

A parallelised and distributed approach to implementing Conway's Game of Life

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Abstract

We intend to explain our two solutions for implementing Conway's Game of Life in Golang, namely the Parallel and Distributed versions. Within this report, we will discuss the impacts of thread usage in both our implementations, as well as the effect of distributed computation as opposed to single-machine computation. In essence, we found that execution time was sped up as we increased thread count, reduced branch instructions and implemented a halo exchange mechanism.

I. INTRODUCTION TO THE PARALLEL SOLUTION

As an initial attempt, we began by implementing a single-threaded Game of Life (GoL) Engine, expanding upon this work with parallelisation by virtue of concurrent go-routine workers. Recognising that there exists various methods to calculating the perimeter for `getNeighbourCount`, we tried various counting methods - taking into account the modularity of Game of Life - as well as finding channel alternatives.

II. BENCHMARKING METHODOLOGY

Our means of evaluating parallelisation performance gains was via the Go testing framework. Using 512px x 512px PGM images, we repeated each benchmark 10 times, taking the average runtime for each thread to acquire the central value, and plotting them. Each feature implementation was benchmarked in the same fashion, using Linux lab machines with CPUs being Intel i7-8700 (6 core, 12 threads).

III. A SPLIT PERSONALITY PROGRAM

A. Parallelisation logic

The baseline implementation's distributor function starts with reading the image into 2D slice via `io` commands, before evenly dividing the workload between workers. With the aid of go-routines, workers have

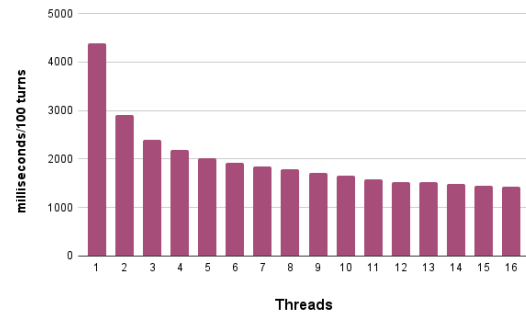


Figure 1: Modulo Implementation

access to the old slice as well as the boundaries in which to process. By using `getNeighbourCount`, we apply the Game of Life laws onto the world, piping results into a blank slice of size:

$$(endRow - startRow) \times ImageWidth$$

Sending the results back to the distributor, we integrate back together the new slices, move the pointer to the old world to this newly-merged world and send the appropriate signals on the `events`, `io` channels.

B. On the topic of analysis 1

From Fig. 1, we can conclude that multithreading have an overall improvement on performance. There is a correlation between increasing number of threads and decreasing execution times, likely due to some functions, such as `getNeighbourCount`,

being "embarrassingly parallelisable". We favour the term "delightfully parallel". As we have more cores for processing, the time taken for each turn is reduced, hence the curve.

We do take notice of the obvious trend of diminishing returns - the gradient of the time-thread curve flattens. We attribute this to unparallelisable core tasks such as IO - the major slowdown that is reading and writing to/from the disk, and submit that using more threads than a CPU physically has causes overhead in scheduling, minimising the benefits of allocating extra threads for processing. We suspect also that, contributing to this, the workload division does not change as much the more threads there are, which explains the reciprocal graph shape curve.

Regarding the numerical results, we find greatest performance was with 16 threads (despite the diminishing returns) with a 67.6% decrease in processing time. As for the worst change in performance thread-to-thread, we see the 14th - 15th threads having the smallest difference in performance change (0.353%), but acknowledge the potential anomalous data point.

IV. HOW TO COUNT?

A. Counting methods

It is well documented that division and other non-atomic arithmetic operations are slow. Thus, we submit our alternative implementations for `getNeighbourCount`. Fig. 1, our original implementation, uses the modulo operation (%), whereas Fig. 2, Fig. 3, use Branching (if-statements) and Bitmasking respectively. From this data, we see that Bitmasking is the fastest on average, but we can identify positive notes from all three.

B. On the topic of Analysis 2

Statistically-speaking, we find the solution using modulo operations is most affected by thread usage, having standard deviation 413ms, as opposed to 107ms and 73ms for branching and bitmasking respectively. Interested persons will find our results achieved by:

$$SD(\forall x \in \text{runtimes} : \max(\text{runtimes}) - x)$$

As discussed before, this, however, implies not that higher threads means greater performance as there exists other, non-parallelisable tasks setting a base level of execution time. The low standard deviation

