



Operating System Concepts

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Contents

1. Introduction
2. System Structures
- ➔ 3. Process Concept
4. Multithreaded Programming
5. Process Scheduling
6. Synchronization
7. Deadlocks
8. Memory-Management Strategies
9. Virtual-Memory Management
10. File System
11. Implementing File Systems
12. Secondary-Storage Systems

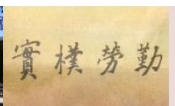




Chapter 3. Process Concept

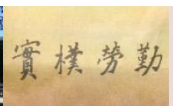
Objectives

- ▶ To introduce the notion of a process
- ▶ To describe the various features of processes, including scheduling, creation and termination, and communication
- ▶ To explore inter-process communication
- ▶ To describe communication in client-server systems

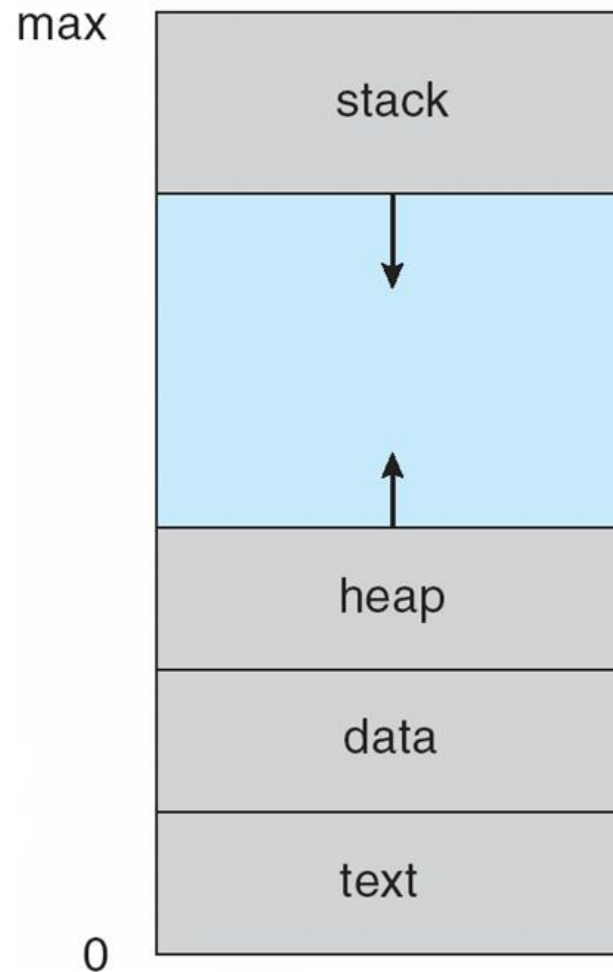


Basic Process Concept

- ▶ A program is a **passive** entity stored on disk, and a process is an **active** entity
 - A program becomes process when the executable file is loaded into memory
 - The execution of a program started via GUI mouse clicks, the command line entry of its name, etc.
 - One program can be executed as several processes
- ▶ An operating system can execute a variety of programs
 - In batch systems: jobs
 - In time-shared systems: user programs or tasks



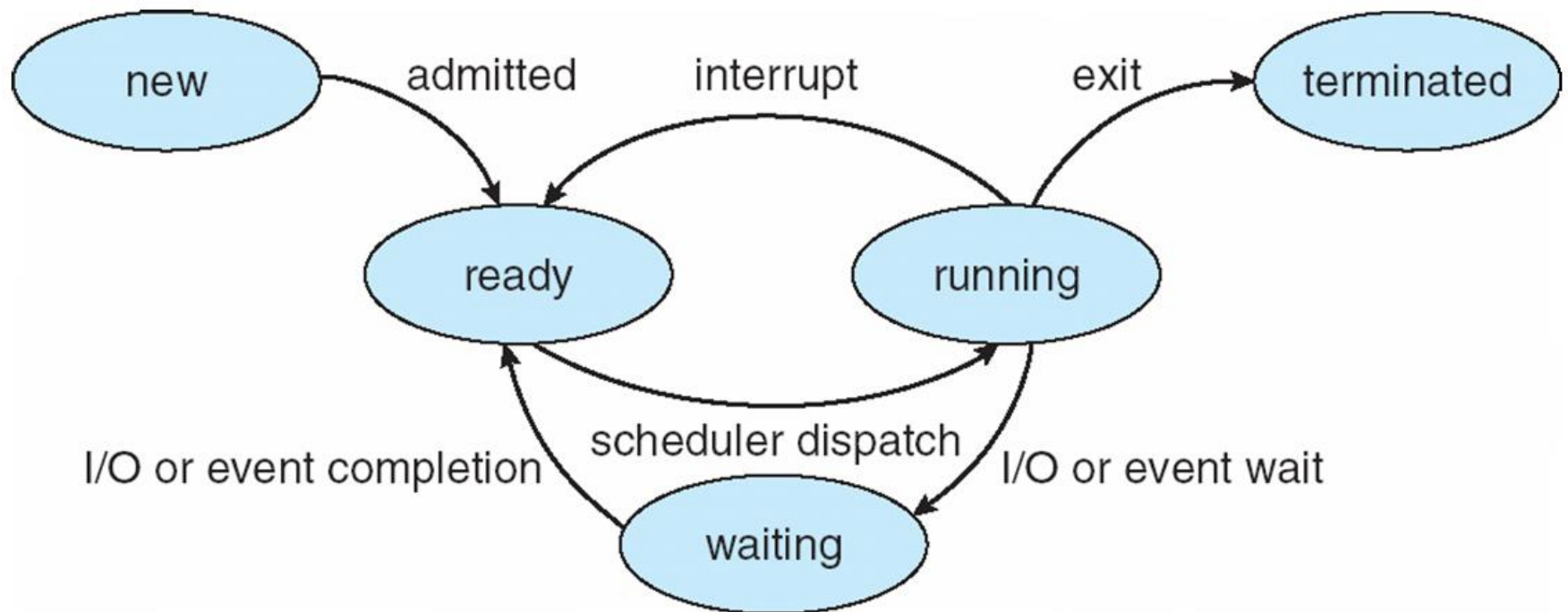
Process in Memory



Process States

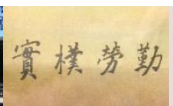
- ▶ **New**: The process is being created
- ▶ **Running**: Instructions are being executed
- ▶ **Waiting**: The process is waiting for some event to occur
- ▶ **Ready**: The process is waiting to be assigned to a processor
- ▶ **Terminated**: The process has finished execution

