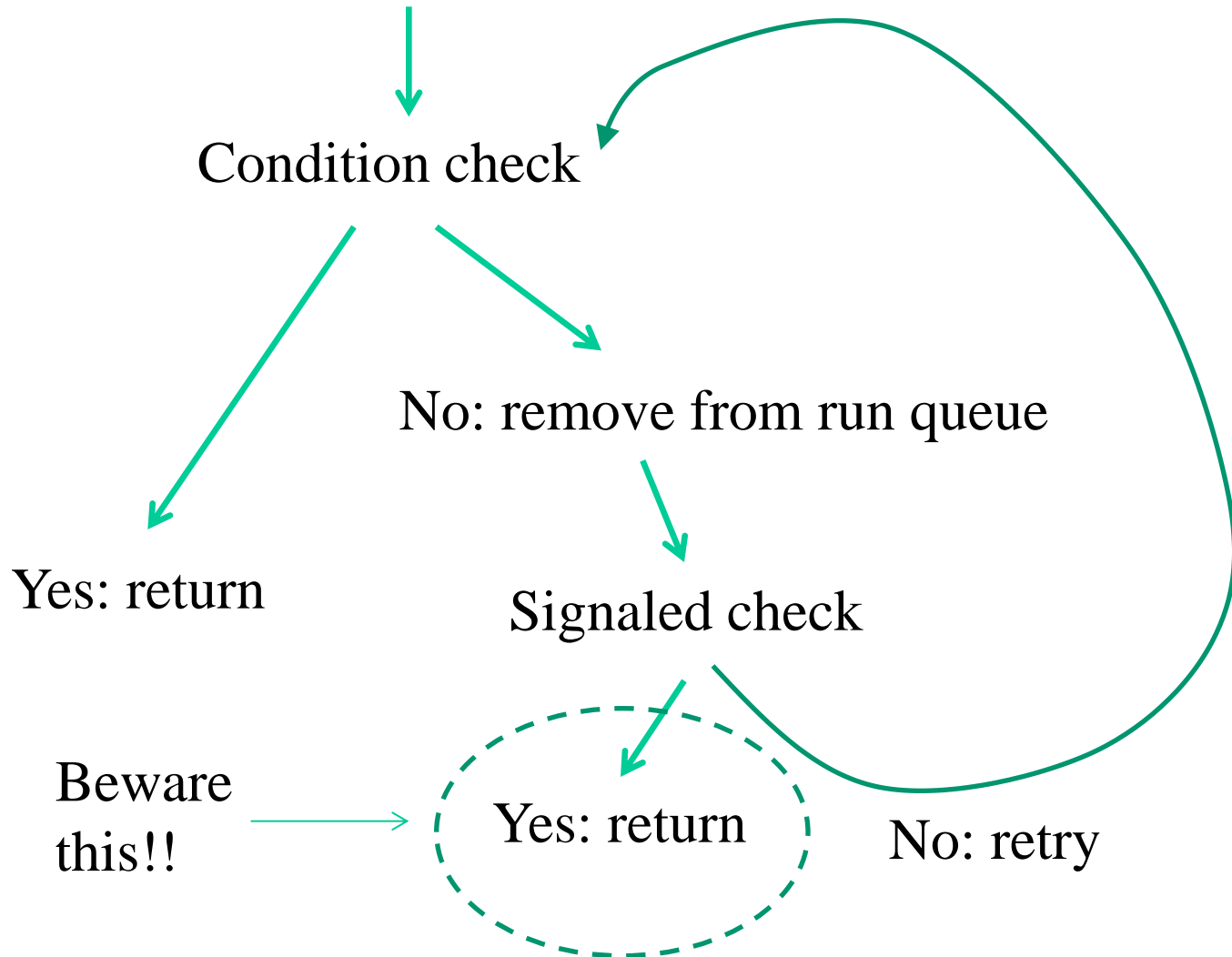
Macro based expansion

```
#define wait_event(wq_head, condition, state, exclusive, ret, cmd) \
({ \
    __label__ __out; \
    struct wait_queue_entry __wq_entry; \
    long __ret = ret; /* explicit shadow */ \
    init_wait_entry(&__wq_entry, exclusive ? WQ_FLAG_EXCLUSIVE : 0); \
    for (;;) { \
        long __int = prepare_to_wait_event(&wq_head, &__wq_entry, state); \
        if (condition) \
            break; \
        if (wait_is_interruptible(state) && __int) { \
            __ret = __int; \
            goto __out; \
        } \
        cmd; \
    } \
    finish_wait(&wq_head, &__wq_entry); \
    __out: __ret; \
})
```



The diagram illustrates a cycle-based approach. A dashed green oval encircles the loop body of the macro, specifically the lines from `long __int = prepare_to_wait_event` to `goto __out;`. A green arrow points from the text "Cycle based approach" at the bottom right to the dashed oval.

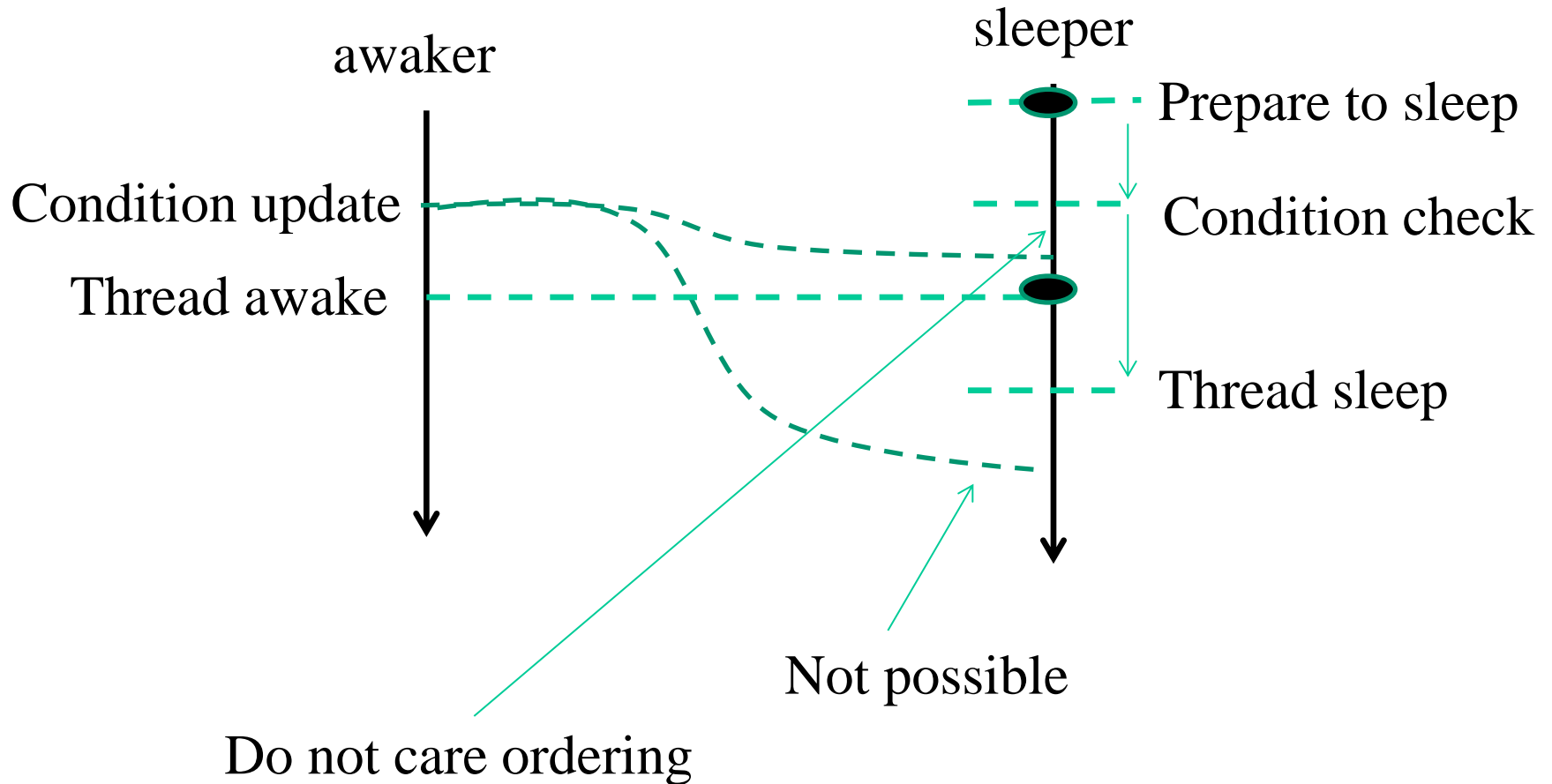
The scheme for interruptible waits



Linearizability

- The actual management of condition checks prevents any possibility of false negatives in scenarios with concurrent threads
- This is still due to the fact that removal from the run queue occurs within the `schedule()` function
- The removal leads to spinlock the TCB
- On the other hand the awake API leads to spinlock the TCS too for updating the thread status and (possibly) relinking it to the run queue
- This leads to memory synchronization (e.g. TSO bypass avoidance)
- The locked actions represent the linearization point of the operations
- An awake updates the thread state after the condition has been set
- A wait checks the condition before checking the thread state via `schedule()`

A scheme



The mm field in the TCB

- The mm of the TCB points to a memory area structured as `mm_struct` which is defined in `include/linux/sched.h` or `include/linux/mm_types.h` in more recent kernel versions
- This area keeps information used for memory management purposes for the specific process, such as
 - Virtual address of the page table (`pgd` field)
 - A pointer to a list of records structured as `vm_area_struct` (`mmap` field)
- Each record keeps track of information related to a specific virtual memory area (user level) which is valid for the process

