In the previous chapters, we examined many operating system principles, abstractions, algorithms, and techniques in general. Now it is time to look at some concrete systems to see how these principles are applied in the real world. We will begin with Linux, a popular variant of UNIX, which runs on a wide variety of computers. It is one of the dominant operating systems on high-end workstations and servers, but it is also used on systems ranging from cell phones to supercomputers. It also illustrates many important design principles well.

Our discussion will start with its history and evolution of UNIX and Linux. Then we will provide an overview of Linux, to give an idea of how it is used. This overview will be of special value to readers familiar only with Windows, since the latter hides virtually all the details of the system from its users. Although graphical interfaces may be easy for beginners, they provide little flexibility and no insight into how the system works.

Next we come to the heart of this chapter, an examination of processes, memory management, I/O, the file system, and security in Linux. For each topic we will first discuss the fundamental concepts, then the system calls, and finally the implementation.

Right off the bat we should address the question: “Why Linux?” Linux is a variant of UNIX, but there are many other versions and variants of UNIX including AIX, FreeBSD, HP-UX, SCO UNIX, System V, Solaris, and others. Fortunately, the fundamental principles and system calls are pretty much the same for all of them (by design). Furthermore, the general implementation strategies, algorithms,
and data structures are similar, but there are some differences. To make the examples concrete, it is best to choose one of them and describe it consistently. Since most readers are more likely to have encountered Linux than any of the others, we will use it as our running example, but again be aware that except for the information on implementation, much of this chapter applies to all UNIX systems. 

A large number of books have been written on how to use UNIX, but there also some about advanced features and system internals (Bovet and Cesati, 2005; Maxwell, 2001; McKusick and Neville-Neil, 2004; Pate, 2003; Stevens and Rago, 2008; and Vahalia, 2007).

10.1 HISTORY OF UNIX AND LINUX

UNIX and Linux have a long and interesting history, so we will begin our study there. What started out as the pet project of one young researcher (Ken Thompson) has become billion dollar industry involving universities, multinational corporations, governments, and international standardization bodies. In the following pages we will tell how this story has unfolded.

10.1.1 UNICS

Back in the 1940s and 1950s, all computers were personal computers, at least in the sense that the then-normal way to use a computer was to sign up for an hour of time and take over the entire machine for that period. Of course, these machines were physically immense, but only one person (the programmer) could use them at any given time. When batch systems took over, in the 1960s, the programmer submitted a job on punched cards by bringing it to the machine room. When enough jobs had been assembled, the operator read them all in as a single batch. It usually took an hour or more after submitting a job until the output was returned. Under these circumstances, debugging was a time-consuming process, because a single misplaced comma might result in wasting several hours of the programmer’s time.

To get around what almost everyone viewed as an unsatisfactory and unproductive arrangement, timesharing was invented at Dartmouth College and M.I.T. The Dartmouth system ran only BASIC and enjoyed a short-term commercial success before vanishing. The M.I.T. system, CTSS, was general purpose and was an enormous success among the scientific community. Within a short time, researchers at M.I.T. joined forces with Bell Labs and General Electric (then a computer vendor) and began designing a second generation system, MULTICS (MULTIplexed Information and Computing Service), as we discussed in Chap. 1.

Although Bell Labs was one of the founding partners in the MULTICS project, it later pulled out, which left one of the Bell Labs researchers, Ken Thompson, looking around for something interesting to do. He eventually decided to
write a stripped down MULTICS by himself (in assembler this time) on a discarded PDP-7 minicomputer. Despite the tiny size of the PDP-7, Thompson’s system actually worked and could support Thompson’s development effort. Consequently, one of the other researchers at Bell Labs, Brian Kernighan, somewhat jokingly called it UNICS (UNiplexed Information and Computing Service). Despite puns about “EUNUCHS” being a castrated MULTICS, the name stuck, although the spelling was later changed to UNIX.

10.1.2 PDP-11 UNIX

Thompson’s work so impressed many of his colleagues at Bell Labs, that he was soon joined by Dennis Ritchie, and later by his entire department. Two major developments occurred around this time. First, UNIX was moved from the obsolete PDP-7 to the much more modern PDP-11/20 and then later to the PDP-11/45 and PDP-11/70. The latter two machines dominated the minicomputer world for much of the 1970s. The PDP-11/45 and PDP-11/70 were powerful machines with large physical memories for their era (256 KB and 2 MB, respectively). Also, they had memory protection hardware, making it possible to support multiple users at the same time. However, they were both 16-bit machines that limited individual processes to 64 KB of instruction space and 64 KB of data space, even though the machine may have had far more physical memory.

The second development concerned the language in which UNIX was written. By now it was becoming painfully obvious that having to rewrite the entire system for each new machine was no fun at all, so Thompson decided to rewrite UNIX in a high-level language of his own design, called B. B was a simplified form of BCPL (which itself was a simplified form of CPL, which, like PL/I, never worked). Due to weaknesses in B, primarily lack of structures, this attempt was not successful. Ritchie then designed a successor to B, (naturally) called C, and wrote an excellent compiler for it. Working together, Thompson and Ritchie rewrote UNIX in C. C was the right language at the right time, and has dominated system programming ever since.

In 1974, Ritchie and Thompson published a landmark paper about UNIX (Ritchie and Thompson, 1974). For the work described in this paper they were later given the prestigious ACM Turing Award (Ritchie, 1984; Thompson, 1984). The publication of this paper stimulated many universities to ask Bell Labs for a copy of UNIX. Since Bell Labs’ parent company, AT&T, was a regulated monopoly at the time and was not permitted to be in the computer business, it had no objection to licensing UNIX to universities for a modest fee.

In one of those coincidences that often shape history, the PDP-11 was the computer of choice at nearly all university computer science departments, and the operating systems that came with the PDP-11 were widely regarded as being dreadful by professors and students alike. UNIX quickly filled the void, not in the least because it was supplied with the complete source code, so people could, and
did, tinker with it endlessly. Numerous scientific meetings were organized around UNIX, with distinguished speakers getting up in front of the room to tell about some obscure kernel bug they had found and fixed. An Australian professor, John Lions, wrote a commentary on the UNIX source code of the type normally reserved for the works of Chaucer or Shakespeare (reprinted as Lions, 1996). The book described Version 6, so named because it was described in the sixth edition of the UNIX Programmer’s Manual. The source code was 8200 lines of C and 900 lines of assembly code. As a result of all this activity, new ideas and improvements to the system spread rapidly.

Within a few years, Version 6 was replaced by Version 7, the first portable version of UNIX (it ran on the PDP-11 and the Interdata 8/32), by now 18,800 lines of C and 2100 lines of assembler. A whole generation of students was brought up on Version 7, which contributed to its spread after they graduated and went to work in industry. By the mid 1980s, UNIX was in widespread use on minicomputers and engineering workstations from a variety of vendors. A number of companies even licensed the source code to make their own version of UNIX.

One of these was a small startup called Microsoft, which sold Version 7 under the name XENIX for a number of years until its interest turned elsewhere.

10.1.3 Portable UNIX

Now that UNIX was written in C, moving it to a new machine, known as porting it, was much easier than in the early days. A port requires first writing a C compiler for the new machine. Then it requires writing device drivers for the new machine’s I/O devices, such as monitors, printers, and disks. Although the driver code is in C, it cannot be moved to another machine, compiled, and run there because no two disks work the same way. Finally, a small amount of machine-dependent code, such as the interrupt handlers and memory management routines, must be rewritten, usually in assembly language.

The first port beyond the PDP-11 was to the Interdata 8/32 minicomputer. This exercise revealed a large number of assumptions that UNIX implicitly made about the machine it was running on, such as the unspoken supposition that integers held 16 bits, pointers also held 16 bits (implying a maximum program size of 64 KB), and that the machine had exactly three registers available for holding important variables. None of these were true on the Interdata, so considerable work was needed to clean UNIX up.

Another problem was that although Ritchie’s compiler was fast and produced good object code, it produced only PDP-11 object code. Rather than write a new compiler specifically for the Interdata, Steve Johnson of Bell Labs designed and implemented the portable C compiler, which could be retargeted to produce code for any reasonable machine with a only a moderate amount of effort. For years, nearly all C compilers for machines other than the PDP-11 were based on Johnson’s compiler, which greatly aided the spread of UNIX to new computers.
The port to the Interdata initially went slowly because all the development work had to be done on the only working UNIX machine, a PDP-11, which happened to be on the fifth floor at Bell Labs. The Interdata was on the first floor. Generating a new version meant compiling it on the fifth floor and then physically carrying a magnetic tape down to the first floor to see if it worked. After several months of tape carrying, an unknown person said: “You know, we’re the phone company. Can’t we run a wire between these two machines?” Thus was UNIX networking born. After the Interdata port, UNIX was ported to the VAX and other computers.

After AT&T was broken up in 1984 by the U.S. government, the company was legally free to set up a computer subsidiary, and soon did. Shortly thereafter, AT&T released its first commercial UNIX product, System III. It was not well received, so it was replaced by an improved version, System V, a year later. Whatever happened to System IV is one of the great unsolved mysteries of computer science. The original System V has since been replaced by System V, releases 2, 3, and 4, each one bigger and more complicated than its predecessor. In the process, the original idea behind UNIX, of having a simple, elegant system has gradually diminished. Although Ritchie and Thompson’s group later produced an 8th, 9th, and 10th edition of UNIX, these were never widely circulated, as AT&T put all its marketing muscle behind System V. However, some of the ideas from the 8th, 9th, and 10th editions were eventually incorporated into System V. AT&T eventually decided that it wanted to be a telephone company after all, not a computer company, after all, and sold its UNIX business to Novell in 1993. Novell then sold it to the Santa Cruz Operation in 1995. By then it was almost irrelevant who owned it since all the major computer companies already had licenses.

10.1.4 Berkeley UNIX

One of the many universities that acquired UNIX Version 6 early on was the University of California at Berkeley. Because the complete source code was available, Berkeley was able to modify the system substantially. Aided by grants from ARPA, the U.S. Dept. of Defense’s Advanced Research Projects Agency, Berkeley produced and released an improved version for the PDP-11 called 1BSD (First Berkeley Software Distribution). This tape was followed quickly by 2BSD also for the PDP-11.

More important were 3BSD and especially its successor, 4BSD for the VAX. Although AT&T had a VAX version of UNIX, called 32V, it was essentially Version 7. In contrast, 4BSD contained a large number of improvements. Foremost among these was the use of virtual memory and paging, allowing programs to be larger than physical memory by paging parts of them in and out as needed. Another change allowed file names to be longer than 14 characters. The implementation of the file system was also changed, making it considerably faster.
Signal handling was made more reliable. Networking was introduced, causing the network protocol that was used, TCP/IP, to become a de facto standard in the UNIX world, and later in the Internet, which is dominated by UNIX-based servers.

Berkeley also added a substantial number of utility programs to UNIX, including a new editor (**vi**), a new shell (**csh**), Pascal and Lisp compilers, and many more. All these improvements caused Sun Microsystems, DEC, and other computer vendors to base their versions of UNIX on Berkeley UNIX, rather than on AT&T’s “official” version, System V. As a consequence, Berkeley UNIX became well established in the academic, research, and defense worlds. For more information about Berkeley UNIX, see McKusick et al.) 1996.

### 10.1.5 Standard UNIX

By the late 1980s, two different, and somewhat incompatible, versions of UNIX were in widespread use: 4.3BSD and System V Release 3. In addition, virtually every vendor added its own nonstandard enhancements. This split in the UNIX world, together with the fact that there were no standards for binary program formats, greatly inhibited the commercial success of UNIX because it was impossible for software vendors to write and package UNIX programs with the expectation that they would run on any UNIX system (as was routinely done with MS-DOS). Various attempts at standardizing UNIX initially failed. AT&T, for example, issued the **SVID** (**System V Interface Definition**), which defined all the system calls, file formats, and so on. This document was an attempt to keep all the System V vendors in line, but it had no effect on the enemy (BSD) camp, which just ignored it.

The first serious attempt to reconcile the two flavors of UNIX was initiated under the auspices of the IEEE Standards Board, a highly respected and, most important, neutral body. Hundreds of people from industry, academia, and government took part in this work. The collective name for this project was **POSIX**. The first three letters refer to Portable Operating System. The **IX** was added to make the name UNIXish.

After a great deal of argument and counterargument, rebuttal and counterrebuttal, the POSIX committee produced a standard known as **1003.1**. It defines a set of library procedures that every conformant UNIX system must supply. Most of these procedures invoke a system call, but a few can be implemented outside the kernel. Typical procedures are **open**, **read**, and **fork**. The idea of POSIX is that a software vendor who writes a program that uses only the procedures defined by 1003.1 knows that this program will run on every conformant UNIX system.

While it is true that most standards bodies tend to produce a horrible compromise with a few of everyone’s pet features in it, 1003.1 is remarkably good considering the large number of parties involved and their respective vested interests. Rather than take the union of all features in System V and BSD as the starting point (the norm for most standards bodies), the IEEE committee took the
intersection. Very roughly, if a feature was present in both System V and BSD, it was included in the standard; otherwise it was not. As a consequence of this algorithm, 1003.1 bears a strong resemblance to the direct ancestor of both System V and BSD, namely Version 7. The 1003.1 document is written in such a way that both operating system implementers and software writers can understand it, another novelty in the standards world, although work is already underway to remedy this.

Although the 1003.1 standard addresses only the system calls, related documents standardize threads, the utility programs, networking, and many other features of UNIX. In addition, the C language has also been standardized by ANSI and ISO.

10.1.6 MINIX

One property that all UNIX systems have is that they are large and complicated, in a sense, the antithesis of the original idea behind UNIX. Even if the source code were freely available, which it is not in most cases, it is out of the question that a single person could understand it all any more. This situation led the author of this book to write a new UNIX-like system that was small enough to understand, was available with all the source code, and could be used for educational purposes. That system consisted of 11,800 lines of C and 800 lines of assembly code. It was released in 1987, and was functionally almost equivalent to Version 7 UNIX, the mainstay of most computer science departments during the PDP-11 era.

MINIX was one of the first UNIX-like systems based on a microkernel design. The idea behind a microkernel is to provide minimal functionality in the kernel to make it reliable and efficient. Consequently, memory management and the file system were pushed out into user processes. The kernel handled message passing between the processes and little else. The kernel was 1600 lines of C and 800 lines of assembler. For technical reasons relating to the 8088 architecture, the I/O device drivers (2900 additional lines of C) were also in the kernel. The file system (5100 lines of C) and memory manager (2200 lines of C) ran as two separate user processes.

Microkernels have the advantage over monolithic systems that they are easy to understand and maintain due to their highly modular structure. Also, moving code from the kernel to user mode makes them highly reliable because the crash of a user-mode process does less damage than the crash of a kernel-mode component. Their main disadvantage is a slightly lower performance due to the extra switches between user mode and kernel mode. However, performance is not everything: all modern UNIX systems run X Windows in user mode and simply accept the performance hit to get the greater modularity (in contrast to Windows, where the entire GUI (Graphical User Interface) is in the kernel). Other well-known microkernel designs of this era were Mach (Accetta et al., 1986) and
Within a few months of its appearance, MINIX became a bit of a cult item, with its own USENET (now Google) newsgroup, comp.os.minix, and over 40,000 users. Many users contributed commands and other user programs, so MINIX became a collective undertaking done by large numbers of users over the Internet. It was a prototype of other collaborative efforts that came later. In 1997, Version 2.0 of MINIX, was released and the base system, now including networking, had grown to 62,200 lines of code.

Around 2004, the direction of MINIX development changed, with the focus becoming building an extremely reliable and dependable system that could automatically repair its own faults and become self healing, continuing to function correctly even in the face of repeated software bugs being triggered. As a consequence, the modularization idea present in Version 1 was greatly expanded in MINIX 3.0, with nearly all the device drivers being moved to user space, with each driver running as a separate process. The size of the entire kernel abruptly dropped to under 4000 lines of code, something a single programmer could easily understand. Mechanisms were changed to enhance fault tolerance in numerous ways.

In addition, a great deal of popular UNIX software was ported to MINIX 3.0, including the X Window System (sometimes just called X), various compilers (including gcc), text-processing software, networking software, Web browsers and much more. Unlike previous versions, which were primarily educational in nature, starting with MINIX 3.0, the system was quite usable, with the focus moving towards high dependability.

A third edition of the book appeared, describing the new system and giving its source code in an appendix and describing it in detail (Tanenbaum and Woodhull, 2006). The system continues to evolve and has an active user community. For more details and to get the current version for free, you can visit www.minix3.org.

10.1.7 Linux

During the early years of MINIX development and discussion on the Internet, many people requested (or in many cases, demanded) more and better features, to which the author often said “No” (to keep the system small enough for students to understand completely in a one-semester university course). This continuous “No” irked many users. At this time, FreeBSD was not available, so that was not an option. After a number of years went by like this, a Finnish student, Linus Torvalds, decided to write another UNIX clone, named Linux, which would be a full-blown production system with many features MINIX was initially lacking. The first version of Linux, 0.01, was released in 1991. It was cross-developed on a MINIX machine and borrowed numerous ideas from MINIX ranging from the structure of the source tree to the layout of the file system. However, it was a monolithic rather than a microkernel design, with the entire operating system in
the kernel. The code size totaled 9,300 lines of C and 950 lines of assembler, roughly similar to MINIX version in size and also roughly comparable in functionality.

Linux rapidly grew in size and evolved into a full production UNIX clone as virtual memory, a more sophisticated file system, and many other features were added. Although it originally ran only on the 386 (and even had embedded 386 assembly code in the middle of C procedures), it was quickly ported to other platforms and now runs on a wide variety of machines, just as UNIX does. One difference with UNIX does stand out however: Linux makes use of many special features of the gcc compiler and would need a lot of work before it would compile with an ANSI standard C compiler.

The next major release of Linux was version 1.0, issued in 1994. It was about 165,000 lines of code and included a new file system, memory-mapped files, and BSD-compatible networking with sockets and TCP/IP. It also included many new device drivers. Several minor revisions followed in the next two years.

By this time, Linux was sufficiently compatible with UNIX that a vast amount of UNIX software was ported to Linux, making it far more useful than it would have otherwise been. In addition, a large number of people were attracted to Linux and began working on the code and extending it in many ways under Torvalds’ general supervision.

The next major release, 2.0, was made in 1996. It consisted of about 470,000 lines of C and 8000 lines of assembly code. It included support for 64-bit architectures, symmetric multiprogramming, new networking protocols, and numerous other features. A large fraction of the total code mass was taken up by an extensive collection of device drivers. Additional releases followed frequently.

The version numbers of the Linux kernel consist of four numbers, $A.B.C.D$, such as 2.6.9.11. The first number denotes the kernel version. The second number denotes the major revision. Prior to the 2.6 kernel, even revision numbers corresponded to stable kernel releases, whereas odd ones corresponded to unstable revisions, under development. With the 2.6 kernel that is no longer the case. The third number corresponds to minor revisions, such as support for new drivers. The fourth number corresponds to minor bug fixes or security patches.

A large array of standard UNIX software has been ported to Linux, including the X Window System and a great deal of networking software. Two different GUIs (GNOME and KDE) have also been written for Linux. In short, it has grown to a full-blown UNIX clone with all the bells and whistles a UNIX lover might want.

One unusual feature of Linux is its business model: it is free software. It can be downloaded from various sites on the Internet, for example: www.kernel.org. Linux comes with a license devised by Richard Stallman, founder of the Free Software Foundation. Despite the fact that Linux is free, this license, the GPL (GNU Public License), is longer than Microsoft’s Windows license and specifies what you can and cannot do with the code. Users may use, copy, modify, and
CASE STUDY 1: Linux

redistribute the source and binary code freely. The main restriction is that all works derived from the Linux kernel may not be sold or redistributed in binary form only; the source code must either be shipped with the product or be made available on request.

Although Torvalds still controls the kernel fairly closely, a large amount of user-level software has been written by numerous other programmers, many of them originally migrated over from the MINIX, BSD, and GNU online communities. However, as Linux evolves, a steadily smaller fraction of the Linux community want to hack source code (witness hundreds of books telling how to install and use Linux and only a handful discussing the code or how it works). Also, many Linux users now forego the free distribution on the Internet to buy one of many CD-ROM distributions available from numerous competing commercial companies. A Web site listing the current top 100 top Linux distributions is www.distrowatch.org. As more and more software companies start selling their own versions of Linux and more and more hardware companies offer to preinstall it on the computers they ship, the line between commercial software and free software is beginning to blur substantially.

As a footnote to the Linux story, it is interesting to note that just as the Linux bandwagon was gaining steam, it got a big boost from an unexpected source—AT&T. In 1992, Berkeley, by now running out of funding, decided to terminate BSD development with one final release, 4.4BSD, (which later formed the basis of FreeBSD). Since this version contained essentially no AT&T code, Berkeley issued the software under an open source license (not GPL) that let everybody do whatever they wanted with it except one thing—sue the University of California. The AT&T subsidiary controlling UNIX promptly reacted by—you guessed it—suing the University of California. It simultaneously sued a company, BSDI, set up by the BSD developers to package the system and sell support, much as Red Hat and other companies now do for Linux. Since virtually no AT&T code was involved, the lawsuit was based on copyright and trademark infringement, including items such as BSDI’s 1-800-ITS-UNIX telephone number. Although the case was eventually settled out of court, this legal action kept FreeBSD off the market just long enough for Linux to get well established. Had the lawsuit not happened, starting around 1993 there would have been a serious competition between two free, open source UNIX systems: the reigning champion, BSD, a mature and stable system with a large academic following dating back to 1977 versus the vigorous young challenger, Linux, just two years old but with a growing following among individual users. Who knows how this battle of the free UNICES would have turned out?
10.2 OVERVIEW OF LINUX

In this section we will provide a general introduction to Linux and how it is used, for the benefit of readers not already familiar with it. Nearly all of this material applies to just about all UNIX variants with only small deviations. Although Linux has several graphical interfaces, the focus here is how Linux appears to a programmer working in a shell window on X. Subsequent sections will focus on system calls and how it works inside.

10.2.1 Linux Goals

UNIX was always an interactive system designed to handle multiple processes and multiple users at the same time. It was designed by programmers, for programmers, to use in an environment in which the majority of the users are relatively sophisticated and are engaged in (often quite complex) software development projects. In many cases, a large number of programmers are actively cooperating to produce a single system, so UNIX has extensive facilities to allow people to work together and share information in controlled ways. The model of a group of experienced programmers working together closely to produce advanced software is obviously very different from the personal computer model of a single beginner working alone with a word processor, and this difference is reflected throughout UNIX from start to finish. It is only natural that Linux inherited many of these goals, even though the first version was for a personal computer.

What is it that good programmers want in a system? To start with, most like their systems to be simple, elegant, and consistent. For example, at the lowest level, a file should just be a collection of bytes. Having different classes of files for sequential access, random access, keyed access, remote access, etc. (as mainframes do) just gets in the way. Similarly, if the command

`ls A*`

means list all the files beginning with “A” then the command

`rm A*`

should mean remove all the files beginning with “A” and not remove the one file whose name consists of an “A” and an asterisk. This characteristic is sometimes called the principle of least surprise.

Another thing that experienced programmers generally want is power and flexibility. This means that a system should have a small number of basic elements that can be combined in an infinite variety of ways to suit the application. One of the basic guidelines behind Linux is that every program should do just one thing and do it well. Thus compilers do not produce listings, because other programs can do that better.

Finally, most programmers have a strong dislike for useless redundancy. Why
type copy when cp is enough? To extract all the lines containing the string “ard” from the file f, the Linux programmer types

    grep ard f

The opposite approach is to have the programmer first select the grep program (with no arguments), and then have grep announce itself by saying: “Hi, I’m grep, I look for patterns in files. Please enter your pattern.” After getting the pattern, grep prompts for a file name. Then it asks if there are any more file names. Finally, it summarizes what it is going to do and ask if that is correct. While this kind of user interface may or may not be suitable for rank novices, it irritates skilled programmers to no end. What they want is a servant, not a nanny.

10.2.2 Interfaces to Linux

A Linux system can be regarded as a kind of pyramid, as illustrated in Fig. 10-1. At the bottom is the hardware, consisting of the CPU, memory, disks, a monitor and keyboard, and other devices. Running on the bare hardware is the operating system. Its function is to control the hardware and provide a system call interface to all the programs. These system calls allow user programs to create and manage processes, files, and other resources.

![Figure 10-1. The layers in a Linux system.](image)

Programs make system calls by putting the arguments in registers (or sometimes, on the stack), and issuing trap instructions to switch from user mode to kernel mode. Since there is no way to write a trap instruction in C, a library is provided, with one procedure per system call. These procedures are written in assembly language, but can be called from C. Each one first puts its arguments in the proper place, then executes the trap instruction. Thus to execute the read system
call, a C program can call the `read` library procedure. As an aside, it is the library interface, and not the system call interface, that is specified by POSIX. In other words, POSIX tells which library procedures a conformant system must supply, what their parameters are, what they must do, and what results they must return. It does not even mention the actual system calls.