Diagram of Process States



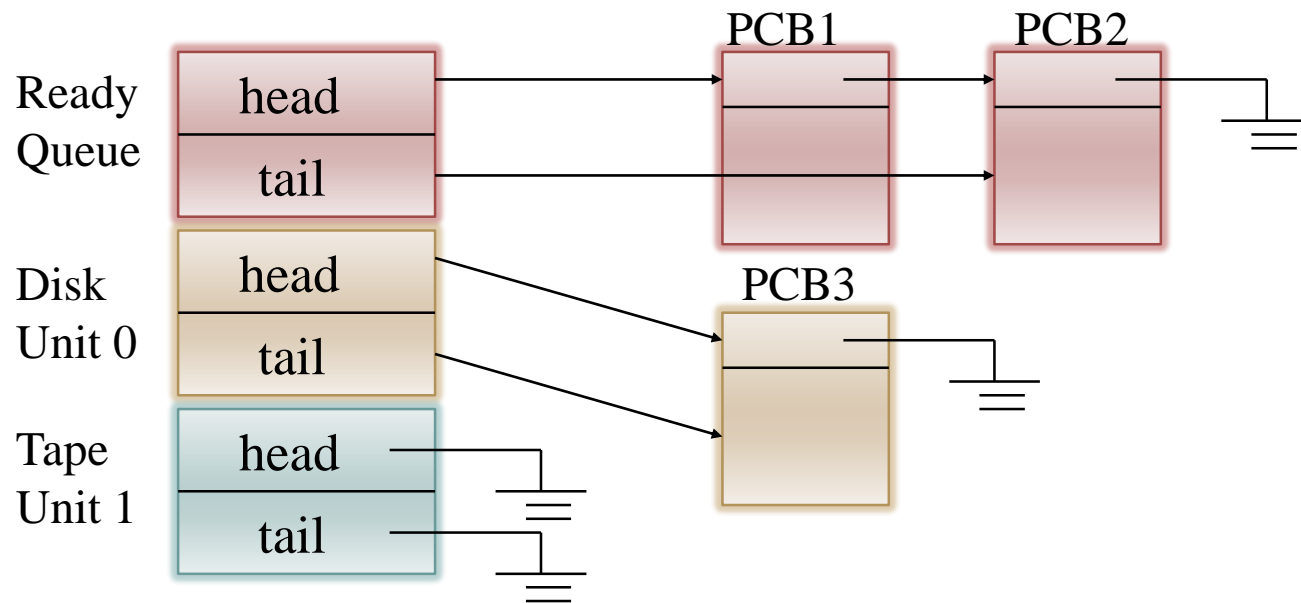
Process Control Block (PCB)

- ▶ PCB: The repository for any information that may vary from process to process
 - Process state— running, waiting, etc
 - Program counter— location of the currently executed instruction
 - CPU registers— contents of all process-centric registers
 - CPU scheduling information— priorities, scheduling queue pointers
 - Memory-management information— memory allocated to the process
 - Accounting information— CPU used, clock time elapsed since start, time limits
 - I/O status information— I/O devices allocated to process, list of opened files

