

## **Formal Verification of a Lock-free Split-order Hashmap**

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**Åsmund Aqissiaq Arild Kløvstad**

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“You don’t need to understand everything at once. You understand one thing,  
then you pat yourself on the back, have a cup of coffee, and understand one  
more thing.”  
–Nada Amin



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## Introduction

Concurrent and distributed systems are extremely important in modern software development. Due to the difficulty of developing ever smaller and more powerful CPUs the trend in hardware design since about 2005 has been to increase the number of cores to allow for high levels of parallelization [1]. Additionally important areas of computing such as image processing and machine learning lend themselves well to such parallelization. [citation needed, Phuong?] At the same time software as a service and the massive scale industry giants like Amazon require a complex network of distributed systems to provide their functionality robustly and efficiently [2].

Hash tables are an important data structure for a variety of applications because they allow for data retrieval in constant time. Several lock-based hash tables for concurrent systems exist [citations], but the overhead of lock management and difficulty of resizing often make these impractical or inefficient [3]. A lock free alternative is proposed by Shalev and Shavit in [3]. This approach has proven to be useful [4] and scale better with number of concurrent processes than lock-based approaches [5].

In both small- and large-scale computer systems it is important to ensure correctness. This is especially evident in critical infrastructure, but all scales and importance levels benefit from confidence in the correctness of their systems. [citation needed]

It is therefore troublesome that such systems are incredibly difficult to design,

debug and reason about. The complexity of interactions between processes and sheer number of possible edge cases makes it infeasible for a person to determine correctness.

Early solutions to the problem of proving correctness include Hoare [6], Floyd [7] and Pnueli's [8] temporal logics and Leslie Lamport's Temporal Logic of Actions [9] which seek to formalize the execution of programs in order to reason about them with logic. These formal methods proved useful, but laborious [10].

Building on the work in temporal logics, model checkers seek to minimize the human labor and ingenuity needed to prove correctness. This is done by specifying a model using some system of logic and then letting a model checker exhaustively survey the possible states of the system. This automates the process of proving correctness. One such model checker is the TLC model checker based on Lamport's TLA and incorporated in the TLA+ IDE.

## 1.1 Thesis

Shalev et al.'s split-ordered list design is a correct extensible hashmap for concurrent systems.

Furthermore it is possible to check this using a formal model checker, and the results of this will correspond to the properties proven by Shalev et al.

## 1.2 Method

In order to prove the correctness of the hashmap, its behavior will be implemented as a specification in TLA+ [11] and the TLC model checker will be used to test the claimed invariants.

The specification will be developed in stages of increasing granularity, assuming the atomicity of operations to begin with and gradually loosening assumptions.

## 1.3 Scope?

## 1.4 Outline

**Chapter 2** discusses the motivation for formal verification and model checking, followed by a description of Temporal Logic in Section 2.1 and the TLA+ language in Section 2.2. Finally Shalev et al.'s hashmap design is described in Section 2.3.

**Chapter 3** describes the specification of the hashmap in TLA+ and the development of this specification.

Finally **Chapter 4** describes the results of model checking and discusses these in relation to our thesis in Section 4.1.



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## Background

**Model Checking: Algorithmic Verification and Debugging [10]** In the Turing Lecture by the winners of the 2007 Turing Award, Edmund Clarke, Allen Emerson and Joseph Sifakis they describe the development and use of model checkers as a verification method for computer systems. Previous efforts to prove correctness had been focused on formal proofs which have three key shortcomings:

1. they require human ingenuity,
2. they are difficult to work with in concurrent and distributed systems,
3. they scale poorly with system size and complexity.

Instead, they propose algorithmic model checkers.

With this method a Temporal Logic is used to specify the correct behavior of a system and the model checker verifies that this behavior is not violated by exploring the state space of the model. Importantly, such model checkers produce a counter example – an example of incorrect behavior – which makes debugging and correcting the system easier. Key properties of a temporal logic are *expressiveness* and *efficiency*.

Model checking also scales poorly with system complexity, so several techniques are introduced to deal with "state space explosion"

- symbolic checking of ordered binary decision diagrams
- isolation of independent events in concurrent systems
- bounded checking by solving SAT
- reduce state space by increasing level of abstraction
  - if counterexamples are found a lower abstraction level is needed, but "good" properties hold through abstraction mappings

**How Amazon Web Services Uses Formal Methods [2]** Amazon's AWS services are all underpinned by large and complex distributed systems. This is necessary for high availability, growth and cost-effective infrastructure. Traditionally these systems have been tested by savvy engineers who know what to test and look for. However, some errors are very rare and will very likely slip through such testing. To catch these errors they employ model checking (with TLA+).

The PlusCal or TLA+ specifications work as a tool to bridge the gap between design and implementation. Designs are expressive, but imprecise while the implementation is precise, but hides overall structure. Through a choice of abstraction level, specifications can bridge this gap and provide both. An expressive specification also provides useful documentation of the system.

The key benefits of model checkers at Amazon are:

- a precisely specified design helps make changes and optimizations safely. This usage improves system understanding.
- they are faster than formal proofs
- a correct design and the understanding the specs provide promote better, more correct code.