In addition to the operating system and system call library, all versions of Linux supply a large number of standard programs, some of which are specified by the POSIX 1003.2 standard, and some of which differ between Linux versions. These include the command processor (shell), compilers, editors, text processing programs, and file manipulation utilities. It is these programs that a user at the keyboard invokes.

Thus we can speak of three different interfaces to Linux: the true system call interface, the library interface, and the interface formed by the set of standard utility programs.

Most personal computer versions of Linux have replaced this keyboard-oriented user interface with a mouse-oriented graphical user interface, without changing the operating system itself at all. It is precisely this flexibility that makes Linux so popular and has allowed it to survive numerous changes in the underlying technology so well.

The GUI for Linux is similar to the first GUIs developed for UNIX systems in the 1970s, and popularized by Macintosh and later Windows for PC platforms. The GUI creates a desktop environment, a familiar metaphor with windows, icons, folders, toolbars, and drag-and-drop capabilities. A full desktop environment contains a window manager, which controls the placement and appearance of windows, as well as various applications, and provides a consistent graphical interface. Popular desktop environments for Linux include GNOME (GNU Network Object Model Environment) and KDE (K Desktop Environment).

GUIs on Linux are supported by the X Windowing System, or commonly X11 or just X, which defines communication and display protocols for manipulating windows on bitmap displays for UNIX and UNIX-like systems. The X server is the main component which controls devices such as keyboards, mouse, screen and is responsible for redirecting input to or accepting output from client programs. The actual GUI environment is typically built on top of a low-level library, `xlib`, which contains the functionality to interact with the X server. The graphical interface extends the basic functionality of X11 by enriching the window view, providing buttons, menus, icons, and other options. The X server can be started manually, from a command line, but is typically started during the boot process by a display manager, which displays the graphical login screen where a user enters his username and password.

When working on Linux systems through a graphical interface, users may use mouse clicks to run applications or open file, drag and drop to copy files from one location to another, etc. In addition, users may invoke a terminal emulator program, or `xterm`, which provides them with the basic command line interface to the
operating system. Its description is given in the following section.

10.2.3 The Shell

Although Linux systems have a graphical user interface, most programmers and sophisticated users still prefer a command line interface, called the shell. Often they start one or more shell windows from the graphical user interface and just work in them. The shell command line interface is much faster to use, more powerful, easily extensible, and does not give the user RSI from having to use a mouse all the time. Below we will briefly describe the bash shell (bash). It is heavily based on the original UNIX shell, Bourne shell, and in fact its name is an acronym for Bourne Again SHell. Many new shells are also in use (ksh, csh, etc.), however, bash is the default shell in most Linux systems.

When the shell starts up, it initializes itself, then types a prompt character, often a percent or dollar sign, on the screen and waits for the user to type a command line.

When the user types a command line, the shell extracts the first word from it, assumes it is the name of a program to be run, searches for this program, and if it finds it, runs the program. The shell then suspends itself until the program terminates, at which time it tries to read the next command. What is important here is simply the observation that the shell is an ordinary user program. All it needs is the ability to read from the keyboard and write to the monitor and the power to execute other programs.

Commands may take arguments, which are passed to the called program as character strings. For example, the command line

```
cp src dest
```

invokes the `cp` program with two arguments, `src` and `dest`. This program interprets the first one to be the name of an existing file. It makes a copy of this file and calls the copy `dest`.

Not all arguments are file names. In

```
head --20 file
```

the first argument, `--20`, tells `head` to print the first 20 lines of `file`, instead of the default number of lines, 10. Arguments that control the operation of a command or specify an optional value are called flags, and by convention are indicated with a dash. The dash is required to avoid ambiguity, because the command

```
head 20 file
```

is perfectly legal, and tells `head` to first print the initial 10 lines of a file called `20`, and then print the initial 10 lines of a second file called `file`. Most Linux commands accept multiple flags and arguments.

To make it easy to specify multiple file names, the shell accepts magic
characters, sometimes called wild cards. An asterisk, for example, matches all possible strings, so

```
ls *.c
```

tells `ls` to list all the files whose name ends in `.c`. If files named `x.c`, `y.c`, and `z.c` all exist, the above command is equivalent to typing

```
ls x.c y.c z.c
```

Another wild card is the question mark, which matches any one character. A list of characters inside square brackets selects any of them, so

```
ls [ape]*
```

lists all files beginning with “a”, “p”, or “e”.

A program like the shell does not have to open the terminal (keyboard and monitor) in order to read from it or write to it. Instead, when it (or any other program) starts up, it automatically has access to a file called standard input (for reading), a file called standard output (for writing normal output), and a file called standard error (for writing error messages). Normally, all three default to the terminal, so that reads from standard input come from the keyboard and writes to standard output or standard error go to the screen. Many Linux programs read from standard input and write to standard output as the default. For example,

```
sort
```

invokes the `sort` program, which reads lines from the terminal (until the user types a CTRL-D, to indicate end of file), sorts them alphabetically, and writes the result to the screen.

It is also possible to redirect standard input and standard output, as that is often useful. The syntax for redirecting standard input uses a less than sign (`<`) followed by the input file name. Similarly, standard output is redirected using a greater than sign (`>`) . It is permitted to redirect both in the same command. For example, the command

```
sort <in >out
```

causes `sort` to take its input from the file `in` and write its output to the file `out`. Since standard error has not been redirected, any error messages go to the screen. A program that reads its input from standard input, does some processing on it, and writes its output to standard output is called a filter.

Consider the following command line consisting of three separate commands:

```
sort <in >temp; head -30 <temp; rm temp
```

It first runs `sort`, taking the input from `in` and writing the output to `temp`. When that has been completed, the shell runs `head`, telling it to print the first 30 lines of `temp` and print them on standard output, which defaults to the terminal. Finally,
the temporary file is removed.

It frequently occurs that the first program in a command line produces output that is used as the input on the next program. In the above example, we used the file temp to hold this output. However, Linux provides a simpler construction to do the same thing. In

```
sort <in | head -30
```

the vertical bar, called the **pipe symbol**, says to take the output from *sort* and use it as the input to *head*, eliminating the need for creating, using, and removing the temporary file. A collection of commands connected by pipe symbols, called a **pipeline**, may contain arbitrarily many commands. A four-component pipeline is shown by the following example:

```
grep ter *.*t | sort | head -20 | tail -5 >foo
```

Here all the lines containing the string "ter" in all the files ending in .t are written to standard output, where they are sorted. The first 20 of these are selected out by *head* which passes then to *tail*, which writes the last five (i.e., lines 16 to 20 in the sorted list) to *foo*. This is an example of how Linux provides basic building blocks (numerous filters), each of which does one job, along with a mechanism for them to be put together in almost limitless ways.

Linux is a general-purpose multiprogramming system. A single user can run several programs at once, each as a separate process. The shell syntax for running a process in the background is to follow its command with an ampersand. Thus

```
wc -l <a >b &
```

runs the word count program, *wc*, to count the number of lines (*-l* flag) in its input, *a*, writing the result to *b*, but does it in the background. As soon as the command has been typed, the shell types the prompt and is ready to accept and handle the next command. Pipelines can also be put in the background, for example, by

```
sort <x | head &
```

Multiple pipelines can run in the background simultaneously.

It is possible to put a list of shell commands in a file and then start a shell with this file as standard input. The (second) shell just processes them in order, the same as it would with commands typed on the keyboard. Files containing shell commands are called **shell scripts**. Shell scripts may assign values to shell variables and then read them later. They may also have parameters, and use if, for, while, and case constructs. Thus a shell script is really a program written in shell language. The Berkeley C shell is an alternative shell that has been designed to make shell scripts (and the command language in general) look like C programs in many respects. Since the shell is just another user program, various other people have written and distributed a variety of other shells.
The command-line (shell) user interface to Linux consists of a large number of standard utility programs. Roughly speaking, these programs can be divided into six categories, as follows:

1. File and directory manipulation commands.
2. Filters.
3. Program development tools such as editors and compilers.
4. Text processing.
5. System administration.
6. Miscellaneous.

The POSIX 1003.2 standard specifies the syntax and semantics of just under 100 of these, primarily in the first three categories. The idea of standardizing them is to make it possible for anyone to write shell scripts that use these programs and work on all Linux systems.

In addition to these standard utilities, there are many application programs as well, of course, such as Web browsers, image viewers, etc.

Let us consider some examples of these programs, starting with file and directory manipulation.

```bash
cp a b
```
copies file `a` to `b`, leaving the original file intact. In contrast,

```bash
mv a b
```
copies `a` to `b` but removes the original. In effect, it moves the file rather than really making a copy in the usual sense. Several files can be concatenated using `cat`, which reads each of its input files and copies them all to standard output, one after another. Files can be removed by the `rm` command. The `chmod` command allows the owner to change the rights bits to modify access permissions. Directories can be created with `mkdir` and removed with `rmdir`. To see a list of the files in a directory, `ls` can be used. It has a vast number of flags to control how much detail about each file is shown (e.g., size, owner, group, creation date), to determine the sort order (e.g., alphabetical, by time of last modification, reversed), to specify the layout on the screen, and much more.

We have already seen several filters: `grep` extracts lines containing a given pattern from standard input or one or more input files; `sort` sorts its input and writes it on standard output; `head` extracts the initial lines of its input; `tail` extracts the final lines of its input. Other filters defined by 1003.2 are `cut` and `paste`, which allow columns of text to be cut and pasted into files; `od` which converts its
(usually binary) input to ASCII text, in octal, decimal, or hexadecimal; \textit{tr}, which does character translation (e.g., lower case to upper case), and \textit{pr} which formats output for the printer, including options to include running heads, page numbers, and so on.

Compilers and programming tools include \textit{gcc}, which calls the C compiler, and \textit{ar}, which collects library procedures into archive files.

Another important tool is \textit{make}, which is used to maintain large programs whose source code consists of multiple files. Typically, some of these are \textbf{header files}, which contain type, variable, macro, and other declarations. Source files often include these using a special \textit{include} directive. This way, two or more source files can share the same declarations. However, if a header file is modified, it is necessary to find all the source files that depend on it, and recompile them. The function of \textit{make} is to keep track of which file depends on which header, and similar things, and arrange for all the necessary compilations to occur automatically. Nearly all Linux programs, except the smallest ones, are set up to be compiled with \textit{make}.

A selection of the POSIX utility programs is listed in Fig. 10-2, along with a short description of each one. All Linux systems have these programs, and many more.

<table>
<thead>
<tr>
<th>Program</th>
<th>Typical use</th>
</tr>
</thead>
<tbody>
<tr>
<td>cat</td>
<td>Concatenate multiple files to standard output</td>
</tr>
<tr>
<td>chmod</td>
<td>Change file protection mode</td>
</tr>
<tr>
<td>cp</td>
<td>Copy one or more files</td>
</tr>
<tr>
<td>cut</td>
<td>Cut columns of text from a file</td>
</tr>
<tr>
<td>grep</td>
<td>Search a file for some pattern</td>
</tr>
<tr>
<td>head</td>
<td>Extract the first lines of a file</td>
</tr>
<tr>
<td>ls</td>
<td>List directory</td>
</tr>
<tr>
<td>make</td>
<td>Compile files to build a binary</td>
</tr>
<tr>
<td>mkdir</td>
<td>Make a directory</td>
</tr>
<tr>
<td>od</td>
<td>Octal dump a file</td>
</tr>
<tr>
<td>paste</td>
<td>Paste columns of text into a file</td>
</tr>
<tr>
<td>pr</td>
<td>Format a file for printing</td>
</tr>
<tr>
<td>rm</td>
<td>Remove one or more files</td>
</tr>
<tr>
<td>rmdir</td>
<td>Remove a directory</td>
</tr>
<tr>
<td>sort</td>
<td>Sort a file of lines alphabetically</td>
</tr>
<tr>
<td>tail</td>
<td>Extract the last lines of a file</td>
</tr>
<tr>
<td>tr</td>
<td>Translate between character sets</td>
</tr>
</tbody>
</table>

Figure 10-2. A few of the common Linux utility programs required by POSIX.
10.2.5 Kernel Structure

In Fig. 10-1 we saw the overall structure of a Linux system. Now let us zoom in and look more closely at the kernel before examining the various parts.

![Diagram of Linux kernel structure]

The kernel sits directly on the hardware and enables interactions with various devices, the system memory and controls CPU accesses. At the lowest level, as shown in Fig. 10-3 it contains interrupt handlers, which are the primary way for interacting with devices, and low-level dispatching mechanism. This dispatching occurs when an interrupt happens. The low-level code here stops the running process, saves its state in the kernel process structures, and starts the appropriate driver. Process dispatching also happens when the kernel completes some operations and it is time to start up a user process again. The dispatching code is in assembler and is quite distinct from scheduling.

Next, we divide the various kernel subsystems into three main components. The I/O component in Fig. 10-3 contains all kernel pieces responsible for interacting with devices and performing network and storage I/O operations. At the highest level, the I/O operations are all integrated under a Virtual File System layer. That is, at the top level, performing a read operation to a file, whether it is...
in memory or on disk, is the same as performing a read operation to retrieve a character from a terminal input. At the lowest level, all I/O operations pass through some device driver. All Linux drivers are classified as either character device drivers or block device drivers, with the main difference that seeks and random accesses are allowed on block devices and not on character devices. Technically, network devices are character devices, but they are handled somewhat differently that it is probably clearer to separate them, as has been done in the figure.

Above the device driver level, the kernel code is different for each device type. Character devices may be used in two different ways. Some programs, such as visual editors like *vi* and *emacs*, want every key stroke as it is hit. Raw terminal (tty) I/O makes this possible. Other software, such as the shell, is line oriented, and allows users to edit the whole line before hitting ENTER to send it to the program. In this case the character stream from the terminal device is passed through a so called line discipline, and appropriate formatting is applied.

Networking software is often modular, with different devices and protocols supported. The layer above the network drivers handles a kind of routing function, making sure that the right packet goes to the right device or protocol handler. Most Linux systems contain the full functionality of a hardware router within the kernel, although the performance is less than that of a hardware router. Above the router code is the actual protocol stack, always including IP and TCP, but also many additional protocols. Overlaying all the network is the socket interface, which allows programs to create sockets for particular networks and protocols, getting back a file descriptor for each socket to use later.

On top of the disk drivers is the I/O scheduler, which is responsible for ordering and issuing disk operation requests in a way that tries to conserve wasteful disk head movement, or to meet some other system policy.

At the very top of the block device column are the file systems. Linux may have, and it does in fact, multiple file systems coexisting concurrently. In order to hide the gruesome architectural differences of various hardware devices from the file system implementation, a generic block device layer provides an abstraction used by all file systems.

To the right in Fig. 10-3 are the other two key components of the Linux kernel. These are responsible for the memory and process management tasks. Memory management tasks include maintaining the virtual to physical memory mappings, maintaining a cache of recently accessed pages and implementing a good page replacement policy, and on-demand bringing in new pages of needed code and data into memory.

The key responsibility of the process management component is the creation and termination of processes. It also includes the process scheduler, which chooses which process or, rather, thread to run next. As we shall see in the next section, the Linux kernel treats both processes and threads simply as executable entities, and will schedule them based on a global scheduling policy. Finally, code
While the three components are represented separately in the figure, they are highly interdependent. File systems typically access files through the block devices. However, in order to hide the large latencies of disk accesses, files are copied into the page cache in main memory. Some files may even be dynamically created and may only have an in-memory representation, such as files providing some runtime resource usage information. In addition, the virtual memory systems may rely on a disk partition or in-file swap area to back up parts of the main memory when it needs to free up certain pages, and therefore relies on the I/O component. Numerous other interdependencies exist.

In addition to the static in-kernel components, Linux supports dynamically loadable modules. These modules can be used to add or replace the default device drivers, file system, networking, or other kernel codes. The modules are not shown in Fig. 10-3.

Finally, at the very top is the system call interface into the kernel. All system calls come here, cause a trap which switches the execution from user mode into protected kernel mode and passes control to one of the kernel components described above.

10.3 PROCESSES IN LINUX

In the previous sections, we started out by looking at Linux as viewed from the keyboard, that is, what the user sees in an xterm window. We gave examples of shell commands and utility programs that are frequently used. We ended with a brief overview of the system structure. Now it is time to dig deeply into the kernel and look more closely at the basic concepts Linux supports, namely, processes, memory, the file system, and input/output. These notions are important because the system calls—the interface to the operating system itself—manipulate them. For example, system calls exist to create processes and threads, allocate memory, open files, and do I/O.

Unfortunately, with so many versions of Linux in existence, there are some differences between them. In this chapter, we will emphasize the features common to all of them rather than focus on any one specific version. Thus in certain sections (especially implementation sections), the discussion may not apply equally to every version.

10.3.1 Fundamental Concepts

The main active entities in a Linux system are the processes. Linux processes are very similar to the classical sequential processes that we studied in Chap 2. Each process runs a single program and initially has a single thread of control. In other words, it has one program counter, which keeps track of the next instruction
to be executed. Linux allow a process to create additional threads once it starts executing.

Linux is a multiprogramming system, so multiple, independent processes may be running at the same time. Each user may have several active processes at once, so on a large system, there may be hundreds or even thousands of processes running. In fact, on most single-user workstations, even when the user is absent, dozens of background processes, called **daemons**, are running. These are started by a shell script when the system is booted. (“Daemon” is a variant spelling of “demon,” which is a self-employed evil spirit.)

A typical daemon is the **cron daemon**. It wakes up once a minute to check if there is any work for it to do. If so, it does the work. Then it goes back to sleep until it is time for the next check.

This daemon is needed because it is possible in Linux to schedule activities minutes, hours, days, or even months in the future. For example, suppose a user has a dentist appointment at 3 o’clock next Tuesday. He can make an entry in the cron daemon’s database telling the daemon to beep at him at, say, 2:30. When the appointed day and time arrives, the cron daemon sees that it has work to do, and starts up the beeping program as a new process.

The cron daemon is also used to start up periodic activities, such as making daily disk backups at 4 A.M., or reminding forgetful users every year on October 31 to stock up on trick-or-treat goodies for Halloween. Other daemons handle incoming and outgoing electronic mail, manage the line printer queue, check if there are enough free pages in memory, and so forth. Daemons are straightforward to implement in Linux because each one is a separate process, independent of all other processes.

Processes are created in Linux in an especially simple manner. The fork system call creates an exact copy of the original process. The forking process is called the **parent process**. The new process is called the **child process**. The parent and child each have their own, private memory images. If the parent subsequently changes any of its variables, the changes are not visible to the child, and vice versa.

Open files are shared between parent and child. That is, if a certain file was open in the parent before the fork, it will continue to be open in both the parent and the child afterward. Changes made to the file by either one will be visible to the other. This behavior is only reasonable, because these changes are also visible to any unrelated process that opens the file as well.

The fact that the memory images, variables, registers, and everything else are identical in the parent and child leads to a small difficulty: How do the processes know which one should run the parent code and which one should run the child code? The secret is that the fork system call returns a 0 to the child and a nonzero value, the child’s **PID (Process Identifier)** to the parent. Both processes normally check the return value, and act accordingly, as shown in Fig. 10-4.

Processes are named by their PIDs. When a process is created, the parent is
SEC. 10.3 PROCESSES IN LINUX

Figure 10-4. Process creation in Linux.

given the child’s PID, as mentioned above. If the child wants to know its own
PID, there is a system call, getpid, that provides it. PIDs are used in a variety of
ways. For example, when a child terminates, the parent is given the PID of the
child that just finished. This can be important because a parent may have many
children. Since children may also have children, an original process can build up
an entire tree of children, grandchildren, and further descendants.

Processes in Linux can communicate with each other using a form of message
passing. It is possible to create a channel between two processes into which one
process can write a stream of bytes for the other to read. These channels are called
pipes. Synchronization is possible because when a process tries to read from an
empty pipe it is blocked until data are available.

Shell pipelines are implemented with pipes. When the shell sees a line like

\[ \text{sort } < \text{f} | \text{head} \]

it creates two processes, sort and head, and sets up a pipe between them in such a
way that sort’s standard output is connected to head’s standard input. In this way,
all the data that sort writes go directly to head, instead of going to a file. If the
pipe fills up, the system stops running sort until head has removed some data from
the pipe.

Processes can also communicate in another way: software interrupts. A pro-
cess can send what is called a signal to another process. Processes can tell the
system what they want to happen when a signal arrives. The choices are to ignore
it, to catch it, or to let the signal kill the process (the default for most signals). If a
process elects to catch signals sent to it, it must specify a signal handling pro-
cedure. When a signal arrives, control will abruptly switch to the handler. When
the handler is finished and returns, control goes back to where it came from,
analogous to hardware I/O interrupts. A process can only send signals to
members of its process group, which consists of its parent (and further ances-
tors), siblings, and children (and further descendants). A process may also send a
signal to all members of its process group with a single system call.

Signals are also used for other purposes. For example, if a process is doing
floating-point arithmetic, and inadvertently divides by 0, it gets a SIGFPE
(floating-point exception) signal. The signals that are required by POSIX are
Many Linux systems have additional signals as well, but programs using them may not be portable to other versions of Linux and UNIX in general.

<table>
<thead>
<tr>
<th>Signal</th>
<th>Cause</th>
</tr>
</thead>
<tbody>
<tr>
<td>SIGABRT</td>
<td>Sent to abort a process and force a core dump</td>
</tr>
<tr>
<td>SIGALRM</td>
<td>The alarm clock has gone off</td>
</tr>
<tr>
<td>SIGFPE</td>
<td>A floating-point error has occurred (e.g., division by 0)</td>
</tr>
<tr>
<td>SIGHUP</td>
<td>The phone line the process was using has been hung up</td>
</tr>
<tr>
<td>SIGILL</td>
<td>The user has hit the DEL key to interrupt the process</td>
</tr>
<tr>
<td>SIGQUIT</td>
<td>The user has hit the key requesting a core dump</td>
</tr>
<tr>
<td>SIGKILL</td>
<td>Sent to kill a process (cannot be caught or ignored)</td>
</tr>
<tr>
<td>SIGPIPE</td>
<td>The process has written to a pipe which has no readers</td>
</tr>
<tr>
<td>SIGSEGV</td>
<td>The process has referenced an invalid memory address</td>
</tr>
<tr>
<td>SIGTERM</td>
<td>Used to request that a process terminate gracefully</td>
</tr>
<tr>
<td>SIGUSR1</td>
<td>Available for application-defined purposes</td>
</tr>
<tr>
<td>SIGUSR2</td>
<td>Available for application-defined purposes</td>
</tr>
</tbody>
</table>

Figure 10-5. The signals required by POSIX.

10.3.2 Process Management System Calls in Linux

Let us now look at the Linux system calls dealing with process management. The main ones are listed in Fig. 10-6. Fork is a good place to start the discussion. The Fork system call, supported also by other traditional UNIX systems, is the main way to create a new process in Linux systems (We will discuss another alternative in the following subsection). It creates an exact duplicate of the original process, including all the file descriptors, registers and everything else. After the fork, the original process and the copy (the parent and child) go their separate ways. All the variables have identical values at the time of the fork, but since the entire parent address space is copied to create the child, subsequent changes in one of them do not affect the other one. The fork call returns a value, which is zero in the child, and equal to the child’s PID in the parent. Using the returned PID, the two processes can see which is the parent and which is the child.

In most cases, after a fork, the child will need to execute different code from the parent. Consider the case of the shell. It reads a command from the terminal, forks off a child process, waits for the child to execute the command, and then reads the next command when the child terminates. To wait for the child to finish, the parent executes a waitpid system call, which just waits until the child terminates (any child if more than one exists). Waitpid has three parameters. The
<table>
<thead>
<tr>
<th>System call</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>pid = fork()</code></td>
<td>Create a child process identical to the parent</td>
</tr>
<tr>
<td><code>pid = waitpid(pid, &amp;statloc, opts)</code></td>
<td>Wait for a child to terminate</td>
</tr>
<tr>
<td><code>s = execve(name, argv, envp)</code></td>
<td>Replace a process’ core image</td>
</tr>
<tr>
<td><code>exit(status)</code></td>
<td>Terminate process execution and return status</td>
</tr>
<tr>
<td><code>s = sigaction(sig, &amp;act, &amp;oldact)</code></td>
<td>Define action to take on signals</td>
</tr>
<tr>
<td><code>s = sigreturn(&amp;context)</code></td>
<td>Return from a signal</td>
</tr>
<tr>
<td><code>s = sigprocmask(how, &amp;set, &amp;old)</code></td>
<td>Examine or change the signal mask</td>
</tr>
<tr>
<td><code>s = sigpending(set)</code></td>
<td>Get the set of blocked signals</td>
</tr>
<tr>
<td><code>s = sigsuspend(sigmask)</code></td>
<td>Replace the signal mask and suspend the process</td>
</tr>
<tr>
<td><code>s = kill(pid, sig)</code></td>
<td>Send a signal to a process</td>
</tr>
<tr>
<td><code>residual = alarm(seconds)</code></td>
<td>Set the alarm clock</td>
</tr>
<tr>
<td><code>s = pause()</code></td>
<td>Suspend the caller until the next signal</td>
</tr>
</tbody>
</table>

Figure 10-6. Some system calls relating to processes. The return code `s` is −1 if an error has occurred, `pid` is a process ID, and `residual` is the remaining time in the previous alarm. The parameters are what the name suggests.