vm_area_struct

```
struct vm_area_struct {
    struct mm_struct * vm_mm; /* The address space we belong to. */
    unsigned long vm_start; /* Our start address within vm_mm. */
    unsigned long vm_end; /* The first byte after our end address
                           within vm_mm. */

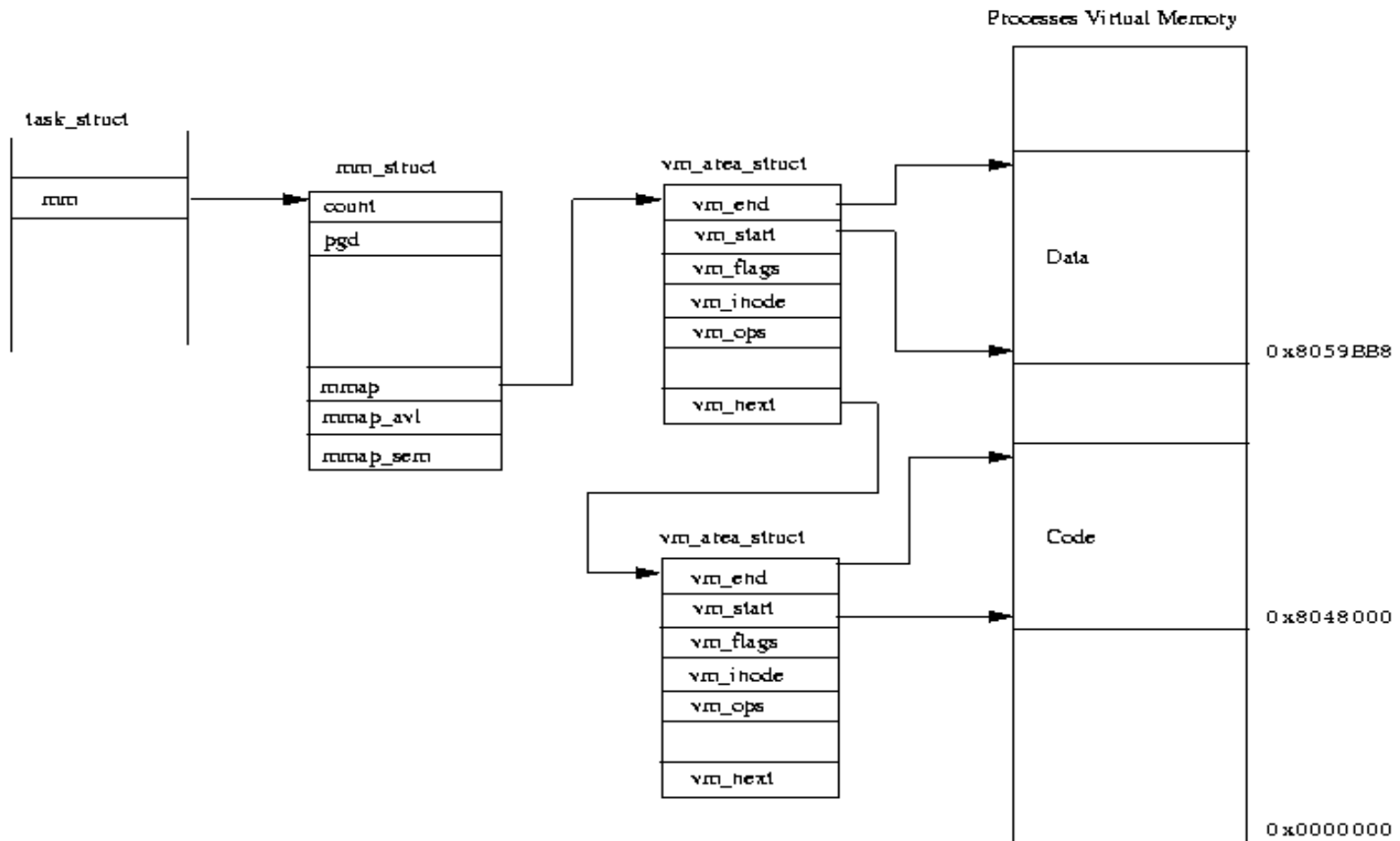
    struct vm_area_struct *vm_next;
    pgprot_t vm_page_prot; /* Access permissions of this VMA. */

    .....
    /* Function pointers to deal with this struct. */
    struct vm_operations_struct * vm_ops;
    .....
};
```

- The `vm_ops` field points to a structure used to define the treatment of faults occurring within that virtual memory area
- This is specified via the field `nopage` or `fault`
- As an example this pointer identifies a function signed as

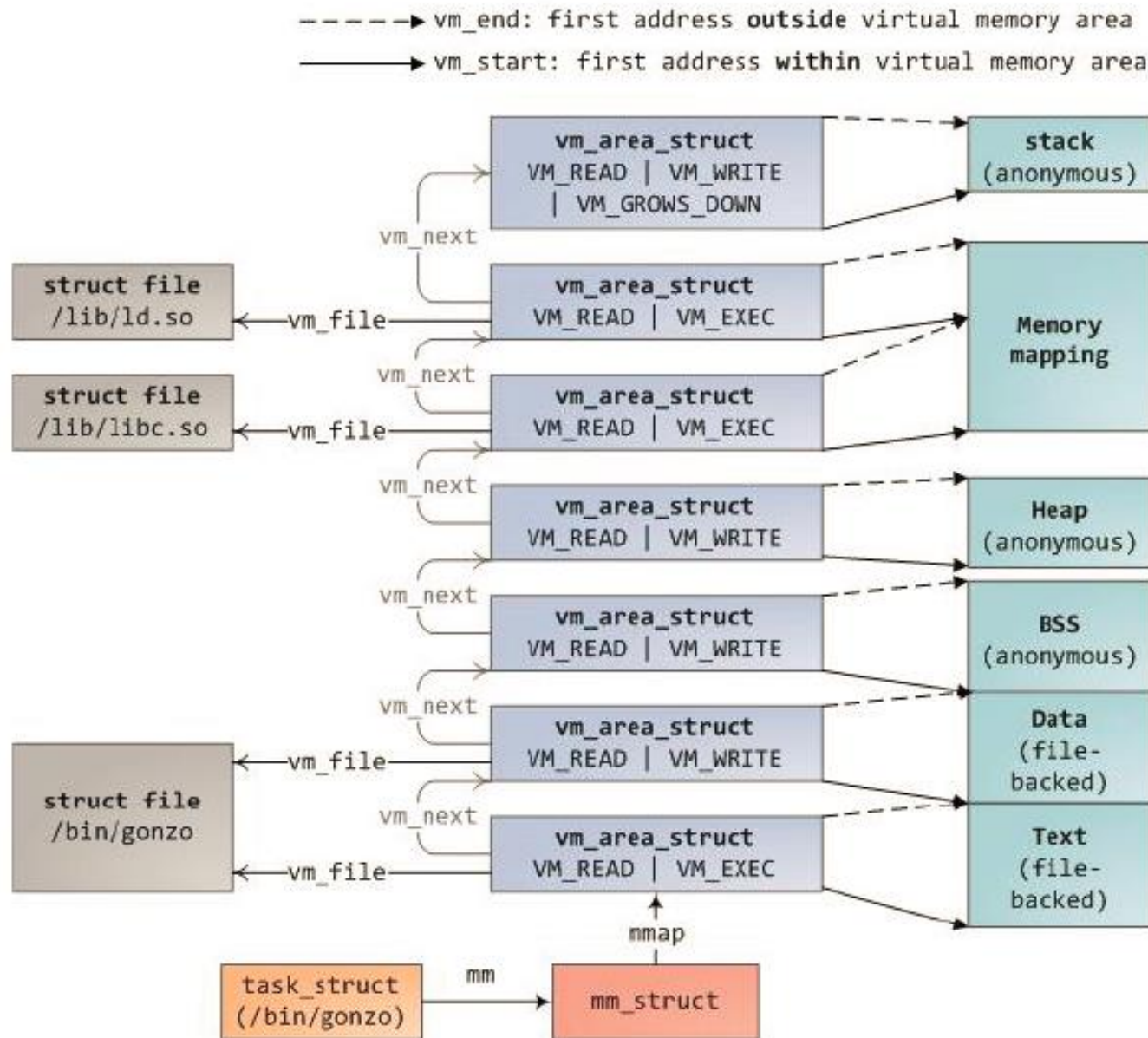
```
struct page * (*nopage)(struct vm_area_struct * area,  
    unsigned long address, int unused)
```

A scheme



- The executable format for Linux is ELF
- This format specifies, for each section (text, data) the positioning within the virtual memory layout, and the access permission

An example



Threads identification

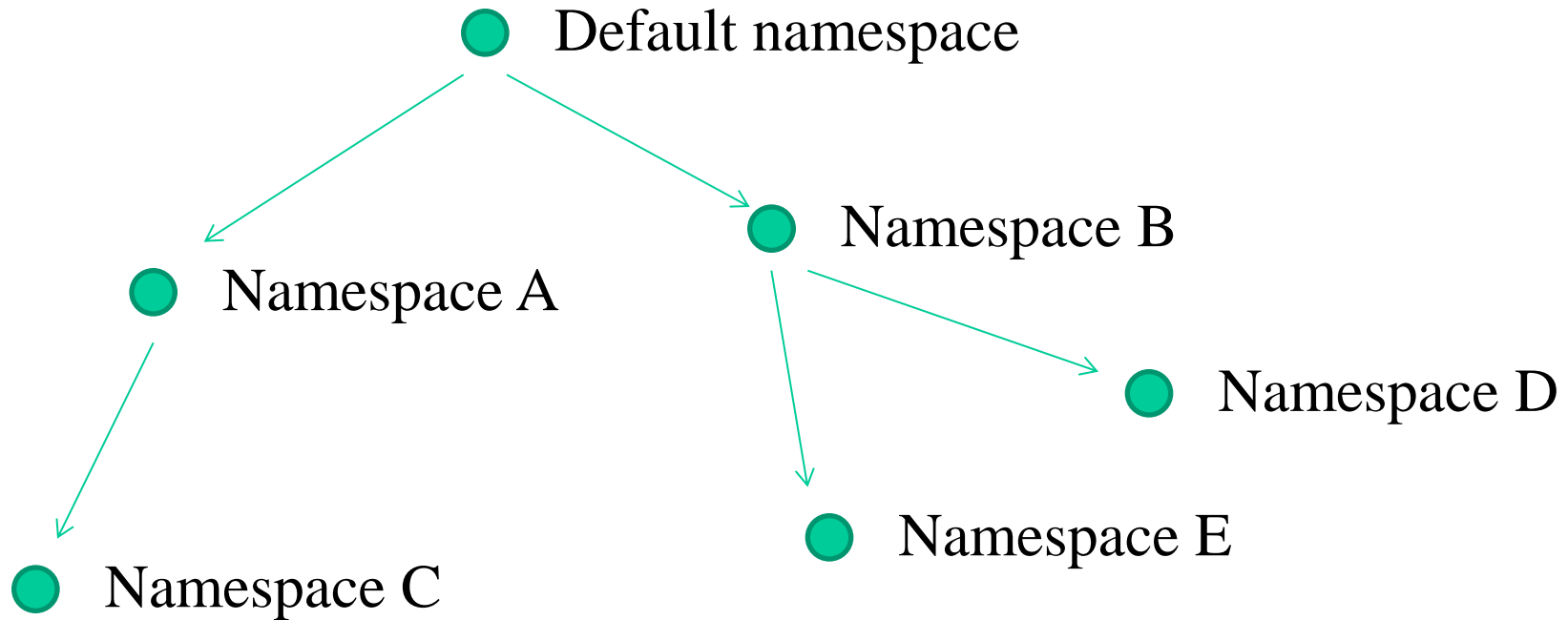
- In modern implementations of OS kernels we can also virtualize PIDs
- So each thread may have more than one PID
 - ✓ a real one (say `current->pid`)
 - ✓ a virtual one
- This concept is linked to the notion of **namespaces**
- Depending on the namespace we are working with then one PID value (not the other) is the reference one for a set of common operations
- As an example, if we call the `ppid()` system call, then the id that is returned is the PID of the parent thread referring to the current namespace of the invoking one

PID namespace scheme

- The baseline kernel namespace is by default used to set the value `current->pid`
- When a new thread is created, then we can specify to move to another PID namespace, which becomes a child level PID namespace with respect to the current one
- A maximum of 32 levels of PID namespaces can be used in Linux, based on the define

```
#define MAX_PID_NS_LEVEL 32
```