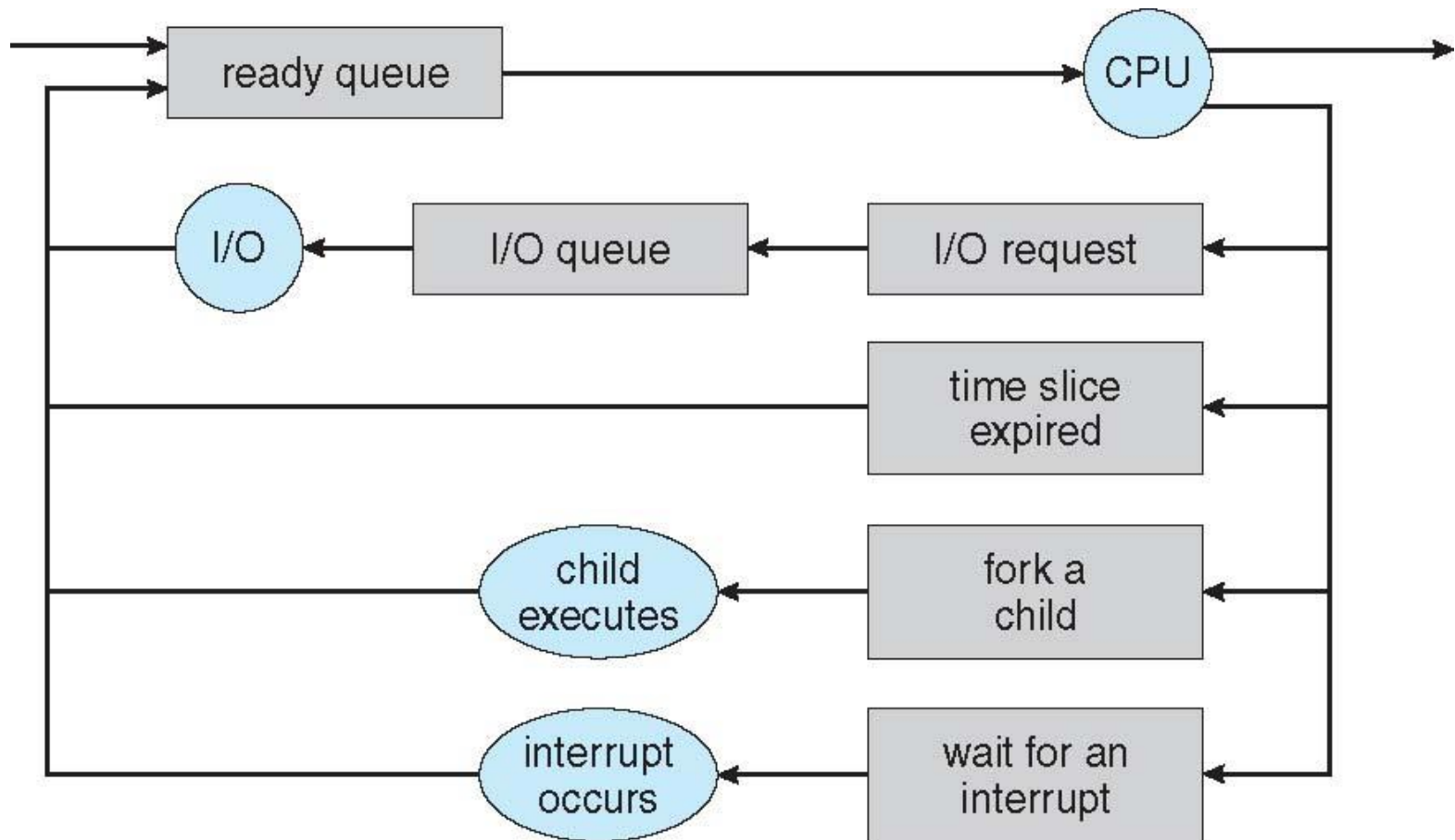


Process Scheduling with PCB

- ▶ The goal of multiprogramming
 - Maximize CPU/resource utilization
- ▶ The goal of time sharing
 - Allow each user to interact with his/her program



Process Scheduling- A Queueing Diagram



Processor Schedulers

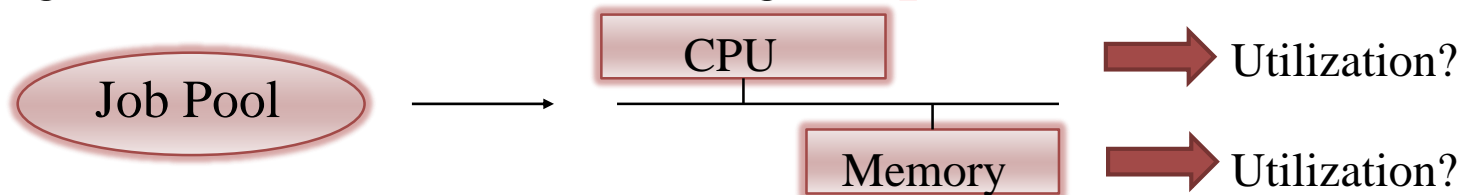
- ▶ **Long-term scheduler (or job scheduler)**— selects which processes should be brought into the ready queue
- ▶ **Short-term scheduler (or CPU scheduler)**— selects which process should be executed next and allocates CPU
- ▶ **Medium-term scheduler** can be added as **swapper**



Long-Term Scheduler

- ▶ Processes can be described as either:
 - **I/O-bound process** – spends more time doing I/O than computations, many short CPU bursts
 - **CPU-bound process** – spends more time doing computations; few very long CPU bursts

- ▶ Long-term scheduler strives for good **process mix**



- ▶ Remarks :
 - Control the degree of multiprogramming
 - Can take more time in selecting processes because of a longer interval between executions
 - May not exist physically



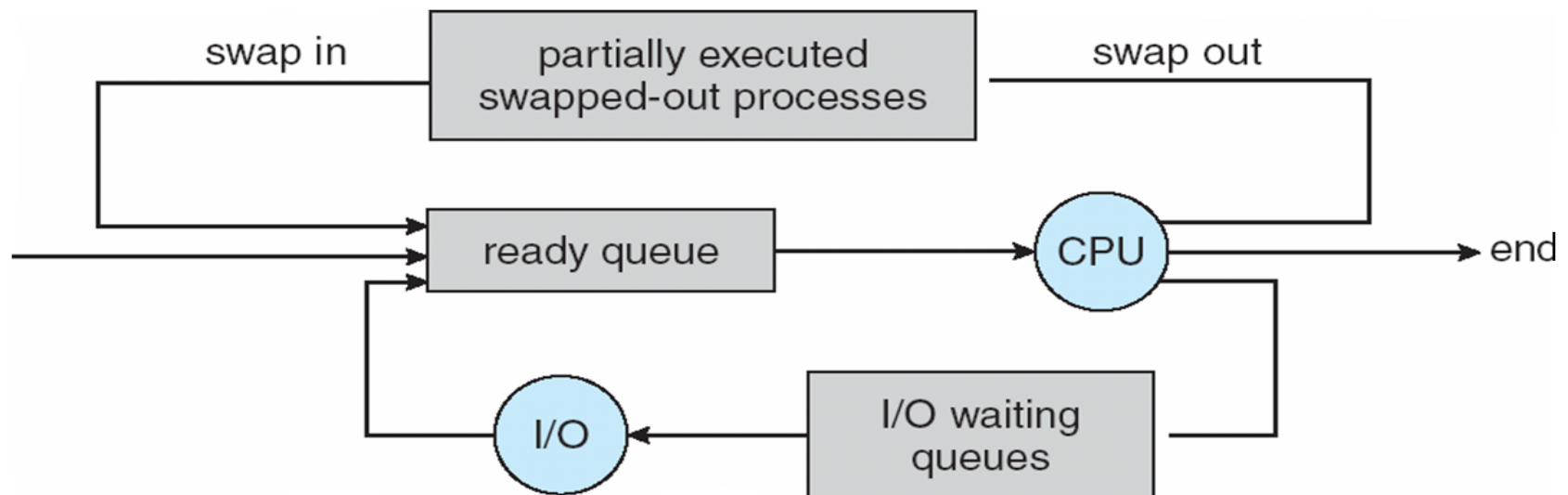
Short-Term Scheduler

- ▶ Goal: To efficiently allocate the CPU to one of the ready processes according to some criteria
- ▶ Short-term scheduler is invoked very frequently (milliseconds) → must be fast
- ▶ In Linux, after version 2.6.23, the scheduler is the Completely Fair Scheduler (CFS)



