- CPU accesses physical memory over a bus
- Devices access memory over I/O bus with DMA
- Devices can appear to be a region of memory
Realistic ~2005 PC architecture

- North Bridge
- South Bridge
- CPU
- CPU
- Advanced Programable Interrupt Controller bus
- Main memory
- I/O APIC
- AGP bus
- PCI bus
- USB
- ISA bus
- Front-side bus

Bus Connections:
- PCI IRQs
- PCI bus
- AGP bus
- USB
- ISA bus
What is memory?

- **SRAM – Static RAM**
  - Like two NOT gates circularly wired input-to-output
  - 4–6 transistors per bit, actively holds its value
  - Very fast, used to cache slower memory

- **DRAM – Dynamic RAM**
  - A capacitor + gate, holds charge to indicate bit value
  - 1 transistor per bit – extremely dense storage
  - Charge leaks – need slow comparator to decide if bit 1 or 0
  - Must re-write charge after reading, and periodically refresh

- **VRAM – “Video RAM”**
  - Dual ported DRAM, can write while someone else reads
What is I/O bus? E.g., PCI

- monitor
- processor
- graphics controller
- bridge/memory controller
- cache
- memory
- SCSI controller
- IDE disk controller
- expansion bus interface
- keyboard
- disk
- parallel port
- serial port
- expansion bus
- PCI bus
- SCSI bus
Communicating with a device

- **Memory-mapped device registers**
  - Certain *physical* addresses correspond to device registers
  - Load/store gets status/sends instructions – not real memory

- **Device memory** – device may have memory OS can write to directly on other side of I/O bus

- **Special I/O instructions**
  - Some CPUs (e.g., x86) have special I/O instructions
  - Like load & store, but asserts special I/O pin on CPU
  - OS can allow user-mode access to I/O ports at byte granularity

- **DMA** – place instructions to card in main memory
  - Typically then need to “poke” card by writing to register
  - Overlaps unrelated computation with moving data over (typically slower than memory) I/O bus
x86 I/O instructions

```c
static inline uint8_t
inb (uint16_t port)
{
    uint8_t data;
    asm volatile ("inb %w1, %b0" : "=a" (data) : "Nd" (port));
    return data;
}

static inline void
outb (uint16_t port, uint8_t data)
{
    asm volatile ("outb %b0, %w1" : : "a" (data), "Nd" (port));
}

static inline void
insw (uint16_t port, void *addr, size_t cnt)
{
    asm volatile ("rep insw" : '+'D" (addr), '+'c" (cnt)
                  : "d" (port) : "memory");
}
```
Example: parallel port (LPT1)

- Simple hardware has three control registers:

<table>
<thead>
<tr>
<th>D7</th>
<th>D6</th>
<th>D5</th>
<th>D4</th>
<th>D3</th>
<th>D2</th>
<th>D1</th>
<th>D0</th>
</tr>
</thead>
<tbody>
<tr>
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</tbody>
</table>

read/write data register (port 0x378)

<table>
<thead>
<tr>
<th>BSY</th>
<th>ACK</th>
<th>PAP</th>
<th>OFON</th>
<th>ERR</th>
<th>–</th>
<th>–</th>
<th>–</th>
</tr>
</thead>
<tbody>
<tr>
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</tbody>
</table>

read-only status register (port 0x379)

<table>
<thead>
<tr>
<th>–</th>
<th>–</th>
<th>–</th>
<th>IRQ</th>
<th>DSL</th>
<th>INI</th>
<th>ALF</th>
<th>STR</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td></td>
<td></td>
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</tr>
</tbody>
</table>

read/write control register (port 0x37a)

- Every bit except IRQ corresponds to a pin on 25-pin connector:
void
sendbyte(uint8_t byte)
{
    /* Wait until BSY bit is 1. */
    while ((inb (0x379) & 0x80) == 0)
        delay ();

    /* Put the byte we wish to send on pins D7-0. */
    outb (0x378, byte);

