Chapter 8

Basic Synchronization Principles

Need for Synchronization

- Multiprogramming
  - ➔ Multiple concurrent, independent processes
  - ➔ Those processes might want to coordinate activities

```
                shared x, y

Proc A {                      Proc B {
while (true) {                while (true) {
      <compute A1>                  read(x)
      write(x)                      <compute B1>
      <compute A2>                  write(y)
      read(y)                       <compute B2>
      }                             }
}                             }
```

- Clearly, synchronization is needed if
  - A wants B to read `x` after it writes it & before it re-writes

---

Barriers to providing synchronization

- What are the barriers to providing good synchronization capabilities ?
  - No widely accepted parallel programming languages
    - CSP
    - Linda
  - No widely use paradigm
    - How do you decompose a problem ?
  - OS only provides minimal support
    - Test and Set
    - Semaphore
    - Monitor

Critical Section Problem

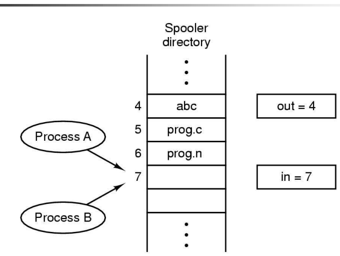
```
              shared float balance;

/* Code schema for p1 */          /* Code schema for p2 */
..                                ..
balance = balance + amount;       balance = balance - amount;
..                                ..

  /* Schema for p1 */               /* Schema for p2 */
    load R1, balance                  load R1, balance
    load R2, amount                   load R2, amount
    add R1, R2                        sub R1, R2
    store R1, balance                 store R1, balance
```

Critical Section Problem…

```
/* Schema for p1 */                 /* Schema for p2 */
  { load R1, balance  } 1             4 { load R1, balance  }
5 { load R2, amount   }                 { load R2, amount   } 2
  { add R1, R2        } 3             6 { sub R1, R2        }
  { store R1, balance }                 { store R1, balance }
```

- Suppose:
  - Execution sequence : 1, 2, 3
    - Lost update : 2
  - Execution sequence : 1, 4, 3 ,6
    - Lost update : 3
- Together => non-determinacy
- Race condition exists

Race Condition Example 2



Taken from Modern Operating Systems, 2nd Ed, Tanenbaum, 2001

Two processes want to access shared memory at same time

Using Shared Global Variables – Ver 1

```
Shared integer processnumber = 1;

void processone;
{
  while (true)    {                      Hard wait
      while (processnumber == 2)
          ;
      criticalsectionone;
      processnumber = 2;
      otherstuffone;
  }
}

void processtwo;
{                                        Hard wait
  while (true)
  {
      while (processnumber == 1)
          ;
      criticalsectiontwo;
      processnumber = 1;
      otherstufftwo;
  }
}
```

Single global variable forces **lockstep synchronization**

Using Shared Global Variables – Ver 2

```
Shared boolean p1inside = false, p2inside = false;

void processone;
  {
      while (true)  {
          while (p2inside)
            ;
          p1inside = true;
          criticalsectionone;
          p1inside = false;
          otherstuffone;
      }
  }

void processtwo;
  {
      while (true) {
          while (p1inside)
            ;
          p2inside = true;
          criticalsectiontwo;
          p2inside = false;
          otherstufftwo;
      }
  }
```

- Process 1 & 2 can both be **in the critical sections at the same time** Because Test & Set operations are **not atomic**
  ==> Move setting of p1inside/p2inside before test

Using Shared Global Variables – Ver 3

```
Shared boolean: p1wantsin = false, p2wantsin = false;

void processone;
  {
      while (true)  {
          p1wantsin = true;
          while (p2wantsin)
              ;
          criticalsectionone;
          p1wantsin = false;
          otherstuffone;
      }
  }

void processtwo;
  {
      while (true) {
          p2wantsin = true;
          while (p1wantsin)
              ;
          criticalsectiontwo;
          p2wantsin = false;
          otherstufftwo;
      }
  }
```

- **Deadlock** can occur if both sets flag at the same time
  ==> Need a way to break out of loops…..

