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# Resource Access Protocols

Prof. Dr. Jian-Jia Chen

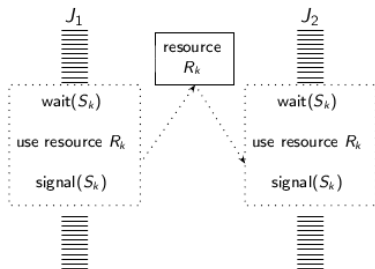
**LS 12, TU Dortmund**

26, Nov. 2014

# Why do We Have to Worry about Resource Sharing?

## Shared Resources:

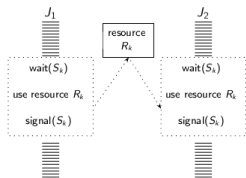
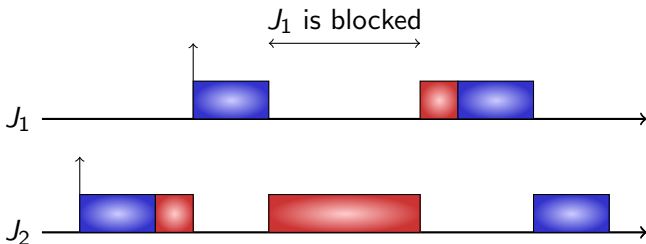
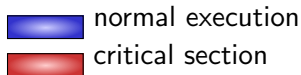
- Data structures, variables, main memory area, file, set of registers, I/O unit, the processor, etc.
- Mutual exclusion, critical section
  - When a job enters the critical section of a shared resource, the accesses to the shared resource from other jobs are *blocked*.



# Priority Inversion

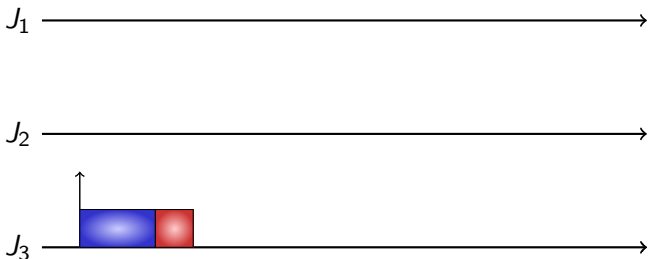
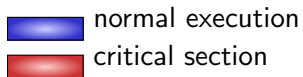
Priority Inversion: A higher priority job is *blocked* by a lower-priority job.

- Unavoidable when there are critical sections





# Priority Inversion: Another Example

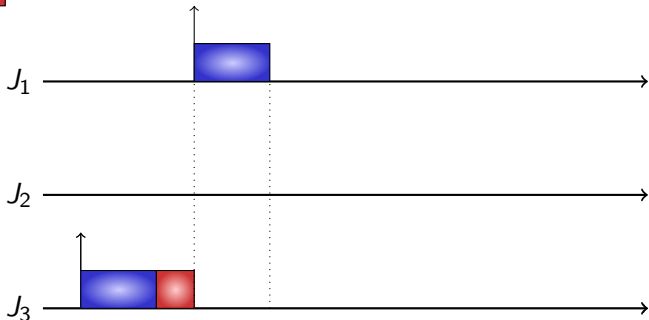
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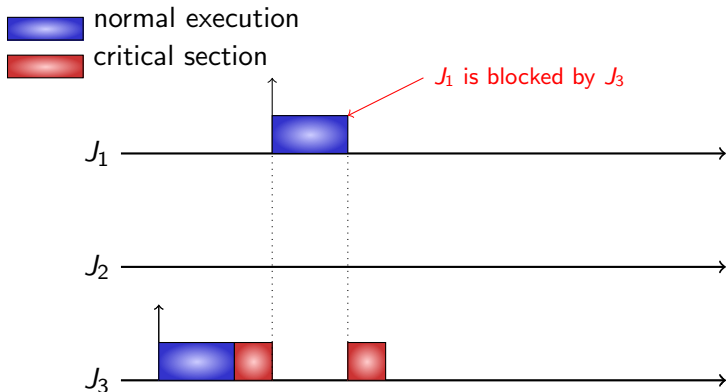
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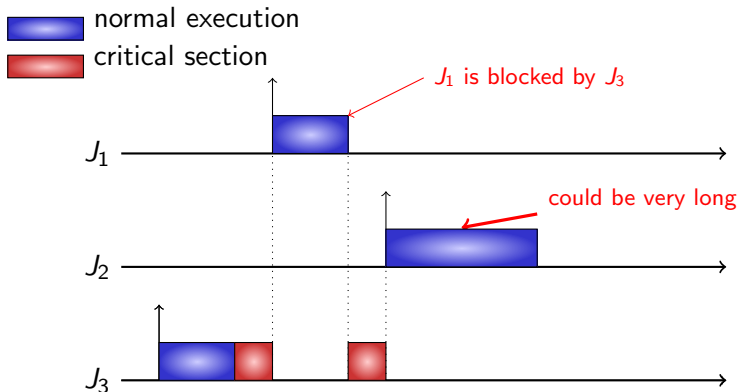
 normal execution  
 critical section



