# Facilitating Large-Scale Graph Searches with Lock-Free Pairing Heaps

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# Project Overview

- We are constructing a lock-free version of a Pairing heap (a self-balancing heap.)
- Pairing heaps have an efficient `decreaseKey` implementation (near-constant performance) that allow you to decrease the value in a heap without reinserting it.
- This improves the asymptotic performance of certain algorithms (e.g., Dijkstra's algorithm.)
- We are comparing our heap against Skipqueues (a priority queue backed with a Skiplist.)

# Dijkstra's Algorithm

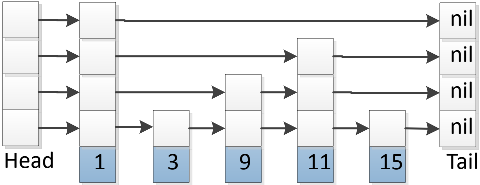
**Single-Source Shortest Path Problem**

In a weighted graph $G = (V, E)$, find the shortest path from a target vertex $v \in V$ to all other vertices in the graph.

- Push every node in a graph into a priority queue (PQ.) In the PQ, each node is weighted by current information we have about their distance.
- Initially, all nodes have a distance of $\infty$, except the target node, which has a distance of $0$.
- Dynamic programming approach: Inductively build up our shortest routes.
  - Pop off the node on the PQ with the smallest distance. (The shortest path from the source to this node is finished.)
  - Update the weights in the PQ with the distances emanating from the popped node.

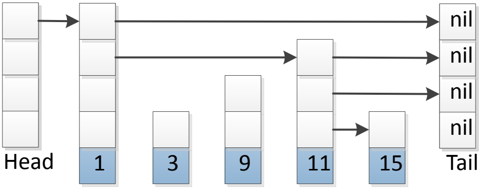
# Skiplists

- Skiplists are constructed from a hierarchy of linked lists with the *Skiplist property*: the set of elements contained in level $i$ is a subset of all the levels below it.
- Links allow you to do a binary search and "jump" around a list.
- The height of an element is randomly sampled from a power-law distribution: the probability of a node having a height of $i \geq 0$ is $2^{-i}$.
- Time complexity of operations are probabilistically the same as for a binary search tree, but $\mathcal{O}(n)$ in the worst case.



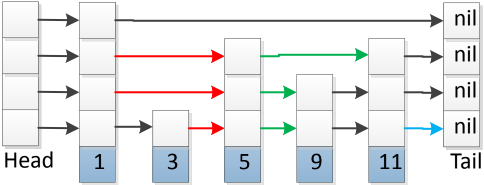
# Skiplists (Search)

- For each level, move right until you run into a node greater than your target. Then, from this point, move right on the next lowest level, and repeat.
- Likely runs in $\mathcal{O}(\log n)$ time.
- Head / tail nodes have values of $-\infty$ and $\infty$, respectively.



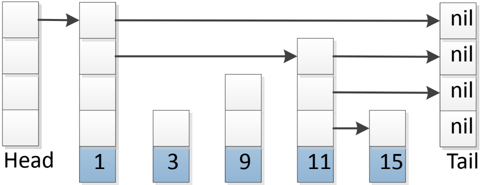
# Next and Previous Windows

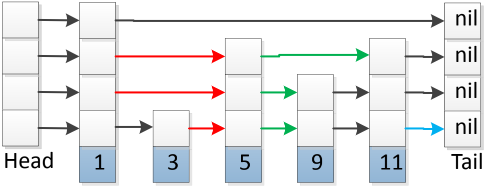
- A useful abstraction to make is the set of all pointers related to a given node. (Aggregate all the pointers related to one node.)
- `prev`$[i] \rightarrow$ the node in level $i$ pointing to the target node.
- `next`$[i] \rightarrow$ the node the target node points to at level $i$.
- Use the search process to construct these sets.