    /* Pulse STR (strobe) line to inform the printer
     * that a byte is available */
    uint8_t ctrlval = inb (0x37a);
    outb (0x37a, ctrlval | 0x01);
    delay ();
    outb (0x37a, ctrlval);
}
IDE disk driver

void IDE_ReadSector(int disk, int off, void *buf)
{
    outb(0x1F6, disk == 0 ? 0xE0 : 0xF0);  // Select Drive
    IDEWait();
    outb(0x1F2, 1);  // Read length (1 sector = 512 B)
    outb(0x1F3, off);  // LBA low
    outb(0x1F4, off >> 8);  // LBA mid
    outb(0x1F5, off >> 16);  // LBA high
    outb(0x1F7, 0x20);  // Read command
    insw(0x1F0, buf, 256);  // Read 256 words
}

void IDEWait()
{
    // Discard status 4 times
    inb(0x1F7); inb(0x1F7);
    inb(0x1F7); inb(0x1F7);
    // Wait for status BUSY flag to clear
    while ((inb(0x1F7) & 0x80) != 0)
    {
    }
}
Memory-mapped IO

- **in/out instructions slow and clunky**
  - Instruction format restricts what registers you can use
  - Only allows $2^{16}$ different port numbers
  - Per-port access control turns out not to be useful (any port access allows you to disable all interrupts)

- **Devices can achieve same effect with physical addresses, e.g.**:
  
  ```c
  volatile int32_t *device_control
  = (int32_t *) (0xc0100 + PHYS_BASE);
  *device_control = 0x80;
  int32_t status = *device_control;
  ```

  - OS must map physical to virtual addresses, ensure non-cachable

- **Assign physical addresses at boot to avoid conflicts. PCI:**
  - Slow/clunky way to access configuration registers on device
  - Use that to assign ranges of physical addresses to device
- Idea: only use CPU to transfer control requests, not data
- Include list of buffer locations in main memory
  - Device reads list and accesses buffers through DMA
  - Descriptions sometimes allow for scatter/gather I/O
- Link interface talks to wire/fiber/antenna
  - Typically does framing, link-layer CRC
- FIFOs on card provide small amount of buffering
- Bus interface logic uses DMA to move packets to and from buffers in main memory
Example: IDE disk read w. DMA

1. device driver is told to transfer disk data to buffer at address X
2. device driver tells disk controller to transfer C bytes from disk to buffer at address X
3. disk controller initiates DMA transfer
4. disk controller sends each byte to DMA controller
5. DMA controller transfers bytes to buffer X, increasing memory address and decreasing C until C = 0
6. when C = 0, DMA interrupts CPU to signal transfer completion
Driver architecture

• Device driver provides several entry points to kernel
  - Reset, ioctl, output, interrupt, read, write, strategy …

• How should driver synchronize with card?
  - E.g., Need to know when transmit buffers free or packets arrive
  - Need to know when disk request complete

• One approach: Polling
  - Sent a packet? Loop asking card when buffer is free
  - Waiting to receive? Keep asking card if it has packet
  - Disk I/O? Keep looping until disk ready bit set

• Disadvantages of polling?
Driver architecture

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- Disadvantages of polling?
  - Can’t use CPU for anything else while polling
  - Schedule poll in future? High latency to receive packet or process disk block bad for response time
Interrupt driven devices

- Instead, ask card to interrupt CPU on events
  - Interrupt handler runs at high priority
  - Asks card what happened (xmit buffer free, new packet)
  - This is what most general-purpose OSes do

- Bad under high network packet arrival rate
  - Packets can arrive faster than OS can process them
  - Interrupts are very expensive (context switch)
  - Interrupt handlers have high priority
  - In worst case, can spend 100% of time in interrupt handler and never make any progress – receive livelock
  - Best: Adaptive switching between interrupts and polling

- Very good for disk requests

- Rest of today: Disks (network devices in 3 lectures)
Anatomy of a disk [Ruemmler]

- **Stack of magnetic platters**
  - Rotate together on a central spindle @3,600-15,000 RPM
  - Drive speed drifts slowly over time
  - Can’t predict rotational position after 100-200 revolutions

- **Disk arm assembly**
  - Arms rotate around pivot, all move together
  - Pivot offers some resistance to linear shocks
  - One disk head per recording surface (2× platters)
  - Sensitive to motion and vibration [Gregg] (demo on youtube)
Disk
Storage on a magnetic platter