## 2.1 Temporal Logics

**The Temporal Logic of Programs [8]** In The Temporal Logic of Programs [8], Amir Pnueli proposes a unified approach to the verification of both sequential and concurrent programs. His work seeks to unify approaches to both, while also presenting a system that emulates the design intuition of programmers. The key concepts in this work are *invariance* – which covers par-

tial correctness, clean behavior, mutual exclusion and deadlock freedom – and *eventuality* – which generalizes these notions to cyclic programs and provides a special case of total correctness.

A dynamic discrete system is generalized as a three-tuple  $\langle S, R, s_0 \rangle$  where  $S$  is the set of possible states,  $R$  a transition relation, and  $s_0$  the initial state of the system. In order to make later constructions easier we further specify

$$s = \langle \pi, u \rangle$$

where  $\pi$  is the control component specifying the location in the program and  $u$  is the data component describing the state of any variables and data structures, and

$$R(\pi, u) = N(\pi, u) \wedge T(\pi, u)$$

where  $N$  describes the control flow and  $T$  the change in data such that a step in the execution may be described by

$$R(\langle \pi, u \rangle, \langle \pi', u' \rangle) \iff \pi' = N(\pi, u) \wedge u' = T(\pi, u)$$

To reason about concurrent programs we let states have multiple control components  $s = \langle \pi_1, \pi_2, \dots, \pi_n, u \rangle$  and randomly choose one control component to update in each step. Finally we let  $X$  be the set of all reachable states for the system. A predicate  $p(s)$  is **invariant** if  $p(s)$  is true  $\forall s \in X$ .

We can now start to define useful properties of the systems described in this way.

**Partial correctness** is the claim that given the correct input, a program produces the correct output. We let  $\phi(x)$  be the statement "reaching the end state  $\implies$  (correct input  $\implies$  correct output)". Partial correctness is equivalent to saying  $\phi$  is an invariant.

**Clean execution** means the program does not behave illegally, i.e it does not access illegal memory locations or divide by zero. We may define these restrictions as a predicate to make clean execution equivalent to this predicate being invariant.

**Mutual exclusion.** Given a critical section  $C$ , mutual exclusion of the processes  $\pi_1$  and  $\pi_2$  is described by the invariance of the predicate  $\neg(\pi_1 \in C \wedge \pi_2 \in C)$ .

In addition to these properties we wish to reason about *temporal* implications. We let time be described by a  $t \in \mathbb{N}$  and  $H(p, t)$  denote the value of the predicate  $p$  at time  $t$ . We then introduce the temporal operator  $p \rightsquigarrow q$  to mean

$p$  eventually leads to  $q$ , or formally:

$$p \rightsquigarrow q : \forall t_1 \exists t_2 \text{ s.t. } t_1 \leq t_2, H(p, t_1) \implies H(q, t_2)$$

For all times  $t_1$  there is a later time  $t_2$  such that if  $p$  holds at  $t_1$ ,  $q$  will hold at  $t_2$ . Armed with eventuality we can define temporally useful properties of systems.

**Total correctness** is stronger than partial correctness because it also requires that the program reaches an end state. We can express total correctness as  $\langle \pi = l_0, u = \phi \rangle \rightsquigarrow \langle \pi = l_m, u = \psi \rangle$  where  $\phi$  denotes correct input, and  $\psi$  denotes correct output and  $l_0, l_m$  are the start and end labels of the system, respectively.

**Accessibility** is the guarantee that some segment  $S$  of a program can be reached. It can be expressed by  $\pi = l_0 \rightsquigarrow \pi \in S$

**Responsiveness.** It is often desirable that some request  $r$  will be met by a response  $s$ . We call this responsiveness and describe it by  $r \rightsquigarrow s$ .

With these definitions under our belt, Pnueli defines the necessary axioms and inference rules to reason about the correctness of programs.

$$[\forall s, s' p(s) \wedge R(s, s') \implies q(s')] \Rightarrow p \rightsquigarrow q \quad (\text{A1})$$

$$(p \implies q) \Rightarrow p \rightsquigarrow q \quad (\text{A2})$$

**Figure 2.1:** Pnueli's axioms

These axioms define two ways to establish eventuality. A2 says that any logical implication is also an eventuality. A1 is a little more involved, but states that if for all consecutive states  $p$  being true in the first implies  $q$  being true in the second, then  $p$  eventually leads to  $q$ .

Using these axioms and inference rules as well as first-order logic, Pnueli goes on to formalize invariance and eventuality for sequential programs and concurrent programs.

