Overrun-Resilient Multiprocessor Real-Time Locking

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Abstract

Existing real-time locking protocols require accurate worst-case execution time (WCET) estimates for both tasks and critical sections (CSs) in order to function correctly. On multicore platforms, however, the only seemingly viable strategy for obtaining such estimates is via measurements, which cannot produce a true WCET with certainty. The absence of correct WCETs can be partially ameliorated by enforcing execution budgets at both the task and CS levels and by using a locking protocol that is resilient to budget overruns, i.e., that ensures that the schedulability of non-overrunning tasks is not compromised by tasks that do overrun their budgets. Unfortunately, no fully overrun-resilient locking protocol has been proposed to date for multiprocessor systems. To remedy this situation, this paper presents two such protocols, the OR-FMLP and the OR-OMLP, which introduce overrun-resiliency mechanisms to two existing multiprocessor protocols, the spin-based FMLP and suspension-based global OMLP, respectively. In devising such mechanisms, undo code can be problematic. For the important locking use case of protecting shared data structures, it is shown that such code can be avoided entirely by using abortable critical sections, a concept proposed herein that leverages obstruction-free synchronization techniques. Experiments are presented that demonstrate both the effectiveness of the mechanisms introduced in this paper and their cost.

2012 ACM Subject Classification Computer systems organization → Real-time systems

Keywords and phrases Real-Time Systems, Real-Time Synchronization, Budget Enforcement

Digital Object Identifier 10.4230/LIPIcs.ECRTS.2022.9

Funding Supported by NSF grants CPS 1837337, CPS 2038855, and CPS 2038960, ARO grant W911NF-20-1-0237, and ONR grant N00014-20-1-2698.

1 Introduction

Many safety-critical systems require real-time safety certification that hinges on both timing analysis and schedulability analysis. The goal of timing analysis is to produce worst-case execution times (WCETs) for executable code. Schedulability analysis then determines whether a system’s timing constraints are met, assuming valid WCETs are provided. Due to the advent of multicore technologies, work on timing and schedulability analysis has largely focused on the multiprocessor case in recent years [11,17,34].

A troubling disconnect. In the multiprocessor case, a largely unnoticed fundamental disconnect exists when using timing- and schedulability-analysis together to validate real-time correctness. There is consensus today that static timing-analysis tools may never be a practical reality for multicore machines due to the highly complex nature of multicore architectures [43]. The only alternative is to use measurement-based timing analysis, a topic that has been the focus of considerable recent work [16,18]. With measurement-based timing analysis, however, one can never be certain that the true WCET of a piece of code is ever...
captured (hereafter, we assume “WCET” means “true WCET”). Thus, it is necessary to
distinguish between the WCET of a piece of code and its provisioned execution time (PET)
as obtained via measurements and assumed in schedulability analysis. Note that WCETs are
generally unknowable, and a PET may likely be less than the corresponding WCET.

Mitigating this disconnect. Any safety risk introduced by assuming such PETs can be
avoided by instead using (guaranteed) execution-time (upper) bounds (ETBs) obtained under
unrealistically pessimistic conditions. For example, any execution speedups due to caches and
pipelining might be defined away, bus contention might be over-approximated, etc. While
such ETBs might be safe to use as PETs, this would likely be impractical on a multicore
machine, as an ETB could easily be many times larger than the corresponding WCET. In
fact, system-wide pessimism could be high enough to negate the processing capacity of all
“additional” cores [32]. Thus, more reasonable measurement-based PETs are inevitable.

A system provisioned assuming such PETs can have correct tasks whose PETs are at least
their WCETs, and faulty tasks whose PETs are less than their WCETs. Hopefully, PET
overruns (faults) should be rare. Moreover, when they do occur, they should be contained.
The usual approach here is to treat PETs as execution-time budgets that are enforced by the
operating system (OS). Such an approach can ensure the following desirable property.

P1 The response times of correct tasks, as derived using PETs, are not increased by a PET
overrun of a faulty task.

Task-level budgeting is not enough. Unfortunately, due to various realities of real sys-
tems, task-level budget management alone is an incomplete solution to the timing/schedulabil-
ity disconnect. This paper is directed at providing a deep look at one such reality: the need
to support locking protocols for arbitrating accesses to shared resources. In this setting, we
actually care about various different PETs, WCETs, and ETBs. For example, in addition to
task-level PETs, PETs are needed for individual critical sections (CSs), and various locking-
protocol and OS code sequences. To avoid confusion, we will add a qualifying prefix when
referring to non-task-level terms—e.g., “CS PET” refers to the PET of a CS, while “PET”
(without qualification) refers to a task-level PET. When locking protocols are introduced,
CS PETs (and also various protocol- and OS-related PETs) are used to determine blocking
times when tasks access shared resources. Incorrect blocking-time estimates due to inaccurate
PETs can completely compromise schedulability guarantees.

Overrun-resilient locking protocols. To address this issue, we propose in this paper the
notion of an overrun-resilient locking protocol. In addition to not causing a violation of P1,
such a protocol must also uphold its CS-level variant:

P2 The response times of correct tasks, as derived using PETs, are not increased by a CS
PET overrun of a faulty task.

It’s not so easy. The obvious solution to satisfying P1 and P2 is to assign budgets to
both tasks and CSs as given by their respective PETs. The main new complication that
arises when doing this is the need to abort the CS of some task when one of these budgets is
overrun. Such aborts should be avoided if possible, but they cannot be entirely precluded.
For example, a CS budget overrun will necessarily cause a CS abort. The usual approach to
aborting work is to execute undo code. Presumably, a PET would have to be associated with
such code. What happens if the abort code overruns its PET? Additionally, certain code
sequences exist pertaining to lock and budget management for which overruns are similarly
problematic. For example, when a CS is aborted, the unlock logic must execute to free the
resource. What if the PET associated with this unlock code is overrun? It is not clear how
these perplexing “chicken and egg” problems can be addressed. Whatever the solution, an
Table 1 Properties satisfied by prior work. (“NC” means the work does not consider how to satisfy the specified property. As explained in Sec. 9, some of these “NC” entries can be changed to “Y” at the expense of very pessimistic provisioning assumptions.)

<table>
<thead>
<tr>
<th>Protocol</th>
<th>Multi-processor</th>
<th>P1</th>
<th>P2</th>
<th>P3</th>
<th>Protocol</th>
<th>Multi-processor</th>
<th>P1</th>
<th>P2</th>
<th>P3</th>
</tr>
</thead>
<tbody>
<tr>
<td>ICSs [30]</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>FMLP [9]</td>
<td>Y</td>
<td>N</td>
<td>N</td>
<td>N</td>
</tr>
<tr>
<td>RACPwP [39]</td>
<td>N</td>
<td>Y</td>
<td>Y</td>
<td>NC</td>
<td>vMPCP [31]</td>
<td>Y</td>
<td>Y</td>
<td>N</td>
<td>NC</td>
</tr>
<tr>
<td>OMLP [12]</td>
<td>Y</td>
<td>N</td>
<td>N</td>
<td>N</td>
<td>This Work</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
<td>Y</td>
</tr>
</tbody>
</table>

P3: The response times of correct tasks, as derived using PETs, are not increased by the budget-enforcement mechanism.

Related work. Various locking protocols have been proposed in prior work that considers budget overruns. However, no prior work focusing on multiprocessors fully considers properties P1–P3. Relevant prior work is summarized in Tbl. 1 and discussed in detail in Sec. 9.

Contributions. In this paper, we present overrun-resilient multiprocessor locking protocols that satisfy P1–P3. Our contributions are fourfold. First, we introduce the overrun-resilient flexible multiprocessor locking protocol (OR-FMLP), an overrun-resilient extension of the spin-based FMLP [9]. Second, we introduce the overrun-resilient global optimal multiprocessor locking protocol (OR-OMLP), an overrun-resilient extension of the suspension-based global OMLP [12]. Third, for the important locking use case of coordinating accesses to shared data structures, we propose the concept of an abortable CS, which facilitates satisfying P2 and P3. Finally, we present the results of an experimental evaluation of the cost of overrun-resilient locking and its isolation benefits with respect to timing faults.

Both the OR-FMLP and OR-OMLP use a concept called a “forbidden zone” [28] to satisfy P1. A forbidden zone (FZ) is a length of time at the end of a job’s task budget during which any lock request will be denied. However, the application of this concept is very different in the two protocols. To circumvent the various chicken-and-egg problems related to P3, ETBs must be used for certain code sequences. As ETBs can be very pessimistic, reliance on them should be minimized. With this in mind, we carefully sift through the various design choices and conclude that in a spinlock like the OR-FMLP, coarse-grained FZs should be used that include both CS execution time and blocking time, while in a suspension-based lock like the OR-OMLP, fine-grained FZs based on CS execution times only are better.