A representation

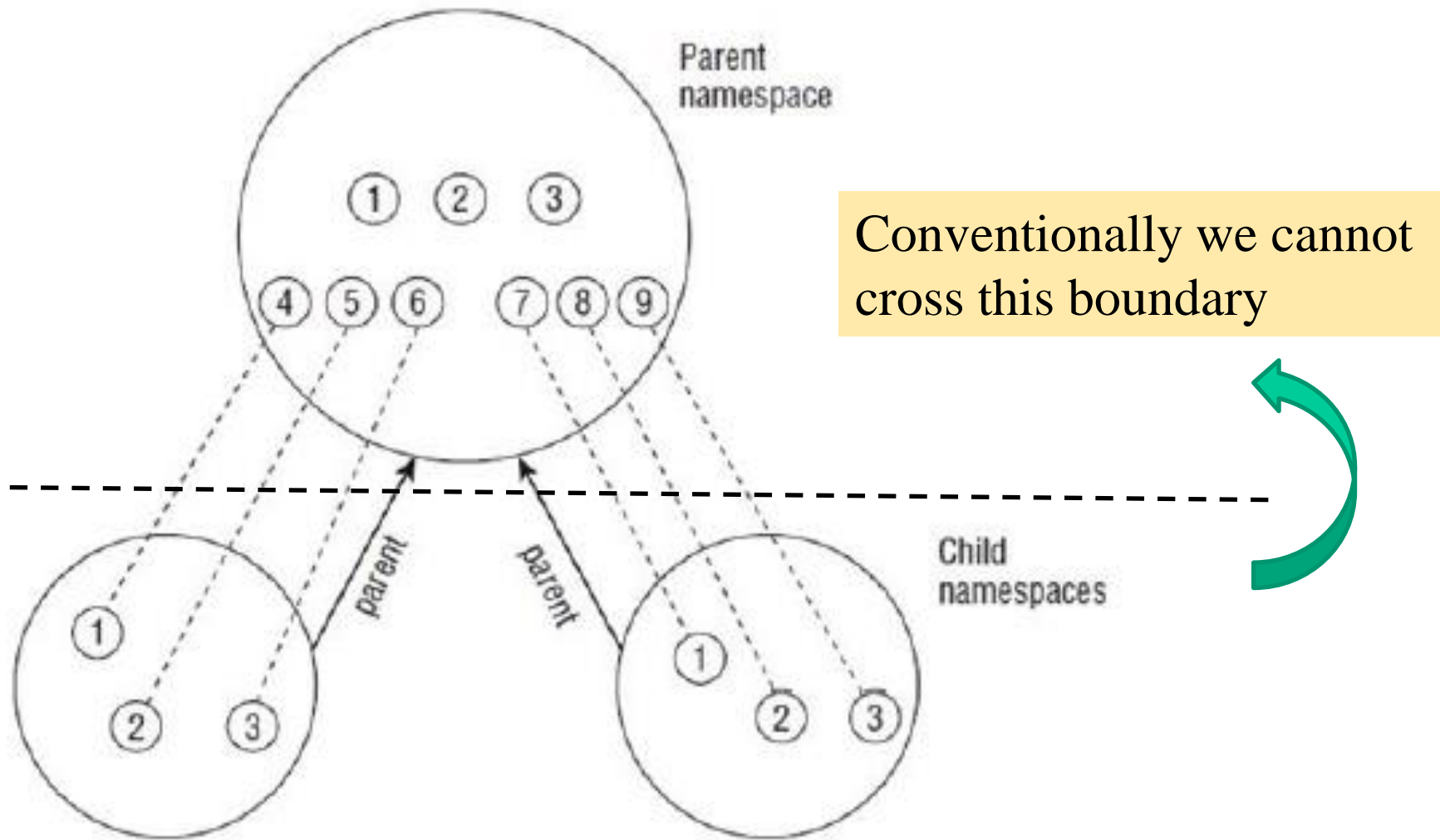


thread whose creation leads to create a new namespace has virtual PID set to 1 in that namespace, and its ancestor is PID zero

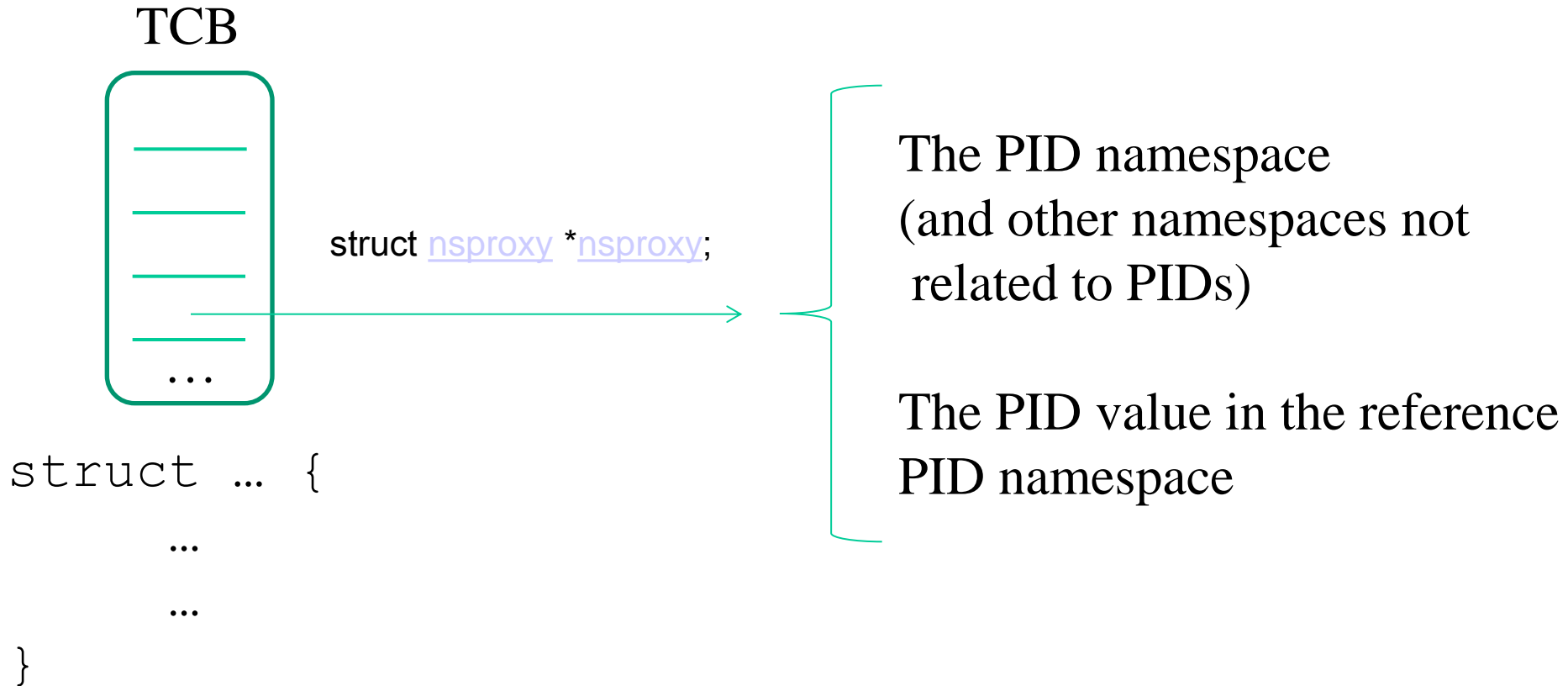
Namespace visibility

- By relying on common OS kernel services, a thread that leaves in a given namespace has no visibility of ancestor namespaces
- So it cannot “see” the existence of ancestor threads
- As an example, we cannot kill threads living into ancestral namespaces
- A namespace is therefore a sort of container (a concept you should be already familiar with)
- **NOTE:** all the above is true in an agreed upon environmental settings, it can change if we modify kernel operations

A scheme



The implementation



PID to `task_struct` mappings

- A lot of kernel services work by using the address of the TCB of a thread (see awake from sleep/wait queues)
- So we need a mapping between PIDs and TCB addressed
- The mapping is based on linked data, such as TCB linkage or namespaces linkage
- So Linux offers services for transparently traversing these linkages

Accessing TCBs in the default namespace (the only one existing originally)

- TCBs were linked in various lists with hash access supported via the below fields within the PCB structure

```
/* PID hash table linkage. */  
struct task_struct *pidhash_next;  
struct task_struct **pidhash_pprev;
```

- There existed a hashing structure defined as below in `include/linux/sched.h`

```
#define PIDHASH_SZ (4096 >> 2)  
extern struct task_struct *pidhash[PIDHASH_SZ];  
#define pid_hashfn(x) (((x) >> 8) ^ (x)) & (PIDHASH_SZ  
- 1))
```

- We also have the following function (of `static` type), still defined in `include/linux/sched.h` which allows retrieving the memory address of the PCB by passing the process/thread `pid` as input

```
static inline struct task_struct *find_task_by_pid(int
pid) {
    struct task_struct *p,
        **htable = &pidhash[pid_hashfn(pid)];

    for(p = *htable; p && p->pid != pid;
        p = p->pidhash_next) ;
    return p;
}
```

Querying across namespaces

- The newer kernel versions (e.g. ≥ 2.6) support

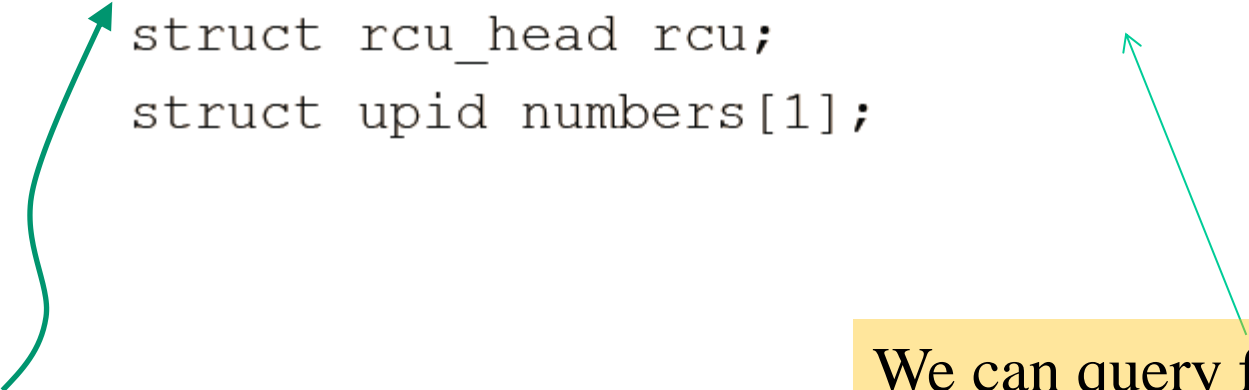
```
struct task_struct  
*find_task_by_vpid(pid_t vpid)
```

- This is based on the notion of virtual pid (so the one in the current namespace we are working with)
- We access a hashing system that more or less directly links vPIDs to TCBs
- The vPID of thread by default coincides with its PID if no namespace different from the default one is setup

vPIDs hashing

- It is based on a specific data structure

```
struct pid {  
    atomic_t count;  
    unsigned int level;  
    /* lists of tasks that use this pid */  
    struct hlist_head tasks[PIDTYPE_MAX];  
    struct rcu_head rcu;  
    struct upid numbers[1];  
};
```

A diagram with two green arrows. One arrow starts from a yellow box at the bottom left and points to the 'tasks' array in the struct definition. The other arrow starts from a yellow box at the bottom right and points to the 'numbers' array in the struct definition.