First one allows the caller to wait for a specific child. If it is −1, any old child (i.e., the first child to terminate) will do. The second parameter is the address of a variable that will be set to the child’s exit status (normal or abnormal termination and exit value). The third one determines whether the caller blocks or returns if no child is already terminated.

In the case of the shell, the child process must execute the command typed by the user. It does this by using the `exec` system call, which causes its entire core image to be replaced by the file named in its first parameter. A highly simplified shell illustrating the use of `fork`, `waitpid`, and `exec` is shown in Fig. 10-7.

In the most general case, `exec` has three parameters: the name of the file to be executed, a pointer to the argument array, and a pointer to the environment array. These will be described shortly. Various library procedures, including `execl`, `execv`, `execl`, and `execve`, are provided to allow the parameters to be omitted or specified in various ways. All of these procedures invoke the same underlying system call. Although the system call is `exec`, there is no library procedure with this name; one of the others must be used.

Let us consider the case of a command typed to the shell such as

```
cp file1 file2
```

used to copy `file1` to `file2`. After the shell has forked, the child locates and executes the file `cp` and passes it information about the files to be copied.

The main program of `cp` (and many other programs) contains the function declaration
while (TRUE) {
    type_prompt( ); /* display prompt on the screen */
    read_command(command, params); /* read input line from keyboard */
    pid = fork(); /* fork off a child process */
    if (pid < 0) {
        printf("Unable to fork0); /* error condition */
        continue; /* repeat the loop */
    }
    if (pid != 0) {
        waitpid (−1, &status, 0); /* parent waits for child */
    } else {
        execve(command, params, 0); /* child does the work */
    }
}

Figure 10-7. A highly simplified shell.

main(argc, argv, envp)

where argc is a count of the number of items on the command line, including the program name. For the example above, argc is 3.

The second parameter, argv, is a pointer to an array. Element i of that array is a pointer to the i-th string on the command line. In our example, argv[0] would point to the string “cp”. Similarly, argv[1] would point to the 5-character string “file1” and argv[2] would point to the 5-character string “file2”.

The third parameter of main, envp, is a pointer to the environment, an array of strings containing assignments of the form name = value used to pass information such as the terminal type and home directory name to a program. In Fig. 10-7, no environment is passed to the child, so the third parameter of execve is a zero in this case.

If exec seems complicated, do not despair; it is the most complex system call. All the rest are much simpler. As an example of a simple one, consider exit, which processes should use when they are finished executing. It has one parameter, the exit status (0 to 255), which is returned to the parent in the variable status of the waitpid system call. The low-order byte of status contains the termination status, with 0 being normal termination and the other values being various error conditions. The high-order byte contains the child’s exit status (0 to 255), as specified in the child’s call to exit. For example, if a parent process executes the statement

n = waitpid(−1, &status, 0);

it will be suspended until some child process terminates. If the child exits with, say, 4 as the parameter to exit, the parent will be awakened with n set to the child’s PID and status set to 0x0400 (0x as a prefix means hexadecimal in C).
The low-order byte of status relates to signals; the next one is the value the child returned in its call to exit.

If a process exits and its parent has not yet waited for it, the process enters a kind of suspended animation called the zombie state. When the parent finally waits for it, the process terminates.

Several system calls relate to signals, which are used in a variety of ways. For example, if a user accidentally tells a text editor to display the entire contents of a very long file, and then realizes the error, some way is needed to interrupt the editor. The usual choice is for the user to hit some special key (e.g., DEL or CTRL-C), which sends a signal to the editor. The editor catches the signal and stops the print-out.

To announce its willingness to catch this (or any other) signal, the process can use the sigaction system call. The first parameter is the signal to be caught (see Fig. 10-5). The second is a pointer to a structure giving a pointer to the signal handling procedure, as well as some other bits and flags. The third one points to a structure where the system returns information about signal handling currently in effect, in case it must be restored later.

The signal handler may run for as long as it wants to. In practice, though, signal handlers are usually fairly short. When the signal handling procedure is done, it returns to the point from which it was interrupted.

The sigaction system call can also be used to cause a signal to be ignored, or to restore the default action, which is killing the process.

Hitting the DEL key is not the only way to send a signal. The kill system call allows a process to signal another related process. The choice of the name “kill” for this system call is not an especially good one, since most processes send signals to other ones with the intention that they be caught.

For many real-time applications, a process needs to be interrupted after a specific time interval to do something, such as to retransmit a potentially lost packet over an unreliable communication line. To handle this situation, the alarm system call has been provided. The parameter specifies an interval, in seconds, after which a SIGALRM signal is sent to the process. A process may have only one alarm outstanding at any instant. If an alarm call is made with a parameter of 10 seconds, and then 3 seconds later another alarm call is made with a parameter of 20 seconds, only one signal will be generated, 20 seconds after the second call. The first signal is canceled by the second call to alarm. If the parameter to alarm is zero, any pending alarm signal is canceled. If an alarm signal is not caught, the default action is taken and the signaled process is killed. Technically, alarm signals may be ignored, but that is a pointless thing to do.

It sometimes occurs that a process has nothing to do until a signal arrives. For example, consider a computer-aided instruction program that is testing reading speed and comprehension. It displays some text on the screen and then calls alarm to signal it after 30 seconds. While the student is reading the text, the program has nothing to do. It could sit in a tight loop doing nothing, but that would
waste CPU time that a background process or other user might need. A better solution is to use the `pause` system call, which tells Linux to suspend the process until the next signal arrives.

### 10.3.3 Implementation of Processes and Threads in Linux

A process in Linux is like an iceberg: what you see is the part above the water, but there is also an important part underneath. Every process has a user part that runs the user program. However, when one of its threads makes a system call, it traps to kernel mode and begins running in kernel context, with a different memory map and full access to all machine resources. It is still the same thread, but now with more power and also its own kernel mode stack and kernel mode program counter. These are important because a system call can block part way through, for example, waiting for a disk operation to complete. The program counter and registers are then saved so the thread can be restarted in kernel mode later.

The Linux kernel internally represents processes as tasks, via the structure `task_struct`. Unlike other OS approaches, which make a distinction between a process, lightweight process and thread), Linux uses the task structure to represent any execution context. Therefore, a single-threaded process will be represented with one task structure, a multi-threaded process will have one task structure for each of the user-level threads. Finally, the kernel itself is multi-threaded, and has kernel level threads which are not associated with any user process and are executing kernel code. We will return to the treatment of multi-threaded processes (and threads in general) later in this section.

For each process, a process descriptor of type `task_struct` is resident in memory at all times. It contains vital information needed for the kernel’s management of all processes, including scheduling parameters, lists of open file descriptors, etc. The process descriptor along with memory for the kernel-mode stack for the process are created upon process creation.

For compatibility with other UNIX systems, Linux identifies processes via the `Process Identifier (PID)`. The kernel organizes all processes in a doubly linked list of task structures. In addition to accessing process descriptors by traversing the linked lists, the PID can be mapped to the address of the task structure, and the process information can be accessed immediately.

The task structure contains a variety of fields. Some of these fields contain pointers to other data structures or segments, such as those containing information about open files. Some of these segments are related to the user-level structure of the process which is not of interest when the user process in not runnable. Therefore, these may be swapped or paged out, in order not to waste memory on information that is not needed. For example, although it is possible for a process to be sent a signal while it is swapped out, it is not possible for it to read a file. For this reason, information about signals must be in memory all the time, even when the
process is not present in memory. On the other hand, information about file descriptors can be kept in the user structure and brought in only when the process is in memory and runnable.

The information in the process descriptor falls into the following broad categories:

1. **Scheduling parameters.** Process priority, amount of CPU time consumed recently, amount of time spent sleeping recently. Together, these are used to determine which process to run next.

2. **Memory image.** Pointers to the text, data, and stack segments, or page tables. If the text segment is shared, the text pointer points to the shared text table. When the process is not in memory, information about how to find its parts on disk is here too.

3. **Signals.** Masks showing which signals are being ignored, which are being caught, which are being temporarily blocked, and which are in the process of being delivered.

4. **Machine registers.** When a trap to the kernel occurs, the machine registers (including the floating-point ones, if used) are saved here.

5. **System call state.** Information about the current system call, including the parameters, and results.

6. **File descriptor table.** When a system call involving a file descriptor is invoked, the file descriptor is used as an index into this table to locate the in-core data structure (i-node) corresponding to this file.

7. **Accounting.** Pointer to a table that keeps track of the user and system CPU time used by the process. Some systems also maintain limits here on the amount of CPU time a process may use, the maximum size of its stack, the number of page frames it may consume, and other items.

8. **Kernel stack.** A fixed stack for use by the kernel part of the process.

9. **Miscellaneous.** Current process state, event being waited for, if any, time until alarm clock goes off, PID, PID of the parent process, and user and group identification.

Keeping this information in mind, it is now easy to explain how processes are created in Linux. The mechanism for creating a new process is actually fairly straightforward. A new process descriptor and user area are created for the child process and filled in largely from the parent. The child is given a PID, its memory map is set up, and it is given shared access to its parent’s files. Then its registers are set up and it is ready to run.
When a fork system call is executed, the calling process traps to the kernel and creates a task structure and few other accompanying data structures, such as the kernel mode stack and a thread_info structure. This structure is allocated at a fixed offset from the process’ end-of-stack, and contains few process parameters, along with the address of the process descriptor. By storing the process descriptor’s address at a fixed location, Linux needs only few efficient operations to locate the task structure for a running process.

The majority of the process descriptor contents are filled out based on the parent’s descriptor values. Linux then looks for an available PID, and updates the PID hash table entry to point to the new task structure. In case of collisions in the hash table, process descriptors may be chained. It also sets the fields in the task_struct to point to the corresponding previous/next process on the task array.

In principle, it should now allocate memory for the child’s data and stack segments, and to make exact copies of the parents’ segments, since the semantics of fork say that no memory is shared between parent and child. The text segment may either be copied or shared since it is read only. At this point, the child is ready to run.

However, copying memory is expensive, so all modern Linux systems cheat. They give the child its own page tables, but have them point to the parent’s pages, only marked read only. Whenever the child tries to write on a page, it gets a protection fault. The kernel sees this and then allocates a new copy of the page to the child and marks it read/write. In this way, only pages that are actually written have to be copied. This mechanism is called copy on write. It has the additional benefit of not requiring two copies of the program in memory, thus saving RAM.

After the child process starts running, the code running there (a copy of the shell) does an exec system call giving the command name as a parameter. The kernel now finds and verifies the executable file, copies the arguments and environment strings to the kernel, and releases the old address space and its page tables.

Now the new address space must be created and filled in. If the system supports mapped files, as Linux and other UNIX-based systems do, the new page tables are set up to indicate that no pages are in memory, except perhaps one stack page, but that the address space is backed by the executable file on disk. When the new process starts running, it will immediately get a page fault, which will cause the first page of code to be paged in from the executable file. In this way, nothing has to be loaded in advance, so programs can start quickly and fault in just those pages they need and no more. (This strategy is demand paging in its purest form, as discussed in Chap. 3.) Finally, the arguments and environment strings are copied to the new stack, the signals are reset, and the registers are initialized to all zeros. At this point, the new command can start running.

Fig. 10-8 illustrates the steps described above through the following example: A user types a command, ls on the terminal, the shell creates a new process by forking off a clone of itself. The new shell then calls exec to overlay its memory
with the contents of the executable file *ls*.

![Diagram](image)

**Figure 10-8.** The steps in executing the command *ls* typed to the shell.

### Threads in Linux

We discussed threads in a general way in Chap. 2. Here we will focus on kernel threads in Linux, particularly focusing on the differences in the Linux thread model and other UNIX systems. In order to better understand the unique capabilities provided by the Linux model, we start with a discussion of some of the challenging decisions present in multithreaded systems.

The main issue in introducing threads is maintaining the correct traditional UNIX semantics. First consider fork. Suppose that a process with multiple (kernel) threads does a fork system call. Should all the other threads be created in the new process? For the moment, let us answer that question with yes. Suppose that one of the other threads was blocked reading from the keyboard. Should the corresponding thread in the new process also be blocked reading from the keyboard? If so, which one gets the next line typed? If not, what should that thread be doing in the new process? The same problem holds for many other things threads can do. In a single-threaded process, the problem does not arise because the one and only thread cannot be blocked when calling fork. Now consider the case that the other threads are not created in the child process. Suppose that one of the not-created threads holds a mutex that the one-and-only thread in the new process tries to acquire after doing the fork. The mutex will never be released and the
one thread will hang forever. Numerous other problems exist too. There is no simple solution.

File I/O is another problem area. Suppose that one thread is blocked reading from a file and another thread closes the file or does an lseek to change the current file pointer. What happens next? Who knows?

Signal handling is another thorny issue. Should signals be directed at a specific thread or at the process in general? A SIGFPE (floating-point exception) should probably be caught by the thread that caused it. What if it does not catch it? Should just that thread be killed, or all threads? Now consider the SIGINT signal, generated by the user at the keyboard. Which thread should catch that? Should all threads share a common set of signal masks? All solutions to these and other problems usually cause something to break somewhere. Getting the semantics of threads right (not to mention the code) is a nontrivial business.

Linux supports kernel threads in an interesting way that is worth looking at. The implementation is based on ideas from 4.4BSD, but kernel threads were not enabled in that distribution because Berkeley ran out of money before the C library could be rewritten to solve the problems discussed above.

Historically, processes were resource containers and threads were the units of execution. A process contained one or more threads that shared the address space, open files, signal handlers, alarms, and everything else. Everything was clear and simple as described above.

In 2000, Linux introduced a powerful new system call, clone, that blurred the distinction between processes and threads and possibly even inverted the primacy of the two concepts. Clone is not present in any other version of UNIX. Classically, when a new thread was created, the original thread(s) and the new one shared everything but their registers. In particular, file descriptors for open files, signal handlers, alarms, and other global properties were per process, not per thread. What clone did was make it possible for each of these aspects and others to be process specific or thread specific. It is called as follows:

\[ \text{pid} = \text{clone} (\text{function, stack\_ptr, sharing\_flags, arg}); \]

The call creates a new thread, either in the current process or in a new process, depending on sharing\_flags. If the new thread is in the current process, it shares the address space with existing threads and every subsequent write to any byte in the address space by any thread is immediately visible to all the other threads in the process. On the other hand, if the address space is not shared, then the new thread gets an exact copy of the address space, but subsequent writes by the new thread are not visible to the old ones. These semantics are the same as POSIX fork.

In both cases, the new thread begins executing at function, which is called with arg as its only parameter. Also in both cases, the new thread gets its own private stack, with the stack pointer initialized to stack\_ptr.

The sharing\_flags parameter is a bitmap that allows a much finer grain of
sharing than traditional UNIX systems. Each of the bits can be set independently of the other ones, and each of them determines whether the new thread copies some data structure of shares it with the calling thread. Fig. 10-9 shows some of the items that can be be shared or copied according to bits in `sharing_flags`.

<table>
<thead>
<tr>
<th>Flag</th>
<th>Meaning when set</th>
<th>Meaning when cleared</th>
</tr>
</thead>
<tbody>
<tr>
<td>CLONE_VM</td>
<td>Create a new thread</td>
<td>Create a new process</td>
</tr>
<tr>
<td>CLONE_FS</td>
<td>Share umask, root, and working dirs</td>
<td>Do not share them</td>
</tr>
<tr>
<td>CLONE_FILES</td>
<td>Share the file descriptors</td>
<td>Copy the file descriptors</td>
</tr>
<tr>
<td>CLONE_SIGHAND</td>
<td>Share the signal handler table</td>
<td>Copy the table</td>
</tr>
<tr>
<td>CLONE_PID</td>
<td>New thread gets old PID</td>
<td>New thread gets own PID</td>
</tr>
<tr>
<td>CLONE_PARENT</td>
<td>New thread has same parent as caller</td>
<td>New thread’s parent is caller</td>
</tr>
</tbody>
</table>

Figure 10-9. Bits in the `sharing_flags` bitmap.

The `CLONE_VM` bit determines whether the virtual memory (i.e., address space) is shared with the old threads or copied. If it is set, the new thread just moves in with the existing ones, so the clone call effectively creates a new thread in an existing process. If the bit is cleared, the new thread gets its own address space. Having its own address space means that the effect of its `STORE` instructions are not visible to the existing threads. This behavior is similar to `fork`, except as noted below. Creating a new address space is effectively the definition of a new process.

The `CLONE_FS` bit controls sharing of the root and working directories and of the umask flag. Even if the new thread has its own address space, if this bit is set, the old and new threads share working directories. This means that a call to `chdir` by one thread changes the working directory of the other thread, even though the other thread may have its own address space. In UNIX, a call to `chdir` by a thread always changes the working directory for other threads in its process, but never for threads in another process. Thus this bit enables a kind of sharing not possible in traditional UNIX versions.

The `CLONE_FILES` bit is analogous to the `CLONE_FS` bit. If set, the new thread shares its file descriptors with the old ones, so calls to `lseek` by one thread are visible to the other ones, again as normally holds for threads within the same process but not for threads in different processes. Similarly, `CLONE_SIGHAND` enables or disables the sharing of the signal handler table between the old and new threads. If the table is shared, even among threads in different address spaces, then changing a handler in one thread affects the handlers in the others. Finally, `CLONE_PID` controls whether the new thread gets its own PID or shares its parent’s PID. This feature is needed during system booting. User processes are not permitted to enable it.

Finally, every process has a parent. The `CLONE_PARENT` bit controls who
the parent of the new thread is. It can either be the same as the calling thread (in which case the new thread is a sibling of the caller) or it can be the calling thread itself, in which case the new thread is a child of the caller. There are a few other bits that control other items, but they are less important.

This fine-grained sharing is possible because Linux maintains separate data structures for the various items listed in Sec. 10.3.3 (scheduling parameters, memory image, and so on). The task structure just points to these data structures, so it is easy to make a new task structure for each cloned thread and have it either point to the old thread’s scheduling, memory, and other data structures or to copies of them. The fact that such fine-grained sharing is possible does not mean that it is useful, however, especially since traditional UNIX versions do not offer this functionality. A Linux program that takes advantage of it is then no longer portable to UNIX.

The Linux thread model raises another difficulty. UNIX systems associate a single PID with a process, independent of whether it is single- or multi-threaded. In order to be compatible with other UNIX systems, Linux distinguishes between a process identifier (PID) and a task identifier (TID). Both fields are stored in the task structure. When clone is used to create a new process which shares nothing with its creator, PID is set to a new value, otherwise, the task receives a new TID, but inherits the PID. In this manner all threads in a process will receive the same PID as the first thread in the process.

10.3.4 Scheduling in Linux

We will now look at the Linux scheduling algorithm. To start with, Linux threads are kernel threads, so scheduling is based on threads, not processes.

Linux distinguishes three classes of threads for scheduling purposes:

1. Real-time FIFO.
2. Real-time round robin.
3. Timesharing.

Real-time FIFO threads are the highest priority and are not preemptable except by a newly-readied real-time FIFO thread with higher priority. Real-time round-robin threads are the same as real-time FIFO threads except that they have time quanta associated with them, and are preemptable by the clock. If multiple real-time round-robin threads are ready, each one is run for its quantum, after which it goes to the end of the list of real-time round-robin threads. Neither of these classes is actually real time in any sense. Deadlines cannot be specified and guarantees are not given. These classes are simply higher priority than threads in the standard timesharing class. The reason Linux calls them real time is that Linux is conformant to the P1003.4 standard (“real-time” extensions to UNIX) which uses those names. The real time threads are internally represented with priority levels from 0
35

to 99, 0 being the highest and 99 the lowest real-time priority level.

The conventional, non-real-time threads are scheduled according to the following algorithm. Internally, the non-real-time threads are associated with priority levels from 100 to 139, i.e., Linux internally distinguishes among 140 priority levels (for real-time and non-real-time tasks). Like for the real-time round robin threads, Linux associates time quantum values for each of the non-real-time priority levels. The quantum is a number of clock ticks the thread may continue to run for. In the current Linux version, the clock runs at 1000Hz and each tick is 1ms, which is called a jiffy.

Like most UNIX systems, Linux associates a nice value with each thread. The default is 0 but this can be changed using the nice(value) system call, where value ranges from -20 to +19. This value determines the static priority of each thread. A user computing π to a billion places in the background might put this call in his program to be nice to the other users. Only the system administrator may ask for better than normal service (meaning values from -20 to -1). Deducing the reason for this rule is left as an exercise for the reader.

A key data structure used by the Linux scheduler is a runqueue. A runqueue is associated with each CPU in the system, and among other information, it maintains two arrays, active and expired. As shown in Fig. 10-10, each of these fields is a pointer to an array of 140 list heads, each corresponding to a different priority. The list head points to a doubly-linked list of processes at a given priority. The basic operation of the scheduler can be described as follows.

The scheduler selects a task from the highest priority active array. If that task’s timeslice (quantum) expires, it is moved to an expired list (potentially at a different priority level). If the task blocks, for instance to wait on an I/O event, before its timeslice expires, once the event occurs and its execution can resume, it is placed back on the original active array, and its timeslice is decremented to reflect the CPU time it already consumed. Once its timeslice is fully exhausted, it too will be placed on an expired array. When there are no more tasks in any of the active arrays, the scheduler simply swaps the pointers, so the expired arrays now become active, and vice versa. This method ensures that low priority tasks will not starve (except when real-time FIFO threads completely hog the CPU, which is unlikely to happen).

Different priority levels are assigned different timeslice values. Linux assigns higher quanta to higher priority processes. For instance, tasks running at priority level 100 will receive time quanta of 800 msec, whereas tasks at priority level of 139 will receive 5 msec.

The idea behind this scheme is to get processes out of the kernel fast. If a process is trying to read a disk file, making it wait a second between read calls will slow it down enormously. It is far better to let it run immediately after each request is completed, so it can make the next one quickly. Similarly, if a process was blocked waiting for keyboard input, it is clearly an interactive process, and as such should be given a high priority as soon as it is ready in order to ensure that
interactive processes get good service. In this light, CPU-bound processes basically get any service that is left over when all the I/O bound and interactive processes are blocked.

Since Linux (or any other OS) does not know apriori whether a task is I/O- or CPU-bound, it relies on continuously maintaining interactivity heuristics. In this manner, Linux distinguishes between static and dynamic priority. The threads’ dynamic priority is continuously recalculated, so as to (1) reward interactive threads, and (2) punish CPU-hogging threads. The maximum priority bonus is \(-5\), since lower priority values correspond to higher priority received by the scheduler. The maximum priority penalty is \(+5\).

More specifically, the scheduler maintains a \texttt{sleep\_avg} variable associated with each task. Whenever a task is awaken, this variable is incremented, whenever a task is preempted or its quantum expires, this variable is decremented by the corresponding value. This value is used to dynamically map the task’s bonus to values from \(-5\) to \(+5\). The Linux scheduler recalculates the new priority level as a thread is moved from the active to the expired list.

The scheduling algorithm described in this section refers to the 2.6 kernel, and was first introduced in the unstable 2.5 kernel. Earlier algorithms exhibited poor
performance in multiprocessor settings and did not scale well with an increased number of tasks. Since the description presented in the above paragraphs indicates that a scheduling decision can be made through access to the appropriate active list, it can be done in constant $O(1)$ time, independent of the number of processes in the system.

In addition, the scheduler includes features particularly useful for multiprocessor or multicore platforms. First, the runqueue structure is associated with each CPU in the multiprocession platform. The scheduler tries to maintain benefits from affinity scheduling, and to schedule tasks on the CPU on which they were previously executing. Second, a set of system calls is available to further specify or modify the affinity requirements of a select thread. Finally, the scheduler performs periodic load balancing across runqueues of different CPUs to ensure that the system load is well balanced, while still meeting certain performance or affinity requirements.

The scheduler considers only runnable tasks, which are placed on the appropriate runqueue. Tasks which are not runnable and are waiting on various I/O operations or other kernel events are placed on another data structure, waitqueue. A waitqueue is associated with each event that tasks may wait on. The head of the waitqueue includes a pointer to a linked list of tasks and a spinlock. The spinlock is necessary so as to ensure that the waitqueue can be concurrently manipulated through both the main kernel code and interrupt handlers or other asynchronous invocations.

In fact, the kernel code contains synchronization variables in numerous locations. Earlier Linux kernels had just one big kernel lock (BLK). This proved highly inefficient, particularly on multiprocessor platforms, since it prevented processes on different CPUs to execute kernel code concurrently. Hence, many new synchronization points were introduced at much finer granularity.