Our notion of an abortable CS requires no undo code when aborting CSs. An abortable CS uses word-based obstruction-free [25] software transactional memory (STM) techniques to linearize a CS to a single write instruction. Obstruction-freedom is a type of non-blocking synchronization that must be used with a contention manager to ensure progress under contention. In our case, the contention manager is a locking protocol. We show that using such a strong contention manager enables significant simplifications in obstruction-free code.

Organization. In the rest of this paper, we provide necessary background information (Sec. 2), delve further into task and CS budget management (Sec. 3), present the OR-FMLP, the OR-OMLP, and the abortable CS concept (Secs. 4–6), present our experimental results (Sec. 7), discuss certain practical implications of our work (Sec. 8), review related work (Sec. 9), and conclude (Sec. 10).
2 System Model and Background

Task model. We consider a system of $n$ implicit-deadline\(^1\) sporadic tasks $\tau_1, \tau_2, \ldots, \tau_n$ to be scheduled on $m$ identical processors by a global job-level fixed-priority scheduler; we assume global earliest-deadline-first (G-EDF) scheduling, unless stated otherwise. Each task $\tau_i$ releases a potentially infinite sequence of jobs $J_{i,1}, J_{i,2}, \ldots$ (we omit the job index if it is irrelevant). Each task $\tau_i$ has a period $T_i$ specifying the minimum spacing between consecutive job releases. Each task has a PET obtained via measurement-based timing analysis.

Resource model. We consider a system that has a set $\{\ell_1, \ldots, \ell_n\}$ of serially reusable shared resources. To ensure mutually exclusive resource access, a locking protocol must be employed. When a job $J_i$ requires a resource $\ell_k$, it issues a request $R$ for $\ell_k$. $R$ is satisfied as soon as $J_i$ holds $\ell_k$, and completes when $J_i$ releases $\ell_k$. $R$ is active from its issuance to its completion. $J_i$ must wait until $R$ can be satisfied if it is held by another job. It may do so either by busy-waiting (or spinning) in a tight loop, thereby wasting processor time, or by being suspended by the OS until $R$ is satisfied. A resource access is called a critical section (CS). Each CS has a CS PET obtained via measurement-based timing analysis. We consider non-nested resource requests only. We let $\Gamma_k$ to denote the set of tasks that share $\ell_k$.

Priority inversions. Priority-inversion blocking (or pi-blocking) occurs when a job is delayed and this delay cannot be attributed to higher-priority demand for processing time. Under a given real-time locking protocol, a job may experience pi-blocking each time it requests a resource—this is called request blocking. In addition, a preemptive ready job may experience pi-blocking due to the non-preemptive execution of lower-priority jobs—this is called non-preemptive blocking. On multiprocessors, the formal definition of pi-blocking actually depends on how schedulability analysis is done. For example, of relevance to suspension-based locks, analysis may be either suspension-oblivious (s-oblivious) or suspension-aware (s-aware) [12]. Under s-oblivious analysis, suspension time is analytically treated as computation time.

FMLP. Under the FMLP [9], non-preemptive spin locks are used to ensure mutually exclusive resource access.\(^2\) Each job that is blocked on a resource busy-waits within a FIFO queue.

Global OMLP. The global OMLP [12] is a suspension-based locking protocol that has asymptotically optimal pi-blocking under s-oblivious analysis. The global OMLP ensures $O(m)$ pi-blocking by utilizing a dual-queue structure, with an $m$-element FIFO queue fed into by a priority queue, as shown in Fig. 1. A new request is enqueued in the FIFO queue (resp., priority queue) if there are fewer than (resp., at least) $m$ active requests. When the request at the head of the FIFO queue (i.e., the resource holder) completes, it is dequeued, the next request (if any) in the FIFO queue becomes satisfied, and the highest-priority request (if any) in the priority queue is moved to the tail of the FIFO queue.

Example 1. Fig. 2 shows five jobs that issue requests to the global OMLP with $m = 3$. Fig. 1 shows the global OMLP queues at time 3.5, where $J_1$’s request is denoted by $R_4$. The first three issued requests are enqueued directly in the FIFO queue. Thus, $R_4$ is satisfied before $R_3$, although $J_4$ has lower priority than $J_3$. Since the FIFO queue is full, $R_3$ and $R_3$ are enqueued in the priority queue upon issuance. When $R_4$ completes at time 6, $R_2$

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\(^1\) The results of this paper do not depend on the choice of deadline constraints. Implicit deadlines are assumed for simplicity.

\(^2\) There are actually two FMLP variants: short (spin-based) and long (suspension-based). We are considering the short variant here.
becomes satisfied, and $R_3$ is moved from the priority queue to the FIFO queue, as $J_3$ has higher priority than $J_5$. Thus, $R_3$ is satisfied before $R_5$, despite being issued later.

For ease of notation, we henceforth assume that all jobs of each task include one request for the same resource, and this request is preceded and followed by non-resource-accessing code. This assumption enables us to refer to a job’s CS without ambiguity. We stress that we are making this assumption only for simplicity; none of our results actually depend on it.

3 Budget Management

Execution budgets that are enforced at runtime are obtained by inflating base budgets that pertain to the execution of task code by adding certain overheads. Additional overheads are then added to obtain analytical budgets that are used in schedulability analysis. In this section, we provide details concerning these budgeting notions and relevant overheads.

Base budgets. We define the base task budget (resp., base CS budget) of a task $\tau_i$ (resp., $\tau_i$’s CS), denoted by $C_b^i$ (resp., $L_b^i$), as its PET (resp., CS PET).

What is and is not included in base budgets. Timing analysis is applied to determine relevant PETs for a task independently of the task system that contains it. As lock-related blocking times are system-dependent, we assume that they are not included in base task budgets. The lock/unlock logic of a suspension-based lock is executed in the OS and hence would not be included in base task budgets. In contrast, for a spinlock, this logic executes at user level. However, as seen later, to satisfy P3, we must take special care in dealing with this logic, so we assume it is not included in base task budgets.

When measurement-based timing analysis is applied, preemptions are notoriously difficult to deal with due to difficulties in predicting cache interactions. For this reason, we assume that CSs are executed non-preemptively and that their base budgets are determined assuming cold caches. However, we do not preclude preemptions outside of CSs, as long as base task budgets include cache-related preemption and migration delay (CPMD), which is a cost that is incurred by a job to re-establish lost cache affinity after a preemption or migration. As the focus of this paper is not timing analysis, determining valid CPMDs is out of scope.

Timers. To enforce base task and CS budgets, we require the usage of timers supported by the OS, which we call task- and CS-budgeting timers, respectively. Such a timer starts when the relevant entity (an entire job or a CS) starts executing and stops when the entity is preempted (not allowed for CSs), aborted (see below), or completes execution. Between starting and stopping, a timer is active.
Execution budgets. In reality, timers cannot be started and stopped in zero time. To start a timer, timer-handling code executes in the OS. We assume no knowledge of the exact structure of this code but do require that an ETB is specified for it. When this code executes, we know that the timer starts at some time point, but not precisely when. Stopping a timer is similar. In order to safely police base budgets, we must account for these timer activities. To do so, we instead police adjusted execution budgets as defined next.

The task execution budget $C^e_i$ of a task $\tau_i$ is obtained by inflating its base task budget $C^b_i$ by adding the worst-case cost of all task- and CS-budgeting timer overheads, as provisioned by their ETBs, that may be incurred by a job of $\tau_i$. The CS execution budget $L^e_i$ of $\tau_i$’s CS is similarly obtained by inflating its base CS budget $L^b_i$ by adding the worst-case cost of all CS-budgeting timer overheads, as provisioned by their ETBs, associated with that CS.

In overrun-resilient locking protocols that we propose, these execution budgets are enforced at runtime. Specifically, we set the task- or CS-budgeting timer of a job to expire when the corresponding task or CS execution budget is exhausted. A job overruns its task/CS execution budget if it does not complete execution before the relevant timer expires.

Example 2. Consider job $J_i$ in Fig. 3. (We consider analytical budgets later.) Starting (resp., stopping) $J_i$’s task-budgeting timer entails executing OS code during $[t_2,t_3]$ (resp., $[t_4,t_5]$). Thus, $J_i$’s task execution budget is derived by inflating its base task budget by $(t_3 - t_2) + (t_5 - t_4)$ units.

Example 3. Fig. 4 depicts three G-EDF-scheduled tasks on two processors. $\tau_1$ and $\tau_3$ use resource $r_1$, which is protected by a spinlock. $\tau_3$’s task (resp., CS) execution budget is 9.0 units (resp., 2.0 units). At time 0, $J_{3,1}$ is scheduled and its task-budgeting timer starts. $J_{3,1}$ consumes 1.0 unit of its task execution budget within the time interval $[0,1]$ during which its task-budgeting timer is active. $J_{3,1}$ is preempted by $J_{2,1}$ at time 1, causing its
Table 2 OR-FMLP and OR-OMLP overhead impact.