**Invariance** of the predicate  $q(\pi, u)$  is described by the conjunction  $\bigwedge_i \pi = l_i \implies q(l_i, u)$ , asserting that  $q$  is true at all points of execution. This method is called an *attachment* of the predicate to the program.

$$p \rightsquigarrow q, \forall s, s' r(s) \wedge R(s, s') \implies r(s') \Rightarrow (p \wedge r) \rightsquigarrow (q \wedge r) \quad (\text{R1})$$

$$p \rightsquigarrow q, q \rightsquigarrow r \implies p \rightsquigarrow r \quad (\text{R2})$$

$$p_1 \rightsquigarrow q, p_2 \rightsquigarrow q \implies (p_1 \vee p_2) \rightsquigarrow q \quad (\text{R3})$$

$$p \rightsquigarrow q \implies (\exists u p) \rightsquigarrow q \quad (\text{R4})$$

**Figure 2.2:** Pnueli's inference rules

In a concurrent program we generalize  $q$  to hold when any  $\pi_i$  is updated by  $N$  and construct either a full attachment

$$\bigwedge_{i_1, i_2, \dots, i_n} (\pi_1 = i_1 \wedge \pi_2 = i_2 \wedge \dots \wedge \pi_n = i_n) \implies q(\pi_1, \dots, \pi_n, u)$$

shown here for  $n$  concurrent execution threads, or the partial attachment

$$\bigwedge_i \pi_1 = i \implies q(\pi_1 = i, \pi_2, u) \wedge \bigwedge_j \pi_2 = j \implies q(\pi_1, \pi_2 = j, u)$$

shown here for two threads  $\pi_1$  and  $\pi_2$ .

**Eventuality** is formulated as the temporal implication  $\pi = l_1 \wedge p(u) \rightsquigarrow \pi = l_2 \wedge q(u)$ . We can then describe the path between  $l_1$  and  $l_2$  by a finite sequence of steps and apply A1 to each step.

Finally, Pnueli introduces two new "tense operators" **Future** and **Global** on predicates such that at some time  $n$

$$F(p) = \exists t \geq n \ s.t \ H(t, p)$$

$$G(p) = \forall t \geq n \ H(t, p)$$

This lets us describe useful properties such as

$p \implies F(q)$  – if  $p$  is true now, then at some point in the future  $q$  will be true.

$G(p \implies F(q))$  – whenever  $p$  is true it will eventually be followed by a state in which  $q$  is true. (this is equivalent to  $p \rightsquigarrow q$ )

## 2.2 TLA+

### 2.3 Split-Ordered List Hashmap

Maybe a description of hashmaps in general here to set up the later use of table, list, key etc. or is that assumed knowledge?

Shalev et al. [3] present the first lock-free extensible hash table implemented using only loads, stores and atomic Compare and Swap (CAS).

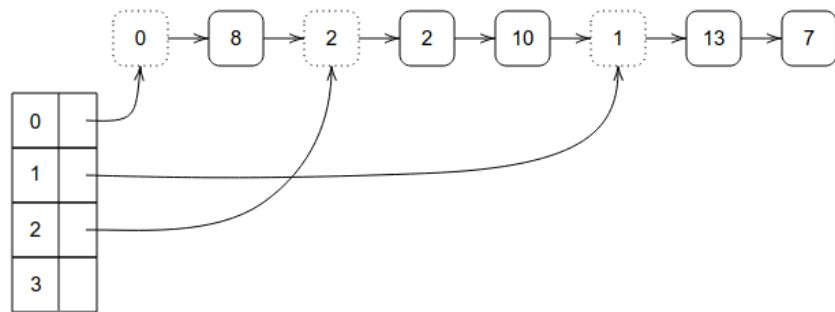
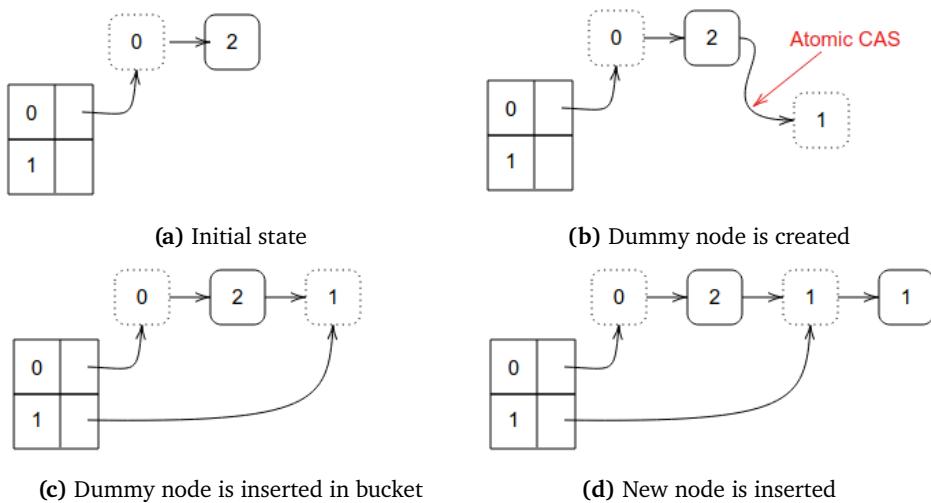
Hashmaps are a key building block in many important systems [citation needed], but are difficult to implement concurrently. In particular, the resizing (extending) of the table is difficult to do atomically because at the very least a node must be moved from one list to another. In order to avoid conflicts and loss of data in this process some overhead is required which impacts performance.