- Platters divided into concentric *tracks*
- A stack of tracks of fixed radius is a *cylinder*
- Heads record and sense data along cylinders
  - Significant fractions of encoded stream for error correction
- Generally only one head active at a time
  - Disks usually have one set of read-write circuitry
  - Must worry about cross-talk between channels
  - Hard to keep multiple heads exactly aligned
Cylinders, tracks, & sectors
Disk positioning system

- Move head to specific track and keep it there
  - Resist physical shocks, imperfect tracks, etc.
- A seek consists of up to four phases:
  - speedup–accelerate arm to max speed or half way point
  - coast–at max speed (for long seeks)
  - slowdown–stops arm near destination
  - settle–adjusts head to actual desired track
- Very short seeks dominated by settle time (~1 ms)
- Short (200-400 cyl.) seeks dominated by speedup
  - Accelerations of 40g
• Head switches comparable to short seeks
  - May also require head adjustment
  - Settles take longer for writes than for reads – Why?

• Disk keeps table of pivot motor power
  - Maps seek distance to power and time
  - Disk interpolates over entries in table
  - Table set by periodic “thermal recalibration”
  - But, e.g., \( \sim 500 \) ms recalibration every \( \sim 25 \) min bad for AV

• “Average seek time” quoted can be many things
  - Time to seek 1/3 disk, 1/3 time to seek whole disk
Seek details

- Head switches comparable to short seeks
  - May also require head adjustment
  - Settles take longer for writes than for reads
    If read strays from track, catch error with checksum, retry
    If write strays, you’ve just clobbered some other track

- Disk keeps table of pivot motor power
  - Maps seek distance to power and time
  - Disk interpolates over entries in table
  - Table set by periodic “thermal recalibration”
    - But, e.g., ~500 ms recalibration every ~25 min bad for AV

- “Average seek time” quoted can be many things
  - Time to seek 1/3 disk, 1/3 time to seek whole disk
Sectors

- Disk interface presents linear array of sectors
  - Historically 512 B, but 4 KiB in “advanced format” disks
  - Written atomically (even if there is a power failure)
- Disk maps logical sector #s to physical sectors
  - Zoning—puts more sectors on longer tracks
  - Track skewing—sector 0 pos. varies by track (why?)
  - Sparing—flawed sectors remapped elsewhere
- OS doesn’t know logical to physical sector mapping
  - Larger logical sector # difference means longer seek time
  - Highly non-linear relationship (and depends on zone)
  - OS has no info on rotational positions
  - Can empirically build table to estimate times
Sectors

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  - Written atomically (even if there is a power failure)

- Disk maps logical sector #s to physical sectors
  - Zoning—puts more sectors on longer tracks
  - Track skewing—sector 0 pos. varies by track (sequential access speed)
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  - Larger logical sector # difference means longer seek time
  - Highly non-linear relationship (and depends on zone)
  - OS has no info on rotational positions
  - Can empirically build table to estimate times
Disk interface

- Controls hardware, mediates access
- Computer, disk often connected by bus (e.g., ATA, SCSI, SATA)
  - Multiple devices may contend for bus
- Possible disk/interface features:
- Disconnect from bus during requests
- Command queuing: Give disk multiple requests
  - Disk can schedule them using rotational information
- Disk cache used for read-ahead
  - Otherwise, sequential reads would incur whole revolution
  - Cross track boundaries? Can’t stop a head-switch
- Some disks support write caching
  - But data not stable—not suitable for all requests
• **SCSI domain** consists of devices and an SDS
  - Devices: host adapters & SCSI controllers
  - *Service Delivery Subsystem* connects devices—e.g., SCSI bus

• **SCSI-2 bus (SDS) connects up to 8 devices**
  - Controllers can have > 1 “logical units” (LUNs)
  - Typically, controller built into disk and 1 LUN/target, but “bridge controllers” can manage multiple physical devices

• **Each device can assume role of initiator or target**
  - Traditionally, host adapter was initiator, controller target
  - Now controllers act as initiators (e.g., COPY command)
  - Typical domain has 1 initiator, ≥ 1 targets
SCSI requests