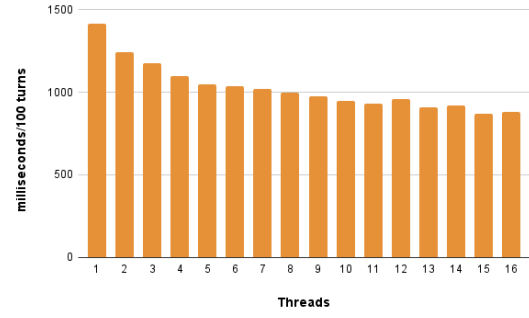


Figure 2: Branching Implementation

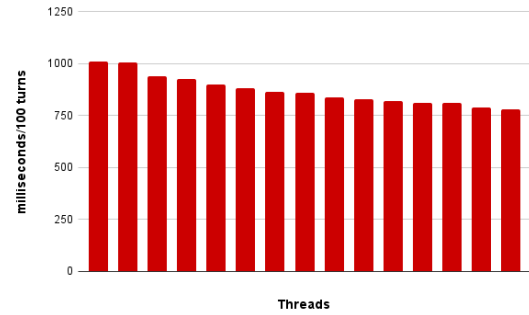


Figure 3: Bitmask Implementation

of the bitmasked implementation alludes to this portion of the program being as near optimised as we possibly can.

When it comes to average times for threads, bitmasking takes the lead with 890ms, followed by 1026ms and 1989ms for branching and modular respectively. This does identify branching for the greatest decrease in runtime, with a 74.2% decrease, as opposed to 32.1%.

C. Our Algorithms

Code-wise, our initial implementation for `getNeighbourCount` used modulo operators unnecessarily. It did the following:

1. Set row = coordinate row % ImageHeight
2. Set col = coordinate col % ImageWidth
3. If row | col < 0, then add ImageHeight/Width respectively
4. If world[row][col] was 255, increment alive count

With this, while it succeeds in its purpose, it does not succeed efficiently. Areas of improvement include removal of the modulo operator, which, here,

does not serve any real purpose. This leads to our second implementation - branching:

Algorithm 1 Branching getNeighbourCount

```

Let  $i, j \leftarrow (row, column)$  on world
Let  $O \leftarrow \{-1, 0, 1\} \times \{-1, 0, 1\} - \{0, 0\}$ 
Let  $alive \leftarrow 0$ 
for  $(x, y) \in O$  do
     $row \leftarrow (i + y)$ 
    if  $row < 0$  then
         $row \leftarrow ImageHeight - 1$ 
    else if  $row = ImageHeight$  then
         $row \leftarrow 0$ 
    end if
     $col \leftarrow (j + x)$ 
    if  $col < 0$  then
         $col \leftarrow ImageWidth - 1$ 
    else if  $col = ImageWidth$  then
         $col \leftarrow 0$ 
    end if
    if  $world[row][col] = 255$  then
         $alive++$ 
    end if
end for
return  $alive$ 
    
```

Although the line count has certainly increased, the performance has drastically improved. Citing the 74.2% decrease, this does appear to be "good enough" as an implementation. An improvement may be to rid ourselves of branches, as this involves branch prediction which itself is intensive, due to how the CPU does not know which path will be taken ahead of time. If we use only logical operations, we get the Bitmasking implementation:

Algorithm 2 Bitmasked getNeighbourCount

```

Let  $i, j \leftarrow (row, column)$  on world
Let  $O \leftarrow \{-1, 0, 1\} \times \{-1, 0, 1\} - \{0, 0\}$ 
Let  $alive \leftarrow 0$ 
for  $(x, y) \in O$  do
     $row \leftarrow (i + y) \& (ImageHeight - 1)$ 
     $col \leftarrow (j + x) \& (ImageWidth - 1)$ 
     $alive \leftarrow alive + world[row][col] >> 7$ 
end for
return  $alive$ 
    
```

This algorithm is our fastest implementation. Minimising both line count and runtime, it counts the neighbours using purely bitwise operators and assignments - no branching needed.

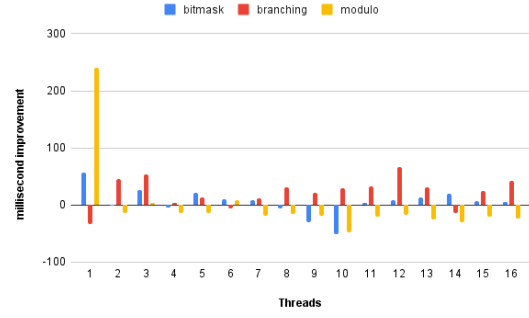


Figure 4: Memory Sharing

V. MEMORY SHARING

A. Motivation

Looking at our achievements in counting, we noticed overhead associated with channel communication. Exploring Go's implementation for channels, we see much overhead. Since we know a channel is a thread-safe memory sharing mechanism, we can rid the overhead, using only mutex locks and condition variables.

B. Implementation

Our homemade channel implementation does the following:

1. Acquire the mutex lock
2. While `condition` is false, await broadcast unless non-blocking send
3. Use the value, then broadcast to other processes
4. Finally, unlock mutex

We introduce 2 methods, `Send` & `Receive`. `Send` waits for the memory space to be empty, and replaces it with a value. `Receive` waits for the memory space to point to a value, and then replaces it with `nil`. Go 1.12 does not have generics, which vastly complicated implementation. Benchmarks with memory sharing (and bitmasked `getNeighbourCount`) is shown in Fig. 4.