### 10.3.5 Booting Linux

Details vary from platform to platform, but in general the following steps represent the boot process. When the computer starts, the BIOS performs Power-On-Self-Test (POST) and initial device discovery and initialization, since the OS’ boot process may rely on access to disks, screens, keyboards, etc. Next, the first sector of the boot disk, the MBR (Master Boot Record) is read into a fixed memory location and executed. This sector contains a small (512-byte) program that loads a standalone program called boot from the boot device, usually an IDE or SCSI disk. The boot program first copies itself to a fixed high memory address to free up low memory for the operating system.

Once moved, boot reads the root directory of the boot device. To do this, it must understand the file system and directory format, which is the case with some bootloaders such as GRUB Bootloader. Other popular bootloaders, such as Intel’s LILO, do not rely on any specific filesystem. Instead, they need a
block map, and low-level addresses, which describe physical sectors, heads, and cylinders, to find the relevant sectors to be loaded.

Then it reads in the operating system kernel and jumps to it. At this point, boot has finished its job and the kernel is running.

The kernel start-up code is written in assembly language and is highly machine dependent. Typical work includes setting up the kernel stack, identifying the CPU type, calculating the amount of RAM present, disabling interrupts, enabling the MMU, and finally calling the C-language main procedure to start the main part of the operating system.

The C code also has considerable initialization to do, but this is more logical than physical. It starts out by allocating a message buffer to help debug boot problems. As initialization proceeds, messages are written here about what is happening, so they can be fished out after a boot failure by a special diagnostic program. Think of this as the operating system’s cockpit flight recorder (the black box investigators look for after a plane crash).

Next the kernel data structures are allocated. Most are fixed size, but a few, such as the page cache and certain page table structures, depend on the amount of RAM available.

At this point the system begins autoconfiguration. Using configuration files telling what kinds of I/O devices might be present, it begins probing the devices to see which ones actually are present. If a probed device responds to the probe, it is added to a table of attached devices. If it fails to respond, it is assumed to be absent and ignored henceforth. Unlike traditional UNIX versions, Linux can device drivers do not need to be statically linked and may be loaded dynamically (as can all versions of MS-DOS and Windows, incidentally).

The arguments for and against dynamically loading drivers are interesting and worth stating briefly. The main argument for dynamic loading is that a single binary can be shipped to customers with divergent configurations and have it automatically load the drivers it needs, possibly even over a network. The main argument against dynamic loading is security. If you are running a secure site, such as a bank’s database or a corporate Web server, you probably want to make it impossible for anyone to insert random code into the kernel. The system administrator may keep the operating system sources and object files on a secure machine, do all system builds there, and ship the kernel binary to other machines over a local area network. If drivers cannot be loaded dynamically, this scenario prevents machine operators and others who know the superuser password from injecting malicious or buggy code into the kernel. Furthermore, at large sites, the hardware configuration is known exactly at the time the system is compiled and linked. Changes are sufficiently rare that having to relink the system when a new hardware device is added is not an issue.

Once all the hardware has been configured, the next thing to do is to carefully handcraft process 0, set up its stack, and run it. Process 0 continues initialization, doing things like programming the real-time clock, mounting the root file system,
and creating init (process 1) and the page daemon (process 2).

Init checks its flags to see if it is supposed to come up single user or multiuser. In the former case, it forks off a process that execs the shell and waits for this process to exit. In the latter case, it forks off a process that executes the system initialization shell script, /etc/rc, which can do file system consistency checks, mount additional file systems, start daemon processes, and so on. Then it reads /etc/ttys, which lists the terminals and some of their properties. For each enabled terminal, it forks off a copy of itself, which does some housekeeping and then execs a program called getty.

Getty sets the line speed and other properties for each line (some of which may be modems, for example), and then types

login:

on the terminal’s screen and tries to read the user’s name from the keyboard. When someone sits down at the terminal and provides a login name, getty terminates by executing /bin/login, the login program. Login then asks for a password, encrypts it, and verifies it against the encrypted password stored in the password file, /etc/passwd. If it is correct, login replaces itself with the user’s shell, which then waits for the first command. If it is incorrect, login just asks for another user name. This mechanism is illustrated in Fig. 10-11 for a system with three terminals.

**Figure 10-11.** The sequence of processes used to boot some Linux systems.

In the figure, the getty process running for terminal 0 is still waiting for input. On terminal 1, a user has typed a login name, so getty has overwritten itself with
login, which is asking for the password. A successful login has already occurred on terminal 2, causing the shell to type the prompt (%). The user then typed

\texttt{cp f1 f2}

which has caused the shell to fork off a child process and have that process exec the \texttt{cp} program. The shell is blocked, waiting for the child to terminate, at which time the shell will type another prompt and read from the keyboard. If the user at terminal 2 had typed \texttt{cc} instead of \texttt{cp}, the main program of the C compiler would have been started, which in turn would have forked off more processes to run the various compiler passes.

10.4 MEMORY MANAGEMENT IN LINUX

The Linux memory model is straightforward, to make programs portable and to make it possible to implement Linux on machines with widely differing memory management units, ranging from essentially nothing (e.g., the original IBM PC) to sophisticated paging hardware. This is an area of the design that has barely changed in decades. It has worked well so it has not needed much revision. We will now examine the model and how it is implemented.

10.4.1 Fundamental Concepts

Every Linux process has an address space logically consisting of three segments: text, data, and stack. An example process’ address space is depicted in Fig. 10-12(a) as process \textit{A}. The \textbf{text segment} contains the machine instructions that form the program’s executable code. It is produced by the compiler and assembler by translating the C, C++, or other program into machine code. The text segment is normally read-only. Self modifying programs went out of style in about 1950 because they were too difficult to understand and debug. Thus the text segment neither grows nor shrinks nor changes in any other way.

The \textbf{data segment} contains storage for all the program’s variables, strings, arrays, and other data. It has two parts, the initialized data and the uninitialized data. For historical reasons, the latter is known as the BSS (historically called \textit{Block Started by Symbol}). The initialized part of the data segment contains variables and compiler constants that need an initial value when the program is started.

For example, in C it is possible to declare a character string and initialize it at the same time. When the program starts up, it expects that the string has its initial value. To implement this construction, the compiler assigns the string a location in the address space, and ensures that when the program is started up, this location contains the proper string. From the operating system’s point of view, initialized data are not all that different from program text—both contain bit patterns...
produced by the compiler that must be loaded into memory when the program starts.

The existence of uninitialized data is actually just an optimization. When a global variable is not explicitly initialized, the semantics of the C language say that its initial value is 0. In practice, most global variables are not initialized explicitly, and are thus 0. This could be implemented by simply having a section of the executable binary file exactly equal to the number of bytes of data, and initializing all of them, including the ones that have defaulted to 0.

However, to save space in the executable file, this is not done. Instead, the file contains all the explicitly initialized variables follows the program text. The uninitialized variables are all gathered together after the initialized ones, so all the compiler has to do is put a word in the header telling how many bytes to allocate.

To make this point more explicit, consider Fig. 10-12(a) again. Here the program text is 8 KB and the initialized data is also 8 KB. The uninitialized data (BSS) is 4 KB. The executable file is only 16 KB (text + initialized data), plus a short header that tells the system to allocate another 4 KB after the initialized data and zero it before starting the program. This trick avoids storing 4 KB of zeros in the executable file.

In order to avoid allocating a physical page frame full of zeros, during initialization Linux allocates a static zero page, a write-protected page full of zeros. When a process is loaded, its uninitialized data region is set to point to the zero page. Whenever a process actually attempts to write in this area, the copy-on-write mechanism kicks in, and an actual page frame is allocated to the process.

Unlike the text segment, which cannot change, the data segment can change. Programs modify their variables all the time. Furthermore, many programs need
to allocate space dynamically, during execution. Linux handles this by permitting
the data segment to grow and shrink as memory is allocated and deallocated. A
system call, brk, is available to allow a program to set the size of its data segment.
Thus to allocate more memory, a program can increase the size of its data seg-
ment. The C library procedure malloc, commonly used to allocate memory, makes
heavy use of this system call. The process address space descriptor contains infor-
mation on the range of dynamically allocated memory areas in the process, typi-
cally called heap.

The third segment is the stack segment. On most machines, it starts at or near
the top of the virtual address space and grows down toward 0. For instance, on
32bit x86 platforms, the stack starts at address 0xC0000000, which is the 3-GB
virtual address limit visible to the process in user mode. If the stack grows below
the bottom of the stack segment, a hardware fault normally occurs, and the operat-
ing system lowers the bottom of the stack segment by one page. Programs do not
explicitly manage the size of the stack segment.

When a program starts up, its stack is not empty. Instead, it contains all the
environment (shell) variables as well as the command line typed to the shell to
invoke it. In this way a program can discover its arguments. For example, when
the command

    cp src dest

is typed, the cp program is run with the string “cp src dest” on the stack, so it can
find out the names of the source and destination files. The string is represented as
an array of pointers to the symbols in the string, to make parsing easier.

When two users are running the same program, such as the editor, it would be
possible, but inefficient, to keep two copies of the editor’s program text in
memory at once. Instead, most Linux systems support shared text segments. In
Fig. 10-12(a) and Fig. 10-12(c) we see two processes, A and B, that have the same
text segment. In Fig. 10-12(b) we see a possible layout of physical memory, in
which both processes share the same piece of text. The mapping is done by the
virtual memory hardware.

Data and stack segments are never shared except after a fork, and then only
those pages that are not modified. If either one needs to grow and there is no
room adjacent to it to grow into, there is no problem since adjacent virtual pages
do not have to map onto adjacent physical pages.

On some computers, the hardware supports separate address spaces for
instructions and data. When this feature is available, Linux can use it. For exam-
ple, on a computer with 32-bit addresses, if this feature is available, there would
be $2^{32}$ bits of address space for instructions and an additional $2^{32}$ bits of address
space for the data and stack segments to share. A jump to 0 goes to address 0 of
text space, whereas a move from 0 uses address 0 in data space. This feature dou-
bles the address space available.

In addition of dynamically allocating more memory, processes in Linux can
access file data through memory-mapped files. This feature makes it possible to map a file onto a portion of a process’ address space so the file can be read and written as if it were a byte array in memory. Mapping a file in makes random access to it much easier than using I/O system calls such as `read` and `write`. Shared libraries are accessed by mapping them in using this mechanism. In Fig. 10-13 we see a file that is mapped into two processes at the same time, at different virtual addresses.

![Figure 10-13. Two processes can share a mapped file.](image)

An additional advantage of mapping a file in is that two or more processes can map in the same file at the same time. Writes to the file by any one of them are then instantly visible to the others. In fact, by mapping in a scratch file (which will be discarded after all the processes exit), this mechanism provides a high-bandwidth way for multiple processes to share memory. In the most extreme case, two or more processes could map in a file that covers the entire address space, giving a form of sharing that is partway between separate processes and threads. Here the address space is shared (like threads), but each process maintains its own open files and signals, for example, which is not like threads. In practice, making two address spaces exactly correspond is never done, however.

### 10.4.2 Memory Management System Calls in Linux

POSIX does not specify any system calls for memory management. This topic was considered too machine dependent for standardization. Instead, the problem was swept under the rug by saying that programs needing dynamic memory management can use the `malloc` library procedure (defined by the ANSI C...
How malloc is implemented is thus moved outside the scope of the POSIX standard. In some circles, this approach is known as passing the buck.

In practice, most Linux systems have system calls for managing memory. The most common ones are listed in Fig. 10-14. Brk specifies the size of the data segment by giving the address of the first byte beyond it. If the new value is greater than the old one, the data segment becomes larger; otherwise it shrinks.

<table>
<thead>
<tr>
<th>System call</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s = brk(addr)</td>
<td>Change data segment size</td>
</tr>
<tr>
<td>a = mmap(addr, len, prot, flags, fd, offset)</td>
<td>Map a file in</td>
</tr>
<tr>
<td>s = unmap(addr, len)</td>
<td>Unmap a file</td>
</tr>
</tbody>
</table>

Figure 10-14. Some system calls relating to memory management. The return code \( s \) is \(-1\) if an error has occurred; \( a \) and \( addr \) are memory addresses, \( len \) is a length, \( prot \) controls protection, \( flags \) are miscellaneous bits, \( fd \) is a file descriptor, and \( offset \) is a file offset.

The mmap and munmap system calls control memory-mapped files. The first parameter to mmap, \( addr \), determines the address at which the file (or portion thereof) is mapped. It must be a multiple of the page size. If this parameter is \( 0 \), the system determines the address itself and returns it in \( a \). The second parameter, \( len \), tells how many bytes to map. It, too, must be a multiple of the page size. The third parameter, \( prot \), determines the protection for the mapped file. It can be marked readable, writable, executable, or some combination of these. The fourth parameter, \( flags \), controls whether the file is private or sharable, and whether \( addr \) is a requirement or merely a hint. The fifth parameter, \( fd \), is the file descriptor for the file to be mapped. Only open files can be mapped, so to map a file in, it must first be opened. Finally, \( offset \) tells where in the file to begin the mapping. It is not necessary to start the mapping at byte \( 0 \); any page boundary will do.

The other call, unmap, removes a a mapped file. If only a portion of the file is unmapped, the rest remains mapped.

### 10.4.3 Implementation of Memory Management in Linux

Each Linux process on a 32-bit machine typically gets 3 GB of virtual address space for itself, with the remaining 1 GB reserved for its page tables and other kernel data. The kernel’s 1 GB is not visible when running in user mode, but becomes accessible when the process traps into the kernel. The kernel memory typically resides in low physical memory, however it is mapped in the top 1 GB of each process virtual address space, between addresses 0xC0000000 and 0xFFFFFFFF (3–4 GB). The address space is created when the process is created and is overwritten on an exec system call.

In order to allow multiple processes to share the underlying physical memory,
Linux monitors the use of the physical memory, allocates more memory as needed by user processes or kernel components, dynamically maps portions of the physical memory into the address space of different processes, and dynamically brings in and out of memory program executables, files and other state, necessary to utilize the platform resources efficiently and to ensure execution progress. The remainder of this chapter describes the implementation of various mechanisms in the Linux kernel which are responsible for these operations.

Physical Memory Management

Due to idiosyncratic hardware limitations on many systems, not all physical memory can be treated identically. Linux distinguishes between three physical memory zones:

1. **ZONE_DMA** - pages that can be used for DMA operations.
2. **ZONE_NORMAL** - normal, regularly-mapped pages.
3. **ZONE_HIGHMEM** - pages with high memory addresses, which are not permanently mapped.

The exact boundaries and layout of the memory zones is architecture dependent. On x86 hardware, certain devices can perform DMA operations only in the first 16 MB of address space, hence **ZONE_DMA** is in the range 0–16 MB. In addition, the hardware cannot directly map memory addresses above 896 MB, hence **ZONE_HIGHMEM** is anything above this mark. **ZONE_NORMAL** is anything in between. Therefore, on x86 platforms, the first 896 MB of the Linux address space are directly mapped, whereas the remaining 128 MB of the kernel address space are used to access high memory regions. The kernel maintains a *zone* structure for each of the three zones, and can perform memory allocations for the three zones separately.

Main memory in Linux consists of three parts. The first two parts, the kernel and memory map, are pinned in memory (i.e., never paged out). The rest of memory is divided into page frames, each of which can contain a text, data, or stack page, a page table page, or be on the free list.

The kernel maintains a map of the main memory which contains all information about the use of the physical memory in the system, such as its zones, free page frames, etc. The information, illustrated in Fig. 10-15, is organized as follows.

First of all, Linux maintains an array of **page descriptors**, of type *page* for each physical page frame in the system, called *mem_map*. Each page descriptor contains a pointer to the address space it belongs to, in case the page is not free, a pair of pointers which allow it to form doubly-linked lists with other descriptors, for instance to keep together all free page frames, and few other fields. In Fig. 10-15 the page descriptor for page 150 contains a mapping to the address...
CASE STUDY 1: Linux

### node_zones[3]
- node_mem_map
- node_id

### ZONE
- HIGHMEM
- NORMAL
- DMA

### Free Areas:
- free_area[0]
- free_area[1]
- ... free_area[10]

### Active List
- inactive_list
- name

### Mem_map: array of page descriptor

#### Physical Memory:
- 200 – 1 free page
- 150 – mapped
- 80 – free page
- 70 – free page

#### Figure 10-15. Linux main memory representation.

Space the page belongs to. Pages 70, 80 and 200 are free, and they are linked together. The size of the page descriptor is 32 bytes, therefore the entire mem_map can consume less than 1% of the physical memory (for a page frame of 4 KB).

Since the physical memory is divided into zones, for each zone Linux maintains a zone descriptor. The zone descriptor contains information about the memory utilization within each zone, such as number of active or inactive pages, low and high watermarks to be used by the page replacement algorithm described later in this chapter, as well as many other fields.

In addition, a zone descriptor contains an array of free areas. The \( i \)-th element in this array identifies the first page descriptor of the first block of \( 2^i \) free pages. Since there may be multiple blocks of \( 2^i \) free pages, Linux uses the pair of page descriptor pointers in each page element, to link these together. This information is used in the memory allocation operations supported in Linux. In Fig. 10-15 free_area[0], which identifies all free areas of main memory consisting of only one page frame (since \( 2^0 \) is one), points to page 70, the first one of the three free areas. The other free blocks of size one can be reached through the links in each
Finally, since Linux is portable to NUMA architectures (where different memory addresses have very different access times), in order to differentiate between physical memory on different nodes (and avoid allocating data structures across nodes), a node descriptor is used. Each node descriptor contains information about the memory usage and zones on that particular node. On UMA platforms, Linux describes all memory via one node descriptor. The first few bits within each page descriptor are used to identify the node and the zone that the page frame belongs to.

In order for the paging mechanism to be efficient on 32- and 64-bit architecture, Linux uses a four-level paging scheme. A three-level paging scheme, originally put into the system for the Alpha was expanded after Linux 2.6.10, and as of version 2.6.11 the four-level paging scheme is used. Each virtual address is broken up into five fields, as shown in Fig. 10-16. The directory fields are used as an index into the appropriate page directory, of which there is a private one for each process. The value found is a pointer to one of the next level directories, which are again indexed by a field from the virtual address. The selected entry in the middle page directory points to the final page table, which is indexed by the page field of the virtual address. The entry found here points to the page needed. On the Pentium, which uses two-level paging, each page upper and middle directory have only one entry, so the global directory entry effectively chooses the page table to use. Similarly, three-level paging can be used when needed, by setting the size of the upper page directory field to zero.

![Figure 10-16. Linux uses four-level page tables.](image)

Physical memory is used for various purposes. The kernel itself is fully
hardwired; no part of it is ever paged out. The rest of memory is available for
user pages, the paging cache, and other purposes. The page cache holds pages
containing file blocks that have recently been read or have been read in advance
in expectation of being used in the near future, or pages of file blocks which need
to be written to disk, such as those which have been created from user mode
processes which have been swapped out to disk. It is dynamic in size and com-
petes for the same pool of pages as the user processes. The paging cache is not
really a separate cache, but simply the set of user pages that are no longer needed
and are waiting around to be paged out. If a page in the paging cache is reused
before it is evicted from memory, it can be reclaimed quickly.

In addition, Linux supports dynamically loaded modules, generally device
drivers. These can be of arbitrary size and each one must be allocated a contigu-
ous piece of kernel memory. As a consequence of these requirements, Linux
manages physical memory in such a way that it can acquire an arbitrary-sized
piece of memory at will. The algorithm it uses is known as the buddy algorithm
and is described below.

**Memory Allocation Mechanisms**

Linux supports several mechanisms for memory allocation. The main
mechanism for allocating new page frames of physical memory is the **page allo-
cator**, which operates using the so called **buddy algorithm**.

The basic idea for managing a chunk of memory is as follows. Initially
memory consists of a single contiguous piece, 64 pages in the simple example of
Fig. 10-17(a). When a request for memory comes in, it is first rounded up to a
power of two, say 8 pages. The full memory chunk is then divided in half, as
shown in (b). Since each of these pieces is still too large, the lower piece is
divided in half again (c) and again (d). Now we have a chunk of the correct size,
so it is allocated to the caller, as shown shaded in (d).

![Figure 10-17](image-url)

Now suppose that a second request comes in for 8 pages. This can be satisfied
directly now (e). At this point a third request comes in for 4 pages. The smallest available chunk is split (f) and half of it is claimed (g). Next, the second of the 8-page chunks is released (h). Finally, the other 8-page chunk is released. Since the two adjacent 8-page chunks that were just freed are buddies, that is, originated from the same 16-page chunk, they are merged to get the 16-page chunk back (i).

Linux manages memory using the buddy algorithm, with the additional feature of having an array in which the first element is the head of a list of blocks of size 1 unit, the second element is the head of a list of blocks of size 2 units, the next element points to the 4-unit blocks, etc. In this way, any power-of-2 block can be found quickly.

This algorithm leads to considerable internal fragmentation because if you want a 65-page chunk, you have to ask for and get a 128-page chunk.

To alleviate this problem, Linux has a second memory allocation, the slab allocator, that takes chunks using the buddy algorithm but then carves slabs (smaller units) from them and manages the smaller units separately.

Since the kernel frequently creates and destroy objects of certain type (e.g., task_struct), it relies on so called object caches. These caches consist of pointers to one or more slab which can store a number of objects of the same type. Each of the slabs may be full, partially full, or empty.

For instance, when the kernel needs to allocate a new process descriptor, that is, a new task_struct it looks in the object cache for task structures, and first tries to find a partially full slab, and allocate a new task_struct object there. If no such slab is available, it looks through the list of empty slabs. Finally, if necessary, it will allocate a new slab, place the new task structure there, and link this slab with the task structure object cache. The kmalloc kernel service, which allocates physically contiguous memory regions in the kernel address space, is in fact built on top of the slab and object cache interface described here.

A third memory allocator, vmalloc, is also available and is used when the requested memory need only be contiguous in virtual space, but not in physical memory. In practice, this is true for most of the requested memory. One exception are devices, which live on the other side of the memory bus and the memory management unit, and therefore do not understand virtual addresses. However, the use of vmalloc results in some performance degradation, and is used primarily for allocating large amounts of contiguous virtual address space, such as for dynamically inserting kernel modules. All these memory allocators are derived from those in System V.

**Virtual Address Space Representation**

The virtual address space is divided into homogeneous, contiguous, page-aligned areas or regions. That is to say, each area consists of a run of consecutive pages with the same protection and paging properties. The text segment and mapped files are examples of areas (see Fig. 10-15). There can be holes in the
virtual address space between the areas. Any memory reference to a hole results in a fatal page fault. The page size is fixed, for example, 4 KB for the Pentium and 8 KB for the Alpha. Starting with the Pentium, which supports page frames of 4 MB, Linux can support jumbo page frames of 4 MB each. In addition, in a PAE (Physical Address Extension) mode, which is used on certain 32-bit architecture to increase the process address space beyond 4 GB, page sizes of 2 MB are supported.

Each area is described in the kernel by a `vm_area_struct` entry. All the `vm_area_structs` for a process are linked together in a list sorted on virtual address so all the pages can be found. When the list gets too long (more than 32 entries), a tree is created to speed up searching. The `vm_area_struct` entry lists the area’s properties. These include the protection mode (e.g., read only or read/write), whether it is pinned in memory (not pageable), and which direction it grows in (up for data segments, down for stacks).

The `vm_area_struct` also records whether the area is private to the process or shared with one or more other processes. After a fork, Linux makes a copy of the area list for the child process, but sets up the parent and child to point to the same page tables. The areas are marked as read/write, but the pages are marked as read only. If either process tries to write on a page, a protection fault occurs and the kernel sees that the area is logically writable but the page is not, so it gives the process a copy of the page and marks it read/write. This mechanism is how copy on write is implemented.

The `vm_area_struct` also records whether the area has backing storage on disk assigned, and if so, where. Text segments use the executable binary as backing storage and memory-mapped files use the disk file as backing storage. Other areas, such as the stack, do not have backing storage assigned until they have to be paged out.

A top-level memory descriptor, `mm_struct`, gathers information about all virtual memory areas belonging to an address space, information about the different segments - text, data, stack, about users sharing this address space, etc. All `vm_area_struct` elements of an address space can be accesses through its memory descriptor in two ways. First, they are organized in a linked lists, ordered by virtual memory addresses. This way is useful when all virtual memory areas need to be accessed, or when the kernel is searching to allocated a virtual memory region of a specific size. In addition, the `vm_area_struct` entries are organized in a binary “red-black” tree, a data structure optimized for fast lookups. This method is used when a specific virtual memory needs to be accessed. By enabling access to elements of the process address space via these two methods, Linux uses more state per process, but allows different kernel operations to use the access method which is more efficient for the task at hand.
10.4.4 Paging in Linux

Early UNIX systems relied on a *swapper* process to move entire processes between memory and disk, whenever not all active processes could fit in the physical memory. Linux, as well as other modern UNIX versions, no longer move entire processes. The main memory management unit is a *page* and almost all memory management components, operate on a page granularity. The swapping subsystem also operates on page granularity and is tightly coupled with the Page Frame Reclaiming Algorithm, described later in this section.

