Thread-Local Storage

- **Thread-local storage** (**TLS**) allows each thread to have its own copy of data
- Useful when you do not have control over the thread creation process (i.e., when using a thread pool)
- Different from local variables
  - Local variables visible only during single function invocation
  - TLS visible across function invocations
- Similar to `static` data
  - TLS is unique to each thread

Linux Threads

- Linux refers to them as ***tasks*** rather than ***threads***
- Thread creation is done through **`clone()`** system call
- **`clone()`** allows a child task to share the address space of the parent task (process)
  - Flags control behavior

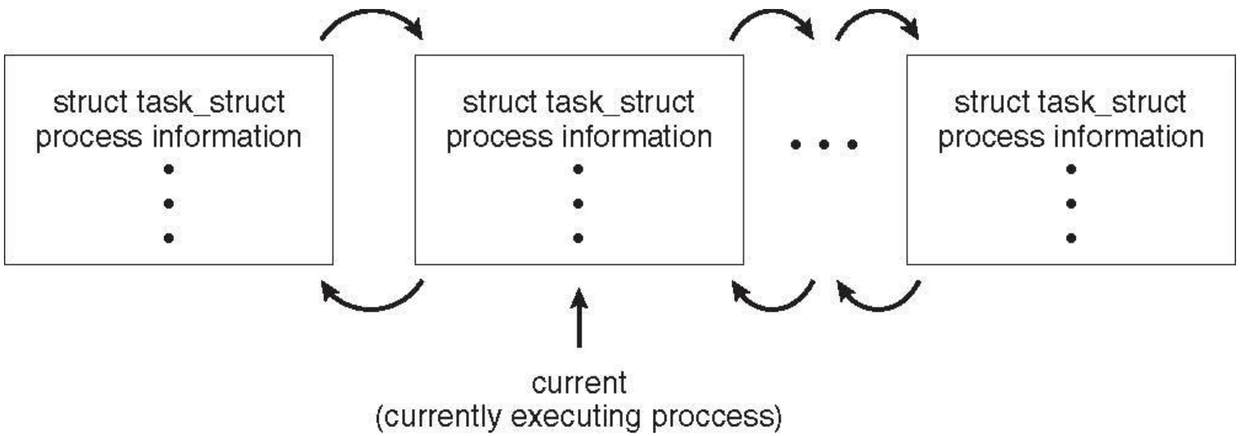
flag	meaning
`CLONE_FS`	File-system information is shared.
`CLONE_VM`	The same memory space is shared.
`CLONE_SIGHAND`	Signal handlers are shared.
`CLONE_FILES`	The set of open files is shared.

- **`struct task_struct`** points to process data structures (shared or unique)

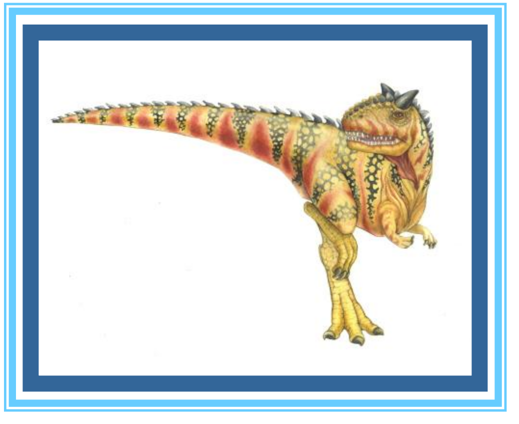
Process Representation in Linux

Represented by the C structure `task_struct`

```
pid t_pid; /* process identifier */
long state; /* state of the process */
unsigned int time_slice /* scheduling information */
struct task_struct *parent; /* this process's parent */
struct list_head children; /* this process's children */
struct files_struct *files; /* list of open files */
struct mm_struct *mm; /* address space of this process */
```



Chapter 5: Process Synchronization



Chapter 5: Process Synchronization

- Background
- The Critical-Section Problem
- Peterson's Solution
- Synchronization Hardware
- Mutex Locks
- Semaphores
- Classic Problems of Synchronization
- Monitors
- Synchronization Examples
- Alternative Approaches

Objectives

- To present the concept of process synchronization.
- To introduce the critical-section problem, whose solutions can be used to ensure the consistency of shared data
- To present both software and hardware solutions of the critical-section problem
- To examine several classical process-synchronization problems
- To explore several tools that are used to solve process synchronization problems

Background

- Processes can execute concurrently
  - May be interrupted at any time, partially completing execution
- Concurrent access to shared data may result in data inconsistency
- Maintaining data consistency requires mechanisms to ensure the orderly execution of cooperating processes
- Illustration of the problem:
  Suppose that we wanted to provide a solution to the consumer-producer problem that fills ***all*** the buffers. We can do so by having an integer **counter** that keeps track of the number of full buffers. Initially, **counter** is set to 0. It is incremented by the producer after it produces a new buffer and is decremented by the consumer after it consumes a buffer.

