I/O Devices
Motivation

What good is a computer without any I/O devices?
- keyboard, display, disks

We want:
- **H/W** that will let us plug in different devices
- **OS** that can interact with different combinations
Motivation

What good is a computer without any I/O devices?
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We want:
- **H/W** that will let us plug in different devices
- **OS** that can interact with different combinations

*Largely a communication problem…*
CPU | RAM | Graphics
---|---|---
Memory Bus | General I/O Bus (e.g., PCI)
CPU

RAM

Graphics

Memory Bus

General I/O Bus (e.g., PCI)

Peripheral I/O Bus (e.g., SCSI, SATA, USB)
Why use hierarchical buses?

- CPU
- RAM
- Graphics

Memory Bus
General I/O Bus (e.g., PCI)
Peripheral I/O Bus (e.g., SCSI, SATA, USB)
Canonical Device... Is a rectangle!
## Canonical Device

### Device Registers:

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<th>DATA</th>
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Canonical Device

Device Registers:

| Status | COMMAND | DATA |

OS reads/writes to these
Canonical Device

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Hidden Internals:

???
Canonical Device

Device Registers:

- Status
- COMMAND
- DATA

Hidden Internals:

- Microcontroller (CPU+RAM)
- Extra RAM
- Other special-purpose chips

OS reads/writes to these
Example Protocol

while (STATUS == BUSY)
    ; // spin
Write data to DATA register
Write command to COMMAND register
while (STATUS == BUSY)
    ; // spin
CPU:

Disk:

while (STATUS == BUSY) ; // 1
;
Write data to DATA register // 2
Write command to COMMAND register // 3
while (STATUS == BUSY) ; // 4
while (STATUS == BUSY)          // 1
;
Write data to DATA register    // 2
Write command to COMMAND register // 3
while (STATUS == BUSY)         // 4
;
A wants to do I/O

CPU: A

Disk: C

while (STATUS == BUSY) // 1
;
Write data to DATA register // 2
Write command to COMMAND register // 3
while (STATUS == BUSY) // 4
;
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CPU: A
Disk: C A
while (STATUS == BUSY) // 1
;
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while (STATUS == BUSY) // 4
;
while (STATUS == BUSY)             // 1
        
; Write data to DATA register        // 2
Write command to COMMAND register  // 3
while (STATUS == BUSY)             // 4
        
;
while (STATUS == BUSY) // 1
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;

how to avoid spinning? interrupts!
while (STATUS == BUSY)             // 1
    wait for interrupt;
Write data to DATA register        // 2
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how to avoid spinning? interrupts!
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how to avoid spinning? interrupts!

CPU:  A  B  A  B  A  B
Disk: C  A
Interrupts vs. Polling

Discuss: are interrupts ever worse?
Interrupts vs. Polling

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Interrupts can sometimes lead to *livelock*
- e.g., flood of network packets
Interrupts vs. Polling

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Interrupts can sometimes lead to *livelock*
- e.g., flood of network packets

Techniques:
- hybrid approach
- interrupt *coalescing*
Protocol Variants

**Status checks**: polling vs. interrupts

**Data**: PIO vs. DMA

**Control**: special instructions vs. memory-mapped I/O
while (STATUS == BUSY)  // 1
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what else can we optimize?
while (STATUS == BUSY) // 1
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Write data to DATA register // 2
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    wait for interrupt;

what else can we optimize?
data transfer!

CPU: A B A B A B

Disk: C A
Programmed I/O vs. Direct Memory Access

**PIO (Programmed I/O):**
- CPU directly tells device what data is

**DMA (Direct Memory Access):**
- CPU leaves data in memory
- Device reads it directly
while (STATUS == BUSY) // 1
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Special Instructions vs. Mem-Mapped I/O

Special instructions
- each device has a port
- *in/out* instructions (x86) communicate with device

Memory-Mapped I/O
- H/W maps registers into address space
- *loads/stores* sent to device

Tradeoffs?
Special Instructions vs. Mem-Mapped I/O

Special instructions
- each device has a port
- *in/out* instructions (x86) communicate with device

Memory-Mapped I/O
- H/W maps registers into address space
- *loads/stores* sent to device

Doesn’t matter much (both are used).
Protocol Variants

Status checks: polling vs. interrupts

Data: PIO vs. DMA

Control: special instructions vs. memory-mapped I/O
Variety is a Challenge

Problem:
- many, many devices
- each has its own protocol

How can we avoid writing a slightly different OS for each H/W combination?
Solution

Encapsulation!

Write driver for each device.

Drivers are 70% of Linux source code.
Solution

Encapsulation!

Write driver for each device.

Drivers are **70%** of Linux source code.

Encapsulation also enables us to mix-and-match devices, schedulers, and file systems.
Storage Stack

application
file system
scheduler
driver
hard drive

build common interface on top of all HDDs
Storage Stack

- application
- file system
- scheduler
- driver
- hard drive

what about special capabilities?

build common interface on top of all HDDs
Hard Disks
Basic Interface

Disk has a sector-addressable address space (so a disk is like an array of sectors).