Medium-Term Scheduler

- ▶ Goal: Remove process from memory, store on disk, bring back in from disk to continue execution: it is also called “swapping”



Process Scheduling– Context Switches

▶ Context Switch: Pure Overheads

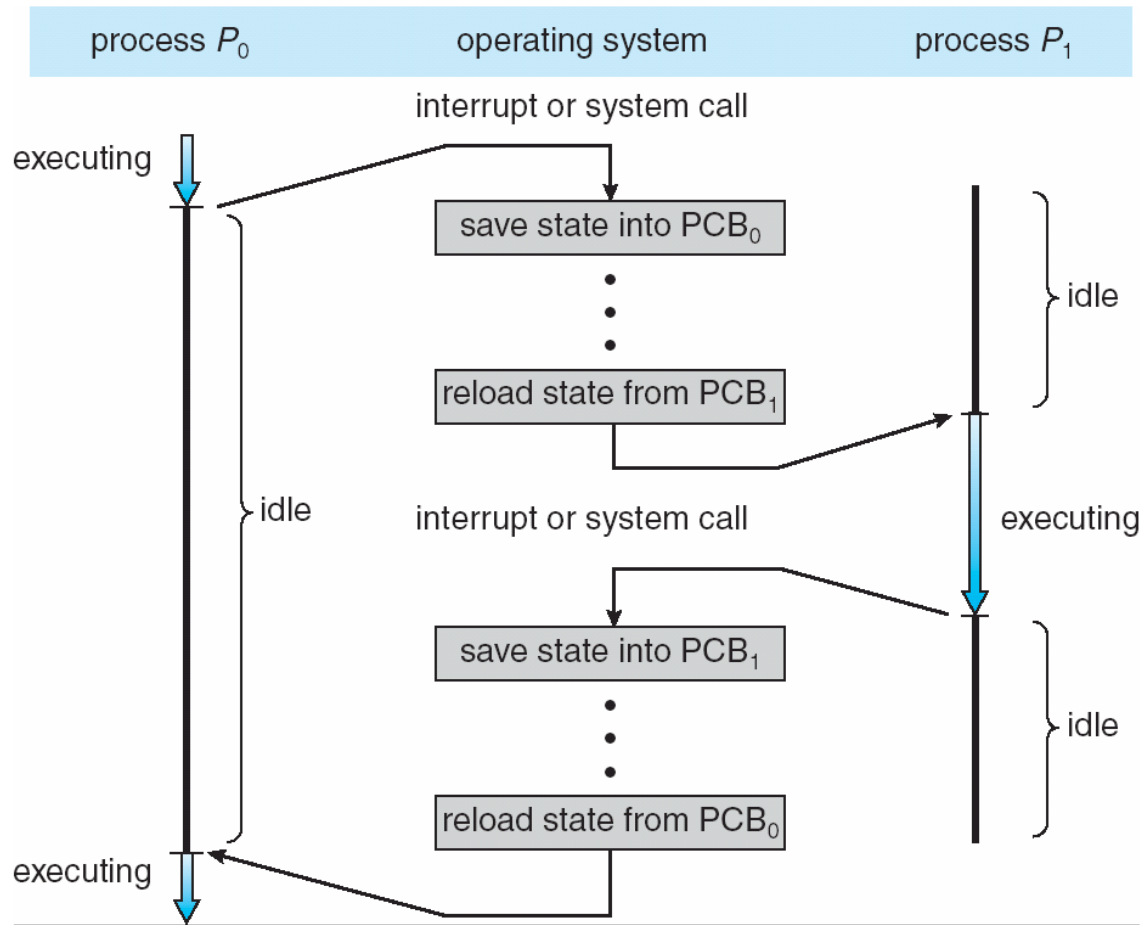
- Save the state of the old process and load the state of the newly scheduled process.
 - The context of a process is usually reflected in PCB

▶ Issues:

- The cost depends on the hardware support
 - e.g. processors with multiple register sets or computers with advanced memory management
- Threads, i.e., light-weight process (LWP), are introduced to break this bottleneck