Producer

```
while (true) {
        /* produce an item in next produced */

        while (counter == BUFFER_SIZE) ;
                /* do nothing */
        buffer[in] = next_produced;
        in = (in + 1) % BUFFER_SIZE;
        counter++;
}
```

Consumer

```
while (true) {
        while (counter == 0)
                ; /* do nothing */
        next_consumed = buffer[out];
        out = (out + 1) % BUFFER_SIZE;
         counter--;
        /* consume the item in next consumed */
}
```

Race Condition

- **`counter++`** could be implemented as

```
register1 = counter
register1 = register1 + 1
counter = register1
```

- **`counter--`** could be implemented as

```
register2 = counter
register2 = register2 - 1
counter = register2
```

- Consider this execution interleaving with "count = 5" initially:

S0: producer execute `register1 = counter`	{register1 = 5}
S1: producer execute `register1 = register1 + 1`	{register1 = 6}
S2: consumer execute `register2 = counter`	{register2 = 5}
S3: consumer execute `register2 = register2 - 1`	{register2 = 4}
S4: producer execute `counter = register1`	{counter = 6 }
S5: consumer execute `counter = register2`	{counter = 4}

Critical Section Problem

- Consider system of ***n*** processes {$p_0, p_1, \ldots p_{n-1}$}
- Each process has **critical section** segment of code
  - Process may be changing common variables, updating table, writing file, etc
  - When one process in critical section, no other may be in its critical section
- ***Critical section problem*** is to design protocol to solve this
- Each process must ask permission to enter critical section in **entry section**, may follow critical section with **exit section**, then **remainder section**

Critical Section

- General structure of process ***P**$_i$*

```
do {
      entry section
            critical section
      exit section
            remainder section
} while (true);
```

Algorithm for Process P_i

```
do {

     while (turn == j);

               critical section

     turn = j;

               remainder section

 } while (true);
```

Solution to Critical-Section Problem

1. **Mutual Exclusion** - If process $\boldsymbol{P_i}$ is executing in its critical section, then no other processes can be executing in their critical sections
2. **Progress** - If no process is executing in its critical section and there exist some processes that wish to enter their critical section, then the selection of the processes that will enter the critical section next cannot be postponed indefinitely
3. **Bounded Waiting** - A bound must exist on the number of times that other processes are allowed to enter their critical sections after a process has made a request to enter its critical section and before that request is granted
   - Assume that each process executes at a nonzero speed
   - No assumption concerning **relative speed** of the ***n*** processes

Critical-Section Handling in OS

Two approaches depending on if kernel is preemptive or non-preemptive

- **Preemptive** – allows preemption of process when running in kernel mode
- **Non-preemptive** – runs until exits kernel mode, blocks, or voluntarily yields CPU
  - Essentially free of race conditions in kernel mode

Preview of pre-empive and non-pre-emptive kernel scheduling (Linux)

- SCHED_FIFO and SCHED_RR are so called "real-time" policies. They implement the fixed-priority real-time scheduling specified by the POSIX standard. Tasks with these policies preempt every other task, which can thus easily go into starvation (if they don't release the CPU).
- The difference between SCHED_FIFO and SCHED_RR is that among tasks with the same priority, SCHED_RR performs a round-robin with a certain timeslice; SCHED_FIFO, instead, needs the task to explicitly yield the processor.
- SCHED_OTHER is the common round-robin time-sharing scheduling policy that schedules a task for a certain timeslice depending on the other tasks running in the system.
- **Update**: since Linux 3.14, there is an additional policy called SCHED_DEADLINE. This policy implements the Earliest Deadline First real-time scheduling algorithm. Each task under this policy is assigned a deadline, and the earliest-deadline task is executed.
- Consult the Linux man page *man7.org/linux/man-pages/man7/sched.7.html*

Peterson's Solution

- Good algorithmic description of solving the problem
- Two process solution
- Assume that the **`load`** and **`store`** machine-language instructions are atomic; that is, cannot be interrupted
- The two processes share two variables:
  - **`int turn;`**
  - **`Boolean flag[2]`**
- The variable **`turn`** indicates whose turn it is to enter the critical section
- The **`flag`** array is used to indicate if a process is ready to enter the critical section. **`flag[i] =`** ***`true`*** implies that process $\mathbf{P_i}$ is ready!

Algorithm for Process P_i

```
do {
      flag[i] = true;
      turn = j;
      while (flag[j] && turn = = j);
               critical section
      flag[i] = false;
               remainder section
 } while (true);
```

NOTE: if (i) and (j) want to enter the critical sector at the same time, both flag[i] and flag[j] will be set to true. But whichever of (i) or (j) gets there later, “turn” will be set to that of the other.

So if both flags are true, **turn** will point to one or the other, and that process will proceed.

If (j) proceeds while (i) is waiting on **while (flag[j] && turn = = j);** flag [j] will be set to false, and (i) will proceed.

Peterson's Solution (Cont.)

- Provable that the three CS requirement are met:

  1. Mutual exclusion is preserved

     P_i enters CS only if:

     either **`flag[j] = false`** or **`turn = i`**

  2. Progress requirement is satisfied since one or the other of (i) or (j) is always allowed into the critical sector – you cannot have the situation in which both flags are true and turn is 2 values at once!

  3. Bounded-waiting requirement is met since whichever of (i) or (j) is waiting on the loop while (flag[j] && turn = = j); will not change the value of "turn", so as soon as the other one leaves the critical sector, "turn" will point to the waiting process.