<table>
<thead>
<tr>
<th>Overheads</th>
<th>Base task budgets</th>
<th>Task exec. budgets</th>
</tr>
</thead>
<tbody>
<tr>
<td></td>
<td>OR-FMLP</td>
<td>OR-OMLP</td>
</tr>
<tr>
<td>Budgeting-timer</td>
<td>×</td>
<td>×</td>
</tr>
<tr>
<td>Locking &amp; unlocking</td>
<td>×</td>
<td>×</td>
</tr>
<tr>
<td>Request blocking</td>
<td>×</td>
<td>×</td>
</tr>
<tr>
<td>Non-preemptive blocking</td>
<td>×</td>
<td>×</td>
</tr>
</tbody>
</table>

task-budgeting timer to stop. Thus, J_{3,1}’s task execution budget remains the same during the time interval [1,3). At time 3, J_{3,1} is scheduled again and it continues executing until completing at time 11, consuming 8.0 units of its task execution budget.

J_{3,1} issues a request for ℓ_1 at time 6 that is satisfied at time 8 (when its CS-budgeting timer starts) and completes at time 10 (after consuming its entire CS execution budget).

Analytical budgets. Some overhead/delay sources do not cause task or CS execution budget to be consumed. However, such sources can impact schedulability. We define the analytical task budget of task τ_1, denoted C^a_{τ_1}, by inflating its task execution budget to account for all overheads/delays. We define the analytical CS budget of τ_1’s CS, denoted L^a_{τ_1}, by inflating its CS execution budget to account for all overheads/delays affecting that CS.

Example 2 (Cont’d). J_i in Fig. 3 suffers π-blocking during the time interval [t_1, t_2) due to a non-preemptively executing lower-priority job. Since J_i is not scheduled during [t_1, t_2), its execution budget does not decrease during this interval. However, J_i may miss its deadline due to the delay caused by this π-blocking. Thus, J_i’s analytical task budget is derived by inflating its task execution budget by t_2 − t_1.

Overheads/Delays. We consider the following overheads/delays that are either locking- or timer-related overheads. We summarize the overheads/delays that affect base and execution task and CS budgets under the OR-FMLP and OR-OMLP in Tbl. 2 and all introduced notation in Tbl. 3. Note that we require ETBs of these overheads to avoid introducing “chicken and egg” problems in satisfying P3, as discussed in Sec. 1.

(i) Budgeting-timer overheads. We denote the ETBs of starting, stopping, and expiring a budgeting-timer by Δ_{tb}, Δ_{te}, and Δ_{tt}, respectively. Since we focus on timer overheads that are due to a CS execution, accounting for overheads due to starting/ stopping a task-budgeting timer for resuming/suspending a job’s non-CS code is out of scope.

(ii) Locking and unlocking overheads. We denote the ETBs of executing the lock and unlock logic (for both spinlocks and suspension-based locks) by Δ_{lock} and Δ_{unlock}, respectively.

(iii) Request blocking. We let B_i denote a bound on request blocking incurred by τ_i’s request.

(iv) Non-preemptive blocking. We let NPB_i denote a bound on non-preemptive blocking incurred by τ_i.

Accounting for these overheads in analytical budgets is a well-researched topic [10]. We detail the required overhead inflation in task and CS execution budgets under the OR-FMLP and OR-OMLP in Secs. 4 and 5, respectively.

Simplifying assumptions. In order to focus only on those overheads/delays of direct relevance to overrun-resilient locking and to simplify the description of the OR-FMLP and OR-OMLP, we make the following assumptions.

A1 ETBs of all overheads are known.

A2 The cost of aborting a CS is included in the ETB of expiring the CS-budgeting timer.
Table 3 Notation summary.

<table>
<thead>
<tr>
<th>Symbol</th>
<th>Meaning</th>
<th>Symbol</th>
<th>Meaning</th>
</tr>
</thead>
<tbody>
<tr>
<td>( n )</td>
<td>Number of tasks</td>
<td>( L_i^b )</td>
<td>Analytical CS budget of ( \tau_i )'s CS</td>
</tr>
<tr>
<td>( m )</td>
<td>Number of processors</td>
<td>( \Delta_{th} )</td>
<td>ETB of starting overhead for a task- or CS- budgeting timer</td>
</tr>
<tr>
<td>( \tau_i )</td>
<td>( i^{th} ) task</td>
<td>( \Delta_{te} )</td>
<td>ETB of stopping overhead for a task- or CS- budgeting timer</td>
</tr>
<tr>
<td>( J_{i,j} )</td>
<td>( j^{th} ) job of ( \tau_i )</td>
<td>( \Delta_{tt} )</td>
<td>ETB of expiring overhead for a task- or CS- budgeting timer</td>
</tr>
<tr>
<td>( T_i )</td>
<td>Period of ( \tau_i )</td>
<td>( \Delta_{lock} )</td>
<td>ETB of locking overhead</td>
</tr>
<tr>
<td>( \ell_k )</td>
<td>( k^{th} ) shared resource</td>
<td>( \Delta_{unlock} )</td>
<td>ETB of unlocking overhead</td>
</tr>
<tr>
<td>( C_{ib}^s )</td>
<td>Base task budget of ( \tau_i )</td>
<td>( \Delta_{abort} )</td>
<td>ETB of overhead for aborting a request</td>
</tr>
<tr>
<td>( C_{ib}^e )</td>
<td>Task execution budget of ( \tau_i )</td>
<td>( B_i )</td>
<td>Maximum request blocking time of ( \tau_i )</td>
</tr>
<tr>
<td>( C_{ab}^a )</td>
<td>Analytical task budget of ( \tau_i )</td>
<td>( NPB_i )</td>
<td>Maximum non-preemptive blocking time of ( \tau_i )</td>
</tr>
<tr>
<td>( L_i^b )</td>
<td>Base CS budget of ( \tau_i )'s CS</td>
<td>( \Gamma_k )</td>
<td>Set of tasks that shares a resource ( \ell_k )</td>
</tr>
<tr>
<td>( L_i^e )</td>
<td>CS execution budget of ( \tau_i )'s CS</td>
<td>( f_i )</td>
<td>Forbidden-zone length for ( J_i )</td>
</tr>
</tbody>
</table>

A3 All overheads/delays other than task- and CS-budgeting timer overheads, locking and unlocking overheads, and request and non-preemptive blocking are negligible.

We discuss how A1 and A3 can be relaxed in Sec. 8 and how to support A2 in Sec. 6.

Refining P1–P3. Properties P1–P3 can be ensured by maintaining the following properties.

P1.1 If a job’s task execution budget expires, then it has no active request (to satisfy P1).

P2.1 If the CS execution budget of a CS expires, then the CS is aborted without corrupting shared-resource state (to satisfy P2).

P3.1 Execution-time variances in executing timer-handling and lock/unlock logic cannot cause task and CS execution budgets to be exceeded (to satisfy P3).

We show how to satisfy P1.1 and P3.1 in the OR-FMLP and OR-OMLP in Secs. 4 and 5. We also show how to satisfy P2.1 in Sec. 6 for the case of shared data structures. In order to focus on P1.1 and P3.1 for now, we make the following assumption.

A4 Property P2.1 is satisfied.

## 4 OR-FMLP

In this section, we introduce the overrun-resilient flexible multiprocessor locking protocol (OR-FMLP), an extension of the FMLP [9] that achieves overrun resiliency by enforcing task and CS execution budgets. Like the FMLP, a job is non-preemptive when executing the OR-FMLP (while both spinning and executing its CS). The OR-FMLP satisfies P1.1 by using a previously proposed concept called a forbidden zone (FZ) [27] that aids in budget enforcement—in fact, the OR-FMLP is very similar to a protocol called the “Skip Protocol” presented in [27]. In our setting, however, much care is required in deriving execution budgets so that “chicken and egg” problems are avoided. The goal of avoiding such problems has a major bearing on the overall lock design and its analysis.

**Design goal.** Spinlocks provide mutual exclusion without OS support, eliminating system-call overheads. While some timer-related OS support is needed, our overriding design goal is nonetheless the following.

G1 Minimize the number of the OS invocations.
Managing CS-budgeting timers. To prevent CS execution budget overruns, OS invocations are needed, contrary to G1, to manage CS-budgeting timers. It is perhaps theoretically possible to avoid using such timers by having the CS itself repeatedly monitor the CS execution budget remaining, but such an approach would have very high overhead.