When accessing the target PID records we can match with the namespace of the caller

We can query for individuals or groups

Managing virtual PIDs in Linux modules

```
struct task_struct *pid_task(struct pid *pid, enum  
pid_type);
```

PIDTYPE_PID or other

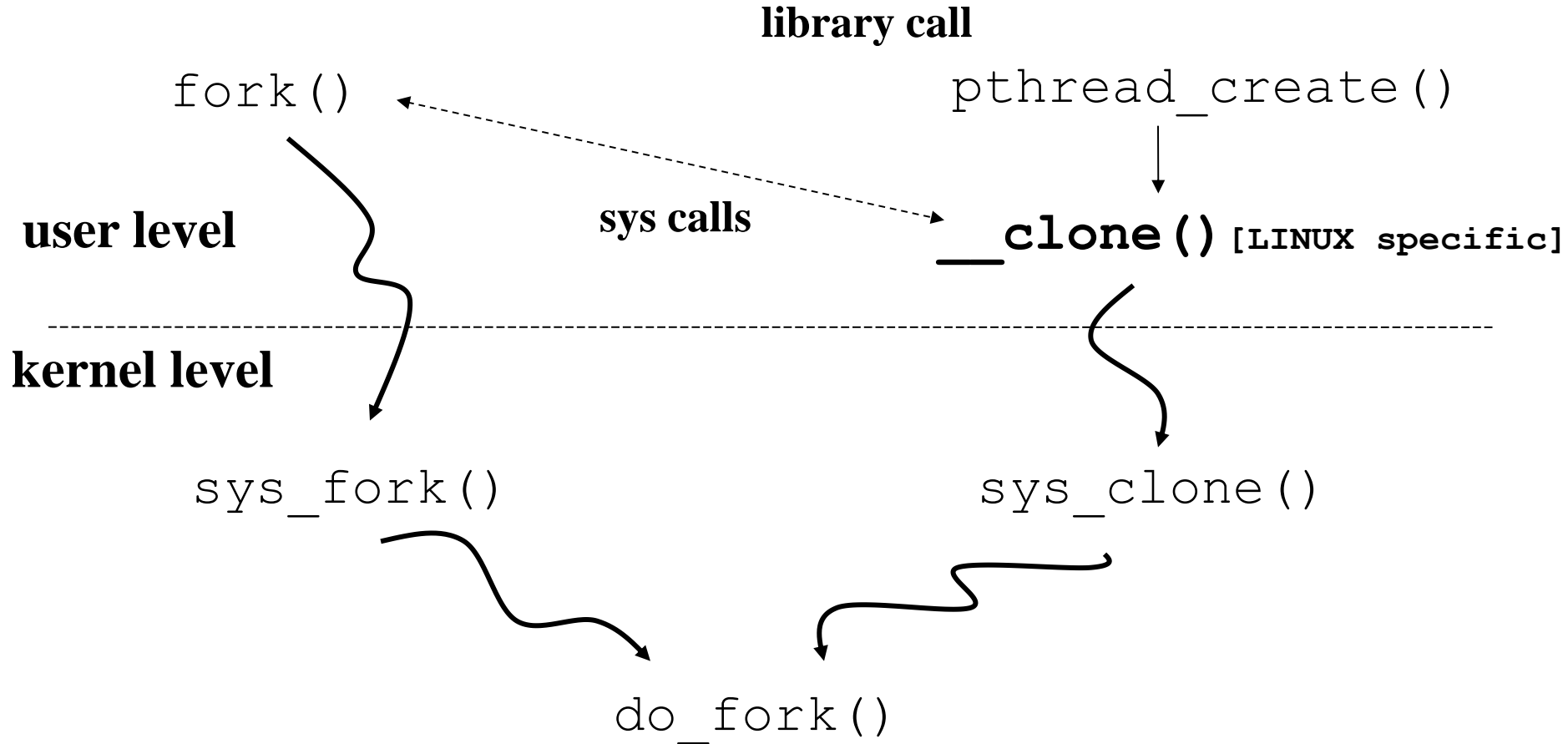
find_vpid(pid)



```
pid_task(find_vpid(pid), PIDTYPE_PID);
```

Querying the TCB address by the default PID

Process and thread creation



The glibc interface

Return value mapped to thread exit code

NAME [top](#)

`clone`, `__clone2` - create a child process

Parameters can vary in number and order

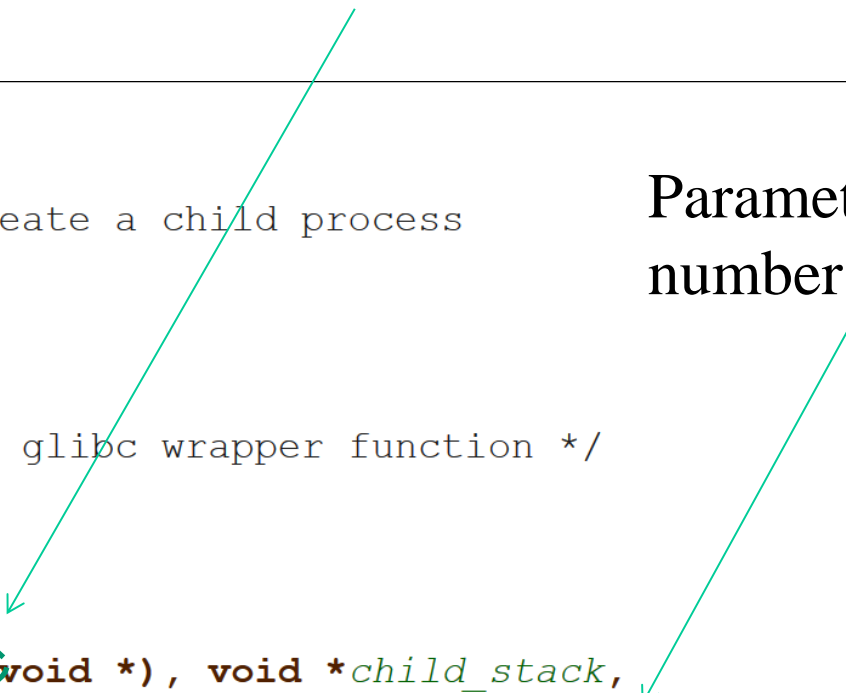
SYNOPSIS [top](#)

```
/* Prototype for the glibc wrapper function */

#define _GNU_SOURCE
#include <sched.h>

int clone(int (*fn)(void *), void *child_stack,
         int flags, void *arg, ...
         /* pid_t *ptid, void *newtls, pid_t *ctid */ );

/* For the prototype of the raw system call, see NOTES */
```

A diagram with two green arrows pointing from the text 'Parameters can vary in number and order' to the function signature of `clone`. One arrow points to the first parameter `int (*fn)(void *)`, which is circled with a dashed green line. The other arrow points to the `int flags` parameter.

DESCRIPTION [top](#)

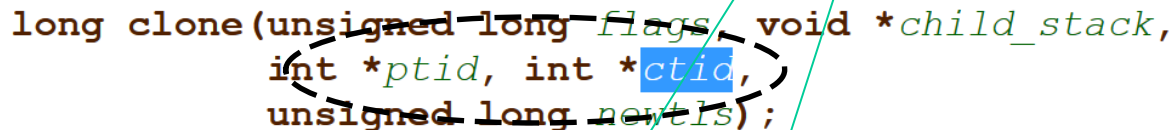
`clone()` creates a new process, in a manner similar to `fork(2)`.

Architecture specific interfaces

Newer pthreadXX () services

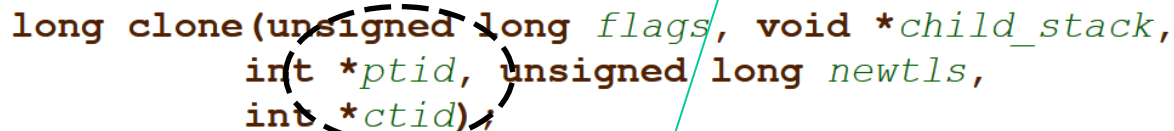
The raw system call interface on x86-64 and some other architectures (including sh, tile, and alpha) is:

```
long clone(unsigned long flags, void *child_stack,  
          int *ptid, int *ctid,  
          unsigned long newtls);
```



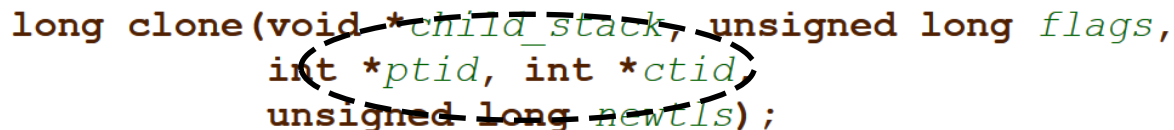
On x86-32, and several other common architectures (including score, ARM, ARM 64, PA-RISC, arc, Power PC, xtensa, and MIPS), the order of the last two arguments is reversed:

```
long clone(unsigned long flags, void *child_stack,  
          int *ptid, unsigned long newtls,  
          int *ctid);
```



On the cris and s390 architectures, the order of the first two arguments is reversed:

```
long clone(void *child_stack, unsigned long flags,  
          int *ptid, int *ctid,  
          unsigned long newtls);
```



The flags (not exhaustive)

<code>CLONE_VM</code>	VM shared between processes
<code>CLONE_FS</code>	fs info shared between processes
<code>CLONE_FILES</code>	open files shared between processes
<code>CLONE_PARENT</code>	we want to have the same parent as the cloner
<code>CLONE_NEWPID</code>	create the process/thread in a new PID namespace
<code>CLONE_SETTLS</code>	the TLS (Thread Local Storage) descriptor is set to newtls
<code>CLONE_THREAD</code>	the child is placed in the same thread group as the calling process

do_fork overview

- Allocate a TCB
- Allocate a stack area
- Get the proper PID (real/virtual)
- Link the parent memory map?
- Link the parent FS view?
- Link the parent files view ?
- share ticks with parent!!!