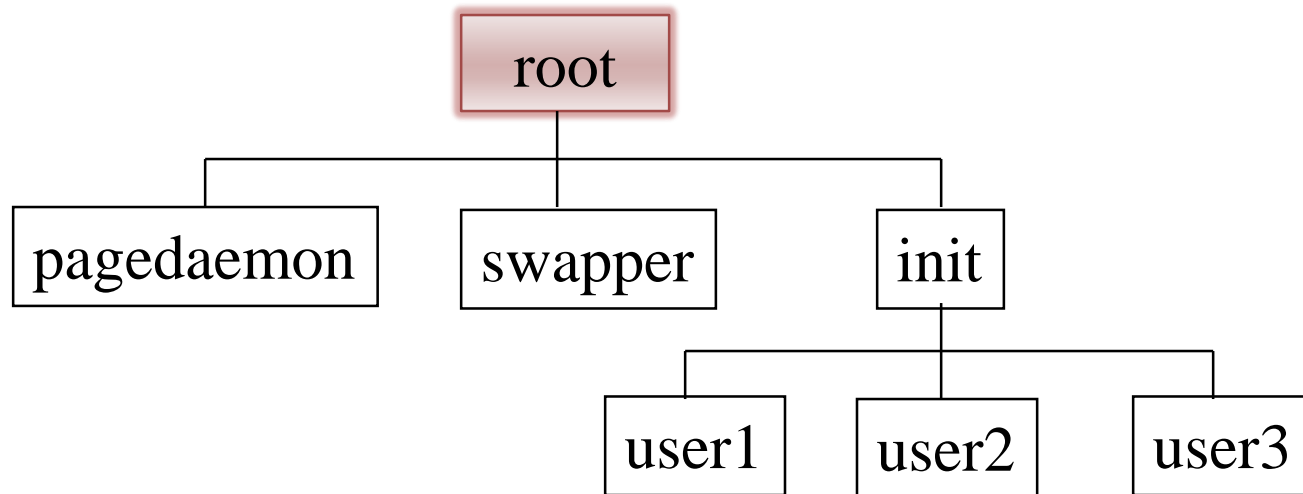


CPU Switch from Process to Process



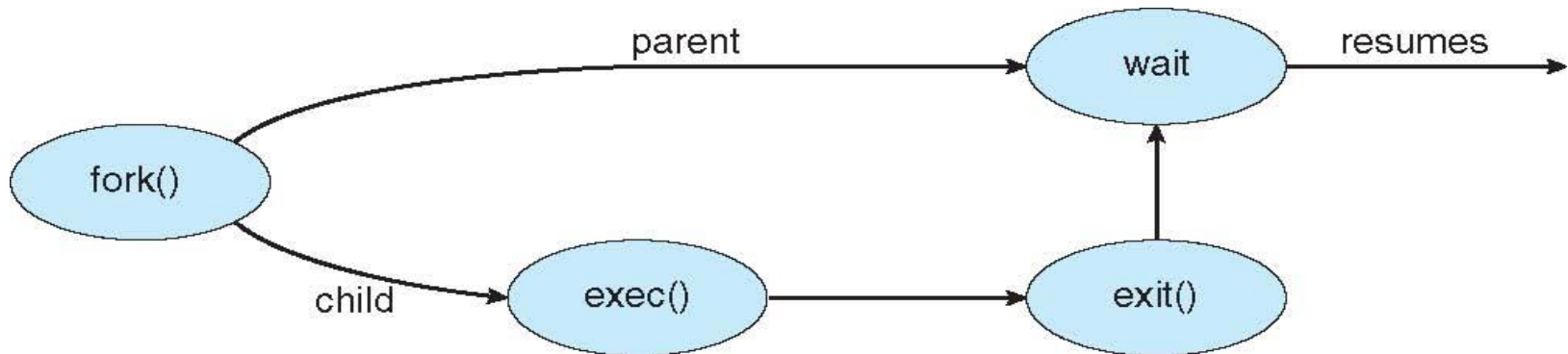
Parent and Child Processes

- ▶ Parent processes create child processes, which in turn create other processes, forming a tree of processes
- ▶ Generally, process identified and managed via a process identifier (PID)



Process Creation

- ▶ Address Space
 - Child duplicate of parent
 - Child has a program loaded into it
- ▶ UNIX Examples
 - **fork()** system call creates new process
 - **exec()** system call used after a **fork()** to replace the process' memory space with a new program



Process Termination

- ▶ Process executes last statement and asks the operating system to delete it: **exit()**
 - Wait the output data from child to parent: **wait()**
- ▶ Parent may terminate the execution of child processes: **abort()**
 - ➔ Child has exceeded allocated resources
 - ➔ Task assigned to child is no longer required
 - Receive the return value from child
 - Some operating systems do not allow child to continue if its parent terminates
 - All children should be terminated - **cascading termination**



C Program Forking a Process

```
#include <sys/types.h>
#include <stdio.h>
#include <unistd.h>

int main()
{
    pid_t pid;

    /* fork a child process */
    pid = fork();

    if (pid < 0) { /* error occurred */
        fprintf(stderr, "Fork Failed");
        return 1;
    }
    else if (pid == 0) { /* child process */
        execlp("/bin/ls", "ls", NULL);
    }
    else { /* parent process */
        /* parent will wait for the child to complete */
        wait(NULL);
        printf("Child Complete");
    }

    return 0;
}
```



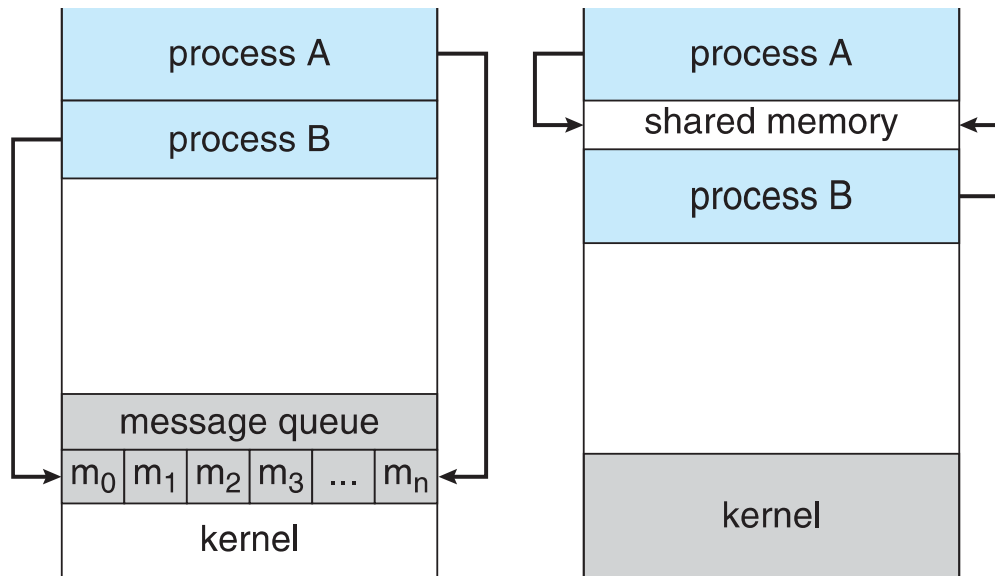
Inter-Process Communication

- ▶ Processes within a system may be independent or cooperating
- ▶ Cooperating process can affect or be affected by other processes, including sharing data
- ▶ Reasons for cooperating processes:
 - Information sharing
 - Computation speedup
 - Modularity
 - Convenience
- ▶ Cooperating processes need inter-process communication (IPC)