Satisfying P1.1. We satisfy P1.1 by employing FZs, as mentioned above. When a job is allocated its task execution budget, a portion of that budget at the end constitutes its FZ. A job is not allowed to issue a resource request during its FZ. The length of $J_i$’s FZ, denoted by $f_i$, is the maximum task execution budget of $J_i$ that can be consumed when a request of $J_i$ is active. Under the OR-FMLP, this task execution budget consumption includes both its CS length and spinning time. The OR-FMLP adds an additional “FZ check” prior to performing the locking logic of the FMLP. This check, which is assumed to be part of the locking overhead of the OR-FMLP, can be implemented entirely in user space by having the OS record the current time as given by the local timestamp counter (TSC) in a shared control page whenever a job begins or resumes execution. Using this recorded value and the current local TSC value, a job can determine whether it is in its FZ.

Example 4. Fig. 5(a) depicts two jobs that issue requests to the OR-FMLP for resource $\ell_1$. Assume that $J_2$’s task execution budget is 7.0 units and its CS execution budget is 2.0 units. $J_2$ could potentially be blocked by $J_1$ for 3.0 time units, the length of $J_1$’s CS execution. $J_2$ enters its FZ at time 2 as it does not have sufficient task execution budget to spin for 3.0 time units and then execute its CS for 2.0 time units. Thus, its request is denied at time 4.

Satisfying P3.1. To satisfy P3.1, we derive task and CS execution budgets by accounting for all lock- and timer-related overheads/delays, given in Tbl. 2, using their ETBs. Before deriving these terms, we first give the rules of the OR-FMLP.

OR-FMLP Rules. We assume the following properties, which we justify later.

B1 The execution and analytical budgets of all tasks and CSs have been determined.

B2 A job’s FZ length can be derived from task/CS base, execution, and analytical budgets. When a job $J_i$ attempts to issue a request $\mathcal{R}$ for a resource $\ell_k$, it proceeds according to the following rules ($J_i$ is non-preemptive while executing according to these rules).

F1 $\mathcal{R}$ is issued only if $J_i$’s remaining task execution budget is at least $f_i$; otherwise, $\mathcal{R}$ is denied. Issued requests spin (if necessary) in per-resource FIFO queues until satisfied. (Policies for handling denied or aborted requests are an application-level concern.)

F2 When $\mathcal{R}$ is satisfied, $J_i$’s CS-budgeting timer is set to expire $L_k^w$ time units in the future.

F3 When $J_i$’s CS completes, $J_i$’s CS-budgeting timer is stopped and $J_i$ releases $\ell_k$. If the CS-budgeting timer expires prior to CS completion, then $\ell_k$ is released (i.e., $J_i$’s CS is aborted, as allowed by Assumption A4).

Figure 5 Illustration of FZs. Overheads/delays other than spinning are omitted to avoid clutter.
Addressing B1 and B2. We now address Properties B1 and B2. Fig. 6 depicts the execution of a request \( R \) of a job \( J_i \), with overheads included, during the time interval from \( R \)'s issuance until its completion. During this interval, \( J_i \) issues \( R \) by inserting \( R \) into the FIFO spin-queue during \([t_1, t_2]\), spins (if required) during \([t_2, t_3]\), starts its CS-budgeting timer during \([t_3, t_5]\), executes its CS during \([t_5, t_6]\), stops its CS-budgeting timer during \([t_6, t_8]\), and unlocks its acquired resource during \([t_8, t_9]\). Using this figure as a reference, we now derive the various terms mentioned in B1 and B2.

CS execution budget. We derive \( L_i^e \) by inflating \( L_i^b \) to account for its CS execution budget consumption due to CS-budgeting timer overheads. Since \( J_i \)'s CS executes non-preemptively under the OR-FMLP, \( J_i \) incurs CS-budgeting timer overheads only when its CS starts and completes execution. However, the CS-budgeting timer can start or stop at an arbitrary time point within the OS’s timer-handling code, as shown by times \( t_4 \) and \( t_7 \) in Fig. 6, respectively. Since \((t_5 - t_4) \leq \Delta_{tb} \) and \((t_7 - t_6) \leq \Delta_{te} \), \( J_i \)'s CS execution budget is consumed by at most \( \Delta_{tb} + \Delta_{te} \) units due to starting and stopping its CS-budgeting timer. Expiring the CS-budgeting timer does not consume any CS execution budget because it occurs only when the CS execution budget is fully consumed. Thus, we have

\[
L_i^e = L_i^b + \Delta_{tb} + \Delta_{te}.
\]

Analytical CS budget. The above derivation of \( L_i^e \) pessimistically assumes that \( t_4 \) (resp., \( t_7 \)) is close to \( t_3 \) (resp., \( t_8 \)). In reality, \( t_4 \) (resp., \( t_7 \)) could instead be close to \( t_5 \) (resp., \( t_6 \)), implying that we must inflate again for timer overheads in determining the analytical CS budget. With this in mind, we derive \( L_i^a \), represented by \([t_3, t_8]\) in Fig. 6, by inflating \( L_i^e \) to account for its task execution budget consumption due to CS-budgeting timer overheads. \( J_i \)'s task execution budget is consumed by at most \( L_i^a \) units during \([t_4, t_7]\). Before (resp., after) the CS-budgeting timer actually starts (resp., stops), the timer-handling code may execute for at most \( \Delta_{tb} \) time units (resp., \( \Delta_{te} \)) during \([t_3, t_4]\) (resp., \([t_7, t_8]\)). If the CS-budgeting timer of \( J_i \) expires, then the expiration and CS abort at most \( \Delta_t \) time units (by Assumption A2). Since the timer stop and expiration cannot both occur for a CS, we have

\[
L_i^a = L_i^e + \Delta_{tb} + \max(\Delta_{te}, \Delta_t).
\]

Request blocking time. Under the FMLP, a request \( R \) for a resource \( \ell_k \) by a job \( J_i \) can be blocked by at most \( m - 1 \) requests for \( \ell_k \) by other jobs. A request \( R' \) by a job \( J_j \) that blocks \( R \) can do so for the entire duration when \( R' \) is satisfied. This duration includes the time needed for \( R' \) to (i) start its the CS-budgeting timer, (ii) execute its CS, (iii) stop/expire its CS-budgeting timer, and then (iv) unlock \( \ell_k \). This time interval is analogous to \([t_3, t_9]\) for \( J_j \) in Fig. 6. \( L_j^a \) upper bounds the total time for (i)–(iii) and \( \Delta_{unlock} \) upper bounds the time for (iv). It follows that

\[
B_i = \sum_{m-1}^{\text{largest in } \Gamma_k} (L_j^a + \Delta_{unlock}).
\]
**FZ length.** $J_i$’s FZ length, $f_i$, is the maximum task execution budget of $J_i$ that can be consumed during the time interval when its request $R$ is active. This time interval corresponds to $[t_1, t_9)$ in Fig. 6. $J_i$ issues $R$ during $[t_1, t_2)$, which takes at most $\Delta_{\text{lock}}$ time units. It then busy-waits for at most $B_i$ time units during $[t_2, t_3)$. It subsequently executes its CS and timer-handling code for at most $L^a_i$ time units during $[t_3, t_8)$ and then unlocks $\ell_k$ during $[t_8, t_9)$, which requires at most $\Delta_{\text{unlock}}$ time units. Therefore,

$$f_i = B_i + \Delta_{\text{lock}} + L^a_i + \Delta_{\text{unlock}}.$$  \hfill (4)

**Task execution budget.** We derive $J_i$’s task execution budget by inflating its base task budget to account for spinning time, locking and unlocking overheads, and task- and CS-budgeting timer overheads incurred when its request $R$ is active (see Tbl. 2). These overheads/delays correspond to all of $[t_1, t_9)$ except $[t_5, t_6)$ in Fig. 6. Since $f_i$ (resp., $L^b_i$) corresponds to $[t_1, t_9)$ (resp., $[t_5, t_6)$), $J_i$’s task execution budget is

$$C^e_i = C^b_i + f_i - L^b_i.$$  

**Analytical task budget.** $J_i$’s analytical task budget is obtained by inflating its task execution budget to account for non-preemptive blocking and a potential task-budgeting timer expiration. Expiring the task-budgeting timer takes at most $\Delta_{\text{tt}}$ time units. Because jobs invoke the OR-FMLP non-preemptively, a newly released job may be blocked by lower-priority jobs for the duration of $m$ CSs (inflated to include overheads). Reasoning similarly to (3), we have

$$NPB_i = \sum_{j \text{ largest}} (L^a_j + \Delta_{\text{unlock}}).$$

Therefore, $J_i$’s analytical task budget is

$$C^a_i = C^e_i + NPB_i + \Delta_{\text{tt}}.$$  

**Fine-grained FZs and why they are problematic.** FZs were originally proposed to be policed upon CS entry [27], but here we have policed them in a more coarse-grained way by also including spinning time. We made this choice to avoid interactions with the OS, per Goal G1, to maintain the use of simple user-level synchronization code, and to reduce the length of code sequences that require ETBs. Here we briefly explore the fine-grained choice of defining FZ lengths based on CS execution times only.