Using Shared Global Variables – Peterson

```
Shared boolean p1wantsin = false, p2wantsin = false;
Shared int will_wait;

void processone;
  {
      while (true)  {
          p1wantsin = true;
          will_wait = 1;
          while (p2wantsin &&
(will_wait == 1))
              ;
          criticalsectionone;
          p1wantsin = false;
          otherstuffone;
      }
  }

void processtwo;
  {
      while (true) {
          p2wantsin = true;
          will_wait = 2;
          while (p1wantsin &&
(will_wait == 2))
              ;
          criticalsectiontwo;
          p2wantsin = false;
          otherstufftwo;
      }
  }
```

- **Guarantees mutual exclusion and no blocking**

Wherein Lies the Problem?

- Problem stems from interruption of software-based process while executing critical code (low-level)
- Solution
  - Identify critical section
  - *Disable interrupts* while in Critical Section

```
shared double balance;

/* Program for P1 */
DisableInterrupts();
balance = balance + amount;  } CS
EnableInterrupts();

/* Program for P2 */
DisableInterrupts();
Balance = balance - amount;  } CS
EnableInterrupts();
```


Using Interrupts…

- This works *BUT*…
  - Allows process to disable interrupts for arbitrarily long time
  - What if I/O interrupt needed ?
  - What if one of the processes is in infinite loop inside the Critical Section
- Let's examine the use of Shared Variables again….

Using Shared Variable to Synchronize

```
shared boolean lock = FALSE;
shared float balance;

/* Program for P1 */              /* Program for P2 */
..                                ..
/* Acquire lock */                /* Acquire lock */
while(lock) {NULL;}               while(lock) {NULL;}
lock = TRUE;                      lock = TRUE;
/* Execute critical section */    /* Execute critical section */
balance = balance + amount;       balance = balance - amount;
/* Release lock */                /* Release lock */
lock = FALSE;                     lock = FALSE;
..                                ..
```

lock == FALSE
=> No process in CS
=> Any process can enter CS

lock == TRUE
=> One process in CS
=> No other process admitted to CS

Synchronizing Variable…

- What if P1 interrupted after lock Set to TRUE
  => P2 cannot execute past while does hard wait
  => Wasted CPU time
- What if P1 interrupted after Test, before Set
  => *P1 & P2 can be in the CS at the same time !!!*
- Wasted CPU time is bad, but tolerable…..
  Critical Section Violation **cannot** be tolerated
  ==> Need Un-interruptable "Test & Set" operation

Un-interruptible Test & Set

```
enter(lock) {
  disableInterrupts();
  /* Loop until lock TRUE */
  while (lock) {
    /* Let interrupts occur */
    enableInterrupts();     <- Enable interrupts so that the OS, I/O can use them
    disableInterrupts();    <- Re-disable interrupts when ready to test again
  }
  lock = TRUE;
  enableInterrupts();
}

exit(lock) {
  disableInterrupts();
  lock = FALSE;
  enableInterrupts();
}
```


Un-interruptible Test & Set…

- Solution

```
P1
enter(lock);
CS { balance = balance + amount;
exit(lock);

P2
enter(lock);
CS { balance = balance - amount;
exit(lock);
```

- Note
  - CS is totally bounded by enter/exit
  - P2 can still wait (wasted CPU cycles) if P1 is interrupted after setting lock (i.e., entering critical section), but
  - **Mutual exclusion is achieved!!!!!**
- Does not generalize to multi-processing

Protecting Multiple Components

```
Shared: list L,
        boolean ListLK = False;
        boolean LngthLK = False;

/* Program for P1 */             /* Program for P2 */
enter(listLK);                   enter(lngthLK);
   <delete element>;                <update length>;
exit(listLK);                    exit(lngthLK);
   <intermediate comp.>;         <intermediate comp.>;
enter(lngthLK);                  enter(listLK);
   <update length>;                 <delete element>;
exit(lngthLK);                   exit(listLK);
```

- Use enter/exit to update structure with 2 pieces if information
- ***But*** **try to** ***minimize time component locked out***

Protecting Multiple Components: 1st try

```
Shared: list L,
        boolean ListLK = False;
        boolean LngthLK = False;

/* Program for P1 */             /* Program for P2 */
enter(listLK);                   enter(lngthLK);
   <delete element>;                <update length>;
exit(listLK);                    exit(lngthLK);
☼ <intermediate comp.>;             <intermediate comp.>;
enter(lngthLK);                  enter(listLK);
   <update length>;                 <delete element>;
exit(lngthLK);                   exit(listLK);
```

Suppose: P1… ☼ ; P2 runs & finishes; P1 ☼ …….

Any access to lngth vble during "intermediate comp." will be incorrect !!!

