

UNIVERSITY OF CALGARY

Title of Thesis

Second Thesis Title Line

by

Student's name

A THESIS

SUBMITTED TO THE FACULTY OF GRADUATE STUDIES

IN PARTIAL FULFILLMENT OF THE REQUIREMENTS FOR THE

DEGREE OF NAME OF DEGREE IN FULL

DEPARTMENT OF NAME OF DEPARTMENT

CALGARY, ALBERTA

monthname, year

© Student's name year

# Abstract

# Table of Contents

<b>Abstract</b>	i
Table of Contents	ii
1 Introduction	1
1.1 Related Work	1
1.2 Statement of Results	1
2 Model of Computation and Definitions	2
3 Dynamic Task Allocation Object	6
4 Correctness Proof	10
4.1 Correctness	10
4.1.1 Analysis and Proofs	10
4.2 Performance	12
4.2.1 DoTask Analysis	12
4.2.2 InsertTask Analysis	12

# Chapter 1

## Introduction

### 1.1 Related Work

(Under work...)

### 1.2 Statement of Results

## Chapter 2

### Model of Computation and Definitions

In this chapter, we will describe our model of computation and give the definitions, which are based on Herlihy and Wing's [2] and Golab, Hadzilacos and Woelfel's [1].

The computational model we consider is the standard asynchronous shared memory model with a set of  $n$  processes, denoted as  $\{p_1, p_2, \dots, p_n\}$ , where up to  $n - 1$  processes may fail by crashing.

**Type and Object.** A *type*  $\tau$  is defined as an automaton as follows [1],

$$\tau = (\mathcal{S}, s_{init}, \mathcal{O}, \mathcal{R}, \delta)$$

where  $\mathcal{S}$  is a set of states,  $s_{init} \in \mathcal{S}$  is the initial state,  $\mathcal{O}$  is a set of operation types,  $\mathcal{R}$  is the set of responses, and  $\delta : \mathcal{S} \times \mathcal{O} \rightarrow \mathcal{S} \times \mathcal{R}$  is a state transition mapping.

An *object* is an implementation of a type. For each type  $\tau$ , the transition mapping  $\delta$  captures the behaviour of objects of type  $\tau$ , in the absence of concurrency, as follows: if a process applies an operation of type *opt* to an object of type  $\tau$  which is in state  $s$ , the object may return to the process a response *rsp* and change its states to  $s'$  if and only if  $(s', rsp) \in \delta(s, opt)$ .

An object that supports only **read()** and **write(x)** operations is called a *read/write register* (or just *register*). Operation **read()** returns the current state of the register and leaves the state unchanged. Operation **write(x)** changes the state of the register to  $x$ .

An object that supports **read()** and **CAS(x,y)** operations is called *compare-and-swap* (CAS) object. Operation **read()** is the same as defined above. Operation **CAS(x,y)** changes the state of the object if and only if the current state is equal to  $x$  and then operation **CAS(x,y)** succeeds, and the state is changed to  $y$  and *true* is returned. Otherwise, operation **CAS(x,y)**

fails, the current state remains unchanged and *false* is returned.

**History** A *history*  $H$ , obtained by processes executing operations on objects, is a sequence of *invocation* and *response* events.

An invocation event is a 5-tuple,

$$INV = (invocation, p, obj, opt, t)$$

where *invocation* is the event type,  $p$  is the process executing the operation, *obj* is the object on which the operation is executed, *opt* is the operation type and  $t$  is the *time* when INV happens which is defined as the position of event INV in history  $H$ .

A response event is also a 5-tuple,

$$RSP = (response, p, obj, rsp, t)$$

where *response* is the event type,  $p$  is the process receiving response *rsp* from an operation on object *obj* and  $t$  is the time when RSP happens which is defined as the position of event RSP in history  $H$ .

Response event  $(response, p_j, obj_q, rsp, t_1)$  *matches* invocation event  $(invocation, p_i, obj_p, opt, t_0)$  in history  $H$ , if the two events are applied by the same process to the same object, i.e,  $i = j$  and  $p = q$ . In this case, the response event is also called the *matching* response of the invocation event.

An *operation execution* in  $H$  is a pair  $oe = (INV, RSP)$  consisting of an invocation event INV and the next matching response event RSP, or just an invocation event INV, denoted as  $oe = (INV, null)$ . In the latter case, we say the operation execution is *pending*. In the former case, we say the operation execution is *complete*. A history  $H$  is *complete* if all operation executions in  $H$  are *complete*, otherwise, it is *incomplete*.