The main advantage of the fine-grained approach is that FZ lengths are shorter. However, now a job may exhaust its task execution budget while executing within the locking protocol. In this case, its request must be extracted from the FIFO spin-queue. Letting $\Delta_{\text{abort}}$ denote that time required to do this, it can be shown that (4) can be replaced by

$$f_i = \max(L^a_{\text{max}} + \Delta_{\text{unlock}}, \Delta_{\text{abort}}).$$  \hfill (5)

**Example 5.** Fig. 5(b) depicts two jobs that issue requests for resource $\ell_1$. At time 3, $J_2$ issues a request $R$ for $\ell_1$. Assume that $J_2$’s task and CS execution budgets are 7.0 and 2.0 units, respectively, and extracting $R$ from the FIFO spin-queue requires 3.0 time units. Then, $J_2$’s fine-grained FZ length is $\max\{2, 3\} = 3$. Thus, $J_2$ reaches its FZ at time 4 after consuming 4.0 units of its task execution budget.

Significant prior research has been directed at abortable spinlocks that allow requests to be aborted [1, 2, 29, 33, 38, 44]. Two approaches have been investigated in designing such locks.
The first approach aborts requests “lazily” by setting a removal flag \([2, 33, 38, 44]\). Proper request removal is performed later by another job whose resource request is pending or satisfied. This removal requires \(O(m^2)\) time \([33]\), which can significantly increase FZ lengths. In the second approach, an aborted request is removed immediately \([1, 29]\). In existing algorithms, such a removal requires \(O(\min(m, \log n))\) time complexity or worse. Moreover, abortable spinlocks require complicated lock/unlock/abort logic. This would significantly increase the ETBs associated with that logic. In contrast, a simple ticket lock can be used in the course-grained variant, thus reducing the length of code sequences requiring ETBs.

\section{OR-OMLP}

In this section, we introduce the overrun-resilient \(O(m)\) locking protocol (OR-OMLP). The original OMLP executes CSs preemptively and uses priority inheritance \([37]\) as a progress mechanism to ensure that if a job waiting to access a resource \(\ell_k\) is among the \(m\) highest-priority jobs, then the currently satisfied request for \(\ell_k\) is scheduled. The OR-OMLP executes CSs non-preemptively (for the timing-analysis-related reasons discussed in Sec. 3) but retains priority inheritance as a progress mechanism. Priority inheritance is still needed to ensure that when a (non-preemptive) CS ends, the next queued request will be satisfied if it is blocking a job whose priority is among the top \(m\). Non-preemptive CSs do not alter the OMLP’s request-blocking bounds, but introduce non-preemptive blocking, which the OMLP avoids.

Similar to the OR-FMLP, the OR-OMLP uses FZs and ETBs of lock- and timer-related overheads to satisfy P1.1 and P3.1, respectively, but here, FZs are fine-grained (i.e., policed on CS entry). Having already seen how these basic mechanisms work in the context of the OR-FMLP, we proceed directly to defining the rules of the OR-OMLP.

\textbf{OR-OMLP rules.} Our description of the OR-OMLP focuses on a single resource \(\ell_k\), for which there are two queues, an \(m\)-element FIFO queue FQ and a priority queue PQ, as shown in Fig. 1. When a job \(J_i\) attempts to issue a request \(R\) for \(\ell_k\), it follows the rules below, which are specified assuming that B1 and B2 in Sec. 4 hold, and that a job’s task-budgeting timer starts (resp., stops) when it begins (resp., ceases) to execute.

\begin{itemize}
  \item \textbf{O1} \(R\) is issued only if \(J_i\)’s remaining task execution budget is at least \(f_i\); otherwise, \(R\) is denied. If not denied, \(R\) is enqueued in FQ if fewer than \(m\) requests for \(\ell_k\) are already active; otherwise, it is added to PQ.
  \item \textbf{O2} All queued jobs except the job at the head of FQ are suspended. The job at the head of FQ inherits the priority of the highest-priority job in FQ or PQ.
  \item \textbf{O3} If \(R\) becomes the head of FQ at time \(t\), then it is satisfied and \(J_i\) becomes eligible to be scheduled at time \(t\) (this depends on its perhaps-inherited priority). If \(J_j\)’s request was the head of FQ before time \(t\) and \(J_i\) is among the \(m\) highest-priority jobs at time \(t\) but cannot preempt the lowest-priority scheduled job due to non-preemptivity, then \(J_i\) preempts \(J_j\) (even if \(J_j\) is one of the top \(m\) priority jobs). Once scheduled, \(J_i\)’s CS-budgeting timer is set to expire \(L_{\ell_k}^i\) time units in the future, and \(J_i\) executes its CS non-preemptively.
  \item \textbf{O4} When \(J_j\)’s CS completes, its CS-budgeting timer is stopped, \(J_i\) releases \(\ell_k\), and \(J_i\) becomes preemptive. If instead its CS-budgeting timer expires prior to its CS completion, then \(\ell_k\) is released (i.e., \(R\) is aborted, as allowed by Assumption A4). In either case, \(R\) is dequeued from FQ and the highest-priority request from PQ is moved to the tail of FQ.
\end{itemize}

\textbf{Lazy preemptions.} In addition to the above rules, we enact preemptions (except the preemption mentioned by Rule O3) lazily by delaying any preemption until the lowest-priority scheduled job becomes preemptable instead of preempting the first-available lower-priority job \([10, \S 3.3.3]\). Lazy preemptions prevent a job from incurring repeated pi-blocking each time
a higher-priority job is released when the scheduler implementation is link-based \cite{10, §3.3.3}, which we assume.

Example 6. Lazy preemption is depicted in Fig. 7. Three jobs are scheduled on two processors under link-based G-EDF. When $J_3$ is released at time 2, the scheduler links $J_3$ to processor 1, which is executing the lowest-priority job among both processors. Since $J_1$ is scheduled on processor 1 and is nonpreemptive at time 2, $J_3$ is not scheduled. At time 5, $J_1$ becomes preemptive again, and $J_3$, the job linked to processor 1, is scheduled on processor 1. Further details concerning lazy preemptions and link-based scheduling are given in an online appendix \cite{41}.

Addressing B1 and B2. We deal with these properties similarly as for the OR-FMLP. Fig. 8 depicts the execution of a request $R$ of a job $J_i$, with overheads included. We omit CS-budgeting timers in Fig. 8 as their accounting is the same as for the OR-FMLP, but we include task-budgeting timers as they are relevant to suspension-based locks. $J_i$’s lock request is issued by enqueueing it in the relevant queue during $[t_1, t_2)$. If $\ell_k$ is held by another job, then $J_i$ suspends. Before suspending $J_i$ at $t_4$, $J_i$’s task-budgeting timer is stopped during $[t_2, t_4)$. $J_i$’s task-budgeting timer is started during $[t_6, t_7]$ after it is scheduled again upon satisfaction of $R$ at $t_5$. During $[t_7, t_8)$, $J_i$’s CS-budgeting timer starts, its CS executes, and then its CS-budgeting timer stops. $J_i$ unlocks $\ell_k$ during $[t_8, t_9)$. If $J_i$ is preempted due to Rule O3 after it unlocks $\ell_k$, then its task-budgeting timer is stopped during $[t_9, t_{11})$. Using this figure as reference, we now derive the various terms mentioned in B1 and B2.

CS execution and analytical budgets. Since CSs execute non-preemptively, the analysis of CS execution and analytical budgets is the same as under the OR-FMLP. Thus, $J_i$’s CS execution budget and analytical CS budgets are determined by (1) and (2), respectively.