The basic idea behind paging in Linux is simple: a process need not be entirely in memory in order to run. All that is actually required is the user structure and the page tables. If these are swapped in, the process is deemed “in memory” and can be scheduled to run. The pages of the text, data, and stack segments are brought in dynamically, one at a time, as they are referenced. If the user structure and page table are not in memory, the process cannot be run until the swapper brings them in.

Paging is implemented partly by the kernel and partly by a new process called the *page daemon*. The page daemon is process 2 (process 0 is the idle process—traditionally called the swapper—and process 1 is *init*, as shown in Fig. 10-11). Like all daemons, the page daemon is started up periodically so it can look around to see if there is any work for it to do. If it discovers that the number of pages on the list of free memory pages is too low, it initiates action to free up more pages.

Linux is a demand-paged system with no prepaging and no working set concept (although there is a system call in which a user can give a hint that a certain page may be needed soon, in the hopes it will be there when needed). Text segments and mapped files are paged to their respective files on disk. Everything else is paged to either the paging partition (if present) or one of the fixed-length paging files, called the **swap area**. Paging files can be added and removed dynamically and each one has a priority. Paging to a separate partition, accessed as a raw device, is more efficient than paging to a file for several reasons. First, the mapping between file blocks and disk blocks is not needed (saves disk I/O reading indirect blocks). Second, the physical writes can be of any size, not just the file block size. Third, a page is always written contiguously to disk; with a paging file, it may or may not be.

Pages are not allocated on the paging device or partition until they are needed. Each device and file starts with a bitmap telling which pages are free. When a page without backing store has to be tossed out of memory, the highest priority paging partition or file that still has space is chosen and a page allocated on it. Normally, the paging partition, if present, has higher priority than any paging file. The page table is updated to reflect that the page is no longer present in memory (e.g., the page-not-present bit is set) and the disk location is written into the page table entry.
The Page Replacement Algorithm

Page replacement works as follows. Linux tries to keep some pages free so they can be claimed as needed. Of course, this pool must be continually replenished, so the PFRA (Page Frame Reclaiming Algorithm) algorithm is how this happens.

First of all, Linux distinguishes between four different types of pages: unreclaimable, swappable, syncable, and discardable. Unreclaimable pages, which include reserved or locked pages, kernel mode stacks, etc., may not be paged out. Swappable pages must be written back to the swap area or the paging disk partition before the page can be reclaimed. Syncable pages must be written back to disk if they have been marked as dirty. Finally, discardable pages can be reclaimed immediately.

At boot time, init starts up a page daemon, kswapd, one per each memory node, and configures them to run periodically. Each time kswapd awakens, it checks to see if there are enough free pages available, by comparing the low and high watermarks with the current memory usage for each memory zone. If there is enough memory, it goes back to sleep, although it can be awakened early if more pages are suddenly needed. If the available memory for any of the zones falls below a threshold, kswapd initiates the page frame reclaiming algorithm. During each run, only a certain target number of pages is reclaimed, typically 32. This number is limited to control the I/O pressure (the number of disk writes, created during the PFRA operations). Both, the number of reclaimed pages and the total number of scanned pages are configurable parameters.

Each time PFRA executes, it first tries to reclaim easy pages, then proceeds with the harder ones. Discardable and un-referenced pages can be reclaimed immediately by moving them onto the zone’s freelist. Next it looks for pages with backing store which have not been referenced recently, using a clock-like algorithm. Following are shared pages that none of the users seems to be using much. The challenge with shared pages is that, if a page entry is reclaimed, the page tables of all address spaces originally sharing that page must be updated in a synchronous manner. Linux maintains efficient tree like data structures to easily find all users of a shared page. Ordinary user pages are searched next, and if chosen to be evicted, they must be scheduled for write in the swap area. The swappiness, of the system, that is, the ratio of pages with backing store versus pages which need to be swapped out selected during PFRA, is a tunable parameter of the algorithm. Finally, if a page is invalid, absent from memory, shared, locked in memory, or being used for DMA, it is skipped.

PFRA uses a clock-like algorithm to select old pages for eviction within a certain category. At the core of this algorithm is a loop which scans through each zone’s active and inactive lists, trying to reclaim different kinds of pages, with different urgency. The urgency value is passed as a parameter telling the procedure how much effort to expend to reclaim some pages. Usually, this means
how many pages to inspect before giving up.

During PFRA, pages are moved between the active and inactive list in a manner described in Fig. 10-18. To maintain some heuristics and try to find pages which have not been referenced and are unlikely to be needed in the near future, PFRA maintains two flags per page: active/inactive, and referenced or not. These two flags encode four states, as shown in Fig. 10-18. During the first scan of a set of pages, PFRA first clears their reference bits. If during the second run over the page it is determined that it has been referenced, it is advanced to another state, from which it is less likely to be reclaimed. Otherwise, the page is moved to a state from where it will more likely to be evicted.

Pages on the inactive list, which have not been referenced since the the last time they were inspected, are best candidates for eviction. These correspond to pages with both $PG_{active}$ and $PG_{referenced}$ equal to zero in Fig. 10-18. However, if necessary, pages may be reclaimed even if they are in some of the other states. The refill arrows in Fig. 10-18 illustrate this fact.

![Figure 10-18. Page states considered in the page frame replacement algorithm.](image)

The reason PRFA maintains pages in the inactive list although they might have been referenced, is to prevent situations such as the following. Consider a process which makes periodic accesses to different pages, with a 1-hour period. A
page accessed since the last loop will have its reference flag set. However, since it will not be needed again for the next hour, there is no reason not to consider it as a candidate for reclamation.

One other aspect of the memory management system that we have not yet mentioned is a second daemon, *pdflush*, actually a set of background daemon threads. The *pdflush* threads either (1) wake up periodically, typically each 500 msec, to write back to disk very old dirty pages, or (2) are explicitly awakened by the kernel when available memory levels fall below a certain threshold, to write back dirty pages from the page cache to disk. In **laptop mode**, in order to conserve battery life, dirty pages are written to disk whenever *pdflush* threads wakeup. Dirty pages may also be written out to disk on explicit requests for synchronization, via systems calls such as *sync*, *fsync*, or *fdatasync*. Older Linux versions used two separate daemons: *kupdate*, for old page write back, and *bdflush*, for page write back under low memory conditions. In the 2.4 kernel this functionality was integrated in the *pdflush* threads. The choice of multiple threads was made in order to hide long disk latencies.

## 10.5 INPUT/OUTPUT IN LINUX

The I/O system in Linux is fairly straightforward. Basically, all I/O devices are made to look like files and are accessed as such with the same **read** and **write** system calls that are used to access all ordinary files. In some cases, device parameters must be set, and this is done using a special system call. We will study these issues in the following sections.

### 10.5.1 Fundamental Concepts

Like all computers, those running Linux have I/O devices such as disks, printers, and networks connected to them. Some way is needed to allow programs to access these devices. Although various solutions are possible, the Linux one is to integrate the devices into the file system as what are called **special files**. Each I/O device is assigned a path name, usually in `/dev`. For example, a disk might be `/dev/hd1`, a printer might be `/dev/lp`, and the network might be `/dev/net`.

These special files can be accessed the same way as any other files. No special commands or system calls are needed. The usual open, read, and write system calls will do just fine. For example, the command

```
cp file /dev/lp
```
copy the file to printer, causing it to be printed (assuming that the user has permission to access `/dev/lp`). Programs can open, read, and write special files the same way as they do regular files. In fact, `cp` in the above example is not even aware that it is printing. In this way, no special mechanism is needed for doing
I/O.

Special files are divided into two categories, block and character. A block special file is one consisting of a sequence of numbered blocks. The key property of the block special file is that each block can be individually addressed and accessed. In other words, a program can open a block special file and read, say, block 124 without first having to read blocks 0 to 123. Block special files are typically used for disks.

Character special files are normally used for devices that input or output a character stream. Keyboards, printers, networks, mice, plotters, and most other I/O devices that accept or produce data for people use character special files. It is not possible (or even meaningful) to seek to block 124 on a mouse.

Associated with each special file is a device driver that handles the corresponding device. Each driver has what is called a major device number that serves to identify it. If a driver supports multiple devices, say, two disks of the same type, each disk has a minor device number that identifies it. Together, the major and minor device numbers uniquely specify every I/O device. In few cases, a single driver handles two closely related devices. For example, the driver corresponding to /dev/tty controls both the keyboard and the screen, which is often thought of as a single device, the terminal.

Although most character special files cannot be randomly accessed, they often need to be controlled in ways that block special files do not. Consider, for example, input typed on the keyboard and displayed on the screen. When a user makes a typing error and wants to erase the last character typed, he presses some key. Some people prefer to use backspace, and others prefer DEL. Similarly, to erase the entire line just typed, many conventions abound. Traditionally @ was used, but with the spread of e-mail (which uses @ within e-mail address), many systems have adopted CTRL-U or some other character. Likewise, to interrupt the running program, some special key must be hit. Here, too, different people have different preferences. CTRL-C is a common choice, but it is not universal.

Rather than making a choice and forcing everyone to use it, Linux allows all these special functions and many others to be customized by the user. A special system call is generally provided for setting these options. This system call also handles tab expansion, enabling and disabling of character echoing, conversion between carriage return and line feed, and similar items. The system call is not permitted on regular files or block special files.

### 10.5.2 Networking

Another example of I/O is networking, as pioneered by Berkeley UNIX and taken over by Linux more-or-less verbatim. The key concept in the Berkeley design is the socket. Sockets are analogous to mailboxes and telephone wall sockets in that they allow users to interface to the network, just as mailboxes allow people to interface to the postal system and telephone wall sockets allow
them to plug in telephones and connect to the telephone system. The sockets’ position is shown in Fig. 10-19.

Figure 10-19. The uses of sockets for networking.

Sockets can be created and destroyed dynamically. Creating a socket returns a file descriptor, which is needed for establishing a connection, reading data, writing data, and releasing the connection.

Each socket supports a particular type of networking, specified when the socket is created. The most common types are

1. Reliable connection-oriented byte stream.
2. Reliable connection-oriented packet stream.

The first socket type allows two processes on different machines to establish the equivalent of a pipe between them. Bytes are pumped in at one end and they come out in the same order at the other. The system guarantees that all bytes that are sent arrive and in the same order they were sent.

The second type is similar to the first one, except that it preserves packet boundaries. If the sender makes five separate calls to write, each for 512 bytes, and the receiver asks for 2560 bytes, with a type 1 socket, all 2560 bytes will be returned at once. With a type 2 socket, only 512 bytes will be returned. Four more calls are needed to get the rest. The third type of socket is used to give the user access to the raw network. This type is especially useful for real-time applications, and for those situations in which the user wants to implement a specialized error handling scheme. Packets may be lost or reordered by the network. There are no guarantees, as in the first two cases. The advantage of this mode is higher performance, which sometimes outweighs reliability (e.g., for multimedia delivery, in which being fast counts for more than being right).
When a socket is created, one of the parameters specifies the protocol to be used for it. For reliable byte streams, the most popular protocol is **TCP** (**Transmission Control Protocol**). For unreliable packet-oriented transmission, **UDP** (**User Datagram Protocol**) is the usual choice. Both are these are layered on top of **IP** (**Internet Protocol**). All of these protocols originated with the U.S. Dept. of Defense’s ARPANET, and now form the basis of the Internet. There is no common protocol for reliable packet streams.

Before a socket can be used for networking, it must have an address bound to it. This address can be in one of several naming domains. The most common domain is the Internet naming domain, which uses 32-bit integers for naming endpoints in Version 4 and 128-bit integers in Version 6 (Version 5 was an experimental system that never made it to the major leagues).

Once sockets have been created on both the source and destination computers, a connection can be established between them (for connection-oriented communication). One party makes a `listen` system call on a local socket, which creates a buffer and blocks until data arrive. The other one makes a `connect` system call, giving as parameters the file descriptor for a local socket and the address of a remote socket. If the remote party accepts the call, the system then establishes a connection between the sockets.

Once a connection has been established, it functions analogously to a pipe. A process can read and write from it using the file descriptor for its local socket. When the connection is no longer needed, it can be closed in the usual way, via the `close` system call.

### 10.5.3 Input/Output System Calls in Linux

Each I/O device in a Linux system generally has a special file associated with it. Most I/O can be done by just using the proper file, eliminating the need for special system calls. Nevertheless, sometimes there is a need for something that is device specific. Prior to POSIX most UNIX systems had a system call `ioctl` that performed a large number of device-specific actions on special files. Over the course of the years, it had gotten to be quite a mess. POSIX cleaned it up by splitting its functions into separate function calls primarily for terminal devices. In Linux, and modern UNIX systems in general, whether each one is a separate system call or they share a single system call or something else is implementation dependent.

The first four listed in Fig. 10-20 are used to set and get the terminal speed. Different calls are provided for input and output because some modems operate at split speed. For example, old videotex systems allowed people to access public databases with short requests from the home to the server at 75 bits/sec with replies coming back at 1200 bits/sec. This standard was adopted at a time when 1200 bits/sec both ways was too expensive for home use. Times change in the networking world. This asymmetry still persists, with some telephone companies
offering inbound service at 8 Mbps and outbound service at 512 kbps, often under the name of **ADSL (Asymmetric Digital Subscriber Line)**.

<table>
<thead>
<tr>
<th>Function call</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>s = cfsetospeed(&amp;termios, speed)</code></td>
<td>Set the output speed</td>
</tr>
<tr>
<td><code>s = cfsetispeed(&amp;termios, speed)</code></td>
<td>Set the input speed</td>
</tr>
<tr>
<td><code>s = cfgetospeed(&amp;termios, speed)</code></td>
<td>Get the output speed</td>
</tr>
<tr>
<td><code>s = cfgtetispeed(&amp;termios, speed)</code></td>
<td>Get the input speed</td>
</tr>
<tr>
<td><code>s = tcsetattr(fd, opt, &amp;termios)</code></td>
<td>Set the attributes</td>
</tr>
<tr>
<td><code>s = tcgetattr(fd, &amp;termios)</code></td>
<td>Get the attributes</td>
</tr>
</tbody>
</table>

**Figure 10-20.** The main POSIX calls for managing the terminal.

The last two calls in the list are for setting and reading back all the special characters used for erasing characters and lines, interrupting processes, and so on. In addition, they enable and disable echoing, handle flow control, and other related functions. Additional I/O function calls also exist, but they are somewhat specialized so we will not discuss them further. In addition, `ioctl` is still available.

### 10.5.4 Implementation of Input/Output in Linux

I/O in Linux is implemented by a collection of device drivers, one per device type. The function of the drivers is to isolate the rest of the system from the idiosyncrasies of the hardware. By providing standard interfaces between the drivers and the rest of the operating system, most of the I/O system can be put into the machine-independent part of the kernel.

When the user accesses a special file, the file system determines the major and minor device numbers belonging to it and whether it is a block special file or a character special file. The major device number is used to index into one of two internal hash tables containing data structures for character or block devices. The structure thus located contains pointers to the procedures to call to open the device, read the device, write the device, and so on. The minor device number is passed as a parameter. Adding a new device type to Linux means adding a new entry to one of these tables and supplying the corresponding procedures to handle the various operations on the device.

Some of the operations which may be associated with different character devices are shown in Fig. 10-21. Each row refers to a single I/O device (i.e., a single driver). The columns represent the functions that all character drivers must support. Several other functions also exist. When an operation is performed on a character special file, the system indexes into hash table of character devices to select the proper structure, then calls the corresponding function to have the work performed. Thus each of the file operation contains a pointer to a function...
Each driver is split into two parts, both of which are part of the Linux kernel and both of which run in kernel mode. The top half runs in the context of the caller and interfaces to the rest of Linux. The bottom half runs in kernel context and interacts with the device. Drivers are allowed to make calls to kernel procedures for memory allocation, timer management, DMA control, and other things. The set of kernel functions that may be called is defined in a document called the **Driver-Kernel Interface**. Writing device drivers for Linux is covered in detail in (Egan and Teixeira, 1992; Rubini and Corbert, 2005).

The I/O system is split into two major components: the handling of block special files and the handling of character special files. We will now look at each of these components in turn.

The goal of the part of the system that does I/O on block special files (e.g., disks) is to minimize the number of actual transfers that must be done. To accomplish this goal, Linux systems have a **cache** between the disk drivers and the file system, as illustrated in Fig. 10-22. Prior to the 2.2 kernel, Linux maintained completely separate page and buffer caches, so a file residing in a disk block could be cached in both caches. Newer versions of Linux have a unified cache. A **generic block layer** holds these components together, and performs the necessary translations between disk sectors, blocks, buffers and pages of data, and enables the operations on them.

The cache is a table in the kernel for holding thousands of the most recently used blocks. When a block is needed from a disk for any purpose (i-node, directory, or data), a check is first made to see if it is in the cache. If so, it is taken from there and a disk access is avoided, thereby resulting in great improvements in system performance.

If the block is not in the page cache, it is read from the disk into the cache and from there, copied to where it is needed. Since the page cache has room for only a fixed number of blocks, the page replacement algorithm described in the previous section is invoked.

The page cache works for writes as well as for reads. When a program writes a block, it goes to the cache, not to the disk. The `pdflush` daemon will flush the

<table>
<thead>
<tr>
<th>Device</th>
<th>Open</th>
<th>Close</th>
<th>Read</th>
<th>Write</th>
<th>ioctl</th>
<th>Other</th>
</tr>
</thead>
<tbody>
<tr>
<td>Null</td>
<td>null</td>
<td>null</td>
<td>null</td>
<td>null</td>
<td>null</td>
<td>...</td>
</tr>
<tr>
<td>Memory</td>
<td>null</td>
<td>null</td>
<td>mem_read</td>
<td>mem_write</td>
<td>null</td>
<td>...</td>
</tr>
<tr>
<td>Keyboard</td>
<td>k_open</td>
<td>k_close</td>
<td>k_read</td>
<td>error</td>
<td>k_ioctl</td>
<td>...</td>
</tr>
<tr>
<td>Tty</td>
<td>tty_open</td>
<td>tty_close</td>
<td>tty_read</td>
<td>tty_write</td>
<td>tty_ioctl</td>
<td>...</td>
</tr>
<tr>
<td>Printer</td>
<td>lp_open</td>
<td>lp_close</td>
<td>error</td>
<td>lp_write</td>
<td>lp_ioctl</td>
<td>...</td>
</tr>
</tbody>
</table>

**Figure 10-21.** Some of the file operations supported for typical character devices.
block to disk in the event the cache grows above a specified value. In addition, to avoid having blocks stay too long in the cache before being written to the disk, all the dirty blocks are written to the disk every 30 seconds.

In order to minimize the latency of repetitive disk head movements, Linux relies on an \textit{I/O scheduler}. The purpose of the I/O scheduler is to reorder or bundle read/write requests to block devices. There are many scheduler variants,
optimized for different types of workloads. The basic Linux scheduler is based on the original Linus Elevator scheduler. The operations of the elevator scheduler can be summarized as follows: disk operations are sorted in a doubly linked list, ordered by the address of the sector of the disk request. New requests are inserted in this list in a sorted manner. This prevents repeated costly disk head movements. The request list is then merged so that adjacent operations are issued via a single disk request. The basic elevator scheduler can lead to starvation. Therefore, the revised version of the Linux disk scheduler includes two additional lists, maintaining read or write operations ordered by their deadline. The default deadlines are 0.5 sec for read requests and 5 sec for write requests. If a system defined deadline for the oldest write operation is about to expire, that write request will be serviced before any of the requests on the main doubly linked list.

The interaction with character devices is much simpler. Since character devices produce or consume streams of characters, or bytes of data, support for random access makes little sense. One exception is the use of line disciplines. A line discipline can be associated with a terminal device, represented via the structure *tty_struct*, and it represents an interpreter for the data exchanged with the terminal device. For instance, local line editing can be done (i.e., erased characters and lines can be removed), carriage returns can be mapped onto line feeds, and other special processing can be completed. However, if a process wants to interact on every character, it can put the line in raw mode, in which case the line discipline will be bypassed.

Output works in a similar way, expanding tabs to spaces, converting line feeds to carriage returns + line feeds, adding filler characters following carriage returns on slow mechanical terminals, and so on. Like input, output can go through the line discipline (cooked mode) or bypass it (raw mode). Raw mode is especially useful when sending binary data to other computers over a serial line and for GUIs. Here, no conversions are desired.

The interaction with network devices is somewhat different. While network devices also produce/consume streams of characters, their asynchronous nature makes them less suitable for easy integration under the same interface as other character devices. The networking device driver produces packets consisting of multiple bytes of data, along with network headers. These packets are then routed through a series of network protocol drivers, and ultimately are passed to the user space application. A key data structure is the socket buffer structure, *skbuff*, which is used to represent portions of memory filled with packet data. The data in an skbuff buffer does not always start at the start of buffer. As it is being processed by various protocols in the networking stack, protocol headers may be removed, or added. The user processes interact with networking devices via sockets, which in Linux support the original BSD socket API. The protocol drivers can be bypassed and direct access to the underlying network device is enabled via *raw_socket*. Only superusers are allowed to create raw sockets.
10.5.5 Modules in Linux

For decades, UNIX device drivers have been statically linked into the kernel so they were all present in memory when the system was booted every time. Given the environment in which UNIX grew up, mostly departmental minicomputers and then high-end workstations, with their small and unchanging sets of I/O devices, this scheme worked well. Basically, a computer center built a kernel containing drivers for the I/O devices and that was it. If next year it bought a new disk, it relinked the kernel. No big deal.

With the arrival of Linux on the PC platform, suddenly all that changed. The number of I/O devices available on the PC is orders of magnitude larger than on any minicomputer. In addition, although all Linux users have (or can easily get) the full source code, probably the vast majority would have considerable difficulty adding a driver, updating the all device-driver related data structures, relinking the kernel, and then installing it as the bootable system (not to mention dealing with the aftermath of building a kernel that does not boot).

Linux solved this problem with the concept of **loadable modules**. These are chunks of code that can be loaded into the kernel while the system is running. Most commonly these are character or block device drivers, but they can also be entire file systems, network protocols, performance monitoring tools, or anything else desired.

When a module is loaded, several things have to happen. First, the module has to be relocated on-the-fly, during loading. Second, the system has to check to see if the resources the driver needs are available (e.g., interrupt request levels) and if so, mark them as in use. Third, any interrupt vectors that are needed must be set up. Fourth, the appropriate driver switch table has to be updated to handle the new major device type. Finally, the driver is allowed to run to perform any device-specific initialization it may need. Once all these steps are completed, the driver is fully installed, the same as any statically installed driver. Some modern UNIX systems also support loadable modules now, too.

10.6 THE LINUX FILE SYSTEM

The most visible part of any operating system, including Linux, is the file system. In the following sections we will examine the basic ideas behind the Linux file system, the system calls, and how the file system is implemented. Some of these ideas derive from MULTICS, and many of them have been copied by MSDOS, Windows, and other systems, but others are unique to UNIX-based systems. The Linux design is especially interesting because it clearly illustrates the principle of **Small is Beautiful**. With minimal mechanism and a very limited number of system calls, Linux nevertheless provides a powerful and elegant file system.
10.6 THE LINUX FILE SYSTEM

10.6.1 Fundamental Concepts

The initial Linux file system was the MINIX 1 file system. However, due to the fact that it limited file names to 14 characters (in order to be compatible with UNIX Version 7) and its maximum file size was 64 MB (which was overkill on the 10-MB hard disks of its era), there was interest in better file systems almost from the beginning of the Linux development, which began about 5 years after MINIX 1 was released. The first improvement was the ext file system, which allowed file names of 255 characters and files of 2 GB, but it was slower than the MINIX 1 file system, so the search continued for a while. Eventually, the ext2 file system was invented with long file names, long files, and better performance, and that has become the main file system. However, Linux supports several dozens of file systems using the Virtual File System (VFS) layer (described in the next section). When Linux is linked, a choice is offered of which file systems should be built into the kernel. Other ones can be dynamically loaded as modules during execution, if need be.

A Linux file is a sequence of 0 or more bytes containing arbitrary information. No distinction is made between ASCII files, binary files, or any other kinds of files. The meaning of the bits in a file is entirely up to the file’s owner. The system does not care. File names are limited to 255 characters, and all the ASCII characters except NUL are allowed in file names, so a file name consisting of three carriage returns is a legal file name (but not an especially convenient one).

By convention, many programs expect file names to consist of a base name and an extension, separated by a dot (which counts as a character). Thus prog.c is typically a C program, prog.f90 is typically a FORTRAN 90 program, and prog.o is usually an object file (compiler output). These conventions are not enforced by the operating system but some compilers and other programs expect them. Extensions may be of any length and files may have multiple extensions, as in prog.java.gz, which is probably a gzip compressed Java program.

Files can be grouped together in directories for convenience. Directories are stored as files, and to a large extent can be treated like files. Directories can contain subdirectories, leading to a hierarchical file system. The root directory is called / and usually contains several subdirectories. The / character is also used to separate directory names, so that the name /usr/ast/books/mos3/chap-10 denotes the file chap-10 located in the directory ast, which itself is in the /usr directory.

Some of the major directories near the top of the tree are shown in Fig. 10-23.