Synchronization Hardware

- Many systems provide hardware support for implementing the critical section code.
- All solutions below based on idea of **locking**
  - Protecting critical regions via locks
- Uniprocessors – could disable interrupts
  - Currently running code would execute without preemption
  - Generally too inefficient on multiprocessor systems
    - Operating systems using this not broadly scalable
- Modern machines provide special atomic hardware instructions
    - **Atomic** = non-interruptible
  - Either test memory word and set value
  - Or swap contents of two memory words

Solution to Critical-section Problem Using Locks

```
do {
    acquire lock
            critical section
    release lock
            remainder section
} while (TRUE);
```

test_and_set Instruction

Definition:

```
boolean test_and_set (boolean *target)
  {
       boolean rv = *target;
       *target = TRUE;
       return rv:
  }
```

1. Executed atomically
2. Returns the original value of passed parameter (could be TRUE or FALSE, initialized to FALSE – see next slide)
3. Set the new value of passed parameter to “TRUE”.

Solution using test_and_set()

- Shared Boolean variable lock, initialized to FALSE
- Solution:

```
do {
    while (test_and_set(&lock))
        ; /* do nothing */
            /* critical section */
    lock = false;
            /* remainder section */
 } while (true);
```

compare_and_swap Instruction

Definition:

```
int compare _and_swap(int *value, int expected, int new_value) {
    int temp = *value;

    if (*value == expected)
       *value = new_value;
 return temp;
}
```

1. Executed atomically
2. Returns the original value of passed parameter "value"
3. Set the variable "value" the value of the passed parameter "new_value" but only if "value" =="expected". That is, the swap takes place only under this condition.

Solution using compare_and_swap

- Shared integer "lock" initialized to 0;
- Solution:

```
do {
     while (compare_and_swap(&lock, 0, 1) != 0)
      ; /* do nothing */
   /* critical section */
 lock = 0;
   /* remainder section */
} while (true);
```

Bounded-waiting Mutual Exclusion with test_and_set

```
do {
   waiting[i] = true;
   key = true;
   while (waiting[i] && key)
      key = test_and_set(&lock);
   waiting[i] = false;
   /* critical section */
   j = (i + 1) % n;
   while ((j != i) && !waiting[j])
      j = (j + 1) % n;
   if (j == i)
      lock = false;
   else
      waiting[j] = false;
   /* remainder section */
} while (true);
```

Mutex Locks

- Previous solutions are complicated and generally inaccessible to application programmers
- OS designers build software tools to solve critical section problem
- Simplest is mutex lock
- Protect a critical section by first **`acquire()`** a lock then **`release()`** the lock
  - Boolean variable indicating if lock is available or not
- Calls to **`acquire()`** and **`release()`** must be atomic
  - Usually implemented via hardware atomic instructions
- But this solution requires **busy waiting**
  - This lock therefore called a **spinlock**

acquire() and release()

- ```
  acquire() {
     while (!available)
        ; /* busy wait */
     available = false;;
  }
  ```
- ```
  release() {
     available = true;
  }
  ```
- ```
  do {
  acquire lock
     critical section
  release lock
    remainder section
  } while (true);
  ```
  ```

Semaphore

- Synchronization tool that provides more sophisticated ways (than Mutex locks) for process to synchronize their activities.
- Semaphore ***S*** – integer variable
- Can only be accessed via two indivisible (atomic) operations
  - **`wait()`** and **`signal()`**
    - Originally called **`P()`** and **`V()`**
- Definition of the **`wait() operation`**

```
wait(S) {
    while (S <= 0)
       ; // busy wait
    S--;
}
```

- Definition of the **`signal() operation`**

```
signal(S) {
    S++;
}
```

Semaphore Usage

- **Counting semaphore** – integer value can range over an unrestricted domain
- **Binary semaphore** – integer value can range only between 0 and 1
  - Same as a **mutex lock**
- Can solve various synchronization problems
- Consider $\boldsymbol{P_1}$ and $\boldsymbol{P_2}$ that require $\boldsymbol{S_1}$ to happen before $\boldsymbol{S_2}$

  Create a semaphore "`synch`" initialized to 0

```
P1:
    S1;
    signal(synch);
P2:
    wait(synch);
    S2;
```

- Can implement a counting semaphore ***S*** as a binary semaphore

Semaphore Implementation

- Must guarantee that no two processes can execute the **`wait()`** and **`signal()`** on the same semaphore at the same time
- Thus, the implementation becomes the critical section problem where the **`wait`** and **`signal`** code are placed in the critical section
  - Could now have **busy waiting** in critical section implementation
    - But implementation code is short
    - Little busy waiting if critical section rarely occupied
- Note that applications may spend lots of time in critical sections and therefore this is not a good solution

Semaphore Implementation with no Busy waiting

- With each semaphore there is an associated waiting queue
- Each entry in a waiting queue has two data items:
  - value (of type integer)
  - pointer to next record in the list
- Two operations:
  - **block** – place the process invoking the operation on the appropriate waiting queue
  - **wakeup** – remove one of processes in the waiting queue and place it in the ready queue
-
```
typedef struct{
int value;
struct process *list;
} semaphore;
```

Implementation with no Busy waiting (Cont.)