Task execution budget. Locking and unlocking overheads during $[t_1, t_2)$ and $[t_8, t_9)$, respectively, occur when $J_i$’s task-budgeting timer is active and thus consume at most $\Delta_{lock}$ and $\Delta_{unlock}$ units, respectively, of $J_i$’s task execution budget. $J_i$’s task-budgeting timer actually starts (resp., stops) at an arbitrary time point $t_6$ (resp., $t_3$ and $t_{10}$) within the OS’s timer-handling code. Thus, $(t_3 - t_2) + (t_{10} - t_9) \leq 2\Delta_{te}$ (resp., $(t_7 - t_6) \leq \Delta_{ib}$) units are consumed from $J_i$’s task execution budget when $J_i$ is suspended/preempted (resp., resumed). By the FZ check in Rule O1, $J_i$’s task-budgeting timer cannot expire when $R$ is active. The CS-budgeting timer overheads are accounted for in $L_i^a$, and are at most $L_i^a - L_i^b$. Thus, $J_i$’s
task execution budget is

\[ C^e_i = C^b_i + \Delta_{lock} + \Delta_{unlock} + \Delta_{tb} + 2\Delta_{te} + L^a_i - L^b_i. \]

**FZ length.** \( f_i \) is given by the maximum task execution budget of \( J_i \) that can be consumed during the time interval when \( R \) is active. \( J_i \) consumes its task execution budget throughout all of \([t_1, t_6)\) except within \([t_3, t_4)\). Therefore,

\[ f_i = \Delta_{lock} + \Delta_{unlock} + \Delta_{tb} + \Delta_{te} + L^a_i. \]

**Request blocking.** Under the OMLP, a job \( J_i \) can be pi-blocked by the length of at most \( 2(m - 1) \) requests for \( \ell_k \) [12]. This result hinges on a progress mechanism, which ensures the progress of the job \( J_j \) holding \( \ell_k \) whenever \( J_j \) is request-blocked. Under the OR-OMLP, Rule O3 and priority inheritance ensure the same progress property. When \( J_j \) becomes the head of FQ, Rule O3 ensures that it is scheduled if its (perhaps-inherited) priority is one of the top \( m \) despite any non-preemptive execution of lower-priority jobs. This may cause non-preemptive blocking for the previous resource holder (if any), which we discuss later. Priority inheritance ensures that \( J_j \) can be scheduled when its priority is raised because of \( J_i \)’s request issuance. (We give a formal proof in an online appendix [41].)

By preserving the same progress property as the OMLP, the OR-OMLP has the same request-blocking bounds as the OMLP. A request \( R' \) by \( J_j \) can pi-block \( J_i \) for the duration in which \( R' \) is satisfied, which is analogous to the time interval \([t_1, t_6)\) in Fig. 8. This duration includes the time needed for \( R' \) to (i) start its task-budgeting timer, (ii) start its CS-budgeting timer, (iii) execute its CS, (iv) stop its CS-budgeting timer, and (v) unlock \( \ell_k \). \( \Delta_{tb} \) upper bounds (i), \( L^a_i \) upper bounds (ii)–(iv), and \( \Delta_{unlock} \) upper bounds (v). Additionally, \( J_j \) can be preempted before the next job holding \( \ell_k \) can be scheduled. This causes \( J_j \)’s task-budgeting timer to stop during \([t_9, t_{11}]\), which takes at most \( \Delta_{te} \) time. Therefore,

\[ B_i = 2 \cdot (m - 1) \cdot (\Delta_{tb} + \Delta_{unlock} + \Delta_{te} + \max_{j \in \Gamma_k} \{ L^a_j \}). \]

**Non-preemptive blocking.** With lazy preemptions, \( J_i \) can incur non-preemptive blocking when it releases \( \ell_k \) (due to Rule O3). (We give an example of the latter case in an online appendix [41].) Note that a job can be pi-blocked when a resource is released even under the OMLP if there is a task with non-preemptive sections [10, §3.3.3]. However, such pi-blocking can be analytically treated the same as pi-blocking incurred upon job release by considering the remaining portion of the job as a new job. Each job release can cause pi-blocking for the length of at most one CS [10, §3.3.3]. Reasoning as above for (6), we have

\[ NPB_i = 2 \cdot (\Delta_{tb} + \Delta_{unlock} + \Delta_{te} + \max \{ L^a_j \}). \]

**Analytical task budget.** We derive \( C^a_i \) by inflating \( C^e_i \) to account for request blocking time \( B_i \), non-preemptive blocking time \( NPB_i \), task-budgeting timer expiration overhead \( \Delta_{tt} \), and task-budgeting timer starting/stopping overheads during \([t_3, t_4), [t_5, t_6), \) and \([t_9, t_{11}]\). Since \((t_4 - t_3) + (t_{11} - t_9) \leq 2\Delta_{te} \) and \((t_6 - t_5) \leq \Delta_{tb} \), we have

\[ C^a_i = C^e_i + B_i + NPB_i + \Delta_{tb} + 2\Delta_{te} + \Delta_{tt}. \]

**Coarse-grained FZs.** Is it possible to have a OR-OMLP variant with coarse-grained FZs like the OR-FMLP? Such a variant would actually be quite tricky to implement due to the need to track task budget consumption by waiting jobs. A waiting job’s task budget should be consumed only when it is pi-blocked, and under s-oblivious analysis, not all suspension time “counts” as pi-blocking time [12]. This mance greatly complicates budget tracking.
Abortable Critical Sections

In this section, we introduce abortable CSs, which enable operations on shared data structures to be aborted without undo code. Abortable CSs are inspired by word-based obstruction-free STM, which linearizes multiple operations to a single instruction, but can only ensure progress in the presence of a contention manager. By executing instructions in CSs, the locking protocol serves as a strong contention manager, allowing us to simplify and address issues in prior obstruction-free techniques.

**Undo code problem.** The following example shows the necessity of undo code when an ordinary CS is aborted.

▶ **Example 7.** Consider the `Modify` procedure in Alg. 1, which updates a two-word buffer `M[1..2]` by incrementing each `M[i] by M[1]’s value. If the procedure is aborted after completing the first for-loop iteration, then the buffer is left in an inconsistent state. In order to restore `M` to a valid state, undo code would need to set `M[1] to its old value.

While the undo code above is simple, such code can be much more complicated for operations that make many changes to object state. Undo code also needs to be provisioned using its ETB to satisfy P3.1, which can be as pessimistic as the ETB of the CS itself.

**Prior work on versioning techniques.** Prior work on versioning techniques attempt to obviate undo code through various means, but they all have unfortunate limitations in our context. Interruptible CSs (ICSs [30]) use the idea of a `continuation` [42] to eliminate undo code by appending memory modifications to a log, which will be applied before the next CS entry. Unfortunately, ICSs can force short CSs to apply the memory modifications of long CSs. When CSs only modify memory, each CS length may increase by the length of the longest CS in the system. Object-based obstruction-free STMs [21, 26, 35] do not face this issue, but may require coarse-grained copies of an entire data structure when only small modifications are performed. Word-based variants [22–24] eliminate the need for coarse-grained copying, but require a garbage collector. Other protocols such as TL2 [19] fix both the problems of word-based STMs and continuations, but can require a lengthy clean-up process on abort.

Our abortable CS concept leverages locks as a strong contention manager. It also addresses the issue present in ICSs, and word-based STMs’ reliance on garbage collectors without requiring a lengthy clean-up process like TL2. We now explain this concept by showing how to convert `Modify` into an abortable version, `AbortableModify`, also given in Alg. 1. We first describe the data structures involved.

**Data structures.** We represent each `M[i]` using the structure shown in Fig. 9(a) and associate a CS, e.g., an invocation of `AbortableModify`, with a transaction record as defined in Fig. 9(b). The fields `M[i].old` and `M[i].new` contain the valid value of `M[i]`—i.e., the value written by the last unaborted request involving a write to `M[i]`—before and after reaching the linearization point, respectively. We modify only `M[i].new` within a CS before it reaches its linearization point. The `txn` field of `M[i]` is a pointer to a transaction record, which is set when `M[i]` is updated in `AbortableModify`.

The `rc1` and `rc2` fields in a transaction record count the number of `M[i]` structures that point to that record, which are used to determine when the record is no longer in use, as discussed later. The `done` field indicates whether the CS corresponding to the record has
AlGORITHM 1 Example buffer data structure.

Variables:
M[1..2]: A shared array of words

1: procedure MODIFY(M)
2: \( x := M[1] \)
3: for \( i \in \{1, 2\} \) do
4: \( M[i] := M[i] + x \)
5: end for
6: end procedure

Variables:
M[1..2]: A shared array of type in Fig. 9(a)
data : Ptr to data structure in Fig. 9(a)
txn : Ptr to txn_record in Fig. 9(b)
new_txn : Ptr to txn_record in Fig. 9(b)
free_stack : Stack of free transaction records
free_stack_top : Ptr to top of free_stack

1: procedure ABORTABLEMODIFY(M)
2: new_txn := NULL
3: if \( M[1].txn \neq \text{NULL} \land M[1].txn.done \)
   then
4: \( x := M[1].new \)
5: else
6: \( x := M[1].old \)
7: end if
8: for \( i \in \{1, 2\} \) do
9: \( \text{txn} := M[i].txn \)
10: \( \text{data} := k(M[i]) \)
11: if \( \text{txn} \neq \text{NULL} \)
12: if \( \text{txn}.done \)

successfully been completed or not. The computation of a CS linearizes to a single write that
sets its transaction record’s done field to true. Thus, we maintain the following invariant.

\[ M[i].old \] contains \( M[i]'s \) valid value if \( M[i].txn.done \) is false or \( M[i].txn \) is NULL. \( M[i].new \) contains \( M[i]'s \) valid value if \( M[i].txn.done \) is true.