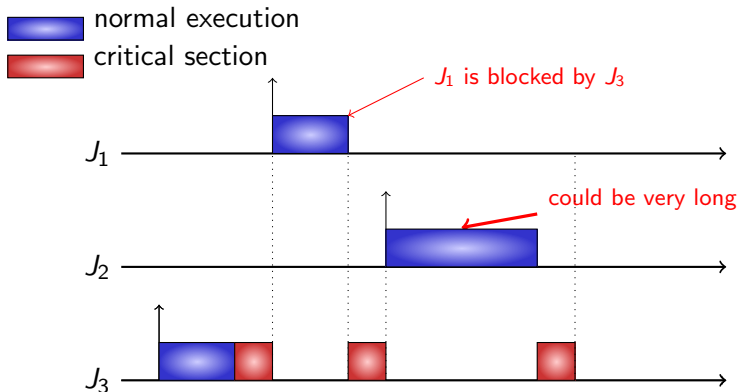
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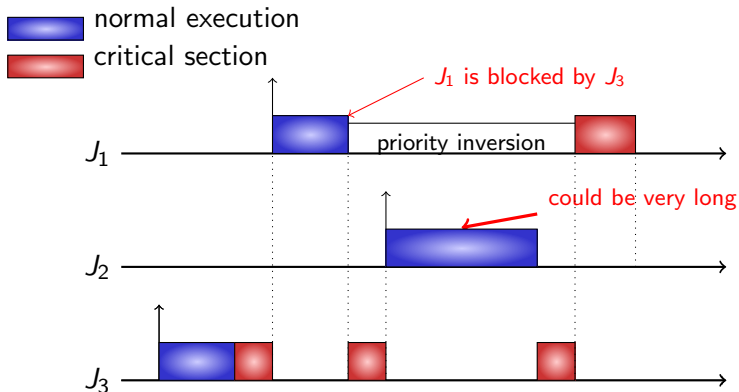


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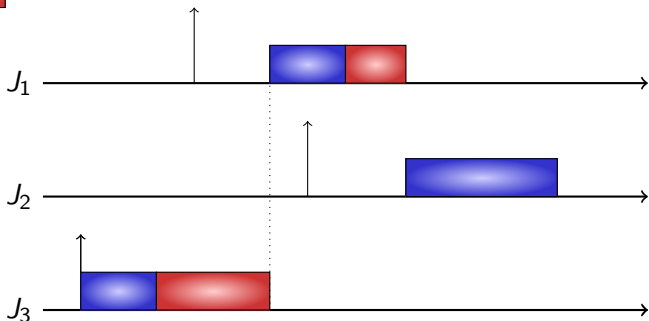


# Naïve Solution for Priority Inversion

*Disallow preemption* during critical sections or set to the highest-priority during priority inversion

- It is simple
- But, it creates unnecessary blocking, as unrelated tasks may be blocked

 normal execution  
 critical section

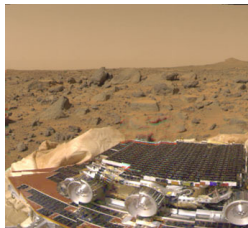


# Case Study: MARS Pathfinder Problem (1)

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A few days into the mission.....

Not long after Pathfinder started gathering meteorological data, the spacecraft began experiencing total system resets, each resulting in losses of data.



## Case Study: MARS Pathfinder Problem (2)

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“VxWorks provides preemptive priority scheduling of threads. Tasks on the Pathfinder spacecraft were executed as threads with priorities that were assigned in the usual manner reflecting the relative urgency of these tasks.”