# Skiplists (Insertion)

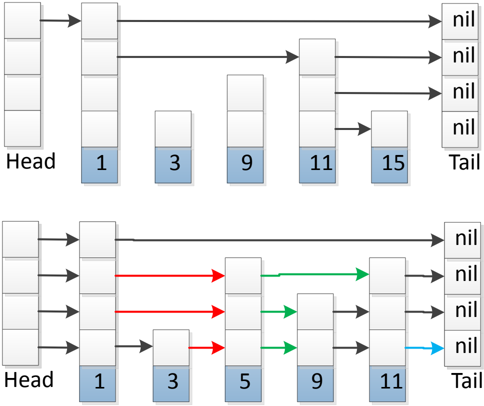
- Insertion: Find the location the target should be at. Set all of the node's next pointers to $\texttt{next}[i]$ and set the next pointers at each $\texttt{prev}[i]$ to the new node.



# Skiplists (Deletion)

- Deletion: Set all of the next pointers in $\texttt{prev}[i]$ equal to $\texttt{next}[i]$.



# Lock-free Skiplists

- Instead of linked lists at each level, we use lock-free linked lists.
- We lose the Skiplist property. (Levels aren't necessarily subsets of each other.) In particular, this means we need to always verify a node is in the lowest level.

# Lock-free Skiplists

- Instead of linked lists at each level, we use lock-free linked lists.
- Linearization point: membership is defined at the lowest level of the Skiplist.
- We lose the Skiplist property. (Levels aren't necessarily subsets of each other.) In particular, this means we need to always verify a node is in the lowest level.

## Lock-Free Skiplists (Insertion)

- Construct the `prev`$[i]$ and `next`$[i]$ sets.
- Set all of the node's next pointers to `next`$[i]$.
- If we can CAS the node into the bottom level, continue. Otherwise, something changed, and restart (reconstruct `prev`$[i]$ and `next`$[i]$).
- Next, CAS all `prev`$[i]$ to the new node. If a CAS fails, reconstruct `prev`$[i]$.

# Lock-Free Skiplists (Deletion)

- Pointers are atomically *markable*.
  - In C / C++, steal a bit from the pointer.
  - In Java, use `AtomicMarkableReference`.
- Construct the `prev`$[i]$ and `next`$[i]$ sets.
- For each pointer in our target node, mark them as deleted.

# Optimized `decreaseKey` for Lock-Free Skiplists

- Currently, to implement a `decreaseKey` for Skiplists, we need to do two $\mathcal{O}(\log n)$ operations (one insert and one delete.)
- We can optimize this in some cases by removing redundant work: reuse the `prev`$[i]$ set as a starting point for the next insertion.

## Pairing Heaps

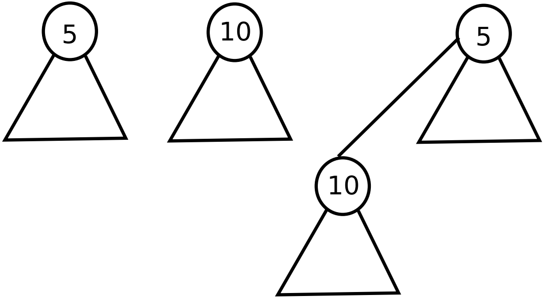
- Pairing Heaps were introduced by Fredman and Tarjan[1] as a simplification of Fibonacci heaps.
  - Fibonacci heaps have a $\mathcal{O}(1)$ `decreaseKey` operator, but require complicated rebalancing.
- `decreaseKey` runs in $2^{\mathcal{O}(\sqrt{\log\log n})}$ time.
  - In practice, constant time. E.g., for a graph with a billion edges, $2^{\sqrt{\log\log 10^9}} = 3.34$.
- Pairing heaps have better performance than Fibonacci heaps on reasonably-sized graphs.[2]

[1] "The Pairing heap: a new form of self-adjusting heap," Fredman, Sedgewick, Sleator, and Tarjan, Algorithmica (1986).

[2] "On the Efficiency of Pairing Heaps and Related Data Structures," Michael Fredman, Journal of the ACM, 1999.