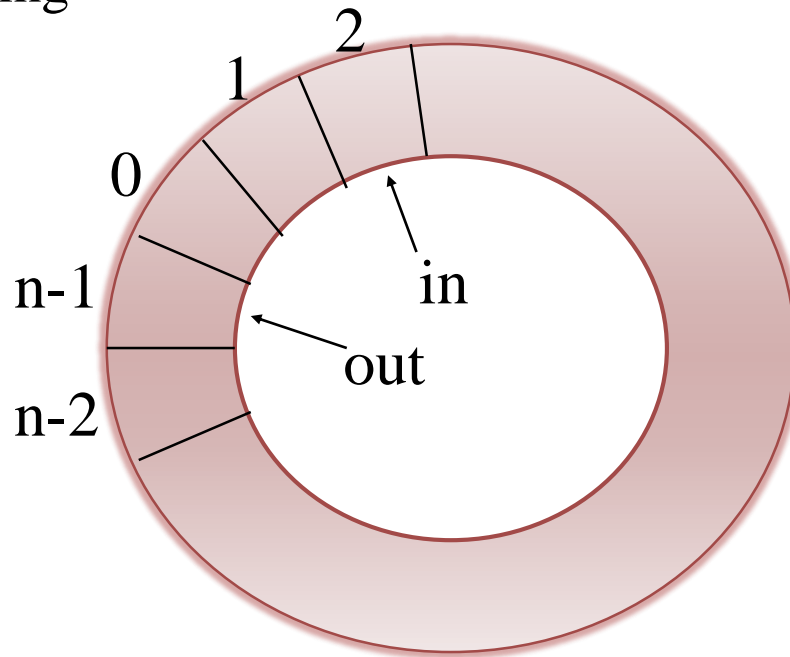
Two Models of IPC

- ▶ Shared Memory
 - Max Speed & Communication Convenience
- ▶ Message Passing
 - No Access Conflict & Easy Implementation



Shared Memory IPC

- ▶ A Consumer-Producer Example:
 - Bounded buffer or unbounded buffer
 - Supported by inter-process communication (IPC) or by hand coding



`buffer[0...n-1]`

Initially, $in=out=0$



Shared Memory– Consumer

```
while (true)
{
    while (in == out);
    /* do nothing and have to wait */
    next_consumed = buffer[out];
    out = (out + 1) % BUFFER_SIZE;
    ... /* use the consumed item */
}
```



Shared Memory– Producer

```
while (true)
{
    ... /* produce a new item */
    while (((in + 1) % BUFFER_SIZE) == out);
    /* do nothing */
    buffer[in] = next_produced;
    in = (in + 1) % BUFFER_SIZE;
}
```



Message Passing IPC

- ▶ Logical Implementation of Message Passing
 - Fixed/variable message size
 - Symmetric/asymmetric communication
 - Direct/indirect communication
 - Synchronous/asynchronous communication
 - Automatic/explicit buffering
 - Send by copy or reference



Direct Message Passing

- ▶ Processes must name each other explicitly:
 - **send** (P , *message*) – send a message to process P
 - **receive**(Q , *message*) – receive a message from process Q
- ▶ Properties of the communication link
 - Links are established automatically
 - A link is associated with exactly one pair of communicating processes
 - Between each pair there exists exactly one link
 - The link may be unidirectional, but is usually bi-directional



Indirect Communication

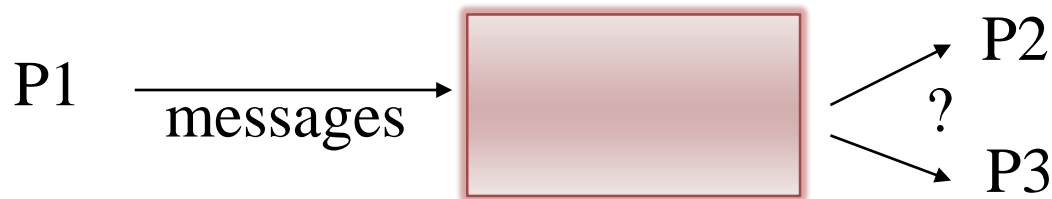
- ▶ Messages are directed and received from mailboxes (also referred to as ports)
 - **send**(*A, message*) – send a message to mailbox *A*
 - **receive**(*A, message*) – receive a message from mailbox *A*
- ▶ Properties of the communication link
 - Links are established only if processes share a common mailbox
 - A link may be associated with many processes
 - Each pair of processes may share several communication links
 - Links may be unidirectional or bi-directional



Issues of Indirect Communication

► Mailbox sharing

- P_1 , P_2 , and P_3 share mailbox A
- P_1 , sends; P_2 and P_3 receive
- Who gets the message?



► Solutions

- Allow a link to be associated with at most two processes
- Allow only one process at a time to execute a receive operation
- Allow the system to select arbitrarily the receiver



IPC Synchronization

- ▶ Synchronous Message Passing IPC
 - Blocking send has the sender block until the message is received
 - Blocking receive has the receiver block until a message is available
- ▶ Asynchronous Message Passing IPC
 - Non-blocking send has the sender send the message and continue
 - Non-blocking receive has the receiver receive a valid message or null



IPC Buffering

- ▶ The capacity of a link: the number of messages could be held in the link
 - Zero capacity – 0 messages
 - Sender must wait for receiver
 - Bounded capacity – finite length of n messages
 - Sender must wait if link is full
 - Unbounded capacity – infinite length
 - Sender never waits
- ▶ The last two items are for asynchronous communication and may need **acknowledgement**



Examples of IPC Systems – POSIX

► POSIX Shared Memory

- Process first creates shared memory segment

```
shm_fd = shm_open(name, O_CREAT | O_RDWR,  
0666);
```

- Set the size of the object

```
ftruncate(shm_fd, 4096);
```

- Memory map the object

```
ptr = mmap(0, 4096, PROT_WRITE, MAP_SHARED,  
shm_fd, 0);
```

- Now the process could write to the shared memory

```
sprintf(ptr, "Writing to shared memory");
```



Examples of IPC Systems – Mach

- ▶ Mach – A message-based OS from the Carnegie Mellon University
 - When a task is created, two special mailboxes, called ports, are also created.
 - The *Kernel* mailbox is used by the kernel to communicate with the tasks
 - The *Notify* mailbox is used by the kernel sends notification of event occurrences.