- A *request* is a command from initiator to target
  - Once transmitted, target has control of bus
  - Target may disconnect from bus and later reconnect
    (very important for multiple targets or even multitasking)

- **Commands contain the following:**
  - *Task identifier*—initiator ID, target ID, LUN, tag
  - *Command descriptor block*—e.g., read 10 blocks at pos. $N$
  - Optional *task attribute*—SIMPLE, ORDERD, HEAD OF QUEUE
  - Optional: output/input buffer, sense data
  - *Status byte*—GOOD, CHECK CONDITION, INTERMEDIATE, . . .
Executing SCSI commands

- Each LUN maintains a queue of tasks
  - Each task is DORMANT, BLOCKED, ENABLED, or ENDED
  - SIMPLE tasks are dormant until no ordered/head of queue
  - ORDERED tasks dormant until no HoQ/more recent ordered
  - HoQ tasks begin in enabled state

- Task management commands available to initiator
  - Abort/terminate task, Reset target, etc.

- Linked commands
  - Initiator can link commands, so no intervening tasks
  - E.g., could use to implement atomic read-modify-write
  - Intermediate commands return status byte INTERMEDIATE
SCSI exceptions and errors

- After error stop executing most SCSI commands
  - Target returns with CHECK CONDITION status
  - Initiator will eventually notice error
  - Must read specifics w. REQUEST SENSE

- Prevents unwanted commands from executing
  - E.g., initiator may not want to execute 2nd write if 1st fails

- Simplifies device implementation
  - Don’t need to remember more than one error condition

- Same mechanism used to notify of media changes
  - I.e., ejected tape, changed CD-ROM
Disk performance

- Placement & ordering of requests a huge issue
  - Sequential I/O much, much faster than random
  - Long seeks much slower than short ones
  - Power might fail any time, leaving inconsistent state

- Must be careful about order for crashes
  - More on this in next two lectures

- Try to achieve contiguous accesses where possible
  - E.g., make big chunks of individual files contiguous

- Try to order requests to minimize seek times
  - OS can only do this if it has a multiple requests to order
  - Requires disk I/O concurrency
  - High-performance apps try to maximize I/O concurrency

- Next: How to schedule concurrent requests
Scheduling: FCFS

- “First Come First Served”
  - Process disk requests in the order they are received

- Advantages

- Disadvantages
Scheduling: FCFS

• “First Come First Served”
  - Process disk requests in the order they are received

• Advantages
  - Easy to implement
  - Good fairness

• Disadvantages
  - Cannot exploit request locality
  - Increases average latency, decreasing throughput
queue = 98, 183, 37, 122, 14, 124, 65, 67
head starts at 53
Shortest positioning time first (SPTF)

- Always pick request with shortest seek time
- Also called Shortest Seek Time First (SSTF)

Advantages

Disadvantages
Shortest positioning time first (SPTF)

- Always pick request with shortest seek time

Also called Shortest Seek Time First (SSTF)

Advantages
- Exploits locality of disk requests
- Higher throughput

Disadvantages
- Starvation
- Don’t always know what request will be fastest

Improvement?

Improvement?

Improvement?
Shortest positioning time first (SPTF)

- Always pick request with shortest seek time
- Also called Shortest Seek Time First (SSTF)
- Advantages
  - Exploits locality of disk requests
  - Higher throughput
- Disadvantages
  - Starvation
  - Don’t always know what request will be fastest
- Improvement: Aged SPTF
  - Give older requests higher priority
  - Adjust “effective” seek time with weighting factor:
    \[ T_{\text{eff}} = T_{\text{pos}} - W \cdot T_{\text{wait}} \]
queue = 98, 183, 37, 122, 14, 124, 65, 67
head starts at 53
“Elevator” scheduling (SCAN)

- Sweep across disk, servicing all requests passed
  - Like SPTF, but next seek must be in same direction
  - Switch directions only if no further requests

- Advantages

- Disadvantages
“Elevator” scheduling (SCAN)

• Sweep across disk, servicing all requests passed
  - Like SPTF, but next seek must be in same direction
  - Switch directions only if no further requests

• Advantages
  - Takes advantage of locality
  - Bounded waiting

• Disadvantages
  - Cylinders in the middle get better service
  - Might miss locality SPTF could exploit