History  $H'$  is an extension of history  $H$  if  $H$  is a prefix of  $H'$ . History  $H'$  is a *completion* of

history  $H$  if  $H'$  contains all the events in  $H$  and  $H'$  is an extension of  $H$ , and each operation execution in  $H'$  is complete.

$H|obj$  of history  $H$  is the subsequence of all invocation and response events in  $H$  on object  $obj$ . If all invocation and response events in a history  $H$  have the same object name  $obj$ , then the  $H|obj = H$ .

Let  $H$  be a complete history. We associate a time interval  $I_{oe} = [t_0, t_1]$  with each operation execution  $oe = (INV, RSP)$  in  $H$ , where  $t_0$  and  $t_1$  are the points in time when INV and RSP happen. Similarly, for an incomplete history, we denote the time interval  $I_{oe}$  with respect to a pending operation execution  $oe = (INV, null)$  by  $I_{oe} = [t_0, \infty]$ .

Operation execution  $oe_0$  *precedes* operation execution  $oe_1$  in  $H$  if the response event of  $oe_0$  happens before the invocation event of  $oe_1$  in  $H$ . We say that  $oe_0$  and  $oe_1$  are *concurrent* in  $H$  if neither precedes the other.

A history is *sequential* if its first event is an invocation event, and each invocation event, except possibly the last one, is immediately followed by a matching response event.

**Linearization.** A history  $H$  *linearizes* to a sequential history  $S$ , if and only if  $S$  satisfies the following conditions: (1)  $S$  and any completion of  $H$  have the same operation executions, (2) sequential history  $S$  is valid, and (3) there is a mapping from each time interval  $I_{oe}$  to a time point  $t_{oe} \in I_{oe}$ , such that the sequential history  $S$  is obtained by sorting the operations in  $H$  based on their  $t_{oe}$  values.

A history is *linearizable* if and only if  $H$  linearizes to some sequential history  $S$ . In this case,  $S$  is called the *linearization* of  $H$ . For each operation  $opt$  in history  $H$ , we call time point  $t_{oe}$ , which is defined as above, the *linearization point* of  $opt$ . An object  $obj$  is linearizable if every history  $H$  on  $obj$  is linearizable.

**Randomness.** A process can execute local coin flip operations that return integer values

distributed uniformly at random from an arbitrary finite set of integers. In the following discussion, we use method `random(s)` to return a value which is distributed uniformly at random from set  $\{0, 1, 2, \dots, s - 1\}$ .

**Adversary.** In the standard shared memory model, each process executes its program by applying shared memory operations (`read()`, `write(x)`, `CAS(x,y)`, etc) on objects, as determined by their program. Operation executions of concurrent processes can be interleaved arbitrarily.

For deterministic shared memory algorithms, we analyze their performance via the standard worst-case analysis assuming that this interleaving occurs in the “worst” possible way. However, in the analysis of randomized algorithms, we use an *adversary* model to describe how the interleaving of executions can be influenced by random choices made by processes.

There are several adversary models with different strengths. The most pessimistic reasonable assumption is modeled by the *strong adaptive adversary*. We analyze our randomized shared memory algorithm under the assumption of a strong adaptive adversary, i.e, at any point of time, it can see the entire past history and knows the states of all processes and decides on the schedule accordingly.



## Chapter 3

### Dynamic Task Allocation Object

The dynamic task allocation (DTA) type supports two operations, `DoTask()` and `InsertTask( $\ell$ )`, where  $\ell$  is the identifier that is unique for each task (*define what is task, give the domain*).

Now we formalize the notion of type DTA by specifying the above two operations. We assume that there exists an atomic operation `PutTask( $M, \ell$ )`, and a process associates (*what is associate?*) task  $\ell$  with memory location (*what is memory location?*)  $M$  by calling `PutTask( $M, \ell$ )`. It returns *success* if task  $\ell$  is associated with location  $M$ , and returns *failure* if location  $M$  was already associated with another task.

Similarly, we assume there exists an atomic operation `TryTask( $M$ )`, and task  $\ell$  associated with memory location  $M$  could be performed atomically by calling `TryTask( $M$ )`. Out of several processes calling `TryTask( $M$ )`, one receives *success* and the index  $\ell$  of that task, while all the others receive *failure*. (*state transition for all initial states, what happens next if there is no...*)

A task is *done* or *performed* if its index has been returned by a process after calling `DoTask()`. A task is *available* at location  $M$  if it has been inserted to  $M$  and *success* is returned by a process after calling `InsertTask( $\ell$ )`, but is not done yet. A task is *available*, if it is *available* at some memory location.