```
wait(semaphore *S) {
   S->value--;
   if (S->value < 0) {
      add this process to S->list;
      block();
   }
}

signal(semaphore *S) {
   S->value++;
   if (S->value <= 0) {
      remove a process P from S->list;
      wakeup(P);
   }
}
```

Sample UNIX parent semaphore code

```
/*Semaphore implementation -- parent*/
#include        <sys/ipc.h>
....
#define SEMKEY 85  /*semaphore id passed to children*/
....
int semid;
struct sembuf psembuf, vsembuf ; /*sembuf type defined in ipcs.h */
....
/* create and initialize semaphore in the parent */
        if((semid=semget(SEMKEY, 1, 0777|IPC_CREAT))==-1)
                {
                perror("semget failed in matrix");
                exit(0);
                }
        varray[0]=1;
        semctl(semid,1,SETALL, varray);
        semctl(semid,1, GETALL, outarray);
        printf("sem init value %d \n", outarray[0]);
        /* semaphore set up*/

.....
```

Sample UNIX child semaphore code

```
int                    semid;
struct                 sembuf psembuf, vsembuf;
.....
/*P or "wait" operation*/
if((semid=semget(SEMKEY,1, 0777))==-1)
          {
          perror("semget failed");
          exit(0);
          }
psembuf.sem_op=-1;
psembuf.sem_flg=SEM_UNDO;
psembuf.sem_num=0;
if((semop(semid,&psembuf,1))==-1)
          {
          perror("semop p failed");
          exit(0);
...............
/*V or "signal" operation-- finished with critical sector*/
vsembuf.sem_op=1;
vsembuf.sem_flg=SEM_UNDO;
vsembuf.sem_num=0;
if((semop(semid,&vsembuf,1))==-1)
          {
          perror("semop v failed");
          exit(0);
          }
```

Deadlock and Starvation

- **Deadlock** – two or more processes are waiting indefinitely for an event that can be caused by only one of the waiting processes
- Let ***S*** and ***Q*** be two semaphores initialized to 1

P_0	P_1
`wait(S);`	`wait(Q);`
`wait(Q);`	`wait(S);`
`...`	`...`
`signal(S);`	`signal(Q);`
`signal(Q);`	`signal(S);`

- **Starvation** – **indefinite blocking**
  - A process may never be removed from the semaphore queue in which it is suspended
- **Priority Inversion** – Scheduling problem when lower-priority process holds a lock needed by higher-priority process
  - Solved via **priority-inheritance protocol**

Classical Problems of Synchronization

- Classical problems used to test newly-proposed synchronization schemes
  - Bounded-Buffer Problem
  - Readers and Writers Problem
  - Dining-Philosophers Problem

Bounded-Buffer Problem

- ***n*** buffers, each can hold one item
- Semaphore **`mutex`** initialized to the value 1
- Semaphore **`full`** initialized to the value 0
- Semaphore **`empty`** initialized to the value n

Bounded Buffer Problem (Cont.)

- The structure of the producer process

```
do {
      ...
       /* produce an item in next_produced */
      ...
    wait(empty);
    wait(mutex);
       ...
       /* add next produced to the buffer */
       ...
    signal(mutex);
    signal(full);
 } while (true);
```

Bounded Buffer Problem (Cont.)

- The structure of the consumer process

```
Do {
    wait(full);
    wait(mutex);
        ...
    /* remove an item from buffer to next_consumed */
        ...
    signal(mutex);
    signal(empty);
        ...
    /* consume the item in next consumed */
        ...
 } while (true);
```

Semaphore Implementation from Stallings

```
semWait(s)
{
   while (compare_and_swap(s.flag, 0 , 1) == 1)
      /* do nothing */;
   s.count--;
   if (s.count < 0) {
      /* place this process in s.queue*/;
      /* block this process (must also set
s.flag to 0) */;
   }
   s.flag = 0;
}

semSignal(s)
{
   while (compare_and_swap(s.flag, 0 , 1) == 1)
      /* do nothing */;
   s.count++;
   if (s.count<= 0) {
      /* remove a process P from s.queue */;
      /* place process P on ready list */;
   }
   s.flag = 0;
}
```

(a) Compare and Swap Instruction

```
semWait(s)
{
   inhibit interrupts;
   s.count--;
   if (s.count < 0) {
      /* place this process in s.queue */;
      /* block this process and allow inter-
rupts*/;
   }
   else
      allow interrupts;
}

semSignal(s)
{
   inhibit interrupts;
   s.count++;
   if (s.count<= 0) {
      /* remove a process P from s.queue */;
      /* place process P on ready list */;
   }
   allow interrupts;
}
```

(b) Interrupts

Readers-Writers Problem

- A data set is shared among a number of concurrent processes
  - Readers – only read the data set; they do ***not*** perform any updates
  - Writers – can both read and write
- Problem – allow multiple readers to read at the same time
  - Only one single writer can access the shared data at the same time
- Several variations of how readers and writers are considered – all involve some form of priorities
- Shared Data
  - Data set
  - Semaphore **`rw_mutex`** initialized to 1
  - Semaphore **`mutex`** initialized to 1
  - Integer **`read_count`** initialized to 0

Readers-Writers Problem (Cont.)

- The structure of a writer process

```
do {
        wait(rw_mutex);
           ...
        /* writing is performed */
           ...
     signal(rw_mutex);
} while (true);
```

Readers-Writers Problem (Cont.)

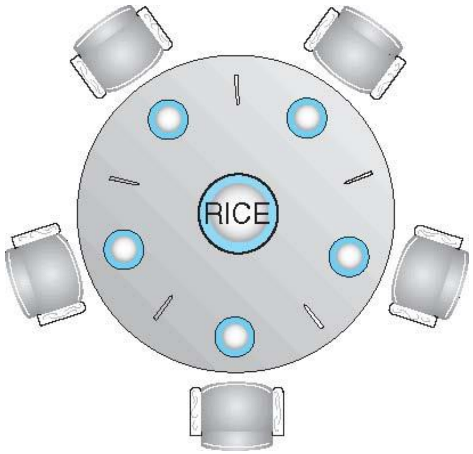
- The structure of a reader process