• CSCAN: Only sweep in one direction
  Very commonly used algorithm in Unix

• Also called LOOK/CLOOK in textbook
  - (Textbook uses [C]SCAN to mean scan entire disk uselessly)
CSCAN example

queue  98, 183, 37, 122, 14, 124, 65, 67
head starts at 53
VSCAN($r$)

- **Continuum between SPTF and SCAN**
  - Like SPTF, but slightly changes “effective” positioning time
    - If request in same direction as previous seek: $T_{\text{eff}} = T_{\text{pos}}$
    - Otherwise: $T_{\text{eff}} = T_{\text{pos}} + r \cdot T_{\text{max}}$
    - when $r = 0$, get SPTF, when $r = 1$, get SCAN
    - E.g., $r = 0.2$ works well

- **Advantages and disadvantages**
  - Those of SPTF and SCAN, depending on how $r$ is set

- **See [Worthington](#) for good description and evaluation of various disk scheduling algorithms**
Flash memory

• Today, people increasingly using flash memory

• Completely solid state (no moving parts)
  - Remembers data by storing charge
  - Lower power consumption and heat
  - No mechanical seek times to worry about

• Limited # overwrites possible
  - Blocks wear out after 10,000 (MLC) – 100,000 (SLC) erases
  - Requires flash translation layer (FTL) to provide wear leveling, so repeated writes to logical block don’t wear out physical block
  - FTL can seriously impact performance
  - In particular, random writes very expensive [Birrell]

• Limited durability
  - Charge wears out over time
  - Turn off device for a year, you can potentially lose data
Types of flash memory

- **NAND flash (most prevalent for storage)**
  - Higher density (most used for storage)
  - Faster erase and write
  - More errors internally, so need error correction

- **NOR flash**
  - Faster reads in smaller data units
  - Can execute code straight out of NOR flash
  - Significantly slower erases

- **Single-level cell (SLC) vs. Multi-level cell (MLC)**
  - MLC encodes multiple bits in voltage level
  - MLC slower to write than SLC
  - MLC has lower durability (bits decay faster)
Flash device has 2112-byte pages
- 2048 bytes of data + 64 bytes metadata & ECC

Blocks contain 64 (SLC) or 128 (MLC) pages

Blocks divided into 2–4 planes
- All planes contend for same package pins
- But can access their blocks in parallel to overlap latencies

Can read one page at a time
- Takes 25 $\mu$sec + time to get data off chip

Must erase whole block before programming
- Erase sets all bits to 1—very expensive (2 msec)
- Programming pre-erased block requires moving data to internal buffer, then 200 (SLC)–800 (MLC) $\mu$sec
## Flash Characteristics [Caulfield’09]

<table>
<thead>
<tr>
<th>Parameter</th>
<th>SLC</th>
<th>MLC</th>
</tr>
</thead>
<tbody>
<tr>
<td>Density Per Die (GB)</td>
<td>4</td>
<td>8</td>
</tr>
<tr>
<td>Page Size (Bytes)</td>
<td>2048+32</td>
<td>2048+64</td>
</tr>
<tr>
<td>Block Size (Pages)</td>
<td>64</td>
<td>128</td>
</tr>
<tr>
<td>Read Latency ($\mu$s)</td>
<td>25</td>
<td>25</td>
</tr>
<tr>
<td>Write Latency ($\mu$s)</td>
<td>200</td>
<td>800</td>
</tr>
<tr>
<td>Erase Latency ($\mu$s)</td>
<td>2000</td>
<td>2000</td>
</tr>
<tr>
<td>40MHz, 16-bit bus Read b/w (MB/s)</td>
<td>75.8</td>
<td>75.8</td>
</tr>
<tr>
<td>Program b/w (MB/s)</td>
<td>20.1</td>
<td>5.0</td>
</tr>
<tr>
<td>133MHz</td>
<td></td>
<td></td>
</tr>
<tr>
<td>Read b/w (MB/s)</td>
<td>126.4</td>
<td>126.4</td>
</tr>
<tr>
<td>Program b/w (MB/s)</td>
<td>20.1</td>
<td>5.0</td>
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</table>