“Pathfinder contained an **information bus**, which you can think of as a shared memory area used for passing information between different components of the spacecraft.”

A bus management task ran frequently with high priority to move certain kinds of data in and out of the information bus. Access to the bus was synchronized with mutual exclusion locks (mutexes).

- The meteorological data gathering task ran as an infrequent, low priority thread, . . . . . When publishing its data, it would acquire a mutex, do writes to the bus, and release the mutex.
- It also had a communications task that ran with medium priority.

## Case Study: MARS Pathfinder Problem (3)

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high priority	medium priority	low priority
data retrieval from memory	communication task	data collection

“Most of the time this combination worked fine. However, very infrequently it was possible for an interrupt to occur that caused the (medium priority) communications task to be scheduled during the short interval while the (high priority) information bus thread was blocked waiting for the (low priority) meteorological data thread. In this case, the long-running communications task, having higher priority than the meteorological task, would prevent it from running, consequently preventing the blocked information bus task from running. After some time had passed, a watchdog timer would go off, notice that the data bus task had not been executed for some time, conclude that something had gone drastically wrong, and initiate a total system reset. **This scenario is a classic case of priority inversion.**”

Resource Access Protocols

Priority Inheritance and Priority Ceiling Protocols

# Resource Access Protocols

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- Spirit
  - Modify (increase) the priority of those tasks/jobs that cause blocking.
  - When a job  $J_j$  blocks one or more higher-priority jobs, it temporarily assumes a higher priority.
- Methods
  - Priority Inheritance Protocol (PIP), for fixed-priority scheduling
  - Priority Ceiling Protocol (PCP), for fixed-priority scheduling
  - Stack Resource Policy (SRP), for both fixed- and dynamic-priority scheduling
  - others.....

# Priority Inheritance Protocol (PIP)

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For example, if the priority order is  $J_1 > J_2 > J_3 > J_4 > J_5$ ,

- When job  $J_4$  blocks jobs  $J_2$  and  $J_3$ , the priority of  $J_4$  is promoted to the priority level of  $J_2$ .
- When job  $J_5$  blocks jobs  $J_1$  and  $J_3$ , the priority of  $J_5$  is promoted to the priority level of  $J_1$ .

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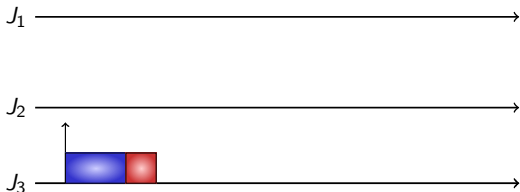
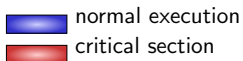
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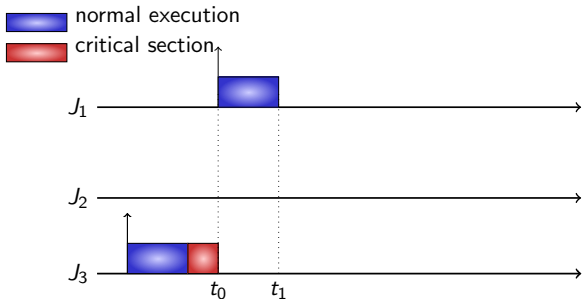
Priority inheritance solved the Mars Pathfinder problem: the VxWorks operating system used in the pathfinder implements a flag for the calls to mutex primitives. This flag allows priority inheritance to be set to **on**. When the software was shipped, it was set to **off**.

# Example of PIP

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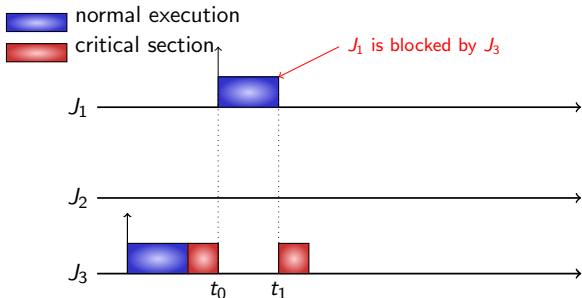