```
do {
        wait(mutex);
        read_count++;
        if (read_count == 1)
        wait(rw_mutex);
    signal(mutex);
         ...
        /* reading is performed */
         ...
    wait(mutex);
        read count--;
        if (read_count == 0)
    signal(rw_mutex);
    signal(mutex);
} while (true);
```

Readers-Writers Problem Variations

- ***First*** variation – no reader kept waiting unless writer has permission to use shared object
- ***Second*** variation – once writer is ready, it performs the write ASAP
- Both may have starvation leading to even more variations
- Problem is solved on some systems by kernel providing reader-writer locks

Dining-Philosophers Problem



- Philosophers spend their lives alternating thinking and eating
- Don't interact with their neighbors, occasionally try to pick up 2 chopsticks (one at a time) to eat from bowl
  - Need both to eat, then release both when done
- In the case of 5 philosophers
  - Shared data
    - Bowl of rice (data set)
    - Semaphore chopstick [5] initialized to 1

Dining-Philosophers Problem Algorithm

- The structure of Philosopher *i*:

```
do {
     wait (chopstick[i] );
      wait (chopStick[ (i + 1) % 5] );

                  //  eat

      signal (chopstick[i] );
      signal (chopstick[ (i + 1) % 5] );

                   //  think

} while (TRUE);
```

- What is the problem with this algorithm?

Dining-Philosophers Problem Algorithm (Cont.)

- Deadlock handling
  - Allow at most 4 philosophers to be sitting simultaneously at the table.
  - Allow a philosopher to pick up the forks only if both are available (picking must be done in a critical section.
  - Use an asymmetric solution -- an odd-numbered philosopher picks up first the left chopstick and then the right chopstick. Even-numbered philosopher picks up first the right chopstick and then the left chopstick.

Problems with Semaphores

- Incorrect use of semaphore operations:
  - signal (mutex) …. wait (mutex)
  - wait (mutex) … wait (mutex)
  - Omitting of wait (mutex) or signal (mutex) (or both)
- Deadlock and starvation are possible.

Deadlock and Starvation

- **Deadlock** – two or more processes are waiting indefinitely for an event that can be caused by only one of the waiting processes
- Let ***S*** and ***Q*** be two semaphores initialized to 1

P_0	P_1
`wait(S);`	`wait(Q);`
`wait(Q);`	`wait(S);`
`...`	`...`
`signal(S);`	`signal(Q);`
`signal(Q);`	`signal(S);`

- **Starvation** – **indefinite blocking**
  - A process may never be removed from the semaphore queue in which it is suspended
- **Priority Inversion** – Scheduling problem when lower-priority process holds a lock needed by higher-priority process
  - Solved via **priority-inheritance protocol**

Monitors

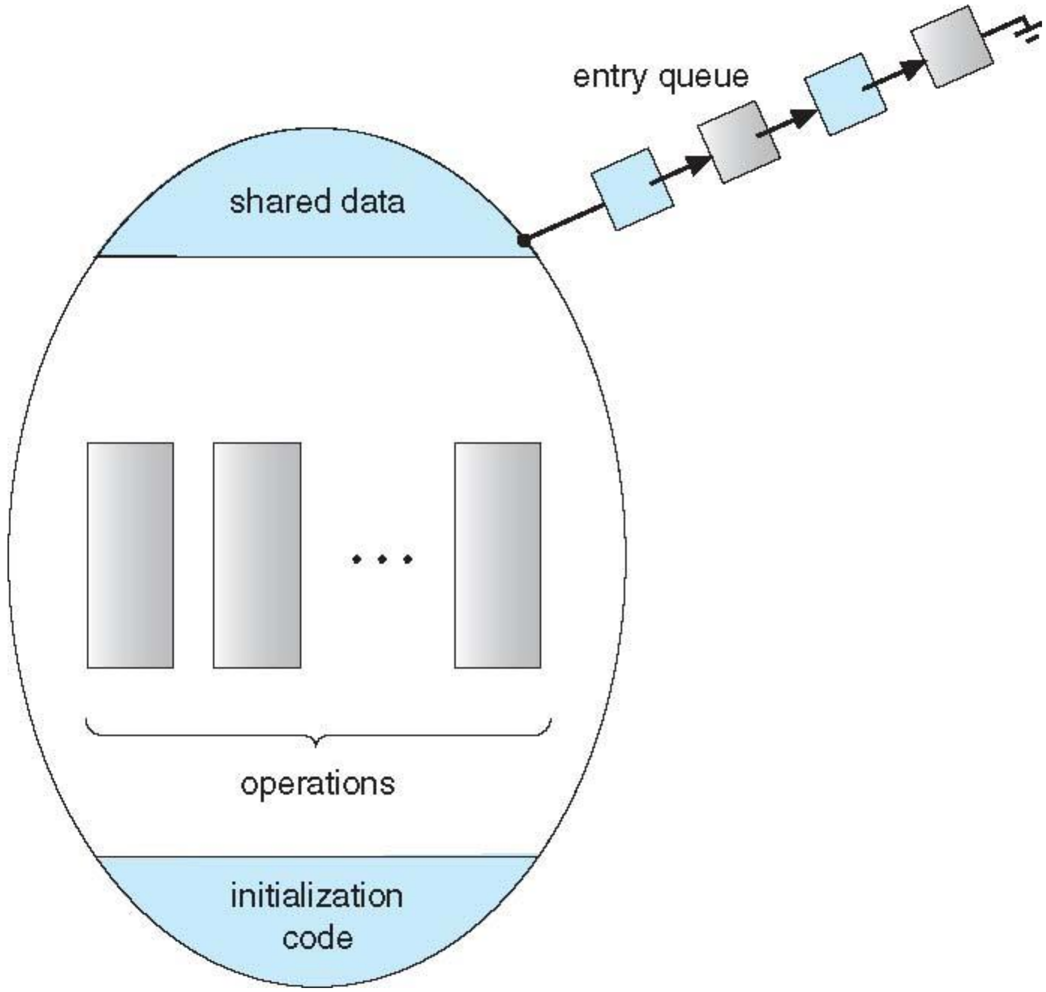
- A high-level abstraction that provides a convenient and effective mechanism for process synchronization
- *Abstract data type*, internal variables only accessible by code within the procedure
- Only one process may be active within the monitor at a time
- But not powerful enough to model some synchronization schemes