The next field in a transaction record is used to maintain a stack free_stack of free
transaction records that are not pointed to by any \( M[i] \). This free_stack is used to reuse a
transaction record for future CSs. We now describe the code in ABORTABLEMODIFY.

Reads of shared variables. Lines 3–6 in ABORTABLEMODIFY replace line 2 of MODIFY.
These lines read \( M[1]'s \) valid value from either the new or old field of \( M[1] \) based on Invariant 1.

Writes of shared variables. Lines 9–39 in ABORTABLEMODIFY replace the write to \( M[i] \)
in line 4 of MODIFY. We note that, while these lines reflect our general transformation

\( \text{struct} \)
\( \begin{array}{ll}
  \text{old}: \text{word} \\
  \text{new}: \text{word} \\
  \text{txn}: \text{Ptr to txn_record}
\end{array} \)
\( \text{data} \)

(a) Data element structure

\( \text{struct} \)
\( \begin{array}{ll}
  \text{rc1}: \text{int} \\
  \text{rc2}: \text{int} \\
  \text{done}: \text{boolean} \\
  \text{next}: \text{Ptr to txn_record}
\end{array} \)
\( \text{txn_record} \)

(b) Transaction record structure

\( \text{Figure 9} \) Data structures for abortable CS.
process for making a CS abortable, it is possible to shorten this code for this simple example. A write to $M[i]$ in `AbortableModify` occurs in three steps: (i) unlink $M[i]$ from its old transaction record to enable future reuse of that record; (ii) link $M[i]$ with the transaction record corresponding to this CS invocation; and (iii) commit that invocation, i.e., make it take effect atomically. We now explain these steps.

**Step (i): Unlinking.** Lines 12–22 in `AbortableModify` unlink $M[i]$ from its old transaction record stored in `txn` by line 9. We depict the steps of unlinking in Fig. 10, where inset (a) shows an initial state prior to executing lines 12–22. To maintain Invariant I, lines 12 and 13 copy $M[i]$.new to $M[i]$.old if `txn.done` is true, as shown in Fig. 10(b). Lines 15, 21, and 22 decrement `rc1` and `rc2` of `txn` before and after setting $M[i]$.txn to NULL, respectively, as shown in insets (c)–(f) of Fig. 10. If `rc1` becomes 0 after line 15, as shown in Fig. 10(c), then lines 17–19 push `txn` onto `free_stack` and unset its `done` field, as shown in Fig. 10(d).

**Step (ii): Linking.** Lines 24–35 link $M[i]$ to a transaction record. Line 24 assigns `new_txn` to `txn`, which is the transaction record corresponding to this invocation of `AbortableModify`. We illustrate the linking process when `new_txn` is NULL by considering insets (b)–(f) of Fig. 10 in reverse order. Fig. 10(f) shows an initial state after executing line 26 of the linking process when `new_txn` is NULL. Insets (e), (d), (c), and (b) of Fig. 10 illustrate incrementing `rc2` (line 27), linking `txn` to $M[i]$ (line 28), removing `txn` from `free_stack` (line 29), and incrementing `rc1` (line 30), respectively. After this linking process, line 36 sets `new_txn` to `txn` to ensure that future loop iterations use this same transaction record. Also, line 37 performs the write operation (from line 4 of `Modify`) by updating $M[i]$.new.

**Step (iii): Committing.** The CS is committed by simply setting `new_txn`.txn to `true` in line 39. It is this one-line commit at the end that obviates the need for any undo code.

Why two reference counters? To see why using only one counter is problematic, consider again the unlinking process shown in Fig. 10. If only `rc1` is used and the CS is aborted after executing the step in Fig. 10(c), then `txn` is left in an inconsistent state, i.e., its `rc1` field indicates no structure points to `txn` yet one does. Using both `rc1` and `rc2` enables this “inopportune” CS abort to be detected by simply checking whether `rc1` is smaller than `rc2`. To fix the inconsistent transaction record in this case, we add a small code sequence to the OS timer-handling code that deals with CS-budgeting timer expirations. This code completes the remaining steps of unlinking by executing lines 15–21 of `AbortableModify` if `txn.rc1` is smaller than `txn.rc2` (with an additional check of `txn = free_stack.top` in line 15 to prevent inserting `txn` to `free_stack` twice). The timer-handling code can access the CS-specific variables involved in these actions via a control page shared with the CS’s task. Note that the added timer-handling code is the same for all abortable CSs and deriving the EBT of

Figure 10 Unlinking process. The field `txn.next` is not shown.
expiring the CS-budgeting timer after adding this code supports Assumption A2. Similar inopportune CS aborts can affect the linking process, and they are dealt with similarly.

**Generalizing to arbitrary shared data structures.** For clarity, we presented the idea of an abortable CS via a simple example. However, in an online appendix [41], we present a set of routines for performing necessary actions (reading, writing, linking, unlinking), a set of rules to transform any ordinary CS into an abortable one, and an invariant-based proof that shows that these rules are correct. In our simple example, reading and writing occurred at the granularity of words. However, in the general scheme, any granularity can be assumed.

**Have we really eliminated undo code?** One could argue that abortable CSs merely intertwine undo-related actions with ordinary CS code. If this is so, do they offer any real advantages over simply following ordinary CS code with potential undo code? The answer is yes. With separate undo code, the “chicken and egg” problem mentioned in Sec. 1 arises: the undo code would have to be budgeted, and to avoid exhausting that budget, an ETB would have to be assumed for it, which could be very costly. Perhaps one could take the same “intertwined view” and inflate the cost of any CS by its undo cost, but then how is the (separate) undo code ever triggered? Presumably, the combined budget would have to be factored into two parts, one for the ordinary CS code and one for the undo code, bringing us back to the chicken-and-egg problem. While abortable CSs are immune from these problems, further research into supporting real-time undo code would certainly be valuable.

### 7 Experimental Evaluation

To assess the costs and benefits of overrun-resilient locking, we conducted two sets of experiments under LITMUS$^{RT}$ [10,15] on an eight-core 2.1GHz Intel Xeon Silver processor. To increase timing predictability, we disabled hyperthreading, low CPU power states, and CPU frequency scaling.

**Experiment 1.** We first assessed the costs of using abortable CSs that satisfy P2.1 vs. using CS ETBs to provision CS execution budgets. As a baseline, we measured the execution times of ordinary (non-abortable) operations on buffers, queues, and binary heaps. To assess the cost of abortable CSs, we compared the baseline to the execution times of corresponding abortable CS implementations. To assess CS ETB budget provisioning (which assumes unrealistically pessimistic conditions), we compared the baseline to the execution times of cacheless runs of the ordinary operations. Two metrics were considered: the worst-case (resp., average-case) inflation factor of an operation is the ratio between the observed maximum (resp., average) execution times of abortable/cacheless CS vs. that of the baseline. As this is not a paper on timing analysis, we note that the ETBs assumed here are provided to give a plausible sense of the pessimism they may entail; we make no claim that they are in fact upper bounds, or if they are, that they cannot be safely tightened.

For each implementation, we determined the maximum and average duration of each operation (measured using the timestamp counter) through 10,000 trials, running alongside contention-generating tasks that contend for the memory bus. We separately measured the duration of our timing code and subtracted it from our results. For the read/write buffer, we used a one-word buffer with single-word reads and writes. We initialized the queue and heap to contain 1,000 items. Our results, shown in Tbl. 4, support the following observations.

- **Observation 1.** The worst-case inflation factor of abortable CSs was around two to five.
- **Observation 2.** The inflation factors for running cacheless was in the hundreds.
Table 4 Comparison between abortable and ordinary CSs.

<table>
<thead>
<tr>
<th>Data structure</th>
<th>Buffer Write</th>
<th>Buffer Read</th>
<th>Queue Enqueue</th>
<th>Queue Dequeue</th>
<th>Heap Insert</th>
<th>Heap Extract</th>
</tr>
</thead>
<tbody>
<tr>
<td>WC Baseline</td>
<td>39.0 ns</td>
<td>33.3 ns</td>
<td>46.7 ns</td>
<td>48.6 ns</td>
<td>89.5 ns</td>
<td>263.8 ns</td>
</tr>
<tr>
<td>WC Abortable</td>
<td>161.9 ns</td>
<td>76.2 ns</td>
<td>97.1 ns</td>
<td>252.4 ns</td>
<td>300.9 ns</td>
<td>981.9 ns</td>
</tr>
<tr>
<td>WC Cacheless</td>
<td>13.0 µs</td>
<td>11.0 µs</td>
<td>22.7 µs</td>
<td>20.6 µs</td>
<td>32.3 µs</td>
<td>15.9 µs</td>
</tr>
<tr>
<td>WC Abortable Inflation</td>
<td>4.14×</td>
<td>2.28×</td>
<td>2.08×</td>
<td>5.19×</td>
<td>2.95×</td>
<td>4.08×</td>
</tr>
<tr>
<td>AC Abortable Inflation</td>
<td>6.91×</td>
<td>2.55×</td>
<td>2.47×</td>
<td>5.53×</td>
<td>5.88×</td>
<td>3.36×</td>
</tr>
<tr>
<td>WC Cacheless Inflation</td>
<td>332.7×</td>
<td>329.8×</td>
<td>486.9×</td>
<td>424.4×</td>
<td>360.7×</td>
<td>784.2×</td>
</tr>
<tr>
<td>AC Cacheless Inflation</td>
<td>93.5×</td>
<td>113.5×</td>
<td>304.8×</td>
<td>200.8×</td>
<td>245.6×</td>
<td>882.4×</td>
</tr>
</tbody>
</table>

The extremely high inflation factors for running cacheless were due to both instructions and data being accessed from main memory instead of mainly the L1 cache. While the effects of disabling caches on other processor mechanisms such as branch prediction, pipelining, and prefetching are not well documented, we suspect that these factors also contributed to the slowdown, especially in the case of heaps where branching code is common.