Synchronization abstractions

```
DECLARE_MUTEX(name);  
/* declares struct semaphore <name> ... */  
  
void sema_init(struct semaphore *sem, int val);  
/* alternative to DECLARE_... */  
void down(struct semaphore *sem); /* may sleep */  
  
int down_interruptible(struct semaphore *sem);  
/* may sleep; returns -EINTR on interrupt */  
  
int down_trylock(struct semaphore *sem);  
/* returns 0 if succeeded; will no sleep */  
  
void up(struct semaphore *sem);
```

Spinlock API

```
#include <linux/spinlock.h>
```

```
spinlock_t my_lock = SPINLOCK_UNLOCKED;
```

```
spin_lock_init(spinlock_t *lock);
```

```
spin_lock(spinlock_t *lock);
```

```
spin_lock_irqsave(spinlock_t *lock, unsigned long flags);
```

```
spin_lock_irq(spinlock_t *lock);
```

```
spin_lock_bh(spinlock_t *lock);
```

```
spin_unlock(spinlock_t *lock);
```

```
spin_unlock_irqrestore(spinlock_t *lock,  
                        unsigned long flags);
```

```
spin_unlock_irq(spinlock_t *lock);
```

```
spin_unlock_bh(spinlock_t *lock);
```

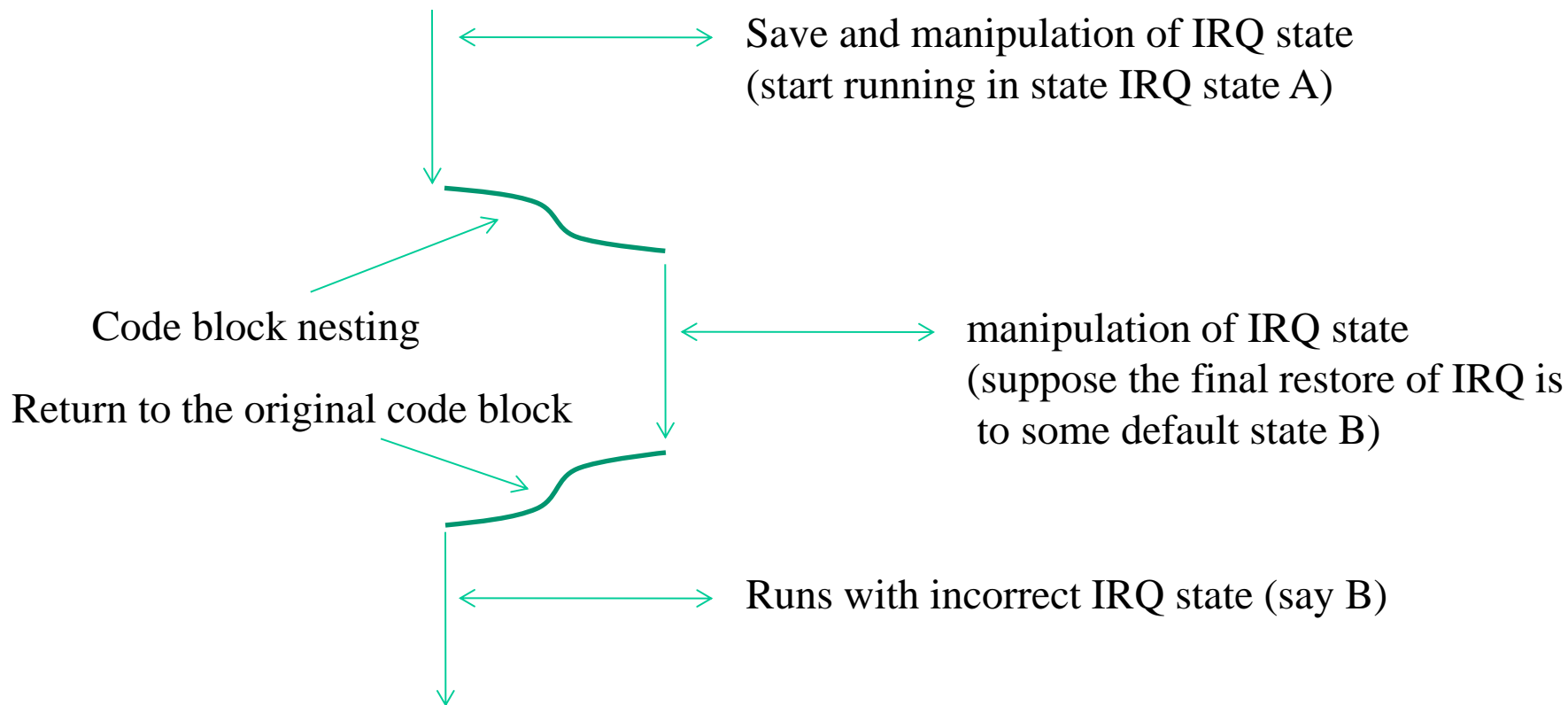
```
spin_is_locked(spinlock_t *lock);
```

```
spin_trylock(spinlock_t *lock)
```

```
spin_unlock_wait(spinlock_t *lock);
```

The “save” version

- it allows not to interfere with IRQ management along the path where the call is nested
- a simple masking (with no saving) of the IRQ state may lead to misbehavior



Variants (discriminating readers vs writers)

```
rwlock_t xxx_lock = __RW_LOCK_UNLOCKED(xxx_lock);  
unsigned long flags;
```

```
read_lock_irqsave(&xxx_lock, flags);  
.. critical section that only reads the info ...  
read_unlock_irqrestore(&xxx_lock, flags);
```

```
write_lock_irqsave(&xxx_lock, flags);  
.. read and write exclusive access to the info ...  
write_unlock_irqrestore(&xxx_lock, flags);
```

Scheduler logic insights

- The planning of tick usage is based on epochs
- An epoch ends when all threads on the runqueue have already ended their ticks
- Threads on waitqueues may still have residuals
- When an epoch ends we recompute the ticks to be assigned to all threads for the next epoch
- Assigned tick volumes reflect priorities

Scheduler logic: perfect loads sharing

- What TCB do we look at upon the execution of `schedule()`?
- ALL those that are not on a waitque
- Ideally any thread can be CPU-dispatched on any CPU-core at any time instant
- CPU-scheduling decisions based on priorities and on the target of maximizing hardware effectiveness (e.g. caching)

The 2.4 kernel perfect load sharing scheduler

- The execution of the function `schedule()` can be seen as entailing 3 distinct phases:
 - check on the current process (do we really need to be removed from the runqueue)
 - “Run-queue analysis” (next process selection) of the unique runqueue in the overall system – affinity still works here
 - context switch to the next process (actually thread)

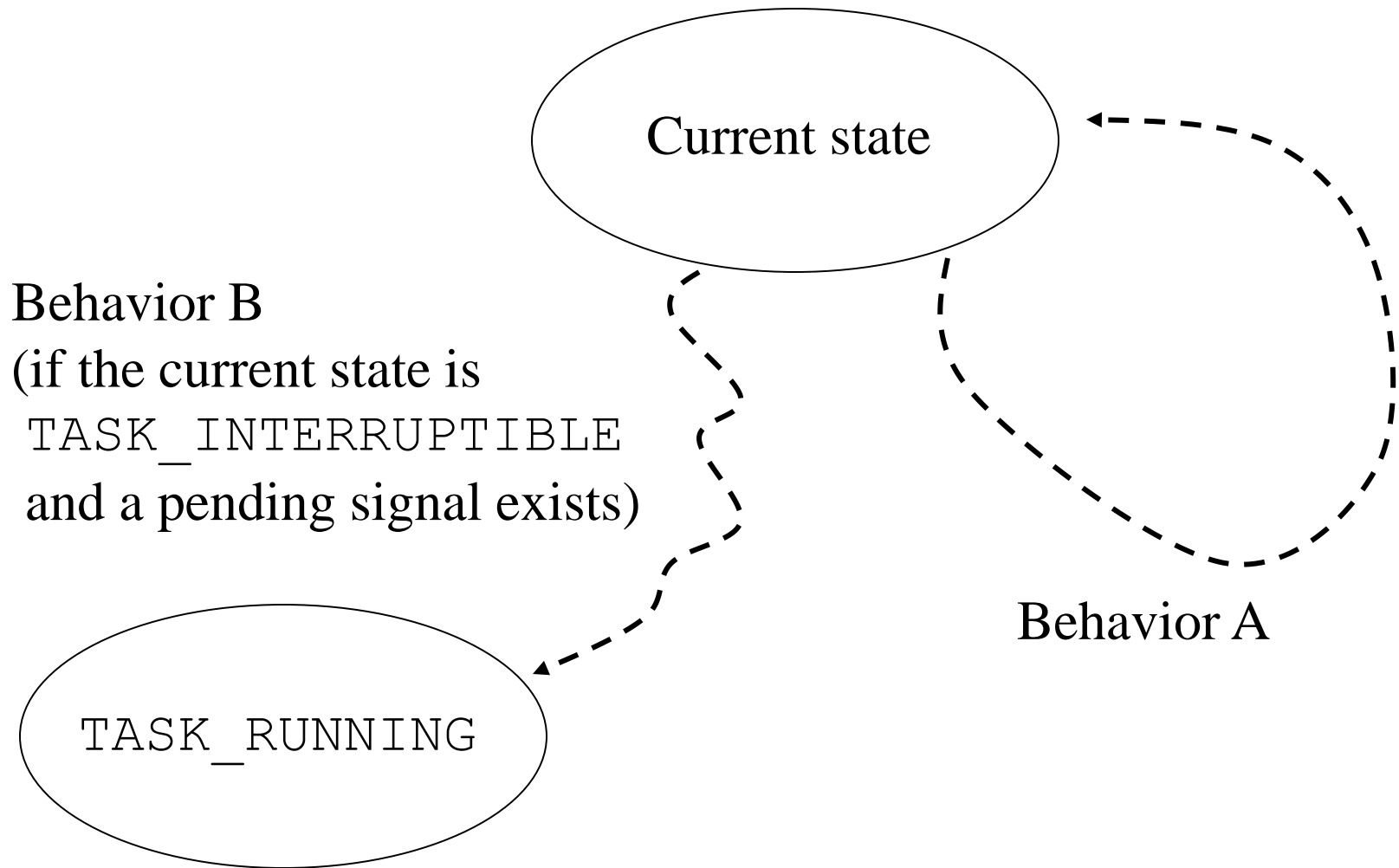
Check on the current process (update of the process state)

.....

```
prev = current;
```

.....

```
switch (prev->state) {  
    case TASK_INTERRUPTIBLE:  
        if (signal_pending(prev)) {  
            prev->state = TASK_RUNNING;  
            break;  
        }  
    default:  
        del_from_runqueue(prev);  
    case TASK_RUNNING::  
}  
prev->need_resched = 0;
```



Helps

```
#define list_for_each(pos, head) \  
for (pos = (head)->next; pos != (head); pos = pos->next)
```



Scan of a circular list through a cursor (i.e. pos)