```
monitor monitor-name
{
  // shared variable declarations
  procedure P1 (…) { …. }

  procedure Pn (…) {……}

     Initialization code (…) { … }
   }
}
```

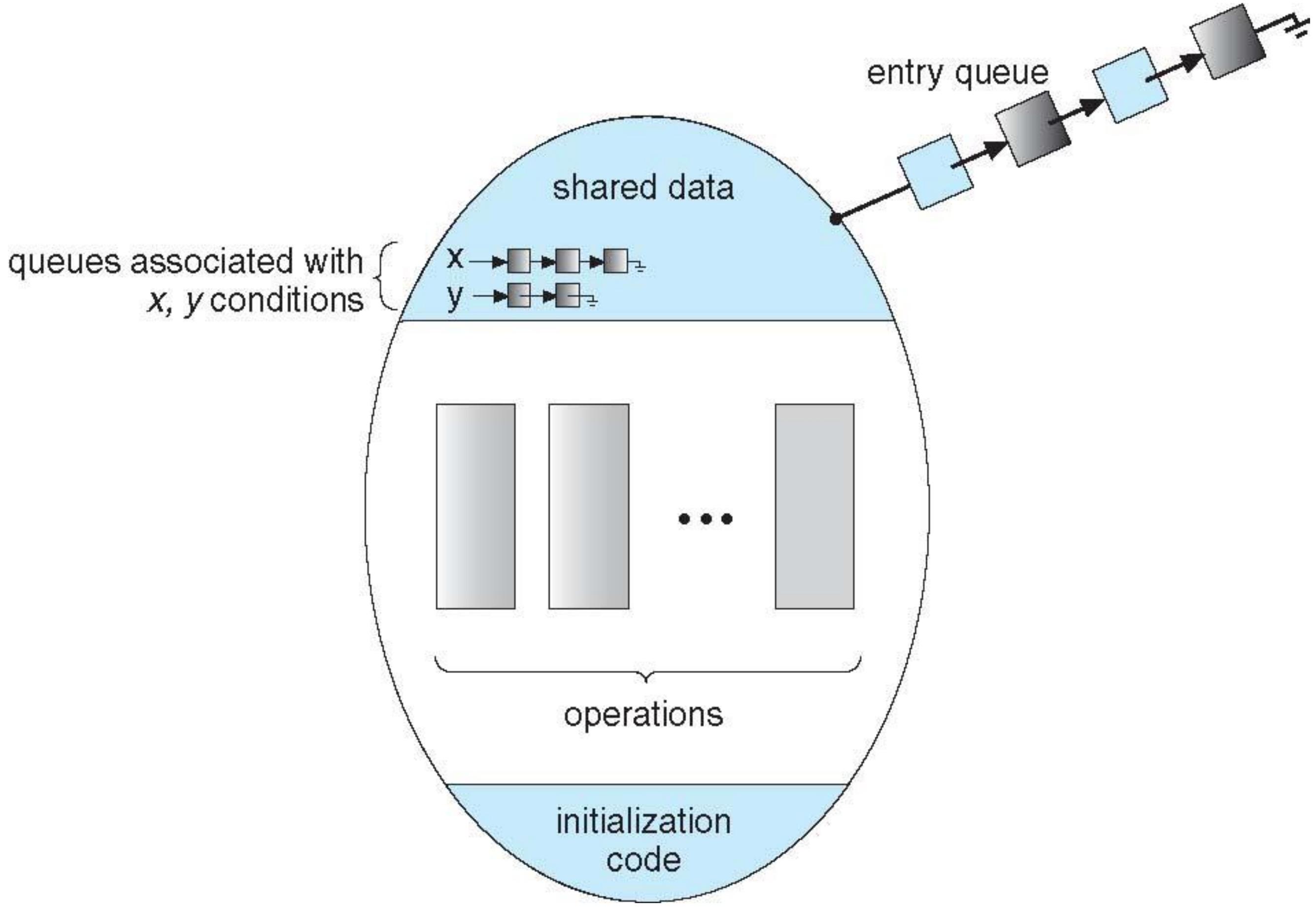
Schematic view of a Monitor



Condition Variables

- **`condition x, y;`**
- Two operations are allowed on a condition variable:
  - **`x.wait()`** – a process that invokes the operation is suspended until **`x.signal()`**
  - **`x.signal()`** – resumes one of processes (if any) that invoked **`x.wait()`**
    - If no **`x.wait()`** on the variable, then it has no effect on the variable

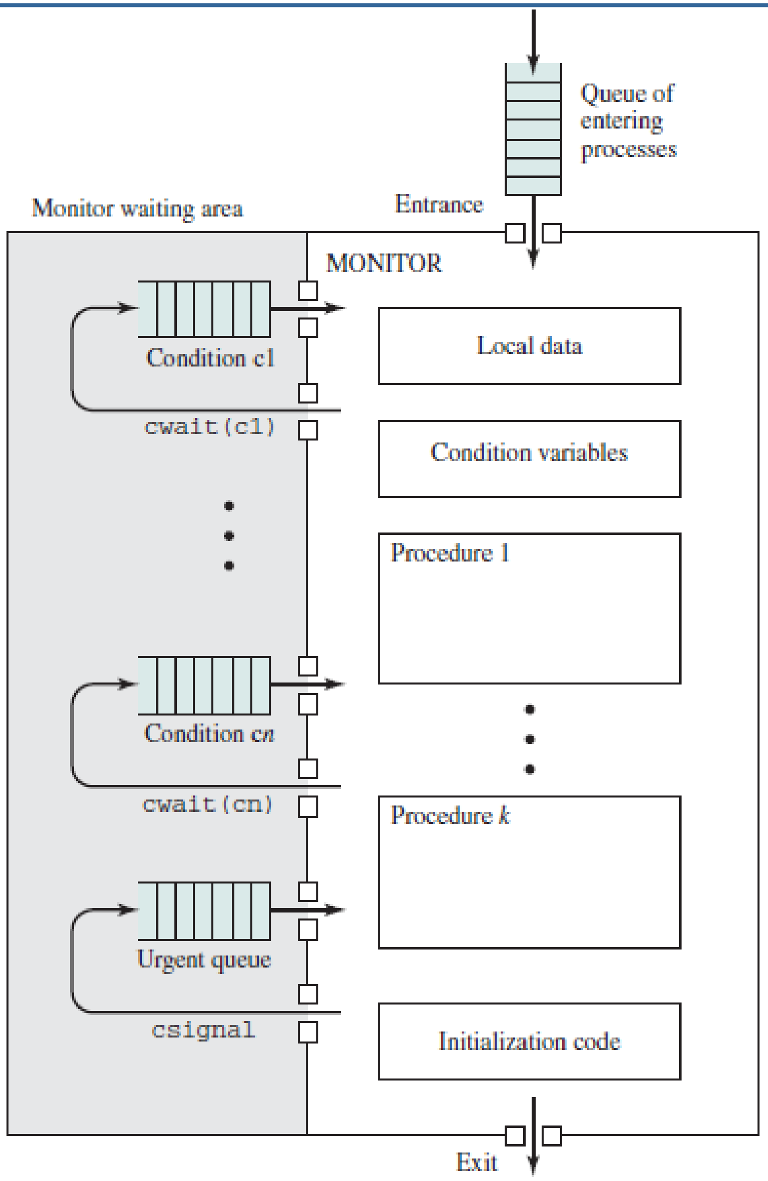
Monitor with Condition Variables



Condition Variables Choices

- If process P invokes **`x.signal()`**, and process Q is suspended in **`x.wait()`**, what should happen next?
  - Both Q and P cannot execute in paralel. If Q is resumed, then P must wait
- Options include
  - **Signal and wait** – P waits until Q either leaves the monitor or it waits for another condition
  - **Signal and continue** – Q waits until P either leaves the monitor or it waits for another condition
  - Both have pros and cons – language implementer can decide
  - Monitors implemented in Concurrent Pascal compromise
    - P executing signal immediately leaves the monitor, Q is resumed
  - Implemented in other languages including Mesa, C#, Java

Stallings' Monitor Diagram



Stallings' Bounded Buffer via Monitor