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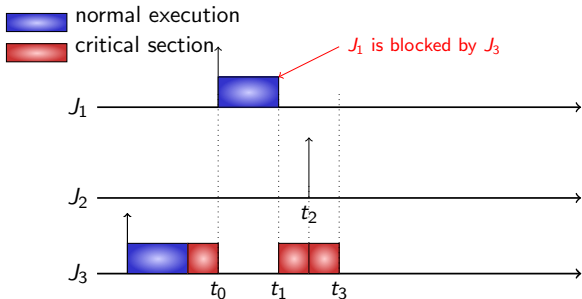
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# Example of PIP



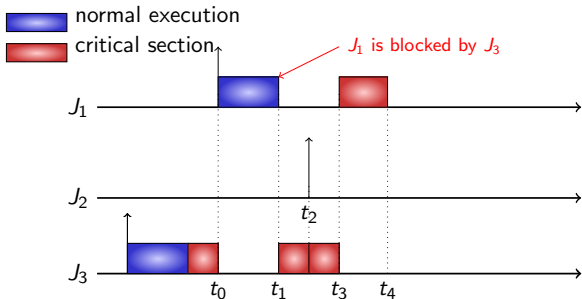
- $t_0$ :  $J_1$  arrives and preempts  $J_3$ , since  $J_1$  does not want to enter the critical section
- $t_1$ :  $J_1$  locks the semaphore and tries to enter the critical section.  $J_1$  is blocked by  $J_3$ , and  $J_3$  inherits  $J_1$ 's priority

# Example of PIP



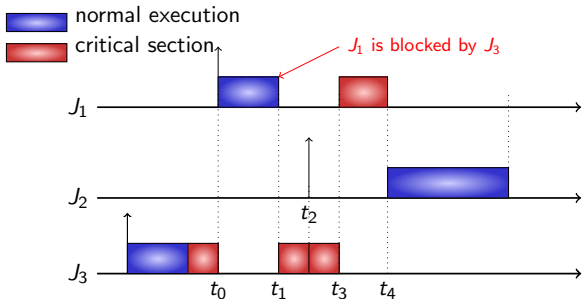
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- $t_3$ :  $J_3$  leaves its critical section, and  $J_1$  now preempts  $J_3$ .

# Example of PIP



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# Example of PIP



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# Blocking Properties of PIP (under Properly Nested)

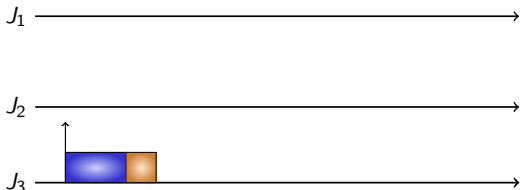
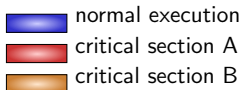
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## Blocking in PIP

- *Direct Blocking*: higher-priority job tries to acquire a resource held by a lower-priority job.
- *Push-through Blocking*: medium-priority job is blocked by a lower-priority job that has a higher priority from a job it directly blocks
- *Transitive Blocking*: higher-priority job is blocked by a medium-priority job due to nested critical sections.
- Under PIP, if there are  $n$  lower priority jobs , a higher-priority job  $J_i$  can be blocked for *as high as the duration of  $n$*  critical sections.
- Under PIP, if there are  $m$  distinct semaphores that can block a job  $J_i$ , then  $J_i$  can be blocked for *as high as the duration of  $m$*  critical sections.
- Under PIP, a higher-priority job  $J_i$  can be blocked for at most  $\min\{n, m\}$  critical sections.