=> Programming Error: List and variable need to be updated together

Protecting Multiple Components: 2nd try

```
Shared: list L,
        boolean ListLK = False;
        boolean LngthLK = False;
```

```
/* Program for P1 */
CS1 {  enter(listLK);
          <delete element>;
       ☼ <intermediate comp.>;
  CS2 {  enter(lngthLK);
            <update length>;
         exit(listLK);
         exit(lngthLK);
```

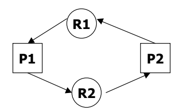
```
/* Program for P2 */
enter(lngthLK);                 } CS2
   <update length>;
⊗ <intermediate comp.>;
enter(listLK)                   } CS1
   <delete element>;
exit(lngthLK);
exit(listLK);
```

- Suppose: P1…☼ ;
  P2 runs to ⊗ and blocks ;
  P1 starts & blocks on "enter"
  => ***DEADLOCK***

Deadlock

- Deadlock
  - When 2 or more processes get into a state whereby each is holding a resource requested by the other

```
P1                          P2
.                           .
Request Resource1           Request Resource2
.                           .
Request Resource2           Request Resource1
.                           .
```




```
P1 requests and gets R1
interrupt
P2 requests and gets R2
interrupt
P1 requests R2 and blocks
P2 requests R1 and blocks
```


Solution to Synchronization

- The previous examples have illustrated 2 methods for synchronizing / coordinating processes
  - Interrupt
  - Shared variable
- Each has its own set of problems
  - Interrupt
    - May be disabled for too long
  - Shared variable
    - Test, then set – interruptible
    - Non-interruptible – gets complex
- Dijkstra introduces a 3rd and much more preferable method
  - Semaphore

Semaphore

- Dijkstra, 1965
- Synchronization primitive with <u>no busy waiting</u>
- It is an integer variable changed or tested by one of the two <u>indivisible</u> operations
- Actually implemented as a protected variable type
  `var x : semaphore`

Semaphore operations

- **P** operation ("wait")
  - Requests permission to use a critical resource

```
S = S - 1;
if (S < 0) then
      put calling process on queue
```

- **V** operation ("signal")
  - Releases the critical resource

```
S = S + 1;
if (S <= 0) then
      remove one process from queue
```

- Queues are associated with each semaphore variable

Semaphore : Example

```
Critical resource    T
Semaphore            S ← initial_value
Processes            A,B
```

Process A	Process B
.	.
P(S);	P(S);
<**CS**> /* access T */	<**CS**> /* access T */
V(S);	V(S);
.	.

Semaphore : Example…

```
var S : semaphore ← 1
```

Queue associated with S

Value of S : 1

Process A	Process B	Process C
P(S);	P(S);	P(S);
<**CS**>	<**CS**>	<**CS**>
V(S);	V(S);	V(S);

Types of Semaphores

- Binary Semaphores
  - Maximum value is 1
- Counting Semaphores
  - Maximum value is greater than 1
- Both use same P and V definitions
- Synchronizing code and initialization determines what values are needed, and therefore, what kind of semaphore will be used

Using Semaphores

```
Shared semaphore mutex = 1;

proc_1() {
  while(true) {
    <compute section>;
    P(mutex);
      <critical section>;
    V(mutex);
    }
  }

proc_2() {
  while(true) {
    <compute section>;
    P(mutex);
      <critical section>;
    V(mutex);
    }
  }
```

(1) P1 => P(mutex)
Decrements; <0 ?; NO (0);
P1 Enters CS;
P1 interrupted

(2) P2 => P(mutex)
Decrements; <0 ?; YES (-1)
P2 **blocks** on **mutex**

(3) P1 finishes CS work
P1 => V(mutex);
Increments; <=0 ?; YES (0)
P2 woken & proceeds

Non-Interruptable "Test & Sets"

Using Semaphores - Example 1

```
Shared semaphore mutex = 1;

proc_0() {
...
P(mutex);
balance = balance + amount;
V(mutex);
...
}

proc_1() {
…
P(mutex);
balance = balance - amount;
V(mutex);
...
}
```

Suppose P1 issues P(mutex) first ……
Suppose P2 issues P(mutex) first …… } No Problem

Note: Could use Interrupts to implement solution,
But (1) with interrupts masked off, what happens if a prior I/O request is satisfied
(2) Interrupt approach would not work on Multiprocessor