```
/* program producerconsumer */
monitor boundedbuffer;
char buffer [N];                                        /* space for N items */
int nextin, nextout;                                    /* buffer pointers */
int count;                                              /* number of items in buffer */
cond notfull, notempty;                 /* condition variables for synchronization */

void append (char x)
{
      if (count == N) cwait(notfull);           /* buffer is full; avoid overflow */
      buffer[nextin] = x;
      nextin = (nextin + 1) % N;
      count++;
      /* one more item in buffer */
      csignal (nonempty);                           /*resume any waiting consumer */
}
void take (char x)
{
      if (count == 0) cwait(notempty);        /* buffer is empty; avoid underflow */
      x = buffer[nextout];
      nextout = (nextout + 1) % N);
      count--;                                          /* one fewer item in buffer */
      csignal (notfull);                               /* resume any waiting producer */
}
{                                                                   /* monitor body */
      nextin = 0; nextout = 0; count = 0;                /* buffer initially empty */
}
```

Stallings' Producer and Consumer

```
void producer()
{
      char x;
      while (true) {
      produce(x);
      append(x);
      }
}
void consumer()
{
      char x;
      while (true) {
      take(x);
      consume(x);
      }
}
void main()
{
      parbegin (producer, consumer);
}
```

Monitor Solution to Dining Philosophers

```
monitor DiningPhilosophers
{
   enum { THINKING; HUNGRY, EATING) state [5] ;
   condition self [5];

   void pickup (int i) {
          state[i] = HUNGRY;
          test(i);
          if (state[i] != EATING) self[i].wait;
}

   void putdown (int i) {
          state[i] = THINKING;
                   // test left and right neighbors
           test((i + 4) % 5);
           test((i + 1) % 5);
}
```

Solution to Dining Philosophers (Cont.)