# Transitive Blocking

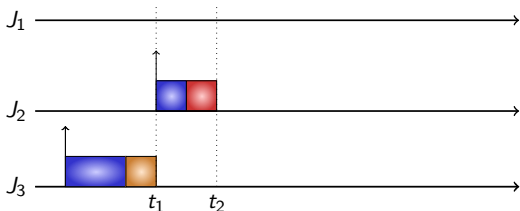
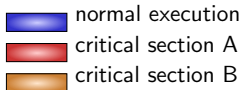
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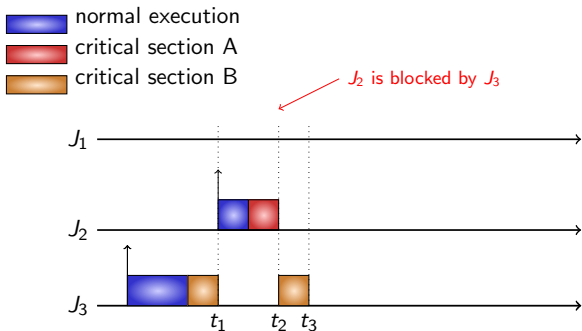
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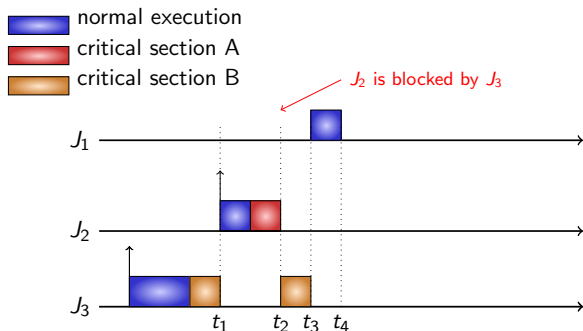
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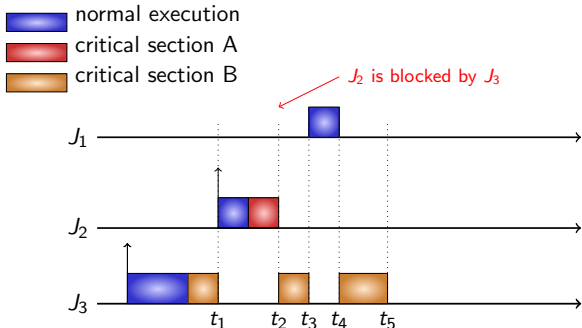
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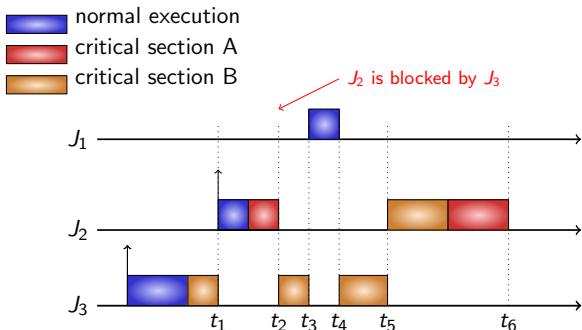
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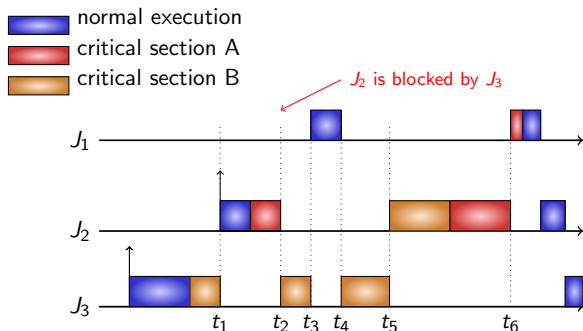
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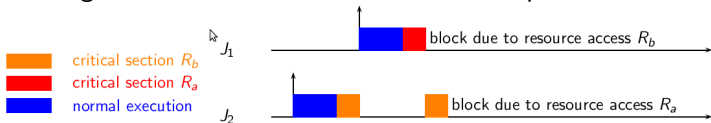
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# Problem of PIP

## Problems of PIP

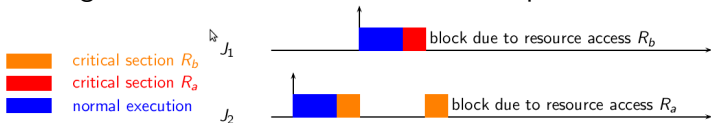
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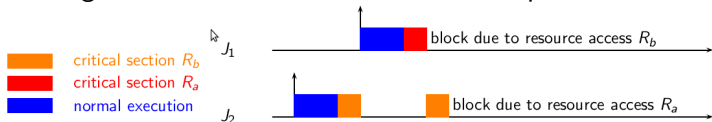
However, if the resource accesses for a task are **properly nested**, then some analysis is still possible.

- This will not be covered in the lecture of Embedded Systems.