The aim of operation `DoTask()` is to perform an available task on location  $M$  by calling `TryTask( $M$ )`. Every `DoTask()` may perform several `TryTask( $M$ )` operations. However, only one of them will succeed. Once one `TryTask( $M$ )` succeeds, then there is no available task on  $M$  and the task index  $\ell$  will be returned by `DoTask()`. Additionally, if there is no available task, then operation `DoTask()` returns  $\perp$ .

The goal of **InsertTask**( $\ell$ ) operation is to find a free memory location  $M$  and insert task  $\ell$  atomically by calling **PutTask**( $M, \ell$ ). **PutTask**( $M, \ell$ ) fails if location  $M$  has been associated with another task, so each **InsertTask**( $\ell$ ) operation may perform several **PutTask**( $M, \ell$ ) operations, but only one of them will succeed. Once one **TryTask**( $M$ ) succeeds, then task  $\ell$  is available on location  $M$  and *success* notification is returned by **InsertTask**( $\ell$ ) operation.

Type DTA is required to satisfy: (*Validity*) If a **DoTask**() operation returns  $\ell$ , then before the **DoTask**() operation, an **InsertTask**( $\ell$ ) was executed and returned *success*. (*Uniqueness*) Each task is performed at most once, i.e, for each task  $\ell$ , at most one **DoTask**() operation returns  $\ell$ .

In addition, the property that every inserted task is eventually done is also a desired progress property of the implementation of type DTA.

## Implementation of DTA

(under work...)

---

**Method 1: DoTask()**

---

```
1 while true do
2    $v \leftarrow \text{root};$ 
3   if  $v.\text{surplus}() \leq 0$  then
4     return  $\perp$ ;
5   end
6   /* Descent */;
7   while  $v$  is not a leaf do
8      $(x_L, y_L) \leftarrow v.\text{left}.\text{read}();$ 
9      $(x_R, y_R) \leftarrow v.\text{right}.\text{read}();$ 
10     $s_L \leftarrow \min(x_L - y_L, 2^{\text{height}(v)});$ 
11     $s_R \leftarrow \min(x_R - y_R, 2^{\text{height}(v)});$ 
12     $r \leftarrow \text{random}(0, 1);$ 
13    if  $(s_L + s_R) = 0$  then
14      Mark-up( $v$ );
15    else if  $r < s_L / (s_L + s_R)$  then
16       $v \leftarrow v.\text{left};$ 
17    else
18       $v \leftarrow v.\text{right};$ 
19    end
20  end
21  /* v is a leaf */;
22   $(x, y) \leftarrow v.\text{read}();$ 
23   $(\text{flag}, l) \leftarrow v.\text{TryTask}(\text{task}[y + 1]);$ 
24  /* Update Insertion Count */;
25   $v.\text{CAS}((x, y), (x, y + 1));$ 
26   $v \leftarrow v.\text{parent};$ 
27  Mark-up( $v$ );
28  if  $\text{flag} = \text{success}$  then
29    return  $\ell$ 
30  end
31 end
```

---

---

**Method 2: InsertTask( $\ell$ )**

---

```
32 while true do
33    $v \leftarrow \text{root};$ 
34   /* Descent */;
35   while  $v$  is not a leaf do
36      $(x_L, y_L) \leftarrow v.\text{left.read}();$ 
37      $(x_R, y_R) \leftarrow v.\text{right.read}();$ 
38      $s_L \leftarrow 2^{\text{height}(v)} - \min(x_L - y_L, 2^{\text{height}(v)});$ 
39      $s_R \leftarrow 2^{\text{height}(v)} - \min(x_R - y_R, 2^{\text{height}(v)});$ 
40      $r \leftarrow \text{random}(0, 1);$ 
41     if  $(s_L + s_R) = 0$  then
42       |  $\text{Mark-up}(v);$ 
43     else if  $r < s_L / (s_L + s_R)$  then
44       |  $v \leftarrow v.\text{left};$ 
45     else
46       |  $v \leftarrow v.\text{right};$ 
47     end
48   end
49   /*  $v$  is a leaf */;
50    $(x, y) \leftarrow v.\text{read}();$ 
51    $\text{flag} \leftarrow v.\text{PutTask}(\text{task}[x + 1]);$ 
52   /* Update Insertion Count */;
53    $v.\text{CAS}((x, y), (x + 1, y));$ 
54    $v \leftarrow v.\text{parent};$ 
55    $\text{Mark-up}(v);$ 
56   if  $\text{flag} = \text{success}$  then
57     | return success
58   end
59 end
```