The key insight of Shalev et al. is to flip the process upside down. Instead of moving nodes between buckets, they suggest moving the buckets among a statically ordered list of nodes. This requires an ordering of the list in which a bucket can always be split into two new buckets while their contents remain correct. A node should always reside in the bucket corresponding to its key mod  $2^i$  where  $2^i$  is the current size of the table.

**Split-Ordered Lists** are introduced to make resizing of the map possible without introducing locks. By sorting the keys according to their reversed binary representation Shalev et al. obtain a list which can be always be split into buckets mod  $2^i$ . This is because such an ordering corresponds to difference in the keys'  $i$ th least significant bit, which is equivalent to having a different remainder mod  $2^i$ .

To deal with the problems caused by removing nodes pointed to by hash table entries dummy nodes with the bucket value are introduced. These nodes signify the start of a bucket and are recursively initialized when an item is inserted into an uninitialized bucket. To distinguish dummy nodes from regular nodes in the list, regular node keys have their most significant bit set to 1 before being reversed. This order and the structure of the map can be seen in Figure 2.3.

Insertion in to the map is done through atomic CAS instructions on the list. If a bucket is not initialized, a dummy node is created and inserted into the list before the new value is added as shown in Figure 2.4. The map is expanded by doubling the number of buckets and inserting new dummy nodes. Because of the split-ordering of the list, it is always possible to insert a new bucket by splitting an existing one. This process is shown in Figure 2.5.

**Figure 2.3:** The layout of the split-ordered list**Figure 2.4:** Insertion without bucket splitting

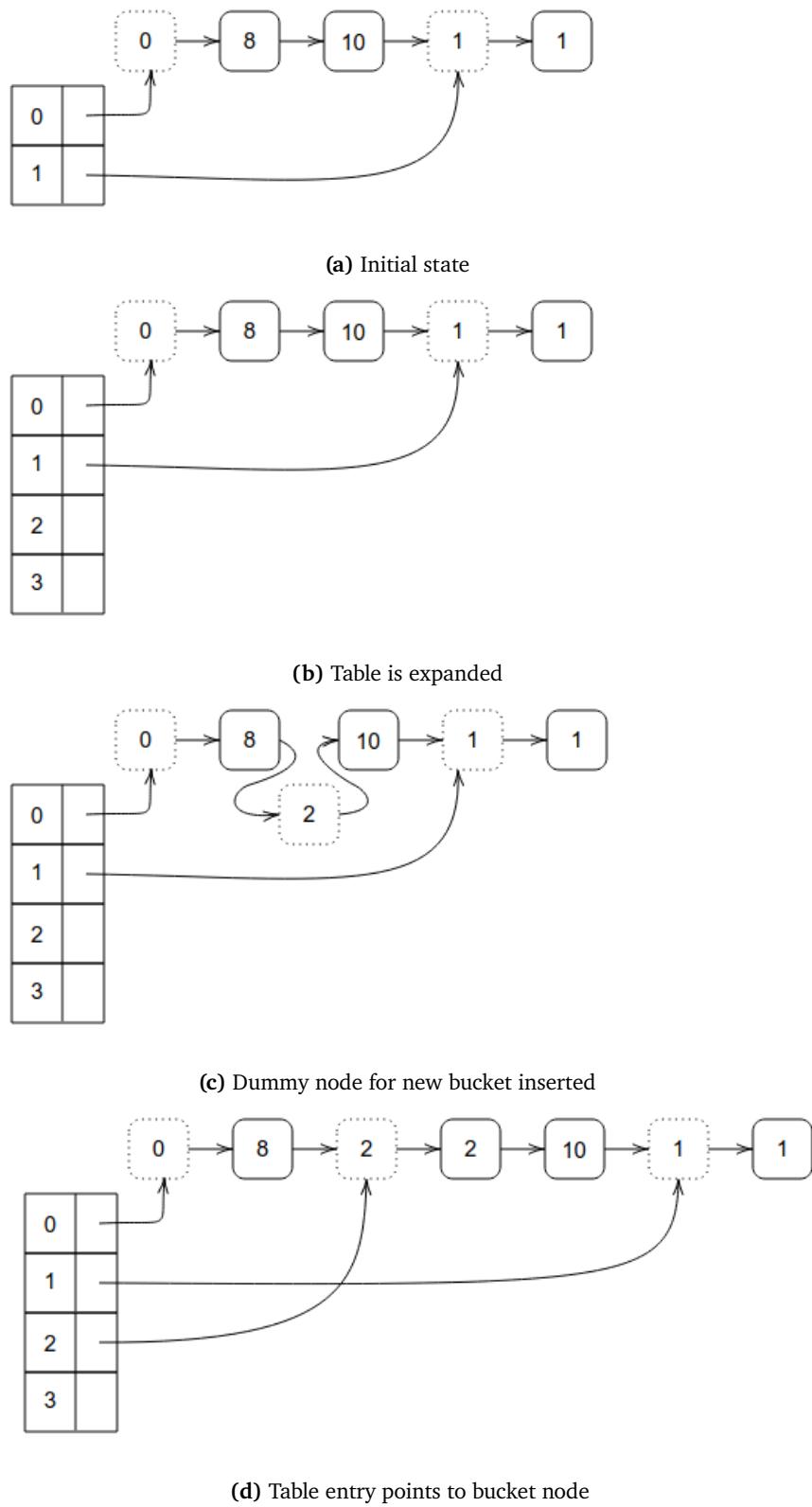


Figure 2.5: Expansion and bucket splitting

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## Specification

This chapter describes the structure of the TLA+ specification and the process of writing the specification. First we introduce the goals and scope of the specification, then describe the definitions of necessary data structures and operations.