C. On the topic of Analysis 3

This data was not very analysable. The lack of clear trend and sporadic data points suggests no real difference in performance when adding memory sharing, or faulty implementation (which we realistically do consider a possibility). A trend, if any, we identify

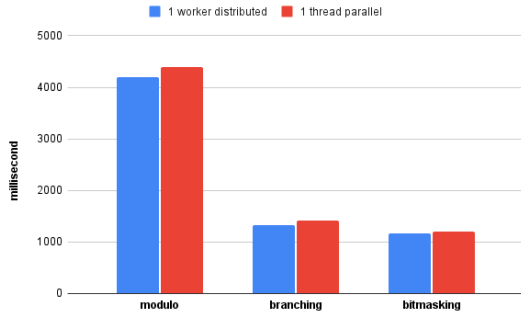


Figure 5: 1 worker vs. 1 thread

is that the Modulo performance suffered, but due to the lack of clarity, this is inconclusive. We add that repeated trials yielded similar style results. Our method used the following:

$$\forall t \in T : ORIG[t] - MEM[t]$$

Where *MEM* is memory sharing implementation time, *ORIG* is channel impl. time, *T* is the number of threads.

VI. DISTRIBUTED IMPLEMENTATION

Similar to how we did the parallel side, we started the distributed section by using a single worker, this time with the worker being a separate process and communicated to via Remote Procedure Calls (RPC henceforth). This expanded to doing using multiple workers, implementing fault tolerance and finally halo exchange.

VII. A LONESOME WORKER

A. Logic

Our single-worker distributed implementation moved much of the processing to said worker. From the distributor, we sent a single RPC call to the worker, processed GoL turns on the worker, then sent the final state back. Results are shown in Fig. 5.

B. On the topic of Analysis 4

The differences between the benchmark times is not significant when compared to multi-threaded work. We identified an average of 4.54% time decrease, which is most likely attributed to how the single-threaded workload had go-routines for Alive Cells

and Key presses, whereas the single worker was Step 1 of Distributed, being "barebones".

VIII. FRIENDS? - MULTI-WORKER GoL

A. Implementing multiple workers

With the introduction of multiple workers, we needed to introduce a broker to interface the workers for the controller and vice versa. This did require moving turn iteration logic to the broker, requiring a major refactor. In the end, the system revolved around the broker with bidirectional RPC communication between workers and the controller. We equally divide work between workers, and all processes keep an internal state of some sort. By massively simplifying, the broker does the following:

1. Listen for worker and controller connections
2. On connect, call the worker/controller back (bidirectional)
3. Listen for GoL process request from controller
4. Iterate, dividing and sending work to each worker.
5. After getting all parts back together, apply changes to broker internal state and divide new state up

- ADD BENCHMARKS HERE

B. Analysis 5

- ADD ANALYSIS HERE
- explain trends, averages, maybe std dev?
- if low std dev then time not affected too much by worker count

IX. TOLERATING FAULTS

A. Managing workers

In our previous implementation, we never checked for worker disconnects. This leaves us in a vulnerable position - if a worker were to be terminated at any point, then we would have one section of changes missing. This would show itself with a static portion on the SDL window. There is also the case of adding more workers. Either way, it means we need to keep the order of workers. We present Algorithm 3 to solve this.

What this algorithm achieves is detection of disconnects and reconnects. Given that we have the

Algorithm 3 Worker-diff checker

```

Require  $ids \subseteq \mathbb{N}$ 
Require  $oldIds \subseteq \mathbb{N}$ 
Let  $idMap \leftarrow Map$ 
for  $id \in ids$  do
     $idMap[id] \leftarrow addr$ 
end for
for  $id \in oldIds$  do
    if  $idMap[id] = \text{nil}$  then
        return False
    end if
end for
return True

```

loop invariant (in turn iterator) "no two workers will have the same worker id", we can use this algorithm, and if we detect a change, recalibrate the workers to adjust for new/missing worker. One may ask, does a worker disconnect not throw errors when calling RPC methods? In this case, we utilise `client.Go`, which notifies the calling process of errors without crashing. So, if error, then trigger recalibration.

X. IMPLEMENTING HALO EXCHANGE

TO BE IMPLEMENTED

XI. BENCHMARKING AND CRITICAL ANALYSIS OF THE HALO EXCHANGE

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XII. COMPARING THE PARRALEL BENCHMARKS

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Table 1: Example table

Name		
First name	Last Name	Grade
John	Doe	7.5
Richard	Miles	2

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Text requiring further explanation¹.

XIII. RESULTS

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¹Example footnote

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XIV. DISCUSSION

A. Areas for improvement

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[Figueredo and Wolf, 2009] Figueredo, A. J. and Wolf, P. S. A. (2009). Assortative pairing and life history strategy - a cross-cultural study. *Human Nature*, 20:317–330.