There are two ways to specify file names in Linux, both to the shell and when opening a file from within a program. The first way is using an absolute path, which means telling how to get to the file starting at the root directory. An example of an absolute path is /usr/last/books/mos3/chap-10. This tells the system to look in the root directory for a directory called usr, then look there for another directory, ast. In turn, this directory contains a directory books, which contains the directory mos3 which contains the file chap-10.
Absolute path names are often long and inconvenient. For this reason, Linux allows users and processes to designate the directory in which they are currently working as the **working directory**. Path names can also be specified relative to the working directory. A path name specified relative to the working directory is a **relative path**. For example, if `/usr/ast/books/mos3` is the working directory, then the shell command

```bash
cp chap-10 backup-10
```

has exactly the same effect as the longer command

```bash
cp /usr/ast/books/mos3/chap-10 /usr/ast/books/mos3/backup-10
```

It frequently occurs that a user needs to refer to a file that belongs to another user, or at least is located elsewhere in the file tree. For example, if two users are sharing a file, it will be located in a directory belonging to one of them, so the other will have to use an absolute path name to refer to it (or change the working directory). If this is long enough, it may become irritating to have to keep typing it. Linux provides a solution to this problem by allowing users to make a new directory entry that points to an existing file. Such an entry is called a **link**.

As an example, consider the situation of Fig. 10-24(a). Fred and Lisa are working together on a project, and each one needs frequent access to the other’s files. If Fred has `/usr/fred` as his working directory, he can refer to the file `x` in Lisa’s directory as `/usr/lisa/x`. Alternatively, Fred can create a new entry in his directory as shown in Fig. 10-24(b), after which he can use `x` to mean `/usr/lisa/x`.

In the example just discussed, we suggested that before linking, the only way for Fred to refer to Lisa’s file `x` was using its absolute path. Actually, this is not really true. When a directory is created, two entries, . and .., are automatically made in it. The former refers to the working directory itself. The latter refers to the directory’s parent, that is, the directory in which it itself is listed. Thus from `/usr/fred`, another path to Lisa’s file `x` is `.lisa/x`.

In addition to regular files, Linux also supports character special files and block special files. Character special files are used to model serial I/O devices such as keyboards and printers. Opening and reading from `/dev/tty` reads from the
keyboard; opening and writing to /dev/lp writes to the printer. Block special files, often with names like /dev/hd1, can be used to read and write raw disk partitions without regard to the file system. Thus a seek to byte \( k \) followed by a read will begin reading from the \( k \)-th byte on the corresponding partition, completely ignoring the i-node and file structure. Raw block devices are used for paging and swapping, by programs that lay down file systems (e.g., mkfs), and by programs that fix sick file systems (e.g., fsck), for example.

Many computers have two or more disks. On mainframes at banks, for example, it is frequently necessary to have 100 or more disks on a single machine, in order to hold the huge databases required. Even personal computers normally have at least two disks—a hard disk and an optical (e.g., DVD) drive. When there are multiple disk drives, the question arises of how to handle them.

One solution is to put a self-contained file system on each one and just keep them separate. Consider, for example, the situation depicted in Fig. 10-25(a). Here we have a hard disk, which we will call C:, and a DVD, which we will call D:. Each has its own root directory and files. With this solution, the user has to specify both the device and the file when anything other than the default is needed. For example, to copy the file \( x \) to the directory \( d \), (assuming C: is the default), one would type

\[
\text{cp} \ D:/x \ /a/d/x
\]

This is the approach taken by systems like MS-DOS, Windows 98, and VMS.

The Linux solution is to allow one disk to be mounted in another disk’s file tree. In our example, we could mount the DVD on the directory /b, yielding the file system of Fig. 10-25(b). The user now sees a single file tree, and no longer has to be aware of which file resides on which device. The above copy command
Figure 10-25.  (a) Separate file systems.  (b) After mounting.

now becomes

    cp /b/x /a/d/x

exactly the same as it would have been if everything had been on the hard disk in the first place.

Another interesting property of the Linux file system is locking. In some applications, two or more processes may be using the same file at the same time, which may lead to race conditions. One solution is to program the application with critical regions. However, if the processes belong to independent users who do not even know each other, this kind of coordination is generally inconvenient.

Consider, for example, a database consisting of many files in one or more directories that are accessed by unrelated users. It is certainly possible to associate a semaphore with each directory or file and achieve mutual exclusion by having processes do a down operation on the appropriate semaphore before accessing the data. The disadvantage, however, is that a whole directory or file is then made inaccessible, even though only one record may be needed.

For this reason, POSIX provides a flexible and fine-grained mechanism for processes to lock as little as a single byte and as much as an entire file in one indivisible operation. The locking mechanism requires the caller to specify the file to be locked, the starting byte, and the number of bytes. If the operation succeeds, the system makes a table entry noting that the bytes in question (e.g., a database record) are locked.

Two kinds of locks are provided, shared locks and exclusive locks. If a portion of a file already contains a shared lock, a second attempt to place a shared lock on it is permitted, but an attempt to put an exclusive lock on it will fail. If a portion of a file contains an exclusive lock, all attempts to lock any part of that portion will fail until the lock has been released. In order to successfully place a
lock, every byte in the region to be locked must be available.

When placing a lock, a process must specify whether it wants to block or not in the event that the lock cannot be placed. If it chooses to block, when the existing lock has been removed, the process is unblocked and the lock is placed. If the process chooses not to block when it cannot place a lock, the system call returns immediately, with the status code telling whether the lock succeeded or not.

Locked regions may overlap. In Fig. 10-26(a) we see that process A has placed a shared lock on bytes 4 through 7 of some file. Later, process B places a shared lock on bytes 6 through 9, as shown in Fig. 10-26(b). Finally, C locks bytes 2 through 11. As long as all these locks are shared, they can co-exist.

Now consider what happens if a process tries to acquire an exclusive lock to byte 9 of the file of Fig. 10-26(c), with a request to block if the lock fails. Since two previous locks cover this block, the caller will block and will remain blocked until both B and C release their locks.

### 10.6.2 File System Calls in Linux

Many system calls relate to files and the file system. First we will look at the system calls that operate on individual files. Later we will examine those that involve directories or the file system as a whole. To create a new file, the `creat` call can be used. (When Ken Thompson was once asked what he would do...
differently if he had the chance to reinvent UNIX, he replied that he would spell `creat` as `create` this time.) The parameters provide the name of the file and the protection mode. Thus

\[ fd = creat("abc", \text{mode}); \]

creates a file called `abc` with the protection bits taken from `mode`. These bits determine which users may access the file and how. They will be described later.

The `creat` call not only creates a new file, but also opens it for writing. To allow subsequent system calls to access the file, a successful `creat` returns as its result a small nonnegative integer called a file descriptor, `fd` in the example above. If a `creat` is done on an existing file, that file is truncated to length 0 and its contents are discarded. Files can also be created using the `open` call with appropriate arguments.

Now let us continue looking at the principal file system calls, which are listed in Fig. 10-27. To read or write an existing file, the file must first be opened using `open`. This call specifies the file name to be opened and how it is to be opened: for reading, writing, or both. Various options can be specified as well. Like `creat`, the call to `open` returns a file descriptor that can be used for reading or writing. Afterward, the file can be closed by `close`, which makes the file descriptor available for reuse on a subsequent `creat` or `open`. Both the `creat` and `open` calls always return the lowest numbered file descriptor not currently in use.

When a program starts executing in the standard way, file descriptors 0, 1, and 2 are already opened for standard input, standard output, and standard error, respectively. In this way, a filter, such as the `sort` program, can just read its input from file descriptor 0 and write its output to file descriptor 1, without having to know what files they are. This mechanism works because the shell arranges for these values to refer to the correct (redirected) files before the program is started.

The most heavily used calls are undoubtedly `read` and `write`. Each one has three parameters: a file descriptor (telling which open file to read or write), a buffer address (telling where to put the data or get the data from), and a count (telling how many bytes to transfer). That is all there is. It is a very simple design. A typical call is

\[ n = read(fd, \text{buffer}, \text{nbytes}); \]

Although nearly all programs read and write files sequentially, some programs need to be able to access any part of a file at random. Associated with each file is a pointer that indicates the current position in the file. When reading (writing) sequentially, it normally points to the next byte to be read (written). If the pointer is at, say, 4096, before 1024 bytes are read, it will automatically be moved to 5120 after a successful `read` system call. The `lseek` call changes the value of the position pointer, so that subsequent calls to `read` or `write` can begin anywhere in the file, or even beyond the end of it. It is called `lseek` to avoid conflicting with `seek`, a now-obsolete call that was formerly used on 16-bit computers for seeking.
### Table of System Calls

<table>
<thead>
<tr>
<th>System call</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td><code>fd = creat(name, mode)</code></td>
<td>One way to create a new file</td>
</tr>
<tr>
<td><code>fd = open(file, how, ...)</code></td>
<td>Open a file for reading, writing or both</td>
</tr>
<tr>
<td><code>s = close(fd)</code></td>
<td>Close an open file</td>
</tr>
<tr>
<td><code>n = read(fd, buffer, nbytes)</code></td>
<td>Read data from a file into a buffer</td>
</tr>
<tr>
<td><code>n = write(fd, buffer, nbytes)</code></td>
<td>Write data from a buffer into a file</td>
</tr>
<tr>
<td><code>position = lseek(fd, offset, whence)</code></td>
<td>Move the file pointer</td>
</tr>
<tr>
<td><code>s = stat(name, &amp;buf)</code></td>
<td>Get a file's status information</td>
</tr>
<tr>
<td><code>s = fstat(fd, &amp;buf)</code></td>
<td>Get a file's status information</td>
</tr>
<tr>
<td><code>s = pipe(&amp;fd[0])</code></td>
<td>Create a pipe</td>
</tr>
<tr>
<td><code>s = fcntl(fd, cmd, ...)</code></td>
<td>File locking and other operations</td>
</tr>
</tbody>
</table>

**Figure 10-27.** Some system calls relating to files. The return code `s` is −1 if an error has occurred; `fd` is a file descriptor, and `position` is a file offset. The parameters should be self explanatory.

`lseek` has three parameters: the first one is the file descriptor for the file; the second one is a file position; the third one tells whether the file position is relative to the beginning of the file, the current position, or the end of the file. The value returned by `lseek` is the absolute position in the file after the file pointer was changed. Slightly ironically, `lseek` is the only file system call that can never cause an actual disk seek because all it does is update the current file position, which is a number in memory.

For each file, Linux keeps track of the file mode (regular, directory, special file), size, time of last modification, and other information. Programs can ask to see this information via the `stat` system call. The first parameter is the file name. The second one is a pointer to a structure where the information requested is to be put. The fields in the structure are shown in Fig. 10-28. The `fstat` call is the same as `stat` except that it operates on an open file (whose name may not be known) rather than on a path name.

The pipe system call is used to create shell pipelines. It creates a kind of pseudofile, which buffers the data between the pipeline components, and returns file descriptors for both reading and writing the buffer. In a pipeline such as

```
sort <in | head -30
```

file descriptor 1 (standard output) in the process running `sort` would be set (by the shell) to write to the pipe and file descriptor 0 (standard input) in the process running `head` would be set to read from the pipe. In this way, `sort` just reads from file descriptor 0 (set to the file `in`) and writes to file descriptor 1 (the pipe) without even being aware that these have been redirected. If they have not been redirected, `sort` will automatically read from the keyboard and write to the screen.
Device the file is on
I-node number (which file on the device)
File mode (includes protection information)
Number of links to the file
Identity of the file's owner
Group the file belongs to
File size (in bytes)
Creation time
Time of last access
Time of last modification

Figure 10-28. The fields returned by the stat system call.

The last system call in Fig. 10-27 is fcntl. It is used to lock and unlock files, apply shared or exclusive locks, and perform a few other file-specific operations.

Now let us look at some system calls that relate more to directories or the file system as a whole, rather than just to one specific file. Some common ones are listed in Fig. 10-29. Directories are created and destroyed using mkdir and rmdir, respectively. A directory can only be removed if it is empty.

<table>
<thead>
<tr>
<th>System call</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s = mkdir(path, mode)</td>
<td>Create a new directory</td>
</tr>
<tr>
<td>s = rmdir(path)</td>
<td>Remove a directory</td>
</tr>
<tr>
<td>s = link(oldpath, newpath)</td>
<td>Create a link to an existing file</td>
</tr>
<tr>
<td>s = unlink(path)</td>
<td>Unlink a file</td>
</tr>
<tr>
<td>s = chdir(path)</td>
<td>Change the working directory</td>
</tr>
<tr>
<td>dir = opendir(path)</td>
<td>Open a directory for reading</td>
</tr>
<tr>
<td>s = closedir(dir)</td>
<td>Close a directory</td>
</tr>
<tr>
<td>dirent = readdir(dir)</td>
<td>Read one directory entry</td>
</tr>
<tr>
<td>rewinddir(dir)</td>
<td>Rewind a directory so it can be reread</td>
</tr>
</tbody>
</table>

Figure 10-29. Some system calls relating to directories. The return code $s$ is $-1$ if an error has occurred; $dir$ identifies a directory stream and $dirent$ is a directory entry. The parameters should be self explanatory.
As we saw in Fig. 10-24, linking to a file creates a new directory entry that points to an existing file. The link system call creates the link. The parameters specify the original and new names, respectively. Directory entries are removed with unlink. When the last link to a file is removed, the file is automatically deleted. For a file that has never been linked, the first unlink causes it to disappear.

The working directory is changed by the chdir system call. Doing so has the effect of changing the interpretation of relative path names.

The last four calls of Fig. 10-29 are for reading directories. They can be opened, closed, and read, analogous to ordinary files. Each call to readdir returns exactly one directory entry in a fixed format. There is no way for users to write in a directory (in order to maintain the integrity of the file system). Files can be added to a directory using creat or link and removed using unlink. There is also no way to seek to a specific file in a directory, but rewinddir allows an open directory to be read again from the beginning.

### 10.6.3 Implementation of the Linux File System

In this section first we will look at the abstractions supported by the Virtual File System layer. The VFS hides from higher level processes and applications the differences among many types of file systems supported by Linux, whether they are residing on local devices or are stored remotely and need to be accessed over the network. Devices and other special files are also accessed through the VFS layer. Next, we will describe the implementation of the first wide-spread Linux file system, ext2, or the second extended file system. Afterward, we will discuss the improvements in the ext3 file system. A wide variety of other file systems are also in use. All Linux systems can handle multiple disk partitions, each with a different file system on it.

#### The Linux Virtual File System

In order to enable applications to interact with different file systems, implemented on different types of local or remote devices, Linux adopts an approach used in other UNIX systems: the Virtual File System (VFS). VFS defines a set of basic file system abstractions and the operations which are allowed on these abstractions. Invocations of the system calls described in the previous section, access the VFS data structures, determine the exact file system where the accessed file belongs, and via function pointers stored in the VFS data structures invoke the corresponding operation in the specified file system.

Fig. 10-30 summarizes the four main file system structures supported by VFS. The superblock contains critical information about the layout of the file system. Destruction of the superblock will render the file system unreadable. The i-nodes (short for index-nodes, but never called that, although some lazy people drop the hyphen and call them inodes) each describe exactly one file. Note that in Linux,
directories and devices are also represented as files, thus they will have corresponding i-nodes. Both superblocks and i-nodes have a corresponding structure maintained on the physical disk where the file system resides.

<table>
<thead>
<tr>
<th>Object</th>
<th>Description</th>
<th>Operation</th>
</tr>
</thead>
<tbody>
<tr>
<td>Superblock</td>
<td>specific filesystem</td>
<td>read_inode, sync_fs</td>
</tr>
<tr>
<td>Dentry</td>
<td>directory entry, single component of a path</td>
<td>create, link</td>
</tr>
<tr>
<td>I-node</td>
<td>specific file</td>
<td>d_compare, d_delete</td>
</tr>
<tr>
<td>File</td>
<td>open file associated with a process</td>
<td>read, write</td>
</tr>
</tbody>
</table>

In order to facilitate certain directory operations and traversal of paths, such as /usr/ast/bin, VFS supports a dentry data structure which represents a directory entry. This data structure is created by the file system on the fly. Directory entries are cached in a dentry_cache. For instance, the dentry_cache would contain entries for /, /usr, /usr/ast, etc. If multiple processes access the same file through the same hard link (i.e., same path), their file object will point to the same entry in this cache.

Finally, the file data structure is an in-memory representation of an open file, and is created in response to the open system call. It supports operations such as read, write, sendfile, lock, and other system calls described in the previous section.

The actual file systems implemented underneath VFS need not use the exact same abstractions and operations internally. They must however implement semantically equivalent file system operations as the ones specified with the VFS objects. The elements of the operations data structures for each of the four VFS objects are pointers to functions in the underlying file system.

The Linux Extended File System - Ext2

We next describe the most popular on-disk file system used in Linux - ext2. The first Linux release used the MINIX file system, and was limited by short filenames and 64-MB file sizes. The MINIX file system was replaced with the first extended file system, ext, which permitted both longer file names and larger file sizes. Due to its performance inefficiencies, ext was replaced by its successor, ext2, which is still in widespread use.

An ext2 Linux disk partition contains a file system with the layout illustrated in Fig. 10-31. Block 0 is not used by Linux and often contains code to boot the computer. Following block 0, the disk partition is divided into groups of blocks, without regard to where the disk cylinder boundaries fall. Each group is organized as follows.

The first block is the superblock. It contains information about the layout of
the file system, including the number of i-nodes, the number of disk blocks, and the start of the list of free disk blocks (typically a few hundred entries). Next comes the group descriptor, which contains information about the location of the bitmaps, the number of free blocks and i-nodes in the group and the number of directories in the group. This information is important since ext2 attempts to spread directories evenly over the disk.

![Disk layout of the Linux ext2 file system.](image)

Figure 10-31. Disk layout of the Linux ext2 file system.

Two bitmaps keep track of the free blocks and free i-nodes, respectively, a choice inherited from the MINIX 1 file system (and in contrast to most UNIX file systems, which use a free list). Each map is one block long. With a 1-KB block, this design limits a block group to 8192 blocks and 8192 i-nodes. The former is a real restriction but the latter is not in practice.

Following the superblock are the i-nodes themselves. They are numbered from 1 up to some maximum. Each i-node is 128 bytes long and describes exactly one file. An i-node contains accounting information (including all the information returned by `stat`, which simply takes it from the i-node), as well as enough information to locate all the disk blocks that hold the file’s data.

Following the i-nodes are the data blocks. All the files and directories are stored here. If a file or directory consists of more than one block, the blocks need not be contiguous on the disk. In fact, the blocks of a large file are likely to be spread all over the disk.

I-nodes corresponding to directories are dispersed throughout the disk block groups. Ext2 attempts to collocate ordinary files in the same block group as the parent directory, and data files in the same block as the original file i-node, provided that there is sufficient space. This idea was taken from the Berkeley Fast File System (McKusick et al., 1984). The bitmaps are used to make quick decisions regarding where to allocate new file system data. When new file blocks are allocated, ext2 also preallocates a number (eight) of additional blocks for that file, so as to minimize the file fragmentation due to future write operations. This scheme balances the file system load across the entire disk. It also performs well due to its tendencies for collocation and reduced fragmentation.

To access a file, it must first use one of the Linux system calls, such as `open`, which requires the file’s pathname. The pathname is parsed to extract individual
directories. If a relative path is specified, the lookup starts from the process’ current directory, otherwise it starts from the root directory. In either case, the i-node for the first directory can easily be located: there is a pointer to it in the process descriptor, or, in the case of a root directory, it is typically stored in a predetermined block on disk.

The directory file allows file names up to 255 characters and is illustrated in Fig. 10-32. Each directory consists of some integral number of disk blocks so that directories can be written atomically to the disk. Within a directory, entries for files and directories are in unsorted order, with each entry directly following the one before it. Entries may not span disk blocks, so often there are some number of unused bytes at the end of each disk block.

Each directory entry in Fig. 10-32 consists of four fixed-length fields and one variable-length field. The first field is the i-node number, 19 for the file colossal, 42 for the file voluminous, and 88 for the directory bigdir. Next comes a field rec_len, telling how big the entry is (in bytes), possibly including some padding after the name. This field is needed to find the next entry for the case that the file name is padded by an unknown length. That is the meaning of the arrow in Fig. 10-32. Then comes the type field: file, directory, etc. The last fixed field is the length of the actual file name in bytes, 8, 10, and 6 in this example. Finally, comes the file name itself, terminated by a 0 byte and padded out to a 32-bit boundary. Additional padding may follow that.

In Fig. 10-32(b) we see the same directory after the entry for voluminous has been removed. All that is done is increase the size of the total entry field for colossal, turning the former field for voluminous into padding for the first entry.
This padding can be used for a subsequent entry, of course.

Since directories are searched linearly, it can take a long time to find an entry at the end of a large directory. Therefore, the system maintains a cache of recently accessed directories. This cache is searched using the name of the file, and if a hit occurs, the costly linear search is avoided. A *dentry* object is entered in the dentry cache for each of the path components, and, through its i-node, the directory is searched for the subsequent path element entry, until the actual file i-node is reached.

For instance, to look up a file specified with an absolute path name such as `/usr/ast/file` the following steps are required. First, the system locates the root directory, which generally uses i-node 2, especially when i-node 1 is reserved for bad block handling. It places an entry in the dentry cache for future lookups of the root directory. Then it looks up the string “usr” in the root directory, to get the i-node number of the `/usr` directory, which is also entered in the dentry cache. This i-node is then fetched, and the disk blocks are extracted from it, so the `/usr` directory can be read and searched for the string “ast”. Once this entry is found, the i-node number for the `/usr/ast` directory can be taken from it. Armed with the i-node number of the `/usr/ast` directory, this i-node can be read and the directory blocks located. Finally, “file” is looked up and its i-node number found. Thus the use of a relative path name is not only more convenient for the user, but it also saves a substantial amount of work for the system.

If the file is present, the system extracts the i-node number, and uses this as an index into the i-node table (on disk) to locate the corresponding i-node and bring it into memory. The i-node is put in the *i-node table*, a kernel data structure that holds all the i-nodes for currently open files and directories. The format of the i-node entries, as a bare minimum, must contain all the fields returned by the *stat* system call so as to make *stat* work (see Fig. 10-28). In Fig. 10-33 we show some of the fields included in the i-node structure supported by the Linux file system layer. The actual i-node structure contains many more fields, since the same structure is also used to represent directories, devices, and other special files. The i-node structure also contains fields reserved for future use. History has shown that unused bits do not remain that way for long.

Let us now see how the system reads a file. Remember that a typical call to the library procedure for invoking the *read* system call looks like this:

```
n = read(fd, buffer, nbytes);
```

When the kernel gets control, all it has to start with are these three parameters, and the information in its internal tables relating to the user. One of the items in the internal tables is the file descriptor array. It is indexed by a file descriptor and contains one entry for each open file (up to the maximum number, usually defaults to 32).

The idea is to start with this file descriptor and end up with the corresponding
i-node. Let us consider one possible design: just put a pointer to the i-node in the file descriptor table. Although simple, unfortunately, this method does not work. The problem is as follows. Associated with every file descriptor is a file position that tells at which byte the next read (or write) will start. Where should it go? One possibility is to put it in the i-node table. However, this approach fails if two or more unrelated processes happen to open the same file at the same time because each one has its own file position.

A second possibility is to put the file position in the file descriptor table. In that way, every process that opens a file gets its own private file position. Unfortunately, this scheme fails too, but the reasoning is more subtle and has to do with the nature of file sharing in Linux. Consider a shell script, s, consisting of two commands, p1 and p2, to be run in order. If the shell script is called by the command line

\[
\text{s >x}
\]

it is expected that p1 will write its output to x, and then p2 will write its output to x also, starting at the place where p1 stopped.

When the shell forks off p1, x is initially empty, so p1 just starts writing at file position 0. However, when p1 finishes, some mechanism is needed to make sure that the initial file position that p2 sees is not 0 (which it would be if the file position were kept in the file descriptor table), but the value p1 ended with.

The way this is achieved is shown in Fig. 10-34. The trick is to introduce a new table, the open file description table between the file descriptor table and the i-node table, and put the file position (and read/write bit) there. In this figure, the parent is the shell and the child is first p1 and later p2. When the shell forks off p1, its user structure (including the file descriptor table) is an exact copy of the shell’s, so both of them point to the same open file description table entry. When

<table>
<thead>
<tr>
<th>Field</th>
<th>Bytes</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Mode</td>
<td>2</td>
<td>File type, protection bits, setuid, setgid bits</td>
</tr>
<tr>
<td>Nlinks</td>
<td>2</td>
<td>Number of directory entries pointing to this i-node</td>
</tr>
<tr>
<td>Uid</td>
<td>2</td>
<td>UID of the file owner</td>
</tr>
<tr>
<td>Gid</td>
<td>2</td>
<td>GID of the file owner</td>
</tr>
<tr>
<td>Size</td>
<td>4</td>
<td>File size in bytes</td>
</tr>
<tr>
<td>Addr</td>
<td>60</td>
<td>Address of first 12 disk blocks, then 3 indirect blocks</td>
</tr>
<tr>
<td>Gen</td>
<td>1</td>
<td>Generation number (incremented every time i-node is reused)</td>
</tr>
<tr>
<td>Atime</td>
<td>4</td>
<td>Time the file was last accessed</td>
</tr>
<tr>
<td>Mtime</td>
<td>4</td>
<td>Time the file was last modified</td>
</tr>
<tr>
<td>Ctime</td>
<td>4</td>
<td>Time the i-node was last changed (except the other times)</td>
</tr>
</tbody>
</table>

Figure 10-33. Some fields in the i-node structure in Linux
After the shell finishes, the shell’s file descriptor is still pointing to the open file description containing $p1$’s file position. When the shell now forks off $p2$, the new child automatically inherits the file position, without either it or the shell even having to know what that position is.