The specification consists of two main parts:

1. a generic hashmap and
2. an [insert name of structure here] *implementing* this map.

The generic specification describes the workings of a hashmap with insert and remove operations and ensures that this structure behaves as specified. The [insert name of structure] specification describes Shalev et al.'s specific structure and algorithms for implementing hashmap functionality.

We present two versions of the specification at two levels of granularity. The first assumes the atomicity of hashmap operations, while the second describes entirely concurrent operations.

## 3.1 Goal

The purpose of our specification is to verify the claims about correctness made by Shalev et al. Because TLA+ is designed for checking liveness and safety properties [12] we will not check claims about the performance of the implementation. This leaves 4 invariants:

- the list beginning at bucket 0 is always sorted
- if a bucket is initialized, then it points to a dummy node which is in the list beginning at bucket 0
- if a key  $k$  is in the map, then `insert(k)` fails. Otherwise  $k$  is added to the map
- if a key  $k$  is in the map, then `remove(k)` removes it from the map. Otherwise it fails.

The non-concurrent specification demonstrates correctness by implementing a generic hashmap specification which describes correct behavior, while the concurrent specification looks directly at the above invariants. Additionally we will check *type safety*: at every point of execution, all keys and values are members of predefined key- and value-sets, respectively.

## 3.2 Non-Concurrent Specification

### 3.2.1 Hashmap for Implementation

The generic hashmap specification seen in Figure 3.1 describes how a hashmap *should* behave. It maintains a set of keys  $keys$  and a mapping  $map$  from keys to values. Additionally it describes two operations: insert and remove.

Insert adds a key to the set of keys and changes one entry in the map. The key is added with a set union, which preserves key uniqueness. Updating the map uses the EXCEPT construct, to say "the map is the same except the new key maps to the new value". The insert action is always enabled since there will always be keys and values in PossibleKeys and PossibleValues.

Remove removes one key from the set and changes its mapping to NULL. This is done through the set difference operator and the same EXCEPT construct as in insert. Both operations are idempotent, so attempting to remove a key that is not in the map will result in no change.

---

 MODULE *hashmap* 

---

This module describes a hashmap to be used for testing with Shalev et al.'s split-ordered list implementation of the data structure

**EXTENDS** *Integers*

**CONSTANTS** *NULL, PossibleKeys, PossibleValues*

**VARIABLES** *keys, map*

Initial state has empty map and no keys

$$\begin{aligned} \text{HashmapInit} &\stackrel{\Delta}{=} \wedge \text{keys} = \{\} \\ &\wedge \text{map} = [k \in \text{PossibleKeys} \mapsto \text{NULL}] \end{aligned}$$

Insert changes exactly one mapping of the hashmap and adds one key to the set of keys

$$\begin{aligned} \text{Insert} &\stackrel{\Delta}{=} \exists k \in \text{PossibleKeys} : \\ &\exists v \in \text{PossibleValues} : \\ &\wedge \text{keys}' = \text{keys} \cup \{k\} \\ &\wedge \text{map}' = [\text{map EXCEPT } ![k] = v] \end{aligned}$$

Remove sets exactly one mapping to NULL

$$\begin{aligned} \text{Remove} &\stackrel{\Delta}{=} \exists k \in \text{PossibleKeys} : \\ &\wedge \text{keys}' = \text{keys} \setminus \{k\} \\ &\wedge \text{map}' = [\text{map EXCEPT } ![k] = \text{NULL}] \end{aligned}$$

Next is either an insert, a remove or a find  $\text{Find}(k)$  returns NULL if not in map, otherwise a value

$$\begin{aligned} \text{HashmapNext} &\stackrel{\Delta}{=} \vee \text{Insert} \\ &\vee \text{Remove} \end{aligned}$$

TypeOK asserts all keys and values are of the right type

$$\begin{aligned} \text{TypeOK} &\stackrel{\Delta}{=} \forall k \in \text{keys} : \\ &\wedge k \in \text{PossibleKeys} \\ &\wedge \text{map}[k] \in \text{PossibleValues} \end{aligned}$$

KeyHasValue asserts that every key is mapped to a value

$$\text{KeyHasValue} \stackrel{\Delta}{=} \forall k \in \text{keys} : \neg(\text{map}[k] = \text{NULL})$$

The hashmap specification as a temporal formula

$$\text{HashmapSpec} \stackrel{\Delta}{=} \text{HashmapInit} \wedge \square[\text{HashmapNext}]_{\langle \text{keys}, \text{map} \rangle}$$


---

**Figure 3.1:** The hashmap specification

The specification also contains temporal formulae *TypeOK* and *KeyHasValue* that specify correct behavior. These have been checked with the TLC model checker [insert results here maybe?].