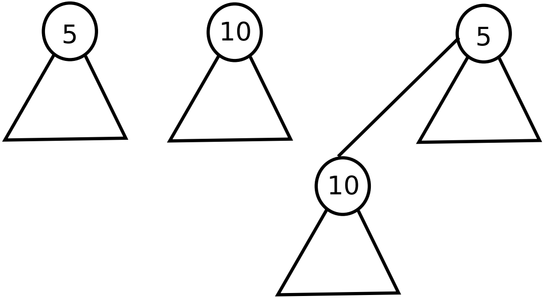
# Pairing Heaps: Melding Two Heaps

- To `meld` two heaps, compare their roots and add the root as a child of the smaller root.
- `meld` is the core operator for Pairing heaps.



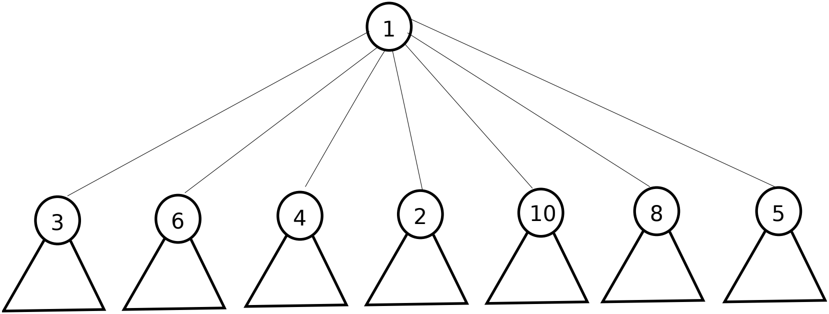
## Pairing Heaps: `insert`

- To insert a new element into a pairing heap, construct a trivial heap containing only that element and `meld` this to the root.
- (The root of the heap will change if the new element is lower.)



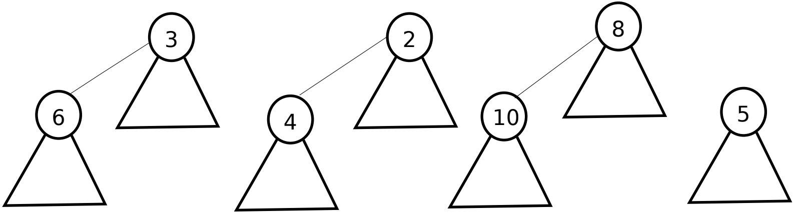
# Pairing Heaps: `deleteMin`

- Pairing heaps have a two-step deleteMin operator.



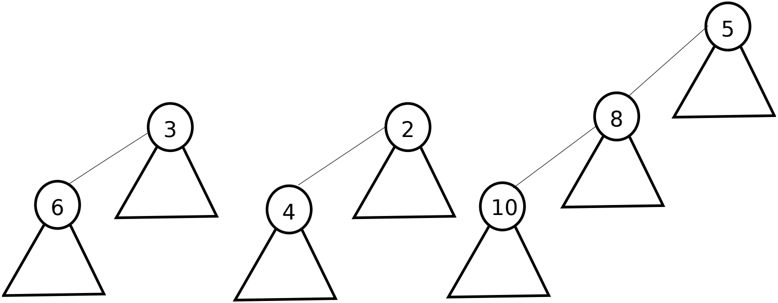
# Pairing Heaps: `deleteMin`

- After removing the root, `meld` each pair of heaps.



## Pairing Heaps: `deleteMin`

- `meld` each resultant heap from right-to-left.