# Problem of PIP

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Ongoing debate about problems with the protocol:

- Victor Yodaiken: Against Priority Inheritance, Sept. 2004, [http://www.fsmlabs.com/resources/white\\_papers/priority\\_inheritance/](http://www.fsmlabs.com/resources/white_papers/priority_inheritance/)

Resource Access Protocols

Priority Inheritance and Priority Ceiling Protocols

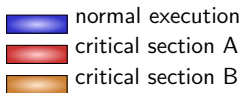
# Priority Ceiling Protocol (PCP)

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- Two key assumptions:
  - The assigned priorities of all jobs are fixed.
  - The resources required by all jobs are known a priori before the execution of any job begins.
- Definition: The *priority ceiling* of a resource  $R$  is the highest priority of all the jobs that require  $R$ , and is denoted  $\Pi(R)$ .
- Definition: The *current priority* of a job  $J$  at time  $t$  is denoted  $\pi(t, J)$ , initialized to the job priority level when  $J$  is released. (smaller means higher priority)
- Definition: The *current priority ceiling*  $\Pi'(t)$  of the system is equal to the highest priority ceiling of the resources currently in use at time  $t$ , or  $\Omega$  if no resources are currently in use ( $\Omega$  is a priority lower than any real priority).
- Use the priority ceiling to decide whether a higher priority can allocate a resource or not.

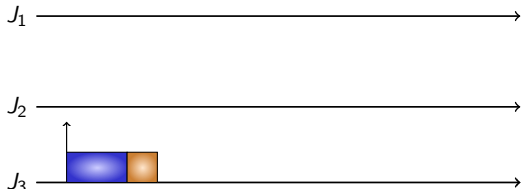
- ① Scheduling Rule
  - Every job  $J$  is scheduled based on the current priority  $\pi(t, J)$ .
- ② Allocation Rule: Whenever a job  $J$  requests a resource  $R$  at time  $t$ , one of the following two conditions occurs:
  - $R$  is held by another job and  $J$  becomes blocked.
  - $R$  is free:
    - If  $J$ 's priority  $\pi(t, J)$  is higher than the current priority ceiling  $\Pi'(t)$ ,  $R$  is allocated to  $J$ .
    - Otherwise, only if  $J$  is the job holding the resource(s) whose priority ceiling equals  $\Pi'(t)$ ,  $R$  is allocated to  $J$
    - Otherwise,  $J$  becomes blocked.
- ③ Priority-inheritance Rule: When  $J$  becomes blocked, the job  $J_I$  that blocks  $J$  inherits the current priority  $\pi(t, J)$  of  $J$ .  $J_I$  executes at its inherited priority until it releases every resource whose priority ceiling is  $\geq \pi(t, J)$  (or until it inherits an even higher priority); at that time, the priority of  $J_I$  returns to its priority  $\pi(t', J_I)$  at the time  $t'$  when it was granted the resources.

# Example of PCP



priority ceilings:

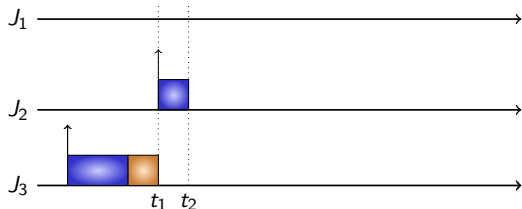
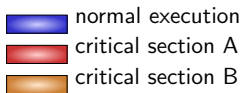
- A: priority level 1
- B: priority level 2



Three jobs with two semaphores A and B.

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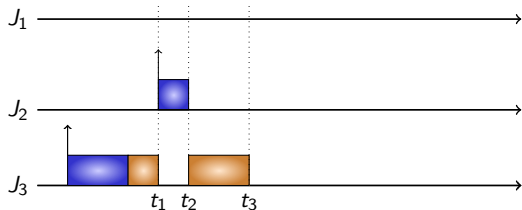
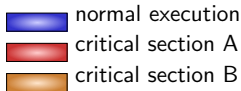
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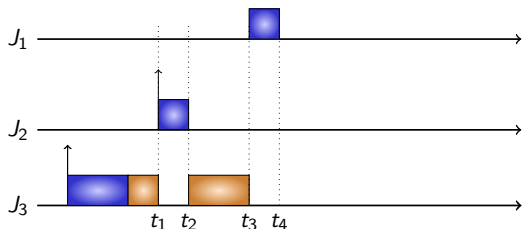
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- normal execution
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- critical section B