Finally the entire hashmap is described by *HashmapSpec*. This temporal formula states that the hashmap specification is fulfilled if the initial state fulfills *HashmapInit* and each action fulfills *HashmapNext*. This formula is used to prove a more complex specification implements the semantics of Hashmap.

The theorem  $SOSpec \Rightarrow HashmapSpec$  states that any program following the split-order specification also follows the hashmap specification. Hence, any program following the split-order specification is a correct implementation of a hashmap. It is tested by checking the property *HashmapSpec* in a model checking SOSpec.

### 3.2.2 Specification

The specification consists of three main parts:

1. the data structures,
2. operations on the map, and
3. the abstract specification tying them together.

This section describes the construction and function of each in turn.

The necessary data structures are a list of nodes and an array of buckets pointing to nodes. These are both specified as TLA+ functions. The list is a function from the set of list-keys to the set of values, while bucekts is a function from keys to list-keys. Additionally the specification includes a set of keys and a map from keys to values that correspond to the keys and map in the generic specification. The initial state of the map, showing these structures and their initial values is shown in Figure 3.2

The *Insert* and *Remove* operations are written in three layers. Figure 3.3 shows the Insert operation. First, *SOInsert* describes a very high-level view: there exists some key and some value, and we insert the value with that key. *BucketInsert* is the most involved, corresponding to the insert operation described by Shalev et al.'s pseudocode [3]. Here the correct bucket is found or initialized and the value is inserted into the list pointed to by this bucket with the split-order key. Finally, *ListInsert* inserts the value into the list, or ignores it if the node already

```

EXTENDS Integers

CONSTANTS NULL, PossibleKeys, PossibleValues, LoadFactor, MaxSize

VARIABLES keys, AuxKeys, list, buckets, size, count, map

ASSUME
   $\wedge \text{PossibleKeys} \subseteq 0..15$ 
   $\wedge \text{NULL} \notin \text{PossibleKeys}$ 
   $\wedge \text{NULL} \notin \text{PossibleValues}$ 

The Init for split-order keys is initially empty the map maps every possible key to NULL The list
initially contains only the o dummy node
 $SOInit \triangleq \wedge \text{keys} = \{\}$ 
 $\wedge \text{AuxKeys} = \{\}$ 
 $\wedge \text{list} = [n \in 0..255 \mapsto \text{IF } n = 0 \text{ THEN } SOInit(0) \text{ ELSE } \text{NULL}]$ 
 $\wedge \text{buckets} = [m \in \text{PossibleKeys} \mapsto \text{IF } m = 0 \text{ THEN } SOInit(0) \text{ ELSE } \text{NULL}]$ 
 $\wedge \text{size} = 1$ 
 $\wedge \text{count} = 0$ 
 $\wedge \text{map} = [k \in \text{PossibleKeys} \mapsto \text{NULL}]$ 

```

**Figure 3.2:** The initial state of the specificaiton

```

 $SOInsert \triangleq \wedge \exists k \in \text{PossibleKeys} :$ 
 $\exists v \in \text{PossibleValues} :$ 
 $BucketInsert(k, v)$ 

 $BucketInsert(k, v) \triangleq$ 
Either a bucket needs to be initialized
 $\vee \wedge \text{buckets}[k\%size] = \text{NULL}$ 
 $\wedge \text{BucketInit}(k\%size)$ 
 $\wedge \text{ListInsert}(SORRegularKey(k), v)$ 
 $\wedge \text{AuxKeys}' = \text{AuxKeys} \cup \{k\}$ 
Or the bucket is already initialized
 $\vee \wedge \text{buckets}[k\%size] \neq \text{NULL}$ 
 $\wedge \text{ListInsert}(SORRegularKey(k), v)$ 
 $\wedge \text{AuxKeys}' = \text{AuxKeys} \cup \{k\}$ 
 $\wedge \text{UNCHANGED } \langle \text{buckets} \rangle$ 

 $ListInsert(k, v) \triangleq \text{IF } \text{list}[k] = \text{NULL}$ 
 $\text{THEN } \text{list}' = [\text{list EXCEPT } ![k] = v] \wedge \text{count}' = \text{count} + 1$ 
 $\text{ELSE } \text{UNCHANGED } \langle \text{list}, \text{count} \rangle$ 

```

**Figure 3.3:** The *Insert* operation

$$\begin{aligned} SONext \triangleq & \quad \vee SOInsert \wedge BucketGrow \wedge \text{UNCHANGED } \langle map, keys \rangle \\ & \vee SORemove \wedge \text{UNCHANGED } \langle size, map, keys \rangle \\ & \vee SOFind \wedge \text{UNCHANGED } \langle size, count, list \rangle \end{aligned}$$
**Figure 3.4:** The Next action
$$\begin{aligned} SOFind \triangleq & \exists k \in AuxKeys : \\ & \wedge keys' = keys \cup \{k\} \\ & \wedge AuxKeys' = AuxKeys \setminus \{k\} \\ & \wedge \text{IF } buckets[k \% size] = \text{NULL} \\ & \quad \text{THEN } \wedge \text{BucketInit}(k \% size) \\ & \wedge map' = [map \text{ EXCEPT } ![k] = \text{ListFind}(k \% size, SOResultKey(k))] \\ & \text{ELSE } \wedge \text{UNCHANGED } buckets \\ & \wedge map' = [map \text{ EXCEPT } ![k] = \text{ListFind}(k \% size, SOResultKey(k))] \end{aligned}$$
**Figure 3.5:** The *SOFind* operation

has a value.