Experiment 2. We assessed the impacts of CS execution budget overruns under the OR-FMLP, OR-OMLP, FMLP, and OMLP by executing a task system consisting of an equal number of synthetic non-overrunning correct tasks and overrunning faulty tasks. (We did not examine task execution budget overruns because they require application-dependent mitigation; note, however, that common mitigations such as aborting the overrunning job can break the FMLP and OMLP.) Each task \( \tau_i \) had \( (C_e^i, T_i) = (1\text{ms}, 40\text{ms}) \). We generated enough tasks so that the sum of all analytical task utilizations \( (C_a^i/T_i) \) was \( 0.8 \). The task system had a single shared resource for which each job issued a single request. For each synthetic task \( \tau_i \), we generated its CS execution budget \( L_e^i \) and an actual CS execution time, denoted \( L_i \), via three steps. When jobs of these synthetic tasks execute CSs, they acquire a lock and spin for the duration of the actual CS execution time. First, for each correct task \( \tau_i \), we set \( L_e^i \) to \( 0.2\text{ms} \) and \( L_i \) to \( 0.19\text{ms} \) (which was sufficient to preclude budget overruns due to overheads). Second, for each faulty task \( \tau_i \), we set \( L_e^i \) to \( 0.2\text{ms} \) under the FMLP and OMLP. Since abortable CSs require more execution budget, we inflated \( L_e^i \) for each faulty task \( \tau_i \) under the OR-FMLP and OR-OMLP by considering three different inflation scenarios based on the data given for buffers, queues, and heaps in Tbl. 4. For each scenario, we inflated each such \( L_e^i \) by the worst-case abortable-CS inflation factor of that scenario’s data structure in Tbl. 4. Third, for each faulty task \( \tau_i \), we determined \( L_i \) by a type-1 Gumbel distribution. Under the FMLP and OMLP, the mean of this Gumbel distribution was set at \( 0.05\text{ms} \). Under the OR-FMLP and OR-OMLP, this mean was inflated according to the average-case abortable-CS inflation factor given in Tbl. 4 for the corresponding scenario. We varied the probability of a job of a faulty task overrunning its CS execution budget from 0.0 to 0.3 with a step size of 0.05. The variance of the Gumbel distribution was determined by this probability value.

For each inflation scenario and CS execution budget overrun probability, we executed the task system for 10 minutes and measured the maximum response time among all correct tasks. Figs. 11 and 12 plot the recorded response times that supports following observations:

Observation 3. The worst-case response times of correct tasks under the OR-FMLP (resp., OR-OMLP) stayed relatively constant as the overrun probability increased.

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4 The Gumbel distribution is often used to represent measurement-based probabilistic WCETs [18].
Observation 4. Cost/benefit tradeoffs are evident in these curves. For example, for buffers in Fig. 12, overrun-resilient protocols increased response times for overrun probabilities less than 0.10 and decreased them for greater probabilities.

8 Revisiting Assumptions A1 and A3

We now return to Assumptions A1 and A3.

Assumption A1. As we have seen, user-level budgets have a fundamental dependency on the execution times of certain OS code paths. If one defines budgets for those code paths, then what entity would enforce them? The only alternative to budgeting is to require ETBs for these code paths, but this has major implications for real-time OS (RTOS) designs. For example, modern OSs tend to be highly preemptive, but preemptions greatly complicate measurement-based timing analysis. To avoid “chicken and egg” problems, RTOS designs need to be rethought, with enabling reliable timing analysis for critical code paths being a first-class concern. These code paths should be simple and non-preemptive and should have reasonable ETBs. Techniques like cache locking may help in this regard.

Assumption A3. Standard techniques [10] can account for the overheads/delays considered negligible by A3. From a timing-analysis point of view, the overhead of most concern is CPMD, as it is incurred on preemptions, which as noted already, are hard to deal with in timing analysis due to difficulties in predicting cache state. These difficulties have important implications for synchronization and scheduling: CSs that execute on a CPU (as opposed to, e.g., an I/O device) should be non-preemptive, and tasks should either be non-preemptive or only preemptive at certain “preemption points” [13]. While both task-scheduling options have been studied for simple task models [7,14,36], they warrant further attention in more complex models relevant today, such those based on processing graphs [4,40,45].

9 Related Work

Locking protocols that consider budget overruns (shown in Tbl. 1) have been explored in the past. However, none satisfy properties P1–P3, which define our notion of overrun resiliency.

Satisfying P1. To satisfy P1, a protocol must deal with jobs overrunning their budgets while in a CS. Prior work such as M-BWI and vMPCP satisfy P1 by allowing task budget overruns to occur inside of CSs and account for them analytically. In contrast, SIRAP and M-BROE satisfy P1 using FZs, introduced in [27], to avoid task budget overruns inside of CSs. Tradeoffs between satisfying P1 using FZs and overrun accounting are detailed in [5].

Satisfying P2. M-BWI and vMPCP both require accurate CS WCETs to produce correct overrun accounting. SIRAP and M-BROE also require accurate CS WCETs to correctly provision FZs. Since CS WCETs may exceed CS PETs, protocols that rely on forbidden
zones and overrun accounting do not satisfy P2. In the absence of correct CS WCETs, ICSs and protocols such as RRP and RACPwP satisfy both P1 and P2 by aborting CSs when their budgets overrun. To maintain consistent state for shared data structures, ICSs, RRP, and RACPwP use versioning techniques.

**Satisfying P3.** No prior work considers P3. However, all protocols that satisfy P1 can satisfy P3 when ETBs are used to account for corresponding budget-enforcement mechanisms. Unfortunately, all protocols that satisfy P2 use versioning techniques that make copies of modified data. Thus, when CSs only modify data, the ETBs of versioning techniques can be as large as the CS ETBs, nullifying the benefits of ensuring P2. Only ICSs avoid the problem by allowing shared-resource state to remain consistent even when a job is aborted while executing the versioning technique, satisfying P3. However, ICSs are intended for uniprocessors, thus the ICS versioning technique cannot handle concurrent resource accesses.

In this work, we proposed the OR-FMLP and OR-OMLP, which in conjunction with abortable CSs, yield overrun-resilient locking protocols. In fact, prior work on versioning techniques can also be used with the OR-FMLP and OR-OMLP to yield overrun-resilient protocols. However, those prior works have unfortunate tradeoffs as discussed in Sec. 6.

## Conclusion

We have presented the OR-FMLP and the OR-OMLP, which are overrun-resilient variants of the FMLP and the OMLP, respectively. Both the OR-FMLP and the OR-OMLP utilize FZs and the ability to abort CSs to circumvent problems associated with overrunning task and CS budgets. As our designs of these two protocols suggest, it is better to apply FZs in a coarse-grained way in a spinlock but in a fine-grained way in a suspension-based lock. For both protocols, we have carefully worked out how execution budgets should be defined. To easily apply these protocols to support operations on shared data structures, we have also presented abortable CSs, which enable such operations to be aborted with no undo code.

In future work, we plan to consider aborting CSs in other contexts, such as when using locks to access shared hardware resources. We also intend to investigate other types of locks, such as $k$-exclusion locks and reader/writer locks, as well as mechanisms for allocating “slack” generated by underrunning CSs to overrunning CSs. Additionally, full budgeting support enables the possibility of freeing system capacity by intentionally under-budgeting certain computations at the expense of aborting work more often; we plan to explore this possibility as well. This paper also establishes a need for timing-analysis techniques that can guarantee safe ETBs without exorbitant pessimism. The various “chicken and egg” problems we have pointed out warrant scrutiny as well.

## References

Overrun-Resilient Multiprocessor Real-Time Locking


Overrun-Resilient Multiprocessor Real-Time Locking