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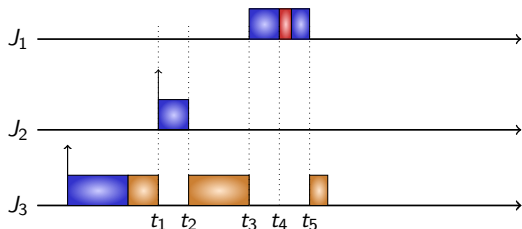
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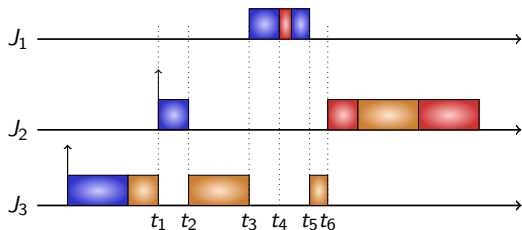
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priority ceilings:

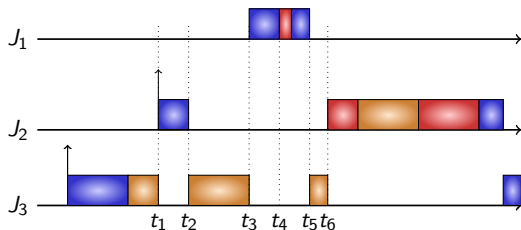
- A: priority level 1
- B: priority level 2

Three jobs with two semaphores A and B.

- $J_1$ : normal execution, wait A, signal A, normal execution
- $J_2$ : normal execution, wait A, wait B, signal B, signal A, normal execution
- $J_3$ : normal execution, wait B, signal B, normal execution

# Example of PCP

- normal execution
- critical section A
- critical section B





priority ceilings:



- A: priority level 1
- B: priority level 2

Three jobs with two semaphores A and B.

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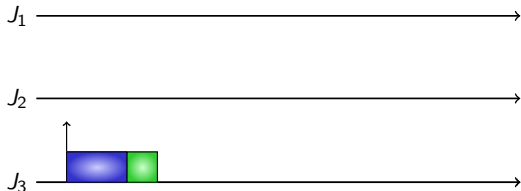
# Example of PCP (2nd)

 normal execution  
 critical section B

 critical section A  
 critical section C

priority ceilings:

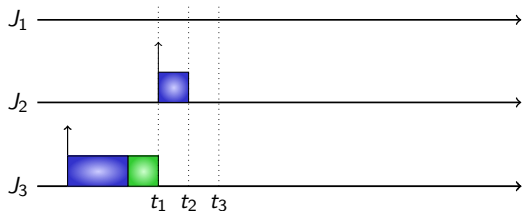
- A: priority level 1
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Three jobs with three semaphores A, B, and C.

- $J_1$ : normal execution, wait A, signal A, normal execution, wait B, signal B, normal execution
- $J_2$ : normal execution, wait C, signal C, normal execution
- $J_3$ : normal execution, wait C, wait B, signal B, signal C, normal execution

# Example of PCP (2nd)



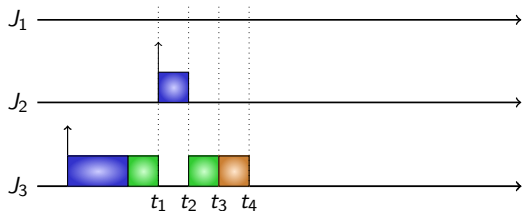
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# Example of PCP (2nd)



priority ceilings:

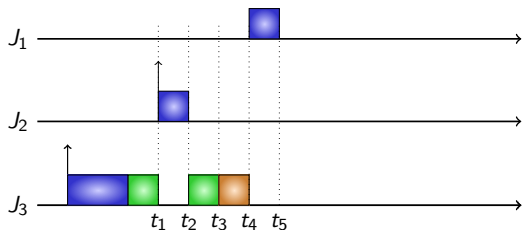
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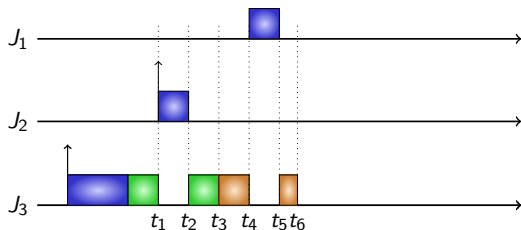
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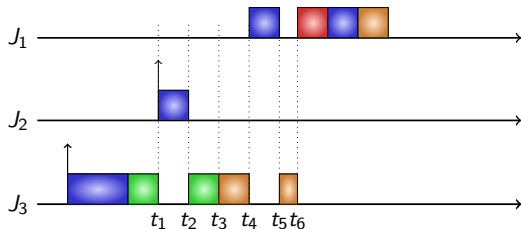
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# Example of PCP (2nd)