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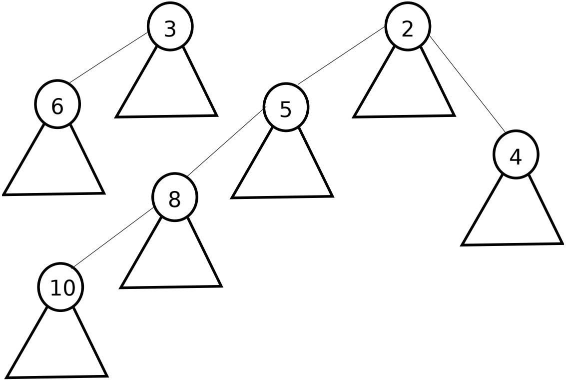

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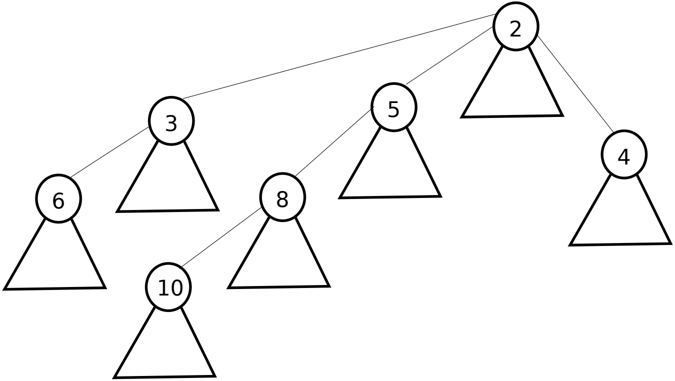

## Parallelizing Dijkstra's Algorithm

- To simplify our Pairing heap implementation, we will only consider function interleavings that can occur when the heap is used for Dijkstra's algorithm.
- For Dijkstra's algorithm, we pop the minimum off the PQ (`deleteMin`) and call `decreaseKey` on the node's neighbors.
- If `decreaseKey` produces new heap minima, this will affect future calls to `deleteMin`
- For this reason, we assume that calls to `decreaseKey` and `deleteMin` never intersect.

# Lock-Free Pairing Heaps: Overview

- Modify the list of sub-heaps to be a lock-free list of subheaps.
- We have identified an easy linearization point for `insert` and `deleteMin`: a node is considered in-place when the root is updated (CAS'd into place.)
  - But, what if the new node is inserted as a subheap of the current root?
  - We create a copy of the root to avoid this issue.

# Lock-Free Pairing Heaps: `insert` an element

- Recall the insertion procedure: create a trivial heap containing only that element and `meld` it to the root.
- Lock-free `insert`:
  - Create a copy of the root, but the root and its copy share the same list of subheaps (this avoids an $\mathcal{O}(n)$ copy.)
  - Meld the new heap with the copy of the root.
  - Try to CAS the new root as the root of the heap.
  - If CAS succeeds, we're done.
  - If CAS fails, delete the subheap list changes and retry.

# Lock-Free Pairing Heaps: `decreaseKey`

- Main observation: If Dijkstra's algorithm is run on a graph with exactly $0$ or $1$ edge between each node, calls to `decreaseKey` will be unique (per iteration.)
- **Case 1**: If the parent is still smaller than the node, just decrease the value.
  - We know that this node won't replace the root, since the parent is larger. An interleaved call to change the parent can only decrease its value.
- **Case 2**: If we're trying to decrease the value of the root, copy the root (as before), decrease its value, and try to CAS the new root into place. After a CAS fails, check if we are still trying to decrease the root and repeat if so.
- **Case 3**: The node is now smaller than its parent, violating the heap invariant. Immediately remove the node from the parent's list of subheaps. Next, follow the same procedure as `insert`.

# Practical Considerations

- Skiplists are extremely concurrent, but require two $\mathcal{O}(\log n)$ operations to implement `decreaseKey`. Also, operations require many pointer updates.
- Pairing heaps have a near-constant `decreaseKey` implementation and fewer pointer updates per call, but every operation is contending for the same location in memory (every thread contends for the root.)

## Experimentation

- Run Dijkstra's algorithm on various large graphs (both randomly generated and real-world, e.g, from Harvard's Human Interactome Database.)
- Compare the time Dijkstra's algorithm takes for a Skiplist-backed implementation vs. a lock-free Pairing heap.
- Run experiments with varying numbers of threads.