---

---

**Method 3: Mark-up( $v$ )**

---

```
60 if  $v$  is not null then
61   for  $(i = 0; i < 2; i++)$  do
62     |  $(x, y) \leftarrow v.\text{read}();$ 
63     |  $(x_L, y_L) \leftarrow v.\text{left.read}();$ 
64     |  $(x_R, y_R) \leftarrow v.\text{right.read}();$ 
65     |  $v.\text{CAS}((x, y), (\max(x, x_L + x_R), \max(y, y_L + y_R)));$ 
66   end
67 end
```

---

# Chapter 4

## Correctness Proof

### 4.1 Correctness

The standard correctness condition for shared memory algorithms is linearizability, which was introduced by Herlihy and Wing in 1990 [2]. The intuition of linearizability is that real-time behavior of method calls must be preserved, i.e, if one method call precedes another, then the earlier call must have taken effect before the later one. By contrast, if two method calls overlap, we are free to order them in any convenient way since the order is ambiguous. Informally, a concurrent object is linearizable if each method call appears to take effect instantaneously at some moment between its invocation and response.

#### 4.1.1 Analysis and Proofs

By the definitions in Subsection 3.1.1, one way to show an object *obj* is linearizable is to prove every history *H* of *obj* is linearizable. Thus, we need to identify for each **DoTask** and **InsertTask** operation *op* (i.e, interval  $I_H(op)$ ) in *H* a linearization point  $t_H(op)$ , and prove that the sequential history *S* obtained by sorting these operations according to their  $t_H(op)$  satisfies the sequential specification  $S_{obj}$  of *obj*.

We notice that each complete **DoTask** or **InsertTask** operation can be associated with a unique task array slot based on the task it removed or inserted. Additionally, the removal and insertion count are both monotonically increasing. Thus, we could associate the node counts with operations which have been propagated to that node.

Now we define “an operation is counted at a node” recursively to formalize the operation

propagation.

A **DoTask** operation is counted at leaf  $v$  when the removal count of  $v$  is updated with the index of the task array slot where the performed task is located. Symmetrically, an **InsertTask** operation is counted at  $v$  when the insertion count of  $v$  is updated with the index of the task array slot where the inserted task is located.

Now we only define **DoTask** operation is counted at an inner node  $v$  because counting an **InsertTask** operation is symmetric as well.

Recall that the removal count of  $v$  is updated through CAS operation (line 6, method 3). Actually there could be more than one operations updating the count with the same value. We linearize all such CAS operations, which update the removal count of  $v$  with the same value  $y$ . We say for all these operations, only the first one in the linearization order counts the corresponding **DoTask** operation. In another word, a **DoTask** operation is counted at an inner node  $v$  as soon as the CAS updating operation that counts the **DoTask** is linearized. Based this definition, no operation will be counted twice at a node.

Please note that, the CAS operation counting the **DoTask** at node  $v$  is not necessarily performed by the **DoTask** operation itself, i.e, suppose process  $p$  executes a **DoTask** operation and has successfully performed task  $\ell$  at certain leaf. Then the CAS operation counting this  $p.DoTask()$  at node  $v$  could be a different process  $q$  as long as  $q$  updates the removal count first in the linearization order.

Given the above concepts and properties, we could prove the following result: (under work...almost done)

## 4.2 Performance

### 4.2.1 DoTask Analysis

### 4.2.2 InsertTask Analysis

## Bibliography

- [1] Wojciech Golab, Vassos Hadzilacos, Danny Hendler, and Philipp Woelfel. Constant-rmr implementations of cas and other synchronization primitives using read and write operations. In *Proceedings of the 26th Annual ACM Symposium on Principles of Distributed Computing (PODC)*, pages 3–12, 2007.
- [2] Maurice P. Herlihy and Jeannette M. Wing. Linearizability: A correctness condition for concurrent objects. *ACM Trans. Program. Lang. Syst.*, 12(3):463–492, July 1990.