Using Semaphores – Example 2

Shared semaphore: s1 = 0, s2 = 0; ← Note: values started at 0… ok?

```
proc_A() {
  while(true) {
    <compute A1>;
    write(x);
    V(s1);
    <compute A2>;
    P(s2);
    read(y);
  }
}

proc_B() {
  while(true) {
    P(s1);
    read(x);
    <compute B1>;
    write(y);
    V(s2);
    <compute B2>;
  }
}
```

A signals B that "write to x" has completed (V(s1))
A blocks until B signals (P(s2))
B blocks till A signals (P(s1))
B signals A that "write to y" has completed (V(s2))

- Cannot use Interrupt disable/enable here because we have *multiple distinct synchronization points*
- Interrupt disable/enable can only distinguish 1 synchronization event
- **Therefore, 2 Semaphores**

Using Hardware Test & Set [TS(s)] to Implement Binary Semaphore "Semantics"

```
boolean s = FALSE;
...
while( TS(s) );
<critical section>
S = FALSE;
...
```

?≡

```
semaphore s = 1;
...
P(s);
<critical section>
V(s);
...
```

- **TS(s)**
  - **Test s**
  - **Set s to True**
  - **Return original value**

} ← Uninterruptable

Note: No actual queueing, each process just "hard waits"

Counting Semaphores

- Most of our examples have only required Binary Semaphore
  - Only 0 or 1 values
- But synchronization problems arise that require a more general form of semaphores
- Use counting semaphores
  - Values : non-negative integers

Classical Problems

- Producer / Consumer Problem
- Readers – Writers Problem

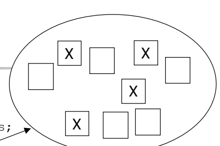
Producer / Consumer Problem (Classic)

- Critical resource
  - Set of message buffers
- 2 Processes
  - Producer : Creates a message and places it in the buffer
  - Consumer : Reads a message and deletes it from the buffer
- Objective
  - Allow the producer and consumer to run concurrently

P/C…

- Constraints
  - Producer must have a non-full buffer to put its message into
  - Consumer must have a non-empty buffer to read
  - Mutually exclusive access to Buffer pool
- Unbounded Buffer problem
  - Infinite buffers
  - Producer never has to wait
  - Not interesting nor practical
- Bounded Buffer Problem
  - Limited set of buffers

P/C - Solution




```
Shared Full: semaphore ← 0;
       Empty semaphore ← MaxBuffers;
       MEPC: semaphore ← 1;
```

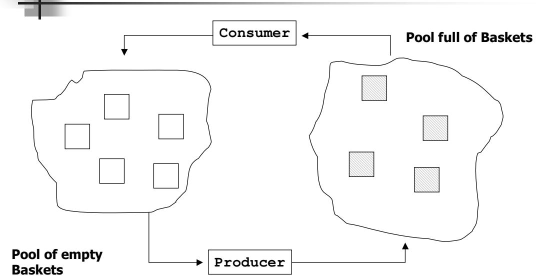
Producer

```
Begin
...
P(Empty);
P(MEPC);
<add item to buffer>
V(MEPC);
V(Full);
...
End;
```

Consumer

```
Begin
...
P(Full);
P(MEPC);
<remove item from buffer>
V(MEPC);
V(Empty);
...
End;
```


P/C – Another Look



P/C – Another Look

- 9 Baskets – Bounded
- Consumer – Empties basket
  - Can *only* remove basket from Full Pool, if one is there
    => Need "full" count
  - Emptys basket and places it in Empty pool
- Producer – Fills basket
  - Can *only* remove basket from Empty pool, if one is there
    => Need "empty" count
  - Fills basket and places it in Full pool

P/C - Another Look

```
Shared semaphore: Emutex = 1, Fmutex = 1; full = 0,  empty = 9;
Shared buf_type: buffer[9];

producer() {
  buf_type *next, *here;
  while(True) {
    produce_item(next);
    P(empty); /*Claim empty buffer*/
    P(Emutex); /*Manipulate the pool*/
    here = obtain(empty);
    V(Emutex);
    copy_buffer(next, here);
    P(Fmutex); /*Manipulate the pool*/
    release(here, fullpool);
    V(Fmutex); /*Signal full buffer*/
    V(full);
  }
}

consumer() {
  buf_type *next, *here;
  while(True) {
    P(full); /*Claim full buffer*/
    P(Fmutex); /*Manipulate the pool*/
    here = obtain(full);
    V(Fmutex);
    copy_buffer(here, next);
    P(Emutex); /*Manipulate the pool*/
    release(here, emptypool);
    V(Enmutex); /*Signal empty buffer*/
    V(empty);
    consume_item(next);
  }
}
```