---

**Figure 10-34.** The relation between the file descriptor table, the open file description table, and the i-node table.

However, if an unrelated process opens the file, it gets its own open file description entry, with its own file position, which is precisely what is needed. Thus the whole point of the open file description table is to allow a parent and child to share a file position, but to provide unrelated processes with their own values.

Getting back to the problem of doing the read, we have now shown how the file position and i-node are located. The i-node contains the disk addresses of the first 12 blocks of the file. If the file position falls in the first 12 blocks, the block is read and the data are copied to the user. For files longer than 12 blocks, a field in the i-node contains the disk address of a single indirect block, as shown in Fig. 10-34. This block contains the disk addresses of more disk blocks. For example, if a block is 1 KB and a disk address is 4 bytes, the single indirect block can...
Beyond that, a double indirect block is used. It contains the addresses of 256 single indirect blocks, each of which holds the addresses of 256 data blocks. This mechanism is sufficient to handle files up to $10^{22}$ blocks (67,119,104 bytes). If even this is not enough, the i-node has space for a triple indirect block. Its pointers point to many double indirect blocks. This addressing scheme can handle file sizes of $2^{24}$ 1 KB blocks (16 GB). For 8 KB block sizes, the addressing scheme can support file sizes up to 64 TB.

The Linux Ext3 File System

In order to prevent data loss after system crashes and power failures, the ext2 file system would have to write out each data block to disk as soon as it was created. The latency incurred during the required disk head seek operation would be so high that the performance would be intolerable. Therefore, writes are delayed, and changes may not be committed to disk for up to 30 sec, which is a very long time interval in the context of modern computer hardware.

To improve the robustness of the file system, Linux relies on journaling file systems. Ext3, a follow-on of the ext2 file system, is an example of a journaling file system.

The basic idea behind this type of file systems is to maintain a journal, which describes all file system operations in a sequential order. By sequentially writing out and changes to the file system data or metadata (i-nodes, superblock, etc.), the operations do not suffer from the overheads of disk head movement during random disk accesses. Eventually, the changes will be written out, committed, to the appropriate disk location, and the corresponding journal entries can be discarded. If a system crash or power failure occurs before the changes are committed, during restart, the system will detect that the file system was not unmounted properly, will traverse the journal, and apply the file system changes described in the journal log.

Ext3 is designed to be highly compatible with ext2, and in fact, all core data structures and disk layout are the same in both systems. Furthermore, a file system which has been unmounted as an ext2 system, can be subsequently mounted as an ext3 system and offer the journaling capability.

The journal is a file used as a circular buffer. It may be stored on the same or separate device from the main file system. Since the journal operations are not "journalled" themselves, these are not handled by the same ext3 file system. Instead, a separate JBD (Journaling Block Device) is used to perform the journal read/write operations.

JBD supports three main data structures: log record, atomic operation handle, and transaction. A log record describes a low level file system operation, typically resulting in changes within a block. Since a system call such as write includes changes at multiple places - i-nodes, existing file blocks, new file blocks,
list of free blocks, etc., related log records are grouped in atomic operations. Ext3 notifies JBD of the start and end of a system call processing, so that JBD can ensure that either all log records in an atomic operation are applied, or none of them. Finally, primarily for efficiency reasons, JBD treats collections of atomic operations as transactions. Log records are stored consecutively within a transaction. JBD will allow portions of the journal file to be discarded only after all log records belonging to a transaction are safely committed to disk.

Since writing out a log entry for each disk change may be costly, ext3 may be configured to keep a journal of all disk changes, or only of changes related to the file system metadata (the i-nodes, superblocks, bitmaps, and so on). Journaling metadata only introduces fewer system overheads and results in better performance, however does not make any guarantees against corruption of file data. Several other journaling file systems maintain logs of only metadata operations (e.g., SGI’s XFS).

The /proc File System

Another Linux file system is the /proc (process) file system, an idea originally devised in the 8th edition of UNIX from Bell Labs and later copied in 4.4BSD and System V. However, Linux extends the idea in several ways. The basic concept is that for every process in the system, a directory is created in /proc. The name of the directory is the process PID expressed as a decimal number. For example, /proc/619 is the directory corresponding to the process with PID 619. In this directory are files that appear to contain information about the process, such as its command line, environment strings, and signal masks. In fact, these files do not exist on the disk. When they are read, the system retrieves the information from the actual process as needed and returns it in a standard format.

Many of the Linux extensions relate to other files and directories located in /proc. They contain a wide variety of information about the CPU, disk partitions, devices, interrupt vectors, kernel counters, file systems, loaded modules, and much more. Unprivileged user programs may read much of this information to learn about system behavior in a safe way. Some of these files may be written to in order to change system parameters.

10.6.4 NFS: The Network File System

Networking has played a major role in Linux, and UNIX in general, right from the beginning (the first UNIX network was built to move new kernels from the PDP-11/70 to the Interdata 8/32 during the port to the later). In this section we will examine Sun Microsystems’s NFS (Network File System), which is used on all modern Linux systems to join the file systems on separate computers into one logical whole. Currently, the most dominant NSF implementation is version 3, introduced in 1994 (Pawloski et al, 1994). NSFv4 was introduced in 2000 and
provides several enhancements over the previous NFS architecture. Three aspects of NFS are of interest: the architecture, the protocol, and the implementation. We will now examine these in turn, first in the context of the simpler NFS version 3, then we will briefly discuss the enhancements included in v4.

**NFS Architecture**

The basic idea behind NFS is to allow an arbitrary collection of clients and servers to share a common file system. In many cases, all the clients and servers are on the same LAN, but this is not required. It is also possible to run NFS over a wide area network if the server is far from the client. For simplicity we will speak of clients and servers as though they were on distinct machines, but in fact, NFS allows every machine to be both a client and a server at the same time.

Each NFS server exports one or more of its directories for access by remote clients. When a directory is made available, so are all of its subdirectories, so in fact, entire directory trees are normally exported as a unit. The list of directories a server exports is maintained in a file, often `/etc/exports`, so these directories can be exported automatically whenever the server is booted. Clients access exported directories by mounting them. When a client mounts a (remote) directory, it becomes part of its directory hierarchy, as shown in Fig. 10-35.

![Figure 10-35. Examples of remote mounted file systems. Directories are shown as squares and files are shown as circles.](image-url)
In this example, client 1 has mounted the `bin` directory of server 1 on its own `bin` directory, so it can now refer to the shell as `/bin/sh` and get the shell on server 1. Diskless workstations often have only a skeleton file system (in RAM) and get all their files from remote servers like this. Similarly, client 1 has mounted server 2’s directory `/projects` on its directory `/usr/ast/work` so it can now access file `a` as `/usr/ast/work/proj1/a`. Finally, client 2 has also mounted the `projects` directory and can also access file `a`, only as `/mnt/proj1/a`. As seen here, the same file can have different names on different clients due to its being mounted in a different place in the respective trees. The mount point is entirely local to the clients; the server does not know where it is mounted on any of its clients.

**NFS Protocols**

Since one of the goals of NFS is to support a heterogeneous system, with clients and servers possibly running different operating systems on different hardware, it is essential that the interface between the clients and servers be well defined. Only then is it possible for anyone to be able to write a new client implementation and expect it to work correctly with existing servers, and vice versa.

NFS accomplishes this goal by defining two client-server protocols. A *protocol* is a set of requests sent by clients to servers, along with the corresponding replies sent by the servers back to the clients.

The first NFS protocol handles mounting. A client can send a path name to a server and request permission to mount that directory somewhere in its directory hierarchy. The place where it is to be mounted is not contained in the message, as the server does not care where it is to be mounted. If the path name is legal and the directory specified has been exported, the server returns a *file handle* to the client. The file handle contains fields uniquely identifying the file system type, the disk, the i-node number of the directory, and security information. Subsequent calls to read and write files in the mounted directory or any of its subdirectories use the file handle.

When Linux boots, it runs the `/etc/rc` shell script before going multiuser. Commands to mount remote file systems can be placed in this script, thus automatically mounting the necessary remote file systems before allowing any logins. Alternatively, most versions of Linux also support *automounting*. This feature allows a set of remote directories to be associated with a local directory. None of these remote directories are mounted (or their servers even contacted) when the client is booted. Instead, the first time a remote file is opened, the operating system sends a message to each of the servers. The first one to reply wins, and its directory is mounted.

Automounting has two principal advantages over static mounting via the `/etc/rc` file. First, if one of the NFS servers named in `/etc/rc` happens to be down, it is impossible to bring the client up, at least not without some difficulty, delay, and quite a few error messages. If the user does not even need that server at the
moment, all that work is wasted. Second, by allowing the client to try a set of servers in parallel, a degree of fault tolerance can be achieved (because only one of them needs to be up), and the performance can be improved (by choosing the first one to reply—presumably the least heavily loaded).

On the other hand, it is tacitly assumed that all the file systems specified as alternatives for the automount are identical. Since NFS provides no support for file or directory replication, it is up to the user to arrange for all the file systems to be the same. Consequently, automounting is most often used for read-only file systems containing system binaries and other files that rarely change.

The second NFS protocol is for directory and file access. Clients can send messages to servers to manipulate directories and read and write files. Also, they can also access file attributes, such as file mode, size, and time of last modification. Most Linux system calls are supported by NFS, with the perhaps surprising exception of `open` and `close`.

The omission of `open` and `close` is not an accident. It is fully intentional. It is not necessary to open a file before reading it, nor to close it when done. Instead, to read a file, a client sends the server a `lookup` message containing the file name, with a request to look it up and return a file handle, which is a structure that identifies the file (i.e., contains a file system identifier and i-node number, among other data). Unlike an `open` call, this `lookup` operation does not copy any information into internal system tables. The `read` call contains the file handle of the file to read, the offset in the file to begin reading, and the number of bytes desired. Each such message is self-contained. The advantage of this scheme is that the server does not have to remember anything about open connections in between calls to it. Thus if a server crashes and then recovers, no information about open files is lost, because there is none. A server like this that does not maintain state information about open files is said to be stateless.

Unfortunately, the NFS method makes it difficult to achieve the exact Linux file semantics. For example, in Linux a file can be opened and locked so that other processes cannot access it. When the file is closed, the locks are released. In a stateless server such as NFS, locks cannot be associated with open files, because the server does not know which files are open. NFS therefore needs a separate, additional mechanism to handle locking.

NFS uses the standard UNIX protection mechanism, with the `rwx` bits for the owner, group, and others (mentioned in Chap. 1 and discussed in detail below). Originally, each request message simply contained the user and group IDs of the caller, which the NFS server used to validate the access. In effect, it trusted the clients not to cheat. Several years’ experience abundantly demonstrated that such an assumption was—how shall we put it?—naïve. Currently, public key cryptography can be used to establish a secure key for validating the client and server on each request and reply. When this option is enabled, a malicious client cannot impersonate another client because it does not know that client’s secret key.
NFS Implementation

Although the implementation of the client and server code is independent of the NFS protocols, most Linux systems use a three-layer implementation similar to that of Fig. 10-36. The top layer is the system call layer. This handles calls like open, read, and close. After parsing the call and checking the parameters, it invokes the second layer, the Virtual File System (VFS) layer.

The task of the VFS layer is to maintain a table with one entry for each open file. The VFS layer has an entry, a **virtual i-node**, or **v-node**, for every open file. V-nodes are used to tell whether the file is local or remote. For remote files, enough information is provided to be able to access them. For local files, the file system and i-node are recorded because modern Linux systems can support multiple file systems (e.g., ext2fs, /proc, FAT, etc.). Although VFS was invented to support NFS, most modern Linux systems now support it as an integral part of the operating system, even if NFS is not used.

To see how v-nodes are used, let us trace a sequence of mount, open, and read system calls. To mount a remote file system, the system administrator (or /etc/rc) calls the `mount` program specifying the remote directory, the local directory on which it is to be mounted, and other information. The `mount` program parses the name of the remote directory to be mounted and discovers the name of

---

**Figure 10-36.** The NFS layer structure
the NFS server on which the remote directory is located. It then contacts that
machine asking for a file handle for the remote directory. If the directory exists
and is available for remote mounting, the server returns a file handle for the direc-
tory. Finally, it makes a mount system call, passing the handle to the kernel.

The kernel then constructs a v-node for the remote directory and asks the NFS
client code in Fig. 10-36 to create an r-node (remote i-node) in its internal tables
to hold the file handle. The v-node points to the r-node. Each v-node in the VFS
layer will ultimately contain either a pointer to an r-node in the NFS client code,
or a pointer to an i-node in one of the local file systems (shown as dashed lines in
Fig. 10-36). Thus from the v-node it is possible to see if a file or directory is local
or remote. If it is local, the correct file system and i-node can be located. If it is
remote, the remote host and file handle can be located.

When a remote file is opened on the client, at some point during the parsing
of the path name, the kernel hits the directory on which the remote file system is
mounted. It sees that this directory is remote in the directory’s v-node finds
the pointer to the r-node. It then asks the NFS client code to open the file. The
NFS client code looks up the remaining portion of the path name on the remote
server associated with the mounted directory and gets back a file handle for it. It
makes an r-node for the remote file in its tables and reports back to the VFS layer,
which puts in its tables a v-node for the file that points to the r-node. Again here
we see that every open file or directory has a v-node that points to either an r-node
or an i-node.

The caller is given a file descriptor for the remote file. This file descriptor is
mapped onto the v-node by tables in the VFS layer. Note that no table entries are
made on the server side. Although the server is prepared to provide file handles
upon request, it does not keep track of which files happen to have file handles out-
standing and which do not. When a file handle is sent to it for file access, it
checks the handle, and if it is valid, uses it. Validation can include verifying an
authentication key contained in the RPC headers, if security is enabled.

When the file descriptor is used in a subsequent system call, for example,
read, the VFS layer locates the corresponding v-node, and from that determines
whether it is local or remote and also which i-node or r-node describes it. It then
sends a message to the server containing the handle, the file offset (which is main-
tained on the client side, not the server side), and the byte count. For efficiency
reasons, transfers between client and server are done in large chunks, normally
8192 bytes, even if fewer bytes are requested.

When the request message arrives at the server, it is passed to the VFS layer
there, which determines which local file system holds the requested file. The VFS
layer then makes a call to that local file system to read and return the bytes. These
data are then passed back to the client. After the client’s VFS layer has gotten the
8-KB chunk it asked for, it automatically issues a request for the next chunk, so it
will have it should it be needed shortly. This feature, known as read ahead,
improves performance considerably.
For writes an analogous path is followed from client to server. Also, transfers are done in 8-KB chunks here too. If a write system call supplies fewer than 8 KB bytes of data, the data are just accumulated locally. Only when the entire 8 KB chunk is full is it sent to the server. However, when a file is closed, all of its data are sent to the server immediately.

Another technique used to improve performance is caching, as in ordinary UX. Servers cache data to avoid disk accesses, but this is invisible to the clients. Clients maintain two caches, one for file attributes (i-nodes) and one for file data. When either an i-node or a file block is needed, a check is made to see if it can be satisfied out of the cache. If so, network traffic can be avoided.

While client caching helps performance enormously, it also introduces some nasty problems. Suppose that two clients are both caching the same file block and that one of them modifies it. When the other one reads the block, it gets the old (stale) value. The cache is not coherent.

Given the potential severity of this problem, the NFS implementation does several things to mitigate it. For one, associated with each cache block is a timer. When the timer expires, the entry is discarded. Normally, the timer is 3 sec for data blocks and 30 sec for directory blocks. Doing this reduces the risk somewhat. In addition, whenever a cached file is opened, a message is sent to the server to find out when the file was last modified. If the last modification occurred after the local copy was cached, the cache copy is discarded and the new copy fetched from the server. Finally, once every 30 sec a cache timer expires, and all the dirty (i.e., modified) blocks in the cache are sent to the server. While not perfect, these patches make the system highly usable in most practical circumstances.

**NFS Version 4**

Version 4 of the Network File System was designed to simplify certain operations from its predecessor. In contrast to to NSFv3 which is described above, NFSv4 is a stateful file system. This permits open operations to be invoked on remote files, since the remote NFS server will maintain all file system related structures, including the file pointer. Read operations then need not include absolute read ranges, but can be incrementally applied from the previous file pointer position. This results in both, use of shorter messages, and also in the ability to bundle multiple NFSv3 operations in one network transaction.

The stateful nature of NFSv4 makes it easy to also integrate the variety of NFSv3 protocols described earlier in this section into one coherent protocol. There is no need to support separate protocols for mounting, caching, locking, or secure operations. NFSv4 also works better with both Linux (and UNIX in general) and Windows file system semantics.
10.7 SECURITY IN LINUX

Linux, as a clone of MINIX and UNIX, has been a multiuser system almost from the beginning. This history means that security and control of information was built in very early on. In the following sections, we will look at some of the security aspects of Linux.

10.7.1 Fundamental Concepts

The user community for a Linux system consists of some number of registered users, each of whom has a unique **UID (User ID)**. A UID is an integer between 0 and 65,535. Files (but also processes, and other resources) are marked with the UID of their owner. By default, the owner of a file is the person who created the file, although there is a way to change ownership.

Users can be organized into groups, which are also numbered with 16-bit integers called **GID (Group ID)**s. Assigning users to groups is done manually, by the system administrator, and consists of making entries in a system database telling which user is in which group. A user could be in one or more groups at the same time. For simplicity, we will not discuss this feature further.

The basic security mechanism in Linux is simple. Each process carries the UID and GID of its owner. When a file is created, it gets the UID and GID of the creating process. The file also gets a set of permissions determined by the creating process. These permissions specify what access the owner, the other members of the owner’s group, and the rest of the users have to the file. For each of these three categories, potential accesses are read, write, and execute, designated by the letters *r*, *w*, and *x*, respectively. The ability to execute a file makes sense only if that file is an executable binary program, of course. An attempt to execute a file that has execute permission but which is not executable (i.e., does not start with a valid header) will fail with an error. Since there are three categories of users and 3 bits per category, 9 bits are sufficient to represent the access rights. Some examples of these 9-bit numbers and their meanings are given in Fig. 10-37.

The first two entries in Fig. 10-37 are clear, allowing the owner and the owner’s group full access, respectively. The next one allows the owner’s group to read the file but not to change it, and prevents outsiders from any access. The fourth entry is common for a data file the owner wants to make public. Similarly, the fifth entry is the usual one for a publicly available program. The sixth entry denies all access to all users. This mode is sometimes used for dummy files used for mutual exclusion because an attempt to create such a file will fail if one already exists. Thus if multiple processes simultaneously attempt to create such a file as a lock, only one of them will succeed. The last example is strange indeed, since it gives the rest of the world more access than the owner. However, its existence follows from the protection rules. Fortunately, there is a way for the owner to subsequently change the protection mode, even without having any
Binary Symbolic Allowed file accesses
111000000 rwx------- Owner can read, write, and execute
111111000 rwxrwx------- Owner and group can read, write, and execute
110100000 rw------- Owner can read and write; group can read
110100100 rw------- Owner can read and write; all others can read
111101101 rwxr--x------ Owner can do everything, rest can read and execute
000000000 -------- Nobody has any access
000000111 -------- Only outsiders have access (strange, but legal)

<table>
<thead>
<tr>
<th>Binary</th>
<th>Symbolic</th>
<th>Allowed file accesses</th>
</tr>
</thead>
<tbody>
<tr>
<td>111000000</td>
<td>rwx-------</td>
<td>Owner can read, write, and execute</td>
</tr>
<tr>
<td>111111000</td>
<td>rwxrwx-----</td>
<td>Owner and group can read, write, and execute</td>
</tr>
<tr>
<td>110100000</td>
<td>rw-------</td>
<td>Owner can read and write; group can read</td>
</tr>
<tr>
<td>110100100</td>
<td>rw-------</td>
<td>Owner can read and write; all others can read</td>
</tr>
<tr>
<td>111101101</td>
<td>rwxr--x----</td>
<td>Owner can do everything, rest can read and execute</td>
</tr>
<tr>
<td>000000000</td>
<td>--------</td>
<td>Nobody has any access</td>
</tr>
<tr>
<td>000000111</td>
<td>--------</td>
<td>Only outsiders have access (strange, but legal)</td>
</tr>
</tbody>
</table>

Figure 10-37. Some example file protection modes.

access to the file itself.

The user with UID 0 is special and is called the superuser (or root). The superuser has the power to read and write all files in the system, no matter who owns them and no matter how they are protected. Processes with UID 0 also have the ability to make a small number of protected system calls denied to ordinary users. Normally, only the system administrator knows the superuser’s password, although many undergraduates consider it a great sport to try to look for security flaws in the system so they can log in as the superuser without knowing the password. Management tends to frown on such activity.

Directories are files and have the same protection modes that ordinary files do except that the x bits refer to search permission instead of execute permission. Thus a directory with mode rwxr-xr-x allows its owner to read, modify, and search the directory, but allows others only to read and search it, but not add or remove files from it.

Special files corresponding to the I/O devices have the same protection bits as regular files. This mechanism can be used to limit access to I/O devices. For example, the printer special file, /dev/lp, could be owned by root or by a special user, daemon, and have mode rw------- to keep everyone else from directly accessing the printer. After all, if everyone could just print at will, chaos would result.

Of course, having /dev/lp owned by, say, daemon with protection mode rw------- means that nobody else can use the printer. While this would save many innocent trees from an early death, sometimes users do have a legitimate need to print something. In fact, there is a more general problem of allowing controlled access to all I/O devices and other system resources.

This problem was solved by adding a new protection bit, the SETUID bit to the 9 protection bits discussed above. When a program with the SETUID bit on is executed, the effective UID for that process becomes the UID of the executable file’s owner instead of the UID of the user who invoked it. When a process attempts to open a file, it is the effective UID that is checked, not the underlying...
CASE STUDY 1: Linux CHAP. 10

real UID. By making the program that accesses the printer be owned by daemon
but with the SETUID bit on, any user could execute it, and have the power of dae-
mon (e.g., access to /dev/lp) but only to run that program (which might queue
print jobs for printing in an orderly fashion).

Many sensitive Linux programs are owned by the root but with the SETUID
bit on. For example, the program that allows users to change their passwords,
passwd, needs to write in the password file. Making the password file publicly
writable would not be a good idea. Instead, there is a program that is owned by
the root and which has the SETUID bit on. Although the program has complete
access to the password file, it will only change the caller’s password and not per-
mit any other access to the password file.

In addition to the SETUID bit there is also a SETGID bit that works analo-
gously, temporarily giving the user the effective GID of the program. In practice,
this bit is rarely used, however.

10.7.2 Security System Calls in Linux

There are only a small number of system calls relating to security. The most
important ones are listed in Fig. 10-38. The most heavily used security system
call is chmod. It is used to change the protection mode. For example,

s = chmod("/usr/ast/newgame", 0755);

sets newgame to rwxr−xr−x so that everyone can run it (note that 0755 is an octal
constant, which is convenient since the protection bits come in groups of 3 bits).
Only the owner of a file and the superuser can change its protection bits.

<table>
<thead>
<tr>
<th>System call</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>s = chmod(path, mode)</td>
<td>Change a file’s protection mode</td>
</tr>
<tr>
<td>s = access(path, mode)</td>
<td>Check access using the real UID and GID</td>
</tr>
<tr>
<td>uid = getuid( )</td>
<td>Get the real UID</td>
</tr>
<tr>
<td>uid = geteuid( )</td>
<td>Get the effective UID</td>
</tr>
<tr>
<td>gid = getgid( )</td>
<td>Get the real GID</td>
</tr>
<tr>
<td>gid = getegid( )</td>
<td>Get the effective GID</td>
</tr>
<tr>
<td>s = chown(path, owner, group)</td>
<td>Change owner and group</td>
</tr>
<tr>
<td>s = setuid(uid)</td>
<td>Set the UID</td>
</tr>
<tr>
<td>s = setgid(gid)</td>
<td>Set the GID</td>
</tr>
</tbody>
</table>

Figure 10-38. Some system calls relating to security. The return code s is −1 if
an error has occurred; uid and gid are the UID and GID, respectively. The
parameters should be self explanatory.