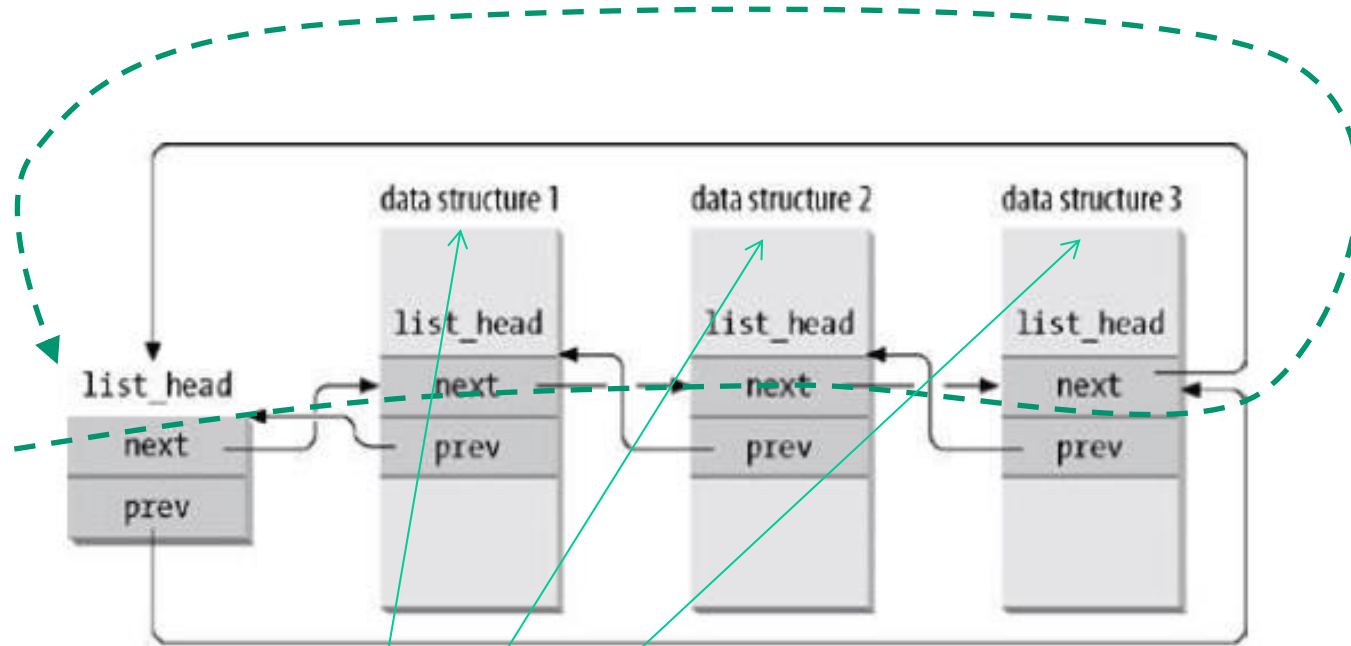
Access to the container element in the list linkage



```
#define list_entry(ptr, type, member) \  
container_of(ptr, type, member)
```

A scheme

`list_for_each()`



`list_entry()`

Run queue analysis

- For all the TCBs currently registered within the run-queue a so called **goodness value** is computed
- The TCB associated with the best goodness value gets pointed by `next` (which is initially set to point to the idle-process PCB)

```
repeat_schedule:
```

```
/*  
 * Default process to select..  
 */  
    next = idle_task(this_cpu);  
    c = -1000;  
    list_for_each(tmp, &runqueue_head) {  
        p = list_entry(tmp, struct task_struct, run_list);  
        if (can_schedule(p, this_cpu)) {  
            int weight = goodness(p, this_cpu, prev->active_mm);  
            if (weight > c)  
                c = weight, next = p;  
        }  
    }  
}
```

The role of memory mappings

- ✓ `mm_struct` fields in the TCB are 2 (not just one)

```
struct mm_struct *mm;
```

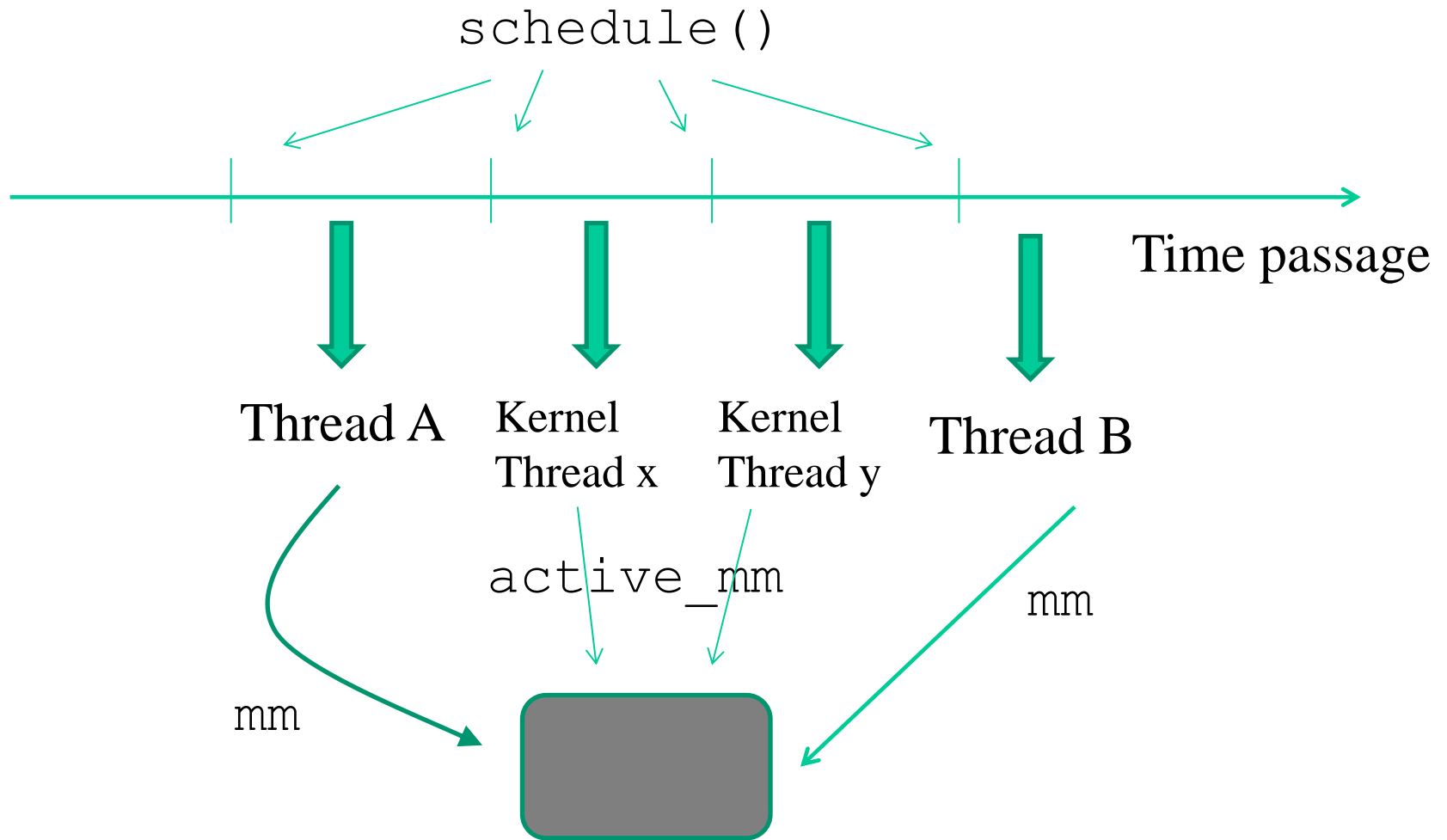
```
struct mm_struct *active_mm;
```



This is the user space memory mapping of the last thread run on this same CPU

- ✓ For an application thread `mm == active_mm` is an invariant
- ✓ For a kernel level thread `mm == NULL` but `active_mm` can be different from `NULL`

Memory mappings and timelines



Computing the goodness

goodness (p) = 20 - p->nice (base time quantum)

+ p->counter (ticks left in time quantum)

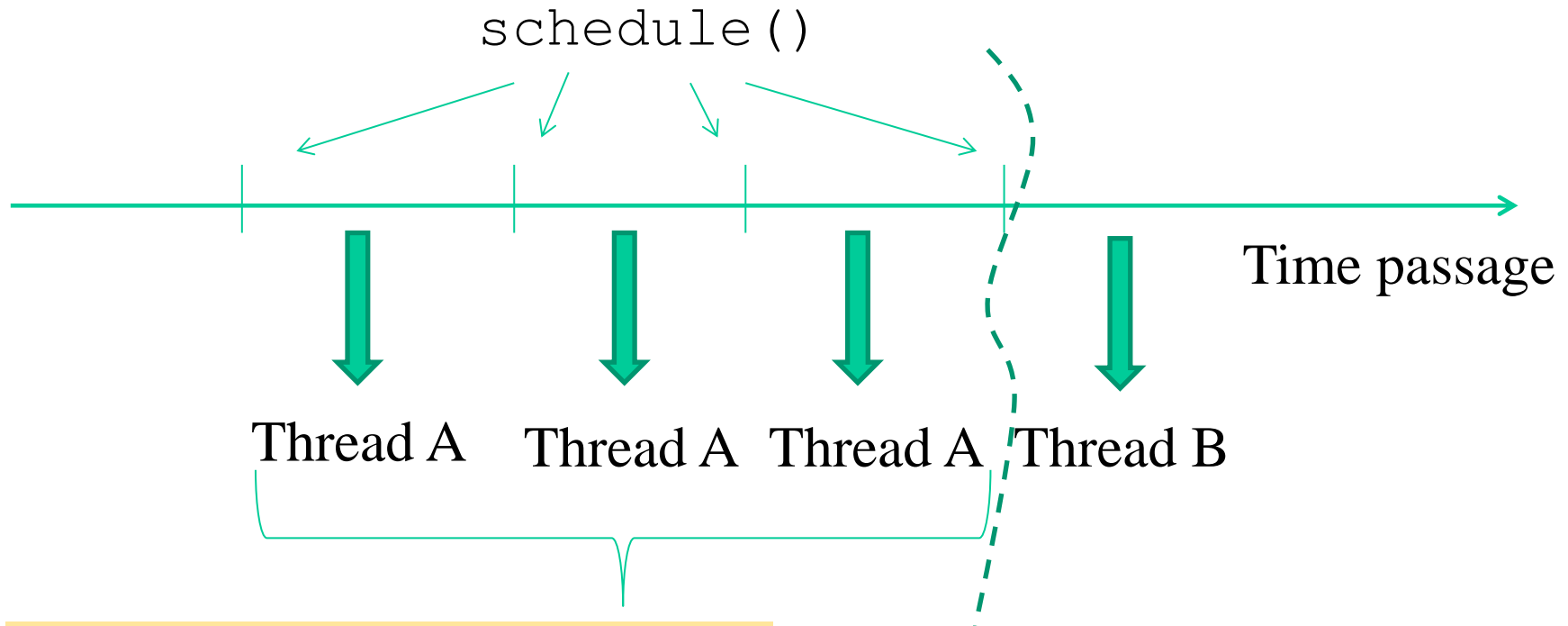
+1 (if page table is shared with the
previous process)

+15 (in SMP, if p was last running
on the same CPU)

**NOTE: goodness is forced to the value 0 in case
p->counter is zero**

Kinds of batch ticks usage

- ✓ The +15 bonus tends to cluster tick usage by threads on a same CPU-core



Extreme exploitation of program flow
and architectural support for locality

`p->counter == 0`
for thread A

Management of the epochs

- Any epoch ends when all the processes registered within the run-queue already used their planned CPU quantum
- This happens when the residual tick counter (`p->counter`) reaches the value zero for all the TCBs kept by the run-queue
- Upon epoch ending, the next quantum is computed for all the active processes
- The formula for the recalculation is as follows

$$p->counter = p->counter / 2 + 6 - p->nice / 4$$

.....

```
/* Do we need to re-calculate counters? */
```

```
if (unlikely(!c)) {
```

```
    struct task_struct *p;
```

```
    spin_unlock_irq(&runqueue_lock);
```

```
    read_lock(&tasklist_lock);
```

```
    for_each_task(p)
```

```
        p->counter = (p->counter >> 1) +
```

```
            NICE_TO_TICKS(p->nice);
```

```
    read_unlock(&tasklist_lock);
```

```
    spin_lock_irq(&runqueue_lock);
```

```
    goto repeat_schedule;
```

```
}
```