Finally, the *Next* action shown in Figure 3.4 describes the transition of the system from one state to another. It states that such a transition consists of either inserting and growing the map, removing, or the *SOFind* operation.

The *SOFind* operation shown in Figure 3.5 corresponds to the find operation in Shalev et al.'s pseudocode and is responsible for updating the map. Because we wish to show that this specification implements the generic hashmap it is necessary to update the set of keys and the map itself at the same time and so a set of auxiliary keys is maintained and only added to the "real" map once a find operation looks for them. Using the "working variables" trick, the specification can be shown to implement the generic hashmap through implication as seen in Figure 3.6.

### 3.3 Concurrent Specification

$$\begin{aligned} SOSpec \triangleq & \quad SOInit \wedge \square[SONext]_{\langle keys, AuxKeys, list, buckets, size, count, map \rangle} \\ \text{INSTANCE } & \text{hashmap} \\ \text{THEOREM } & SOSpec \implies \text{HashmapSpec} \end{aligned}$$
**Figure 3.6:** Implementation of generic hashmap

# 4

## Results

### 4.1 Discussion

[some sort of introduction]

The first attempt at writing a specification served as a learning tool for the TLA+ language, but did not produce a useful specification for the purpose of proving correctness in a concurrent setting. The structure of the specification was based on the structure of an implementation in that actions correspond to the *insert*, *delete* and *bucket init* functions in Shalev et al.'s pseudocode. Such a structure brings with it the implicit assumption that the functions are linearizable since one action corresponds to one state transition.

The attempt to show correctness through implementation also posed difficulties. The idealized hashmap specification proved impossible to directly map to the split-order specification because a *find* operation may result in a bucket needing to be initialized and thus can not be used directly in a refinement mapping. Instead we introduced a set of auxiliary variables [13] and maintained an idealized map that was updated in atomic steps to implement the Hashmap specification. The updates loosely correspond to a *find* operation and the correctness of this idealized map does seem to correspond to a correct underlying structure (albeit at an earlier state), but introduces additional complexity to the spec and does not resolve the underlying issue of assumed linearizability.



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# Split-order Specification

———— MODULE *SplitOrder* —————

This module implements a hashmap using Shalev et al.'s split-ordered list structure

EXTENDS *Integers*

CONSTANTS *NULL*, *PossibleKeys*, *PossibleValues*, *LoadFactor*, *MaxSize*

VARIABLES *keys*, *list*, *buckets*, *size*, *count*

ASSUME

$\wedge \text{PossibleKeys} \subseteq 0 \dots 15$

$\wedge \text{NULL} \notin \text{PossibleKeys}$

$\wedge \text{NULL} \notin \text{PossibleValues}$

The Init for split-order keys is initially empty the map maps every possible key to NULL  
The list initially contains only the o dummy node

$SOInit \stackrel{\Delta}{=} \wedge \text{keys} = \{\}$

$\wedge \text{list} = [\text{n} \in 0 \dots 255 \mapsto \text{IF } \text{n} = 0 \text{ THEN } 0 \text{ ELSE } \text{NULL}]$

$\wedge \text{buckets} = [\text{m} \in \text{PossibleKeys} \mapsto \text{IF } \text{m} = 0 \text{ THEN } 0 \text{ ELSE } \text{NULL}]$