The access call tests to see if a particular access would be allowed using the
real UID and GID. This system call is needed to avoid security breaches in programs that are SETUID and owned by the root. Such a program can do anything, and it is sometimes needed for the program to figure out if the user is allowed to perform a certain access. The program cannot just try it, because the access will always succeed. With the `access` call the program can find out if the access is allowed by the real UID and real GID.

The next four system calls return the real and effective UIDs and GIDs. The last three are only allowed for the superuser. They change a file’s owner, and a process’ UID and GID.

### 10.7.3 Implementation of Security in Linux

When a user logs in, the login program, `login` (which is SETUID root) asks for a login name and a password. It hashes the password and then looks in the password file, `/etc/passwd`, to see if the hash matches the one there (networked systems work slightly differently). The reason for using hashes is to prevent the password from being stored in unencrypted form anywhere in the system. If the password is correct, the login program looks in `/etc/passwd` to see the name of the user’s preferred shell, possibly `bash`, but possibly some other shell such as `csh` or `ksh`. The login program then uses `setuid` and `setgid` to give itself the user’s UID and GID (remember, it started out as SETUID root). Then it opens the keyboard for standard input (file descriptor 0), the screen for standard output (file descriptor 1), and the screen for standard error (file descriptor 2). Finally, it executes the preferred shell, thus terminating itself.

At this point the preferred shell is running with the correct UID and GID and standard input, output, and error all set to their default devices. All processes that it forks off (i.e., commands typed by the user), automatically inherit the shell’s UID and GID, so they also will have the correct owner and group. All files they create also get these values.

When any process attempts to open a file, the system first checks the protection bits in the file’s i-node against the caller’s effective UID and effective GID to see if the access is permitted. If so, the file is opened and a file descriptor returned. If not, the file is not opened and −1 is returned. No checks are made on subsequent `read` or `write` calls. As a consequence, if the protection mode changes after a file is already open, the new mode will not affect processes that already have the file open.

The Linux security model and its implementation are essentially the same as in most other traditional UNIX systems.
10.8 SUMMARY

Linux began its life as an open-source, full production UNIX clone, and is now used on machines ranging from notebook computers to supercomputers. Three main interfaces to it exist: the shell, the C library, and the system calls themselves. In addition, a graphical user interface is often used to simplify user interaction with the system. The shell allows users to type commands for execution. These may be simple commands, pipelines, or more complex structures. Input and output may be redirected. The C library contains the system calls and also many enhanced calls, such as `printf` for writing formatted output to files. The actual system call interface is architecture dependent, and on x86 platforms consists of approximately 250 calls, each of which does what is needed and no more.

The key concepts in Linux include the process, the memory model, I/O, and the file system. Processes may fork off subprocesses, leading to a tree of processes. Process management in Linux is different compared to other UNIX systems in that Linux views each execution entity—a single threaded process, or each thread within a multithreaded process or the kernel—as a distinguishable task. A process, or a single task in general, is then represented via two key components, the task structure and the additional information describing the user address space. The former is always in memory, but the latter data can be paged in and out of memory. Process creation is done by duplicating the process task structure, and then setting the memory image information to point to the parents’ memory image. Actual copies of the memory image pages are created only if sharing is not allowed and a memory modification is required. This mechanism is called copy on write. Scheduling is done using a priority-based algorithm that favors interactive processes.

The memory model consists of three segments per process: text, data, and stack. Memory management is done by paging. An in-memory map keeps track of the state of each page, and the page daemon uses a modified dual-hand clock algorithm to keep enough free pages around.

I/O devices are accessed using special files, each of which has a major device number and a minor device number. Block device I/O uses a the main memory to cache disk blocks and reduce the number of disk accesses. Character I/O can be done in raw mode, or character streams can be modified via line disciplines. Networking devices are treated somewhat differently, by associating entire network protocol modules to process the network packets stream to and from the user process.

The file system is hierarchical with files and directories. All disks are mounted into a single directory tree starting at a unique root. Individual files can be linked into a directory from elsewhere in the file system. To use a file, it must be first opened, which yields a file descriptor for use in reading and writing the file. Internally, the file system uses three main tables: the file descriptor table, the open file description table, and the i-node table. The i-node table is the most...
important of these, containing all the administrative information about a file and
the location of its blocks. Directories and devices are also represented as files,
along with other special files.

Protection is based on controlling read, write, and execute access for the
owner, group, and others. For directories, the execute bit is interpreted to mean
search permission.

PROBLEMS

1. When the kernel catches system call, how does it know which system call it is sup-
posed to carry out?

2. A directory contains the following files:
   
   | aardvark  | feret  | koala  | porpoise | unicorn |
   | bonefish  | hyena  | marmot | quacker  | vicuna  |
   | capybara  | ibex   | nuthatch | seahorse | yak      |
   | dingo     | jellyfish | ostrich | tuna      | zebu    |

   Which files will be listed by the command
   
   `ls [abc]*e*`?

3. What does the following Linux shell pipeline do?
   
   `grep nd xyz | wc -l`

4. Write a Linux pipeline that prints the eighth line of file z on standard output.

5. Why does Linux distinguish between standard output and standard error, when both
default to the terminal?

6. A user at a terminal types the following commands:
   
   `a | b | c &
   d | e | f &`

   After the shell has processed them, how many new processes are running?

7. When the Linux shell starts up a process, it puts copies of its environment variables,
such as `HOME`, on the process’ stack, so the process can find out what its home direc-
tory is. If this process should later fork, will the child automatically get these vari-
ables too?

8. About how long does it take a traditional UNIX system to fork off a child process
under the following conditions: text size = 100 KB, data size = 20 KB, stack size = 10
KB, text structure = 1 KB, user structure = 5 KB. The kernel trap and return takes 1
msec, and the machine can copy one 32-bit word every 50 nsec. Text segments are
shared, but data and stack segments are not.
9. As multi-megabyte programs became more common, the time spent executing the fork system call and copying the data and stack segments of the calling process grew proportionally. When fork is executed in Linux, the parent’s address space is not copied, as traditional fork semantics would dictate. How does Linux prevent the child from doing something that would completely change the fork semantics.

10. A non-real-time Linux process has priority levels from 100 to 139. What is the default static priority and how is the nice value used to change this?

11. Does it make sense to take away a process’ memory when it enters zombie state? Why or why not?

12. To what hardware concept is a signal closely related? Give two examples of how signals are used.

13. Why do you think the designers of Linux made it impossible for a process to send a signal to a another process that is not in its process group?

14. A system call is usually implemented using a software interrupt (trap) instruction. Could an ordinary procedure call be used as well on the Pentium hardware? If so, under what conditions and how? If not, why not?

15. In general, do you think daemons have higher priority or lower priority than interactive processes? Why?

16. When a new process is forked off, it must be assigned a unique integer as its PID. Is it sufficient to have a counter in the kernel that is incremented on each process creation, with the counter used as the new PID? Discuss your answer.

17. In every process’ entry in the task structure, the PID of the process’ parent is stored. Why?

18. What combination of the sharing flags bits used by the Linux clone command corresponds to a conventional UNIX fork call? To creating a conventional UNIX thread?

19. The Linux scheduler went through a major overhaul between the 2.4 and 2.6 kernel. The current scheduler can make scheduling decisions in O(1) time. Explain why is this so?

20. When booting Linux (or most other operating systems for that matter), the bootstrap loader in sector 0 of the disk first loads a boot program which then loads the operating system. Why is this extra step necessary? Surely it would be simpler to have the bootstrap loader in sector 0 just load the operating system directly.

21. A certain editor has 100 KB of program text, 30 KB of initialized data, and 50 KB of BSS. The initial stack is 10 KB. Suppose that three copies of this editor are started simultaneously. How much physical memory is needed (a) if shared text is used, and (b) if it is not?

22. Why are open file descriptor tables necessary in Linux?

23. In Linux, the data and stack segments are paged and swapped to a scratch copy kept on a special paging disk or partition, but the text segment uses the executable binary file instead. Why?
24. Describe a way to use mmap and signals to construct an interprocess communication mechanism.

25. A file is mapped in using the following mmap system call:
   
   ```c
   mmap(65536, 32768, READ, FLAGS, fd, 0)
   ```
   
   Pages are 8 KB. Which byte in the file is accessed by reading a byte at memory address 72,000?

26. After the system call of the previous problem has been executed, the call
   
   ```c
   munmap(65536, 8192)
   ```
   
   is carried out. Does it succeed? If so, which bytes of the file remain mapped? If not, why does it fail?

27. Can a page fault ever lead to the faulting process being terminated? If so, give an example. If not, why not?

28. Is it possible that with the buddy system of memory management it ever occurs that two adjacent blocks of free memory of the same size co-exist without being merged into one block? If so, give an example of how this can happen. If not, show that it is impossible.

29. It is stated in the text that a paging partition will perform better than a paging file. Why is this so?

30. Give two examples of the advantages of relative path names over absolute ones.

31. The following locking calls are made by a collection of processes. For each call, tell what happens. If a process fails to get a lock, it blocks.
   
   (a) A wants a shared lock on bytes 0 through 10.
   (b) B wants an exclusive lock on bytes 20 through 30.
   (c) C wants a shared lock on bytes 8 through 40.
   (d) A wants a shared lock on bytes 25 through 35.
   (e) B wants an exclusive lock on byte 8.

32. Consider the locked file of Fig. 10-26(c). Suppose that a process tries to lock bytes 10 and 11 and blocks. Then, before C releases its lock, yet another process tries to lock bytes 10 and 11, and also blocks. What kind of problems are introduced into the semantics by this situation. Propose and defend two solutions.

33. Suppose that an lseek system call seeks to a negative offset in a file. Given two possible ways of dealing with it.

34. If a Linux file has protection mode 755 (octal), what can the owner, the owner’s group, and everyone else do to the file?

35. Some tape drives have numbered blocks and the ability to overwrite a particular block in place without disturbing the blocks in front or behind it. Could such a device hold a mounted Linux file system?

36. In Fig. 10-24, both Fred and Lisa have access to the file x in their respective directories after linking. Is this access completely symmetrical in the sense anything one of
94

CASE STUDY 1: Linux

them can do with it the other one can too?

37. As we have seen, absolute path names are looked up starting at the root directory and
relative path names are looked up starting at the working directory. Suggest an effi-
cient way to implement both kinds of searches.

38. When the file /usr/ast/work/f is opened, several disk accesses are needed to read i-
node and directory blocks. Calculate the number of disk accesses required under the
assumption that the i-node for the root directory is always in memory, and all direc-
tories are one block long.

39. A Linux i-node has 12 disk addresses for data blocks, as well as the addresses of sin-
gle, double, and triple indirect blocks. If each of these holds 256 disk addresses, what
is the size of the largest file that can be handled, assuming that a disk block is 1 KB?

40. When an i-node is read in from the disk during the process of opening a file, it is put
into an i-node table in memory. This table has some fields that are not present on the
disk. One of them is a counter that keeps track of the number of times the i-node has
been opened. Why is this field needed?

41. On multi-CPU platforms, Linux maintains a runqueue per each CPU. Is this a good
idea? Explain your answer?

42. Pdflush threads can be awaken periodically to write back to disk very old pages—
older than 30 sec. Why is this necessary exist?

43. After a system crash and reboot, a recovery program is usually run. Suppose that this
program discovers that the link count in a disk i-node is 2, but only one directory entry
references the i-node. Can it fix the problem, and if so, how?

44. Make an educated guess as to which Linux system call is the fastest.

45. Is it possible to unlink a file that has never been linked? What happens?

46. Based on the information presented in this chapter, if a Linux ext2 file system were to
be put on a 1.44 Mbyte floppy disk what is the maximum amount of user file data that
could be stored on the disk? Assume that disk blocks are 1 KB.

47. In view of all the trouble that students can cause if they get to be superuser, why does
this concept exist in the first place?

48. A professor shares files with his students by placing them in a publicly accessible
directory on the CS department’s Linux system. One day he realizes that a file placed
there the previous day was left world-writable. He changes the permissions and veri-
ﬁes the file is identical to his master copy. The next day he ﬁnds the file has been
changed. How could this have happened and how could it have been prevented?

49. Linux supports a system call fsuid. Unlike setuid which grants the user all the rights
of effective id associated with a program he is running. In contrast, fsuid grants the
user who is running the program special rights only with respect to access to ﬁles.
Why is this useful?

50. Write a minimal shell that allows simple commands to be started. It should also allow
them to be started in the background.
51. Using assembly language and BIOS calls, write a program that boots itself from a floppy disk on a Pentium-class computer. The program should use BIOS calls to read the keyboard and echo the characters typed, just to demonstrate that it is running.

52. Write a dumb terminal program to connect two Linux or Linux workstations via the serial ports. Use the POSIX terminal management calls to configure the ports.

53. Write a client-server application which, on requests, transfers a large file via sockets. Reimplement the same application using shared memory. Which version do you expect to perform better? Why? Conduct performance measurements with the code you’ve written and using different file sizes. What are your observations? What do you think happens inside the Linux kernel which results in this behavior?

54. Implement a basic user-level threads library to run on top of Linux. The library API should contain function calls like: `mythreads_init`, `mythreads_create`, `mythreads_join`, `mythreads_exit`, `mythreads_yield`, `mythreads_self`, and potentially few others. Next, implement these synchronization variables to enable safe concurrent operations: `mythreads_mutex_init`, `mythreads_mutex_lock`, `mythreads_mutex_unlock`. Before starting, clearly define the API and specify the semantics of each of the calls. Next implement the user-level library with a simple, round-robin preemptive scheduler. You will also need to write one or more multithreaded applications, which use your library, in order to test it. Finally, replace the simple scheduling mechanism with another one which behaves like the Linux 2.6 O(1) scheduler described in this chapter. Compare the performance your application(s) receive when using each of the schedulers.

**SOLUTIONS TO CHAPTER 10 PROBLEMS**

1. The calling process has to put the system call number in a register or on the stack.

2. The files that will be listed are: bonefish, quacker, seahorse, and weasel.

3. It prints the number of lines of the file xyz that contain the string “nd” in them.

4. The pipeline is as follows:
   ```
   head -8 z | tail -1
   ```
   The first part selects out the first eight lines of z and passes them to tail, which just writes the last one on the screen.

5. They are separate so standard output can be redirected without affecting standard error. In a pipeline, standard output may go to another process, but standard error still writes on the terminal.

6. Each program runs in its own process so six new processes are started.

7. Yes. The child’s memory is an exact copy of the parent’s, including the stack. Thus if the environment variables were on the parent’s stack, they will be on the child’s stack too.

8. Since text segments are shared, only 36 KB has to be copied. The machine can copy 80 bytes per microsec, so 36 KB takes 0.46 msec. Add another 1 msec for getting into and out of the kernel, and the whole thing takes roughly 1.46 msec.
9. Linux relies on copy on write. It gives the child pointers to the parent’s address space, but marks the parent’s pages write-protected. When the child attempts to write into the parent’s address space, a fault occurs, and a copy of the parent’s page is created and allocated into the child’s address space.

10. The text says that the nice value is in the range -20 to +19, so the default static priority must be 120, which it is indeed. By being nice and selecting a positive nice value, a process can request to be put under lower priority.

11. Yes. It cannot run any more so the earlier its memory goes back on the free list, the better.

12. Signals are like hardware interrupts. One example is the alarm signal, which signals the process at a specific number of seconds in the future. Another is the floating-point exception signal, which indicates division by zero or some other error. Many other signals also exist.

13. Malicious users could wreak havoc with the system if they could send signals to arbitrary unrelated processes. Nothing would stop a user from writing a program consisting of a loop that sent a signal to the process with PID \( i \) for all \( i \) from 1 to the maximum PID. Many of these processes would be unprepared for the signal and would be killed by it. If you want to kill off your own processes, that is all right, but killing off your neighbor’s processes is not acceptable.

14. It would be impossible using Linux or Windows Vista, but the Pentium hardware does make this possible. What is needed is to use the segmentation features of the hardware, which are not supported by either Linux or Windows Vista. The operating system could be put in one or more global segments, with protected procedure calls to make system calls instead of traps. OS/2 works this way.

15. Generally, daemons run in the background doing things like printing and sending e-mail. Since people are not usually sitting on the edge of their chairs waiting for them to finish, they are given low priority, soaking up excess CPU time not needed by interactive processes.

16. A PID must be unique. Sooner or later the counter will wrap around and go back to 0. Then it will so upward to, for example, 15. If it just happens that process 15 was started months ago, but is still running, 15 cannot be assigned to a new process. Thus after a proposed PID is chosen using the counter, a search of the process table must be made to see if the PID is already in use.

17. When the process exits, the parent will be given the exit status of its child. The PID is needed to be able to identify the parent so the exit status can be transferred to the correct process.

18. If all of the sharing flags bits are set, the clone call starts a conventional thread. If all the bits are cleared the call is essentially a fork.

19. Each scheduling decision requires looking up a bitmap for the active array and searching for the first set bit in the array, which can be done in constant time, dequeuing a single task from the selected queue, again a constant time operation, or if the bitmap value is zero, swapping the values of the active and expired lists, again a constant time operation.
20. The program loaded from block 0 is a maximum of 512 bytes long so it cannot be very complicated. Loading the operating system requires understanding the file system layout in order to find and load the operating system. Different operating systems have very different file systems and it is asking too much to expect a 512-byte program to sort all this out. Instead, the block 0 loader just fetches another loader from a fixed location on the disk partition. This program can be much longer and system specific so it can find and load the OS.

21. With shared text, 100 KB is needed for the text. Each of the three processes needs 80 KB for its data segment and 10 KB for its stack, so the total memory needed is 370 KB. Without shared text, each program needs 190 KB, so three of them need a total of 570 KB.

22. Processes that one to share a file including the current file pointer position, can just share an open file descriptor, without having to update anything in each others private file descriptor table. At the same time, another process can access the same file through a separate open file descriptor, obtain a different file pointer and move through the file at its own will.

23. The text segment cannot change, so it never has to be paged out. If its frames are needed, they can just be abandoned. The pages can always be retrieved from the file system. The data segment must not be paged back to the executable file, because it is likely that it has changed since being brought in. Paging it back would ruin the executable file. The stack segment is not even present in the executable file.

24. Two process could map the same file into their address spaces at the same time. This gives them a way to share physical memory. Half of the shared memory could be used as a buffer from A to B and half as a buffer from B to A. To communicate, one process writes a message to its part of the shared memory, then a signal to the other one to indicate there is a message waiting for it. The reply could use the other buffer.

25. Memory address 65,536 is file byte 0, so memory address 72,000 is file byte 6464.

26. Originally, four pages worth of the file were mapped: 0, 1, 2, and 3. The call succeeds and after it is done, only pages 2 and 3 are still mapped, that is, bytes 16,384 though 32,767

27. It is possible. For example, when the stack grows beyond the bottom page, a page fault occurs and the operating system normally assigns the next lowest page to it. However, it the stack has bumped into the data segment, the next page cannot be allocated to the stack, so the process must be terminated because it has run out of virtual address space. Also, even if there is another page available in virtual memory, the paging area of the disk might be full, making it impossible to allocate backing store for the new page, which would also terminate the process.

28. It is possible if the two blocks are not buddies. Consider the situation of Fig. 10-17(e). Two new requests come in for eight pages each. At this point the bottom 32 pages of memory are owned by 4 different users, each with 8 pages. Now users 1 and 2 release their pages, but users 0 and 3 hold theirs. This yields a situation with eight pages used, eight pages free, eight pages free, and eight pages used. We have two adjacent blocks of equal size that cannot be merged because they are not buddies.
29. Paging to a partition allows the use of a raw device, without the overhead of using file system data structures. To access block \( n \), the operating system can calculate its disk position by just adding it to the starting block of the partition. There is no need to go through all the indirect blocks that would otherwise be needed.

30. Opening a file by a path relative to the working directory is usually more convenient for the programmer or user, since a shorter path name is needed. It is also usually much simpler and requires fewer disk accesses.

31. The results are as follows.
   (a) The lock is granted.
   (b) The lock is granted.
   (c) \( C \) is blocked since bytes 20 through 30 are unavailable.
   (d) \( A \) is blocked since bytes 20 through 25 are unavailable.
   (e) \( B \) is blocked since byte 8 is unavailable for exclusive locking.

At this point we now have a deadlock. None of the processes will ever be able to run again.

32. The issue arises of which process gets the lock when it becomes available. The simplest solution is to leave it undefined. This is what POSIX does because it is the easiest to implement. Another is to require the locks to be granted in the order they were requested. This approach is more work for the implementation, but prevents starvation. Still another possibility is to let processes provide a priority when asking for a lock, and use these priorities to make a choice.

33. One approach is give an error and refuse to carry out the `lseek`. Another is to make the offset become negative. As long as it is not used, there is no harm done. Only if an attempt is made to read or write the file should be error message be given. If the `lseek` is followed by another `lseek` that makes the offset positive, no error is given.

34. The owner can read, write, and execute it, and everyone else (including the owner’s group) can just read and execute it, but not write it.

35. Yes. Any block device capable of reading and writing an arbitrary block can be used to hold a file system. Even if there were no way to seek to a specific block, it is always possible to rewind the tape and then count forward to the requested block. Such a file system would not be a high-performance file system, but it would work. The author has actually done this on a PDP-11 using DECTapes and it works.

36. No. The file still has only one owner. If, for example, only the owner can write on the file, the other party cannot do so. Linking a file into your directory does not suddenly give you any rights you did not have before. It just creates a new path for accessing the file.

37. When the working directory is changed, using the `chdir` system call, the i-node for the new working directory is fetched and kept in memory, in the i-node table. The i-node for the root directory is also there. In the user structure, pointers to both of these are maintained. When a path name has to be parsed, the first character is inspected. If it is a “/”, the pointer to the root i-node is used as the starting place, otherwise the pointer to the working directory’s i-node is used.
38. Access to the root directory’s i-node does not require a disk access, so we have the following:

1. Reading the `/` directory to look up “usr”.
2. Reading in the i-node for `/usr`.
3. Reading the `/usr` directory to look up “ast”.
4. Reading in the i-node for `/usr/ast`.
5. Reading the `/usr/ast` directory to look up “work”.
6. Reading in the i-node for `/usr/ast/work`.
7. Reading the `/usr/ast/work` directory to look up “f”.
8. Reading in the i-node for `/usr/ast/work/f`.

Thus in total, eight disk accesses are needed before the needed i-node is in memory.

39. The i-node holds 12 addresses. The single indirect block holds 256. The double indirect block leads to 65,536, and the triple indirect leads to 16,777,216, for a total of 16,843,018 blocks. This limits the maximum file size to 12 + 256 + 65,536 + 16,777,216 blocks, which is about 16 gigabytes.

40. When a file is closed, the counter of its i-node in memory is decremented. If it is greater than zero, the i-node cannot be removed from the table because the file is still open in some process. Only when the counter hits zero can the i-node be removed. Without the reference count, the system would not know when to remove the i-node from the table. Making a separate copy of the i-node each time the file was opened would not work because changes made in one copy would not be visible in the others.

41. By maintaining per CPU runqueues, scheduling decisions can be made locally, without executing expensive synchronization mechanisms to always access, and update, a shared runqueue. Also, it is more likely that all relevant memory pages will still be in the cache, if we schedule a thread on the same CPU where it already executed.

42. By forcing the contents of the modified file out onto the disk every 30 sec, damage done by a crash is limited to 30 sec. If `pdflush` did not run, a process might write a file, then exit with the full contents of the file still in the cache. In fact, the user might then log out and go home with the file still in the cache. An hour later the system might crash and lose the file, still only in the cache and not on disk. The next day we would not have a happy user.

43. All it has to do is set the link count to 1 since only one directory entry references the i-node.

44. It is generally `getpid`, `getuid`, `getgid`, or something like that. All they do is fetch one integer from a known place and return it. Every other call does more.

45. The file is simply removed. This is the normal way (actually, the only way) to remove a file.

46. A 1.44-MB floppy disk can hold 1440 blocks of raw data. The boot block, super block, group descriptor block, block bitmap, and i-node bitmap of an ext2 file system each use 1 block. If 8192 128-byte i-nodes are created, these i-nodes would occupy another 1024 blocks, leaving only 411 blocks unused. At least one block is needed for the root directory, leaving space for 410 blocks of file data. Actually the Linux `mkfs`
program is smart enough not to make more i-nodes than can possibly be used, so the inefficiency is not this bad. By default 184 i-nodes occupying 23 blocks will be created. However, because of the overhead of the ext2 file system, Linux normally uses the MINIX 1 file system on floppy disks and other small devices.

47. It is often essential to have someone who can do things that are normally forbidden. For example, a user starts up a job that generates an infinite amount of output. The user then logs out and goes on a three-week vacation to London. Sooner or later the disk will fill up, and the superuser will have to manually kill the process and remove the output file. Many other such examples exist.

48. Probably someone had the file open when the professor changed the permissions. The professor should have deleted the file and then put another copy of his master file into the public directory. Also, he should use a better method for distributing files, such as a web page, but that is beyond the scope of this exercise.

49. If say superuser rights are given to another user with the fsuid system call, that user can access superuser files, but will not be able to send signals, kill processes, or perform other operations which require superuser privileges.