**Sectors** are typically 512 bytes or 4096 bytes.

Main operations: reads + writes to sectors.
Platter is covered with a magnetic film.
Spindle
Many platters may be bound to the spindle.
Each surface is divided into rings called **tracks**. A stack of tracks (across platters) is called a **cylinder**.
The tracks are divided into numbered sectors.
Heads on a moving arm can read from each surface.
Spindle/platters rapidly spin.
Don’t try this at home!

http://youtu.be/9eMWG3fwjEU?t=30s
Let’s Read 12!
Seek to right track.
Seek to right track.
Seek to right track.
Wait for rotation.
Wait for rotation.
Wait for rotation.
Wait for rotation.
Wait for rotation.
Wait for rotation.
Transfer data.
Transfer data.
Transfer data.
Yay!
Seek, Rotate, Transfer

Must accelerate, coast, decelerate, settle

Seeks often take several milliseconds!

Settling alone can take 0.5 - 2 ms.

Entire seek often takes 4 - 10 ms.
Seek, **Rotate**, Transfer

Depends on rotations per minute (RPM).
- 7200 RPM is common, 1500 RPM is high end.

\[
1 \div 7200 \text{ RPM} = \\
1 \text{ minute} \div 7200 \text{ rotations} = \\
1 \text{ second} \div 120 \text{ rotations} = \\
12 \text{ ms} \div \text{ rotation}
\]
Seek, **Rotate**, Transfer

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\[
\frac{1}{7200 \text{ RPM}} = \\
1 \text{ minute} / 7200 \text{ rotations} = \\
1 \text{ second} / 120 \text{ rotations} = \\
12 \text{ ms} / \text{ rotation}
\]

so it may take *6 ms* on avg to rotate to target (0.5 * 12 ms)
Seek, Rotate, Transfer

Pretty fast — depends on RPM and sector density.

100+ MB/s is typical.

1s / 100 MB = 10 ms / MB = 4.9 us / sector (assuming 512-byte sector)
Workload

So…
- seeks are slow
- rotations are slow
- transfers are fast

What kind of workload is fastest for disks?
So…
- seeks are slow
- rotations are slow
- transfers are fast

What kind of workload is fastest for disks?

**Sequential**: access sectors in order (transfer dominated)
**Random**: access sectors arbitrarily (seek+rotation dominated)
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Sequential workload: what is throughput for each?
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Cheeta: 125 MB/s.  
Barracuda: 105 MB/s.
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$$\text{avg rotation} = \frac{1}{2} \times \frac{1 \text{ min}}{15000}$$
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\[
\text{avg rotation} = \frac{1}{2} \times \frac{1 \text{ min}}{15000} \times \frac{60 \text{ sec}}{1 \text{ min}} \times \frac{1000 \text{ ms}}{1 \text{ sec}}
\]
How long does an average 16-KB read take with Cheetah?

\[
\text{avg rotation} = \frac{1}{2} \times \frac{1 \text{ min}}{15000} \times \frac{60 \text{ sec}}{1 \text{ min}} \times \frac{1000 \text{ ms}}{1 \text{ sec}} = 2 \text{ ms}
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How long does an average 16-KB read take with Cheetah?

Cheetah time = 4ms + 2ms + 125us = 6.1ms
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How long does an average 16-KB read take w/ Cheetah?

Cheetah time = 4ms + 2ms + 125us = 6.1ms

Throughput = \[
\frac{16 \text{ KB}}{6.1 \text{ ms}}
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### Comparison of Cheetah and Barracuda

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**How long does an average 16-KB read take with Cheetah?**

Cheetah time = \(4\text{ms} + 2\text{ms} + 125\text{us} = 6.1\text{ms}\)

**Throughput**

\[
\text{throughput} = \frac{16 \text{ KB}}{6.1\text{ms}} \times \frac{1 \text{ MB}}{1024 \text{ KB}} \times \frac{100 \text{ ms}}{1 \text{ sec}}
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Cheetah time = 4ms + 2ms + 125us = 6.1ms

Throughput = \( \frac{16 \text{ KB}}{6.1 \text{ ms}} \times \frac{1 \text{ MB}}{1024 \text{ KB}} \times \frac{100 \text{ ms}}{1 \text{ sec}} = 2.5 \text{ MB/s} \)
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How long does an average 16-KB read take w/ Barracuda?

avg rotation = \( \frac{1}{2} \times \frac{1 \text{ min}}{7200} \)
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How long does an average 16-KB read take w/ Barracuda?

\[
\text{avg rotation} = \frac{1}{2} \times \frac{1 \text{ min}}{7200} \times \frac{60 \text{ sec}}{1 \text{ min}} \times \frac{1000 \text{ ms}}{1 \text{ sec}}
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How long does an average 16-KB read take with Barracuda?

\[
\text{avg rotation} = \frac{1}{2} \times \frac{1 \text{ min}}{7200} \times \frac{60 \text{ sec}}{1 \text{ min}} \times \frac{1000 \text{ ms}}{1 \text{ sec}} = 4.1 \text{ ms}
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How long does an average 16-KB read take with Barracuda?

\[
\text{transfer} = \frac{1 \text{ sec}}{105 \text{ MB}} \times 16 \text{ KB}
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How long does an average 16-KB read take with Barracuda?

\[
\text{transfer} = \frac{1 \text{ sec}}{105 \text{ MB}} \times 16 \text{ KB} \times \frac{1,000,000 \text{ us}}{1 \text{ sec}}
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How long does an average 16-KB read take w/ Barracuda?

\[
\text{transfer} = \frac{1 \text{ sec}}{105 \text{ MB}} \times 16 \text{ KB} \times \frac{1,000,000 \text{ us}}{1 \text{ sec}} = 149 \text{ us}
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How long does an average 16-KB read take w/ Barracuda?