$\wedge \text{size} = 1$

$\wedge \text{count} = 0$

Lookup table for bit-reversed keys with MSB set

$$SORegularKey(k) \triangleq \text{CASE } k = 0 \rightarrow 1$$

$$\square k = 1 \rightarrow 9$$

$$\square k = 2 \rightarrow 5$$

$$\square k = 3 \rightarrow 13$$

$$\square k = 4 \rightarrow 3$$

$$\square k = 5 \rightarrow 11$$

$$\square k = 6 \rightarrow 7$$

$$\square k = 7 \rightarrow 15$$

$$\square k = 8 \rightarrow 1$$

$$\square k = 9 \rightarrow 9$$

$$\square k = 10 \rightarrow 5$$

$$\square k = 11 \rightarrow 13$$

$$\square k = 12 \rightarrow 3$$

$$\square k = 13 \rightarrow 11$$

$$\square k = 14 \rightarrow 7$$

$$\square k = 15 \rightarrow 15$$

Lookup table for bit-reversed keys

$$SODummyKey(k) \triangleq \text{CASE } k = 0 \rightarrow 0$$

$$\square k = 1 \rightarrow 8$$

$$\square k = 2 \rightarrow 4$$

$$\square k = 3 \rightarrow 12$$

$$\square k = 4 \rightarrow 2$$

$\square k = 5 \rightarrow 10$

$\square k = 6 \rightarrow 6$

$\square k = 7 \rightarrow 14$

$\square k = 8 \rightarrow 1$

$\square k = 9 \rightarrow 9$

$\square k = 10 \rightarrow 5$

$\square k = 11 \rightarrow 13$

$\square k = 12 \rightarrow 3$

$\square k = 13 \rightarrow 11$

$\square k = 14 \rightarrow 7$

$\square k = 15 \rightarrow 15$

Lookup table for parent buckets

$Parent(b) \triangleq \begin{cases} \text{CASE } b = 0 \rightarrow 0 \\ \dots \end{cases}$

$\square b = 1 \rightarrow 0$

$\square b = 2 \rightarrow 0$

$\square b = 3 \rightarrow 1$

$\square b = 4 \rightarrow 0$

$\square b = 5 \rightarrow 1$

$\square b = 6 \rightarrow 2$

$\square b = 7 \rightarrow 3$

$\square b = 8 \rightarrow 0$

$\square b = 9 \rightarrow 1$

$\square b = 10 \rightarrow 2$

$\square b = 11 \rightarrow 3$

$\square b = 12 \rightarrow 8$

$\square b = 13 \rightarrow 5$

$\square b = 14 \rightarrow 6$

$\square b = 15 \rightarrow 7$

Inserting into the "linked list"

$ListInsert(k, v) \triangleq \text{IF } list[k] = NULL$

THEN  $list' = [list \text{ EXCEPT } ![k] = v] \wedge count' = count + 1$

ELSE UNCHANGED  $\langle list, count \rangle$

Removing from the "linked list"

$ListRemove(k) \triangleq \text{IF } list[k] = NULL$

THEN UNCHANGED  $\langle list, count \rangle$

ELSE  $list' = [list \text{ EXCEPT } ![k] = NULL] \wedge count' = count - 1$

Recursively initializes buckets

RECURSIVE  $BucketInit(\_)$

$BucketInit(b) \triangleq \text{IF } buckets[Parent(b)] = NULL \wedge Parent(b) \neq 0$

THEN  $BucketInit(Parent(b))$

ELSE  $buckets' = [buckets \text{ EXCEPT } ![b] = SODummyKey(b)]$

Find the value of the key k in the bucket b Results in the value if b is initialized and k is in b

$ListFind(b, k) \triangleq \text{IF } k > b \wedge list[b] \neq NULL \text{ THEN } list[k] \text{ ELSE } NULL$

SOFind finds a key in the map

$SOFind(k) \triangleq \text{IF } buckets[k\%size] = \text{NULL}$

THEN  $\text{NULL}$  should initialize bucket, but also needs a "return value"

ELSE  $ListFind(buckets[k\%size], k)$

$Min(a, b) \triangleq \text{IF } a > b \text{ THEN } b \text{ ELSE } a$

$BucketGrow \triangleq \text{IF } count \neq 0 \wedge size \div count > LoadFactor$

THEN  $size' = Min(size * 2, MaxSize) \wedge \text{UNCHANGED } \langle keys, list, buckets, count \rangle$

ELSE  $\text{UNCHANGED } \langle keys, list, buckets, count, size \rangle$

Inserting into the buckets

$BucketInsert(k, v) \triangleq \text{Either a bucket needs to be initialized}$

$\vee \wedge buckets[k\%size] = \text{NULL}$

$\wedge BucketInit(k\%size)$

$\wedge ListInsert(SORegularKey(k), v)$

$\wedge keys' = keys \cup \{k\}$

Or the bucket is already initialized

$\vee \wedge buckets[k\%size] \neq \text{NULL}$

$\wedge ListInsert(SORegularKey(k), v)$

$\wedge keys' = keys \cup \{k\}$

$\wedge \text{UNCHANGED } \langle buckets \rangle$

Removing from the buckets

$BucketRemove(k) \triangleq \wedge ListRemove(SORegularKey(k))$

$\wedge keys' = keys \setminus \{k\}$

$\wedge \text{UNCHANGED } \langle buckets \rangle$

$SOInsert \triangleq \wedge \exists k \in PossibleKeys :$

$\exists v \in PossibleValues :$

$BucketInsert(k, v)$

$\wedge \text{UNCHANGED } size$

$SORemove \triangleq \wedge \exists k \in PossibleKeys :$

$BucketRemove(k)$

$\wedge \text{UNCHANGED } size$

The Next for split order

$SONext \triangleq \vee SOInsert$

$\vee SORemove$

$\vee BucketGrow$

Split-order spec

$SOSpec \triangleq SOInit \wedge \square [SONext]_{\langle keys, list, buckets, size, count \rangle}$

If I can get map to work as intended...

refinement mapping??

INSTANCE  $hashmap$  WITH  $map \leftarrow [k \in PossibleKeys \mapsto SOFind(k)]$   
Split-order implements  $hashmap$

THEOREM  $SOSpec \implies HashmapSpec$

[ ]