System Construction Course 2019,

**Assignment 8**

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# Implementing a Mutex on Lock-Free A2

Goal of this exercise is to implement a scheduled lock on a lock-free operating system, thereby taking into account lock-free implicit cooperative scheduling.

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**Lessons to Learn**

- Understand mechanisms of lock-free scheduling and cooperative scheduling

- Investigate performance differences of spin-locks vs. scheduled locks

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## Preparation

The tool for this exercise contains scripts for an x86 based architectire and for Raspberry Pi. The former can be used in order to run the code in a virtualization environment such as bochs, qemu, VirtualBox or VMWare (or on bare hardware). The latter will be used in order to run the tests on the Raspberry Pi computer.

1. Update your repository.

2. Open a console in directory assignments/assignment08

3. Use the script in files makeA2.RPI.txt or makeA2.x86.txt in order to to compile and link the boot-file for the RPI or x86, respectively, calling

   ```
   oberon execute makeA2.xxx.txt
   ```

4. If you intend to use the Raspberry Pi, connect it to your computer using the Usb-To-Serial TTL cable as we did in Assignment 2. Connection to the RPI can be done via any telnet client you like, e.g. putty or minicom.

## Implement a Mutex

A mutex is a data structure with an algorithm to enforce mutual exclusion of several threads on a set of code regions. For a given mutex `m`, the code regions consist of intervals designated by pair of statements `Mutexes.Acquire(m)` and `Mutexes.Release(m)`.

Prepared for this exercise are files `Mutexes.Mod` containing stub procedures for the implementation of a Mutex and `TestMutexes.Mod` to test the correctness and performance of the implementation.

### Tasks

1. Build the kernel as described above. Copy the kernel `kernel.img` to the SD card of the RPI, open a terminal connecting via serial port to the RPI and check that you see the output of the test module.[1]

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[1] A successful build of the kernel can be detected by a short alternating flashing of the red and green LED on the RPI board at boot time. Then you should see text appearing on the serial console.

2. The stub module `Mutexes.Mod` does not implement a mutex yet. Implement a mutex as a CAS-based Spin-lock first. Check that it works and observe its performance.

3. Modify the implementation of the mutexes in `Mutexes.Mod` such that they employ a scheduled lock. Of course, you are free to experiment later and implement a hybrid scheme but for now you "just" implement the mutex such that when the mutex is currently taken by a different process, then the process goes sleeping on a waiting queue. Test correctness and performance of your implementation.

**Hints**

- The expression `CAS(v, oldvalue, newvalue)` returns the observed value of the variable `v` with the corresponding type of `v`.

- `Activities.GetCurrentActivity()` returns the currently running activity (process).

- Module `Queues.Mod` contains a lock-free queue with precautions against the ABA problem using Hazard-Pointers as discussed in the lecture. While you are encouraged to browse and understand the implementation, you can consider it a given and don't have to worry about lock-free queues in this assignment.

  Declare a lock free queue as `q: Queues.Queue;`.

  A call of `Queues.Enqueue(act,q)` enqueues an activity `act` to queue `q`.

  A call of `Queues.Dequeue(it,q)` dequeues an item `it` from queue `q`. It returns `TRUE` upon success.

  Recall that type guards of the form `it(Activities.Activity)` can be used in order to interpret `it` as of type `Activities.Activity` in a type-safe way.

- The most intricate part of this assignment is about scheduling. Recall from the lecture that it is often required to execute a switch finalizer on behalf of the new scheduled thread as indicated with the following lines of code:

```
IF Activities.Select (nextAct, Activities.IdlePriority) THEN
  Activities.SwitchTo (nextAct, MySwitchFinalizer, ADDRESS OF MyData);
  Activities.FinalizeSwitch;
END;
```

`Activities.Select` fetches a new process from the ready queues with at least idle priority.

`Activities.SwitchTo` performs a synchronous context switch to `nextAct`. This resumed activity continues its execution by first calling the specified finalizer procedure with the given argument. As a rule of this lock-free kernel, each invocation of `Activities.SwitchTo` must be followed by a call to the `Activities.FinalizeSwitch`. This finalizes the task switch performed by calling the task switch finalizer of the previously suspended activity. The interface of the task switch finalizer is as follows.

```
PROCEDURE MySwitchFinalizer(previous {UNTRACED}: Activities.Activity;
            myData {UNTRACED}: POINTER {UNSAFE} TO MyData)
```

- Be aware that in lock-free programming at any times something can happen. Consider all possible interleavings.

## Documents

- System Construction Lecture slides from the course-homepage
  http://lec.inf.ethz.ch/syscon

- F. Negele, Combining Lock-Free Programming with Cooperative Multitasking for a Portable Multiprocessor Runtime System, Dissertation, ETH Zürich (2014)

- Oberon Language Report (Draft 2019) from the A2 repository