Barracuda time = 9ms + 4.1ms + 149us = 13.2ms
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How long does an average 16-KB read take w/ Barracuda?

Barracuda time = 9ms + 4.1ms + 149us = 13.2ms

throughput = \[
\frac{16 \text{ KB}}{13.2\text{ms}}
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How long does an average 16-KB read take w/ Barracuda?

Barracuda time = 9ms + 4.1ms + 149us = 13.2ms

\[
\text{throughput} = \frac{16 \text{ KB}}{13.2 \text{ms}} \times \frac{1 \text{ MB}}{1024 \text{ KB}} \times \frac{1000 \text{ ms}}{1 \text{ sec}}
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### Cheetah vs. Barracuda

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How long does an average 16-KB read take with Barracuda?

**Barracuda time** = 9ms + 4.1ms + 149us = 13.2ms

**Throughput** = \[
\frac{16 \text{ KB}}{13.2\text{ms}} \times \frac{1 \text{ MB}}{1024 \text{ KB}} \times \frac{1000 \text{ ms}}{1 \text{ sec}} = 1.2 \text{ MB/s}
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Other Improvements

Track Skew

Zones

Cache
Other Improvements

Track Skew

Zones

Cache
When reading 16 after 15, the head won’t settle quick enough, so we need to do a rotation.
enough time to settle now
Other Improvements

Track Skew

Zones

Cache
Other Improvements

Track Skew

Zones

Cache
Drive Cache

Drives may cache both reads and writes.

OS does this to.

What advantage does drive have for reads?

What advantage does drive have for writes?
Schedulers
Schedulers

Given a stream of requests, in what order should they be served?
FCFS (First-Come-First-Serve)

Assume seek+rotate = 10 ms on average.
Assume transfer = 100 MB/s.

How long (roughly) does the below workload take?
The integers are sector numbers.

300001, 700001, 300002, 700002, 300003, 700003
FCFS (First-Come-First-Serve)

Assume seek+rotate = 10 ms on average. Assume transfer = 100 MB/s.

How long (roughly) does the below workload take? The integers are sector numbers.

300001, 700001, 300002, 700002, 300003, 700003 (~60ms)
FCFS (First-Come-First-Serve)

Assume seek+rotate = \(10 \text{ ms}\) on average.
Assume transfer = \(100 \text{ MB/s}\).

How long (roughly) do the below workloads take?
The integers are sector numbers.

\[
300001, 700001, 300002, 700002, 300003, 700003 (~60\text{ms})
\]
\[
300001, 300002, 300003, 700001, 700002, 700003
\]
FCFS (First-Come-First-Serve)

Assume seek + rotate = 10 ms on average.
Assume transfer = 100 MB/s.

How long (roughly) do the below workloads take?
The integers are sector numbers.

300001, 700001, 300002, 700002, 300003, 700003 (~60ms)
300001, 300002, 300003, 700001, 700002, 700003 (~20ms)
Schedulers

Where should the scheduler go?
SPTF (Shortest Positioning Time First)

**Strategy**: always choose the request that will take the least time for seeking and rotating.

How to implement in disk?
How to implement in OS?
SPTF (Shortest Positioning Time First)

**Strategy**: always choose the request that will take the least time for seeking and rotating.

How to implement in disk?
How to implement in OS?

Disadvantages?
SCAN

Sweep back and forth, from one end of disk to the other, serving requests as you go.

Pros/Cons?
SCAN

Sweep back and forth, from one end of disk to the other, serving requests as you go.

Pros/Cons?

Better: C-SCAN (circular scan)
- only sweep in one direction
What happens?

Assume 2 processes, and C-SCAN.

```c
void reader(int fd) {
    char buf[1024];
    int rv;
    while((rv = read(buf)) != 0) {
        assert(rv);
        // takes short time, e.g., 1ms
        process(buf, rv);
    }
}
```
Work Conservation

Work conserving schedulers always try to do I/O if there’s I/O to be done.

Sometimes, it’s better to wait instead if you anticipate another request will appear nearby.

Such non-work-conserving schedulers are called anticipatory schedulers.
CFQ (Linux Default)

Completely Fair Queueing.

Queue for each process.

Do weighted round-robin between queues, with slice time proportional to priority.

Optimize order within queue.

Yield slice only if idle for a given time (anticipation).
Summary

Overlap I/O and CPU whenever possible!
- use interrupts, DMA

Never do random I/O unless you must!
- e.g., Quicksort is a terrible algorithm on disk
Announcements

Office hours: after class, in lab.

p3b due Friday.