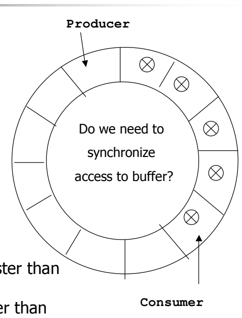

P/C - Example

- How realistic is PCP scenario?
- Consider a circular buffer
  - 12 slots
  - Producer points at next one it will fill
  - Consumer points at next one it will empty
- Don't want :

  Producer = Consumer

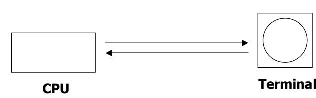
  => (1) Consumer "consumed" faster than producer "produced", or

  (2) Producer "produced" faster than consumer "consumed".



P/C – Real World Scenario

- CPU can produce data faster than terminal can accept or viewer can read

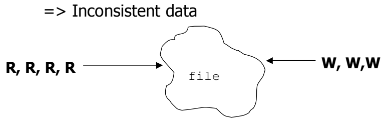


Communication buffers in both

Xon/Xoff Flow Control

Readers / Writers Problem (Classic)

- Multiple readers of the same file?
  - No problem
- Multiple writers to the same file?
  - Might be a problem writing same record
    => Potentially a "lost update"
- Writing while reading
  - Might be a problem – read might occur while being written
    => Inconsistent data



Readers – Writers Problem

- Critical resource
  - File
- Consider multiple processes which can read or write to the file
- What constraints must be placed on these processes?
  - Many readers may read at one time
  - Mutual exclusion between readers and writers
  - Mutual exclusion between writers

Strong Reader Solution

```
Shared int: readCount = 0;
        semaphore: mutexRC = 1, writeBlock = 1;

reader(){
  while(TRUE) {
    P(mutexRC);
    readCount = readCount + 1;
    if (readCount == 1)
        P(writeBlock);
    V(mutexRC);
       access_file;
    P(mutexRC);
    readCount = readCount - 1;
    if (readCount == 0)
       V(writeBlock);
    V(mutexRC);
  }
}

writer(){
  while(TRUE) {
    P(writeBlock);
       access_file;
    V(writeBlock);
  }
}
```

This solution gives preference to **Readers**

If a reader has access to file and other readers want access, they get it... all writers must wait until all readers are done

Reader / Writers – Ver 2

- Create a Strong Writer
- Give priority to a waiting writer
- If a writer wishes to access the file, then it must be the next process to enter its critical section

Strong Writers Solution

Shared int: readCount = 0, writeCount = 0
semaphore: mutex1 = 1, mutex2 = 1, readBlock = 1, writePending = 1, writeBlock = 1;

```
reader(){
  while(TRUE) {
    P(writePending);
      P(readBlock);
        P(mutex1);
          readCount = readCount + 1;
          if (readCount == 1) then
            P(writeBlock);
        V(mutex1);
      V(readBlock);
    V(writePending);
      access file;
    P(mutex1);
      readCount = readCount - 1;
      if (readCount == 0) then
        V(writeBlock);
    V(mutex1);
  }
}

writer(){
  while(TRUE) {
    P(mutex2);
      writeCount = writeCount + 1;
      if (writeCount == 1) then
         P(readBlock);
    V(mutex2);
    P(writeBlock);
       access file;
    V(writeBlock);
    P(mutex2);
      writeCount = writeCount - 1;
      if (writeCount == 0) then
         V(readBlock);
    V(mutex2);
  }
}
```


Implementing Counting Semaphores

```
struct sempahore {
  int value = <initial value>;
  boolean mutex = FALSE;
  boolean hold = TRUE;
};
Shared struct semaphore s;

P(struct sempahore s) {
  while( TS(s.mutex) );
  s.value = s.value - 1;
  if (s.value < 0) {
    s.mutex = FALSE;
    while( TS(s.hold) );
  }
else {
   s.mutex = FALSE;
}

V(struct sempahore s) {
  while( TS(s.mutex) );
  s.value = s.value + 1;
  if (s.value <= 0) {
    while( !s.hold );
    s.hold = FALSE;
  }
  s.mutex = FALSE;
}
```