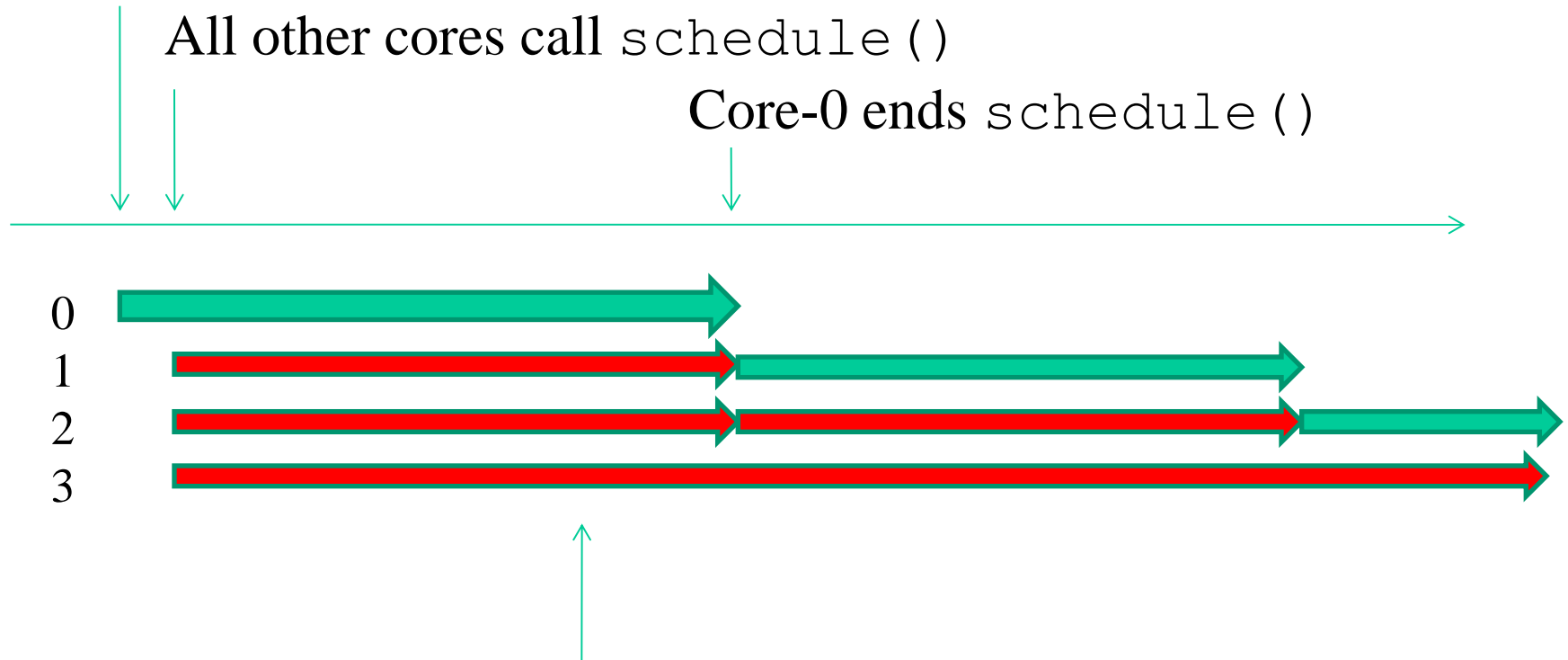
.....

$O(n)$ scheduler causes

- A non-runnable task is anyway searched to determine its goodness
- Mixsture of runnable/non-runnable tasks into a single run-queue in any epoch
- Chained negative performance effects in atomic scan operations in case of SMP/multi-core machines (length of crititcal sections dependent on system load)

A timeline example with 4 CPU-cores

Core-0 calls `schedule()`



Red means busy wait

Newer CPU-scheduling internals

- Constant-time scheduling
- Very low frequency of collisions by CPU-cores in inspecting a same run-queue
- Still keep the workload balanced (in compliance with affinity)
- Still distinguish priorities (even more levels with respect to what done before)

Constant time scheduling

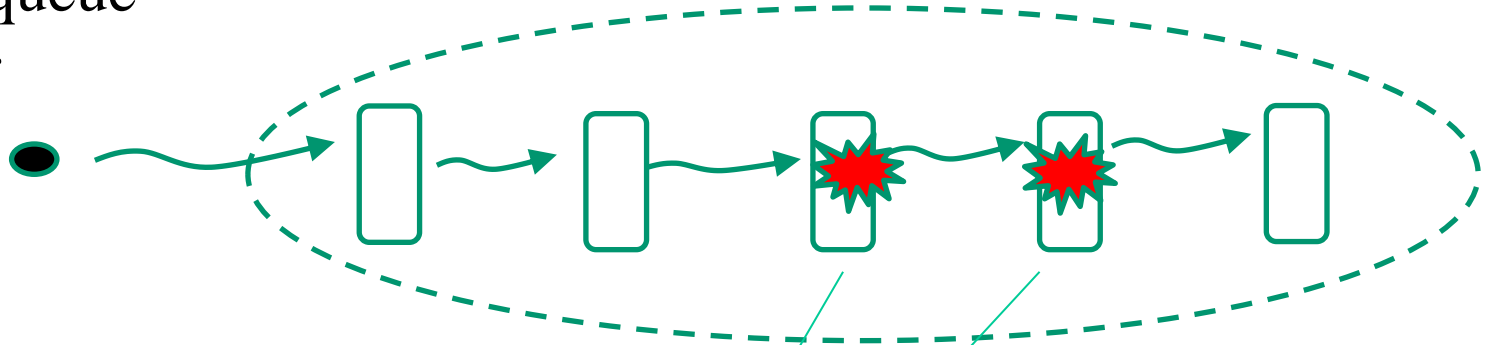
- **No mix of runnable and non-runnable tasks on a runqueue**
- Clear separation of runnable tasks into multiple run queues
 - ✓ we **do not search for priorities into the TCBs**, we already know it, based in the runqueue a TCB stands onto

Infrequent CPU-conflicts in the access to runqueues

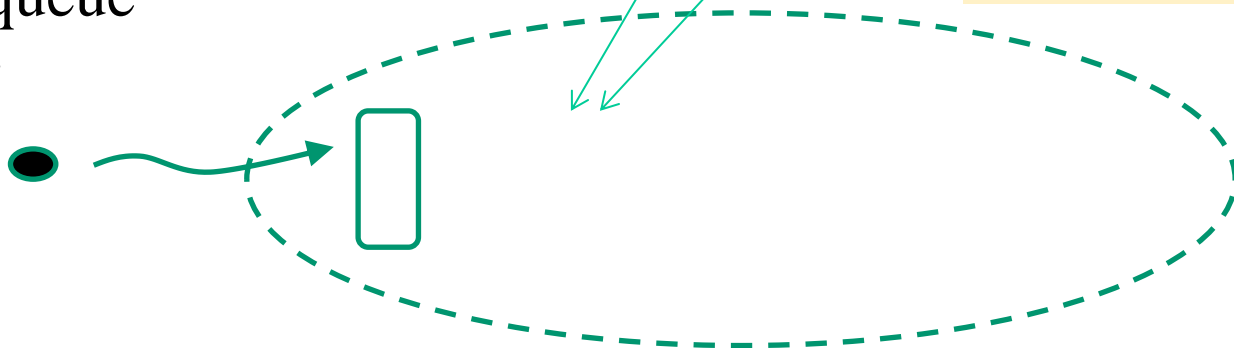
- Fully separated runqueues, one per CPU-core
- Each CPU-core accesses its own runqueue when running the scheduler logic
- A CPU-core can access the runqueue of another one (hopefully infrequently) when
 - ✓ An explicit linkage of the TCB on that runqueue is requested
 - ✓ This is for load balancing or for promptness of reschedule

Load balancing

CPU-0 Runqueue
head pointer



CPU-1 Runqueue
head pointer



Transfer done by the
under-loaded CPU-core
or a demon running on
whatever CPU-core

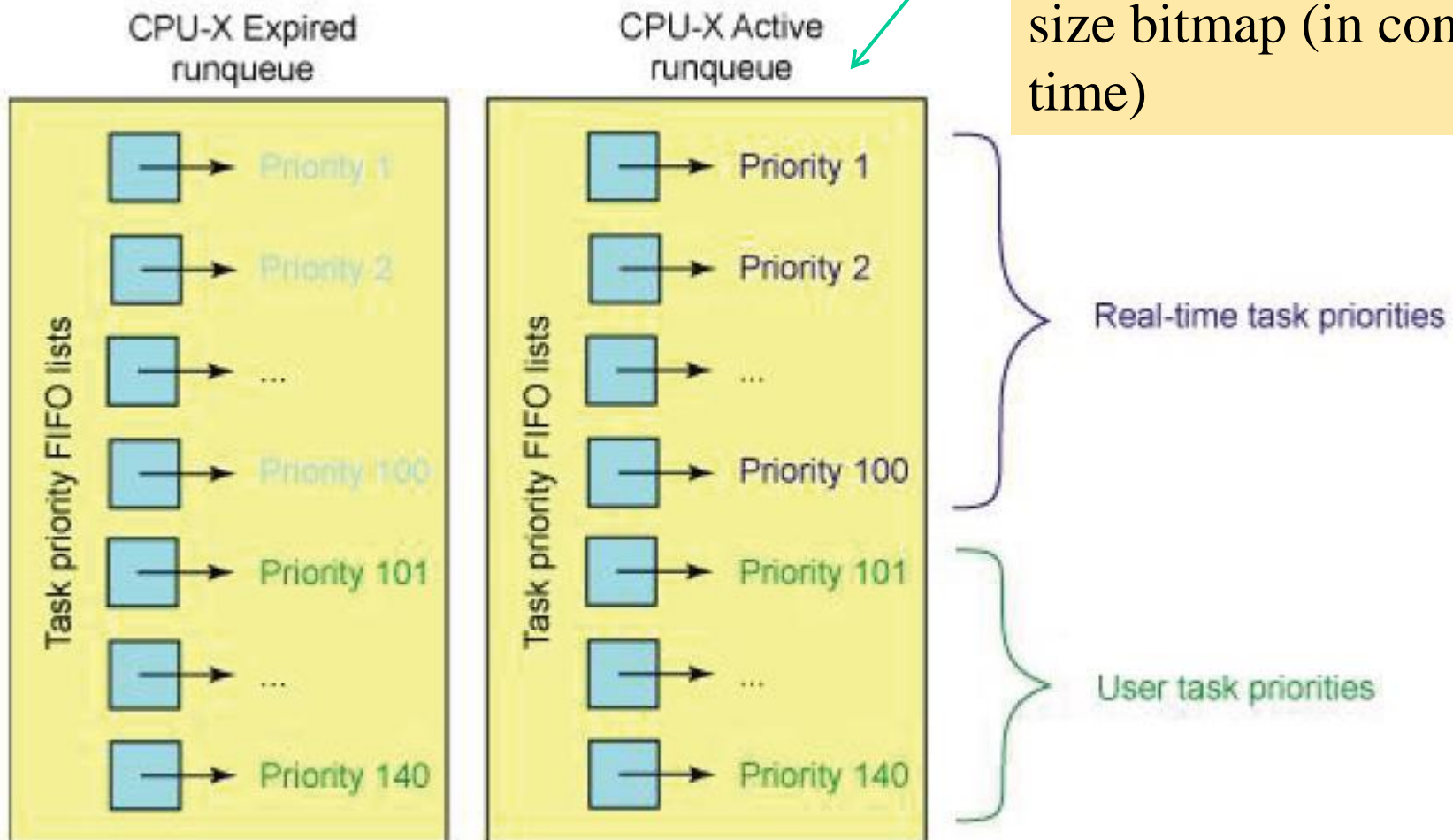
Actual implementation on Linux kernel 2.6 or later versions