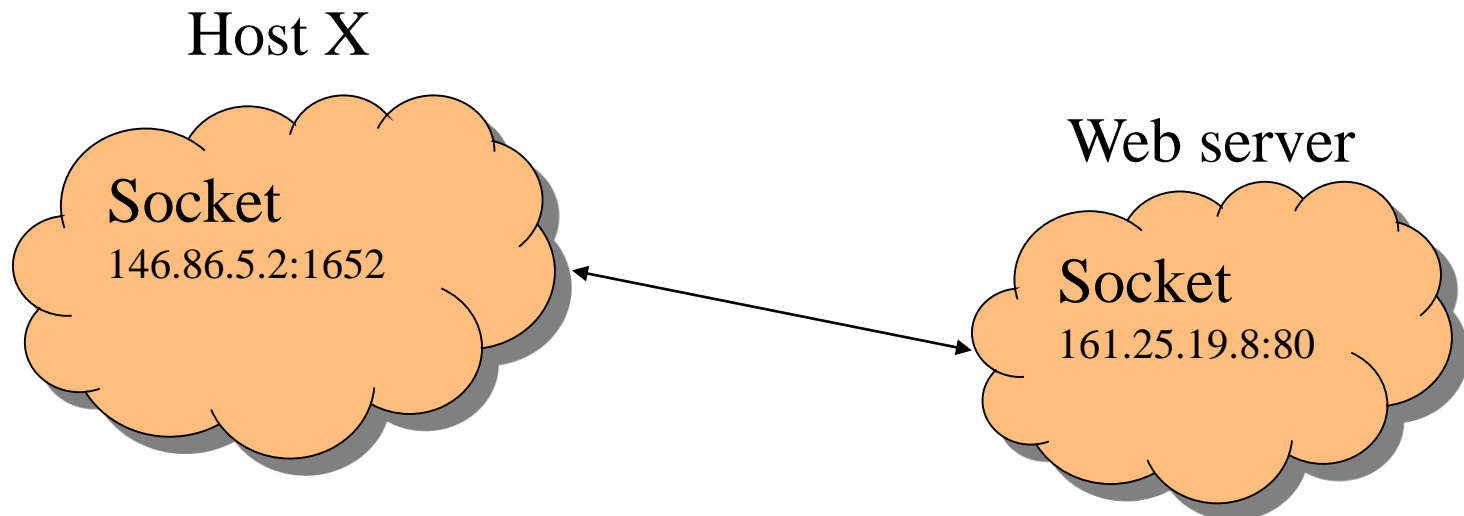
Three IPC System Calls on Mach

- ▶ `msg_send`
 - Options when mailbox is full:
 - Wait indefinitely
 - Return immediately
 - Wait at most for n ms
 - Temporarily cache a message: only one message to a full mailbox can be pending at any time for a sending thread
- ▶ `msg_receive`
 - Only one task can own & have a receiving privilege of a mailbox
 - Options when mailbox is empty:
 - Wait indefinitely
 - Return immediately
 - Wait at most for n ms
- ▶ `msg_rpc`
 - Remote Procedure Calls



Communication in Client-Server Systems

- ▶ **Socket**
 - An endpoint for communication identified by an IP address concatenated with a port number
 - A client-server architecture
- ▶ /etc/services: 23-telnet, 21-ftp, 80-web server, etc.