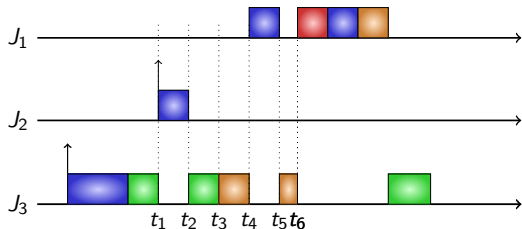
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# Example of PCP (2nd)



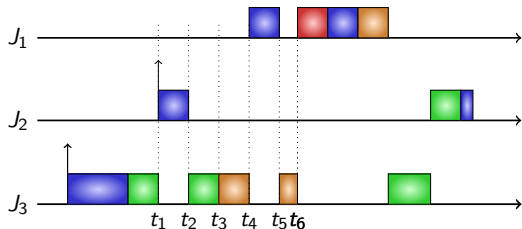
priority ceilings:

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# Example of PCP (2nd)



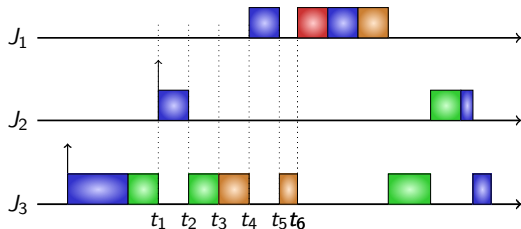
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# Example of PCP (2nd)



priority ceilings:

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# Properties of PCP

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## Theorem

When the resource accesses of a system of preemptive, priority-driven jobs on one processor are controlled by the PCP, deadlock can never occur.

## Theorem

When the resource accesses of a system of preemptive, priority-driven jobs on one processor are controlled by the PCP, a job can be blocked for at most the duration of *one* critical section.

## Properties of PCP (cont.)

### Theorem

The worst-case blocking time  $B_i$  for task  $\tau_i$  is at most

$$\max_{j>i} \{C_{j,R} \mid \Pi(R) \leq i\},$$

where  $C_{j,R}$  is the worst-case (consecutively) execution time when resource  $R$  is required for executing an instance of task  $\tau_j$ .



# Schedulability Test under Blocking Time

## Definition

**Blocking Time**  $B_i$  of a sporadic task  $\tau_i$  is the maximum time, due to *lower-priority jobs*, that a job of task  $\tau_i$  may experience.

The time-demand  $W_i(t)$  of the task  $\tau_i$  is redefined as follows:

$$W_i(t) = B_i + C_i + \sum_{j=1}^{i-1} \left\lceil \frac{t}{T_j} \right\rceil C_j.$$

## Theorem

A system  $\mathcal{T}$  of periodic, preemptable tasks with constrained deadlines is schedulable on one processor by a fixed-priority scheduling algorithm if

$$\forall \tau_i \in \mathcal{T} \exists t \text{ with } 0 < t \leq D_i \text{ and } W_i(t) \leq t.$$

# Schedulability Test under Blocking Time

## Theorem

A system  $\mathcal{T}$  of periodic, preemptable tasks with implicit deadlines is schedulable on one processor by RM if

$$\forall \tau_i \in \mathcal{T} \quad \frac{B_i}{T_i} + \sum_{j=1}^i U_j \leq i(2^{\frac{1}{i}} - 1).$$

## Exercise

Consider the following case with four sporadic tasks and 3 semaphores, where  $S_j(\tau_i)$  is the worst-case execution time of a critical section guarded by semaphore “ $S_j$ ” in task  $\tau_i$  and  $S_j(\tau_i)$  is 0 when task  $\tau_i$  does not need semaphore  $S_j$ .

	$S_1()$	$S_2()$	$S_3()$
$\tau_1$	1	0	0
$\tau_2$	0	0	9
$\tau_3$	3	6	0
$\tau_4$	6	5	4

	$\tau_1$	$\tau_2$	$\tau_3$	$\tau_4$
$C_i$	2	10	16	16
$T_i$	10	24	96	96
$D_i$	10	24	96	96

Suppose that the critical sections are not nested. The worst-case execution time  $C_i$  of a task  $\tau_i$  is derived by assuming that the critical sections are always granted without any blocking.

- Can RM+PCP feasibly schedule the above task set?