- The run queue of each CPU-core is a multiqueue with 140 different levels
- 40 levels (say [100-139]) map to classical Unix time-sharing
- 100 levels (say [0-99]) map to Unix real-time scheduler extensions
- It is also separate into
 - ✓ The active queue, keeping runnable threads
 - ✓ The Expired queue, keeping non-runnable threads

A scheme

We simply switch the queues upon a new epoch

We search for a non empty queue level by searching in to a fixed size bitmap (in constant time)



Relations with the thread wakeup API

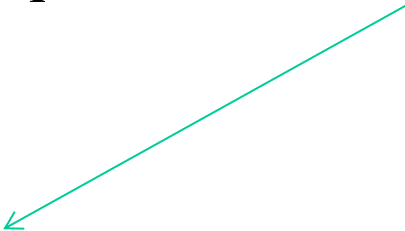
`wake_up_process (...)`



Can the thread run on this CPU?

If YES put on the local runqueue

If NO, get affinity info from TCB and put in
some remote runqueue via the below API



`void ttwu_queue(struct task_struct *p,
 int cpu, int wake_flags`

Coming to priorities

- A thread has two characterizing priority values
 - ✓ **the static priority** – this is defined by the users and defines the level at which the thread will appear in the runqueue
 - ✓ **the dynamic priority** – this is based on a reward or a penalty (applied to the static priority) depending on whether the thread is interactive or not
- Thread is interactive if its sleep time is high enough, and the reward is based on a formula that considers the sleep time
- These two priority values exactly appear as recorded into the TCB
- The one that is looked at when we run the `schedule()` function is the dynamic priority

The effect of dynamic priorities

- A thread that calls the schedule function can be preempted by one that has higher dynamic priority (although lower static priority)
- A classical scenario
 1. The thread calls wakeup of some other thread
 2. The thread calls schedule
- Another classical scenario
 1. Someone calls wakeup putting a thread on the queue of another CPU
 2. The CPU is then hit by a cross-CPU reschedule-request

CPU-scheduling API: a wider view

<code>p->time_slice</code>	The residual ticks of residual ticks in the current epoch
<code>schedule</code>	The main scheduler function. Schedules the highest priority task for execution.
<code>load_balance</code>	Checks the CPU to see whether an imbalance exists, and attempts to move tasks if not balanced.
<code>effective_prio</code>	Returns the effective priority of a task (based on the static priority, but includes any rewards or penalties).
<code>recalc_task_prio</code>	Determines a task's bonus or penalty based on its idle time.
<code>source_load</code>	Calculates the load of the source CPU (from which a task could be migrated).
<code>target_load</code>	Calculates the load of a target CPU (where a task has the potential to be migrated).

Explicit stack refresh

- Software operation
- Used when an action is finalized via local variables with lifetime across different stacks
- Used in 2.6 or later versions for `schedule()` finalization
- Local variables are explicitly repopulated after the stack switch has occurred

```

asmlinkage void __sched schedule(void)
{
    struct task_struct *prev, *next;
    unsigned long *switch_count;
    struct rq *rq;
    int cpu;

    need_resched:
    preempt_disable();
    cpu = smp_processor_id();
    rq = cpu_rq(cpu);
    rcu_qsctr_inc(cpu);
    prev = rq->curr;
    switch_count = &prev->nivcsw;

    release_kernel_lock(prev);
    need_resched_nonpreemptible:

    .....
    spin_lock_irq(&rq->lock);
    update_rq_clock(rq);
    clear_tsk_need_resched(prev);
    .....

```

```

.....
#ifdef CONFIG_SMP
    if (prev->sched_class->pre_schedule)
        prev->sched_class->pre_schedule(rq, prev);
#endif

    if (unlikely(!rq->nr_running)) idle_balance(cpu, rq);

    prev->sched_class->put_prev_task(rq, prev);
    next = pick_next_task(rq, prev);

    if (likely(prev != next)) {
        sched_info_switch(prev, next);

        rq->nr_switches++;
        rq->curr = next;
        ++*switch_count;

        context_switch(rq, prev, next); /* unlocks the rq */
        /* the context switch might have flipped the stack from under
           us, hence refresh the local variables. */
        cpu = smp_processor_id();
        rq = cpu_rq(cpu);
    } else spin_unlock_irq(&rq->lock);

    if (unlikely(reacquire_kernel_lock(current) < 0))
        goto need_resched_nonpreemptible;
    preempt_enable_no_resched();
    if (unlikely(test_thread_flag(TIF_NEED_RESCHED)))
        goto need_resched;
}

```

Struct rq (run-queue)

```
struct rq {
/* runqueue lock: */
spinlock_t lock;

/* nr_running and cpu_load should be in the same cacheline
because remote CPUs use both these fields when doing load
calculation. */
unsigned long nr_running;
#define CPU_LOAD_IDX_MAX 5
unsigned long cpu_load[CPU_LOAD_IDX_MAX];
unsigned char idle_at_tick;

.....

/* capture load from *all* tasks on this cpu: */
struct load_weight load;

.....

struct task_struct *curr, *idle;

.....

struct mm_struct *prev_mm;

.....
};
```

Kernel threads (initial 2.4/i386 binding)

- kernel threads can be generated via the function `kernel_thread()` defined in `kernel/fork.c`
- This function relies on an ASM function called `arch_kernel_thread()` which is `arch/i386/kernel/process.c`
- The latter does some job before calling `sys_clone()`
- Upon returning within the child thread, the target thread function is executed via a call
- In this scenario, the base of user mode stack is a don't care since this thread will never bounce to user mode

```
long kernel_thread(int (*fn)(void *), void * arg, unsigned long flags)
{
    struct task_struct *task = current;
    unsigned old_task_dumpable;
    long ret;

    /* lock out any potential ptracer */
    task_lock(task);
    if (task->ptrace) {
        task_unlock(task);
        return -EPERM;
    }

    old_task_dumpable = task->task_dumpable;
    task->task_dumpable = 0;
    task_unlock(task);

ret = arch_kernel_thread(fn, arg, flags);

    /* never reached in child process, only in parent */
    current->task_dumpable = old_task_dumpable;

    return ret;
}
```

```

int arch_kernel_thread(int (*fn)(void *), void * arg, unsigned long flags)
{
    long retval, d0;

    __asm__ __volatile__(
        "movl %%esp,%%esi\n\t"
        "int $0x80\n\t" /* Linux/i386 system call */
        "cmpl %%esp,%%esi\n\t" /* child or parent? */
        "je 1f\n\t" /* parent - jump */
        /* Load the argument into eax, and push it. That way, it does
         * not matter whether the called function is compiled with
         * -mregparm or not. */
        "movl %4,%%eax\n\t"
        "pushl %%eax\n\t"
        "call *%5\n\t" /* call fn */
        "movl %3,%0\n\t" /* exit */
        "int $0x80\n\t"
        "1:\n\t"
        : "=a" (retval), "=S" (d0)
        : "0" (__NR_clone), "i" (__NR_exit),
          "r" (arg), "r" (fn),
          "b" (flags | CLONE_VM)
        : "memory");

    return retval;
}

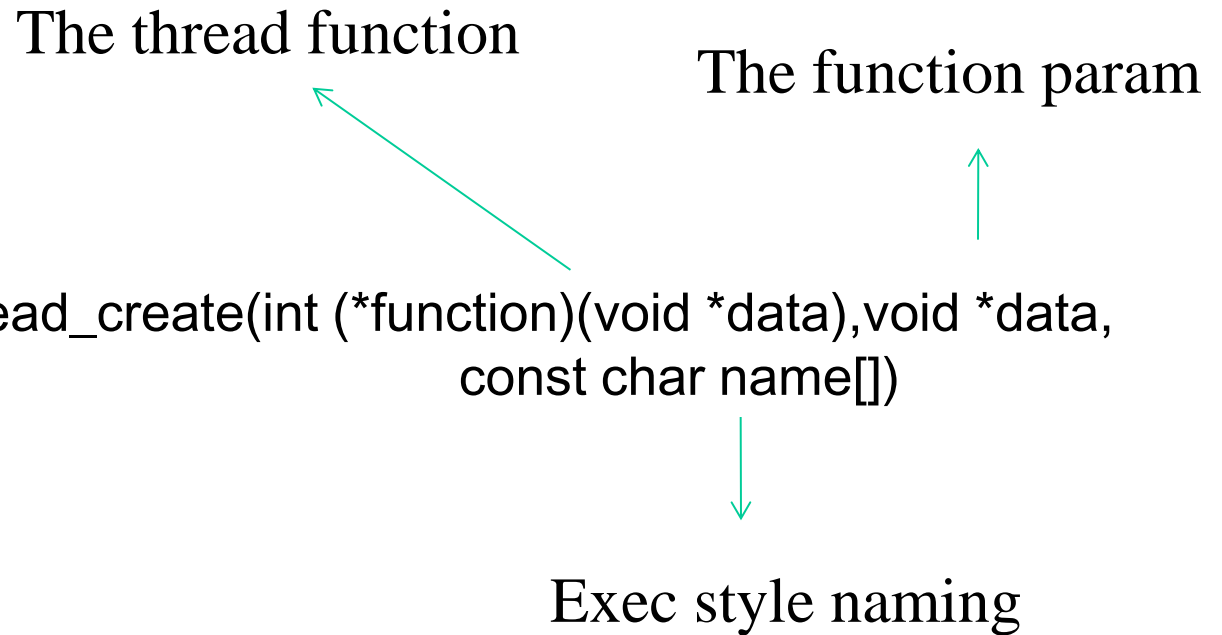
```

More recent (module exposed) API


The thread function

The function param

```
truct task_struct *kthread_create(int (*function)(void *data), void *data,  
                                   const char name[])
```



Exec style naming

In the end this service relies on the core thread-startup
function seen before plus others 

Thread features with `kthread_create`

- The created thread sleeps on a wait queue
- So it exists but is not really active
- We need to explicitly awake it
- As for signals we have the following:
 - ✓ We can kill, if thread (or creator) enables
 - ✓ Killing only has the effect of awakening the thread (if sleeping) but no message delivery is logged in the signal mask
 - ✓ Terminating threads via kills is based on the thread polling a termination bit in its PCB or on poll on the signal mask