```
        void test (int i) {
                if ((state[(i + 4) % 5] != EATING) &&
                (state[i] == HUNGRY) &&
                (state[(i + 1) % 5] != EATING) ) {
                     state[i] = EATING ;
                 self[i].signal () ;
                }
        }

            initialization_code() {
               for (int i = 0; i < 5; i++)
               state[i] = THINKING;
            }
}
```

Solution to Dining Philosophers (Cont.)

- Each philosopher *i* invokes the operations **`pickup()`** and **`putdown()`** in the following sequence:

```
DiningPhilosophers.pickup(i);

     EAT

DiningPhilosophers.putdown(i);
```

- No deadlock, but starvation is possible

Monitor Implementation Using Semaphores

- Variables

```
semaphore mutex;  // (initially  = 1)
semaphore next;   // (initially  = 0)
int next_count = 0;
```

- Each procedure ***F*** will be replaced by

```
wait(mutex);
     …
   body of F;
     …
if (next_count > 0)
 signal(next)
else
 signal(mutex);
```

- Mutual exclusion within a monitor is ensured

Monitor Implementation – Condition Variables

- For each condition variable ***x***, we have:

```
semaphore x_sem; // (initially  = 0)
int x_count = 0;
```

- The operation x.wait can be implemented as:

```
x_count++;
if (next_count > 0)
   signal(next);
else
   signal(mutex);
wait(x_sem);
x_count--;
```

Monitor Implementation (Cont.)

- The operation x.wait can be implemented as:

```
x_count++;
if (next_count > 0)
   signal(next);
else
   signal(mutex);
wait(x_sem);
x_count--;
```

The operation `x.signal` can be implemented as:

```
if (x_count > 0) {
   next_count++;
   signal(x_sem);
   wait(next);
   next_count--;
}
```

Resuming Processes within a Monitor

- If several processes queued on condition x, and x.signal() executed, which should be resumed?
- FCFS frequently not adequate
- **conditional-wait** construct of the form x.wait(c)
  - Where c is **priority number**
  - Process with lowest number (highest priority) is scheduled next

Single Resource allocation

- Allocate a single resource among competing processes using priority numbers that specify the maximum time a process plans to use the resource

```
R.acquire(t);
     ...
  access the resurce;
     ...

 R.release;
```

- Where R is an instance of type **`ResourceAllocator`**

A Monitor to Allocate Single Resource

```
monitor ResourceAllocator
{
   boolean busy;
   condition x;
   void acquire(int time) {
            if (busy)
               x.wait(time);
            busy = TRUE;
   }
   void release() {
            busy = FALSE;
            x.signal();
   }
initialization code() {
    busy = FALSE;
   }
}
```

Synchronization Examples

- Solaris
- Windows
- Linux
- Pthreads

Solaris Synchronization

- Implements a variety of locks to support multitasking, multithreading (including real-time threads), and multiprocessing
- Uses **adaptive mutexes** for efficiency when protecting data from short code segments
  - Starts as a standard semaphore spin-lock
  - If lock held, and by a thread running on another CPU, spins
  - If lock held by non-run-state thread, block and sleep waiting for signal of lock being released
- Uses **condition variables**
- Uses **readers-writers** locks when longer sections of code need access to data
- Uses **turnstiles** to order the list of threads waiting to acquire either an adaptive mutex or reader-writer lock
  - Turnstiles are per-lock-holding-thread, not per-object
- Priority-inheritance per-turnstile gives the running thread the highest of the priorities of the threads in its turnstile

Windows Synchronization

- Uses interrupt masks to protect access to global resources on uniprocessor systems
- Uses **spinlocks** on multiprocessor systems
  - Spinlocking-thread will never be preempted
- Also provides **dispatcher objects** user-land which may act mutexes, semaphores, events, and timers
  - **Events**
    - An event acts much like a condition variable
  - Timers notify one or more thread when time expired
  - Dispatcher objects either **signaled-state** (object available) or **non-signaled state** (thread will block)

Linux Synchronization

- Linux:
  - Prior to kernel Version 2.6, disables interrupts to implement short critical sections
  - Version 2.6 and later, fully preemptive
- Linux provides:
  - Semaphores
  - atomic integers
  - spinlocks
  - reader-writer versions of both
- On single-cpu system, spinlocks replaced by enabling and disabling kernel preemption

Pthreads Synchronization

- Pthreads API is OS-independent
- It provides:
  - mutex locks
  - condition variable
- Non-portable extensions include:
  - read-write locks
  - spinlocks

Alternative Approaches

- Transactional Memory
- OpenMP
- Functional Programming Languages

Transactional Memory

- A **memory transaction** is a sequence of read-write operations to memory that are performed atomically.

```
void update()
{
    /* read/write memory */
}
```

OpenMP

- OpenMP is a set of compiler directives and API that support parallel progamming.

```
void update(int value)
{
      #pragma omp critical
      {
            count += value
      }
}
```

The code contained within the **`#pragma omp critical`** directive is treated as a critical section and performed atomically.

Functional Programming Languages

- Functional programming languages offer a different paradigm than procedural languages in that they do not maintain state.
- Variables are treated as immutable and cannot change state once they have been assigned a value.
- There is increasing interest in functional languages such as Erlang and Scala for their approach in handling data races.

End of Chapter 5