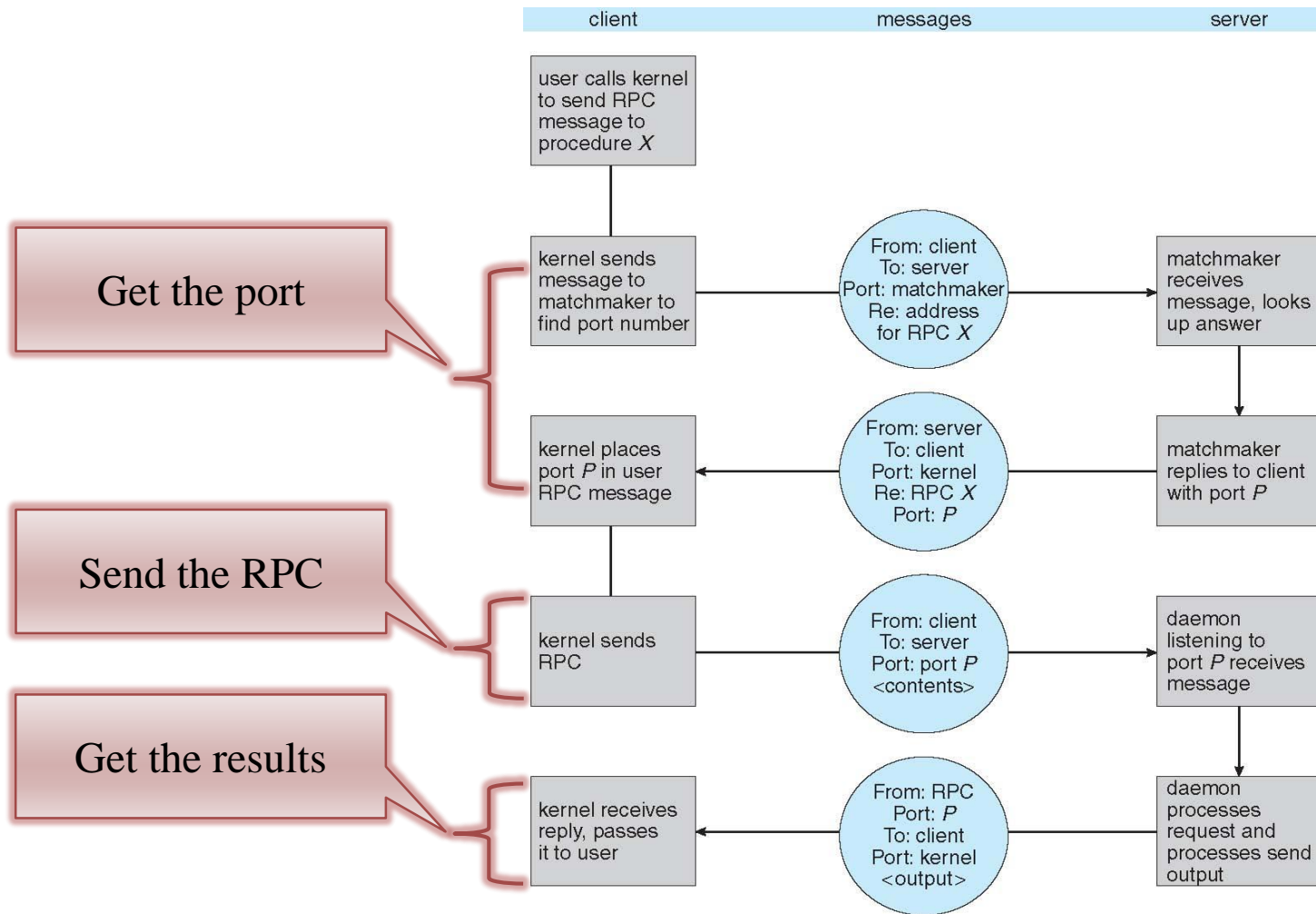


Remote Procedure Calls

- ▶ A way to abstract the procedure-call mechanism for use between systems with network connection
- ▶ Stubs at the client site
 - One for each RPC
 - Locate the proper port and marshal parameters
- ▶ Stubs at the server site
 - Receive the message
 - Invoke the procedure and return the results
- ▶ Data representation handled via the External Data Representation (XDL) format to account for different architectures
 - Big-endian and little-endian

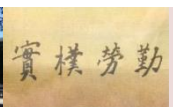


Execution of RPC



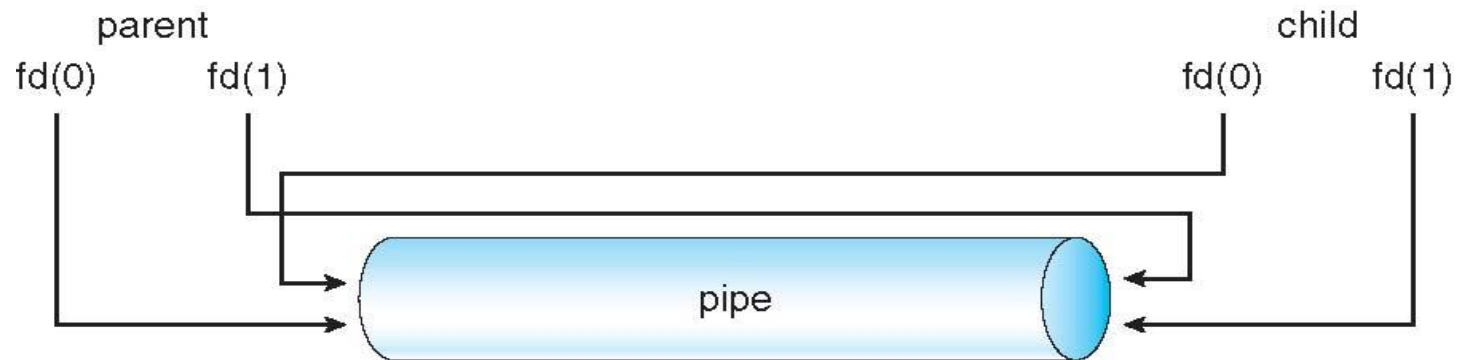
Pipes

- ▶ Acts as a conduit allowing two processes to communicate
- ▶ Issues
 - Is communication unidirectional or bidirectional?
 - In the case of two-way communication, is it half-duplex or full-duplex?
 - Must there exist a relationship (i.e. parent-child) between the communicating processes?
 - Can the pipes be used over a network?



Ordinary Pipes

- ▶ Ordinary Pipes allow communication in the standard producer-consumer style
- ▶ Producer writes to the **write-end** of the pipe
- ▶ Consumer reads from the **read-end** of the pipe
- ▶ Ordinary pipes are therefore unidirectional
- ▶ Require parent-child relationship between communicating processes



Named Pipes

- ▶ Named Pipes are more powerful than ordinary pipes
- ▶ Communication is bidirectional
- ▶ No parent-child relationship is necessary between the communicating processes
- ▶ Several processes can use the named pipe for communication
- ▶ Provided on both UNIX and Windows systems



Question 1

- ▶ Assume that the fork() function is always successful
- ▶ Please show the output

```
#include<sys/types.h>
#include<stdio.h>
#include<unistd.h>
int main()
{
    pid_t pid, pid2;
    printf("Statement 1 !\n");
    pid = fork();
    if (pid > 0)
    {
        wait(NULL);
    }
    else
    {
        pid2 = fork();
        if (pid2 == 0)
        {
            printf("Statement 2 !\n");
        }
        else
        {
            wait(NULL);
            printf("Statement 3 !\n");
        }
        printf("Statement 4 !\n");
    }
    printf("Statement 5 !\n");
    return 0;
}
```

