Non-determinism

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References for this chapter

[Ben-Ari06]
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Non-determinism

Definitions

Non-determinism by design:

A property of a computation which may have more than one result.

Non-determinism by interaction:

A property of the operation environment which may lead to different sequences of (concurrent) stimuli.
Non-determinism by design

Dijkstra’s **guarded commands** (non-deterministic case statements):

```plaintext
if  x <= y -> m := x
    x >= y -> m := y
fi
```

Selection is non-deterministic for \(x = y\)

The programmer needs to design the alternatives as ‘parallel’ options:
- all cases need to be covered and overlapping conditions need to lead to the same result

All true case statements in any language are potentially concurrent and non-deterministic.
Dijkstra’s **guarded commands** (non-deterministic case statements):

```plaintext
if x <= y -> m := x
▌ x >= y -> m := y
fi
```

Selection is non-deterministic for x=y

The programmer needs to design the alternatives as ‘parallel’ options:

- all cases need to be covered and overlapping conditions need to lead to the same result
- All true case statements in any language are potentially concurrent and non-deterministic.

Numerical non-determinism in **concurrent statements** (Chapel):

```plaintext
writeln (* reduce [i in 1..10] exp (i));
writeln (+ reduce [i in 1..1000000] i ** 2.0);
```

Results may be non-deterministic depending on numeric type

The programmer needs to understand the numerical implications of out-of-order expressions.
Non-determinism

Non-determinism by design

Motivation for non-deterministic design

By explicitly leaving the sequence of evaluation or execution undetermined:

- The compiler / runtime environment can directly (i.e. without any analysis) translate the source code into a concurrent implementation.

- The implementation gains potentially significantly in performance

- The programmer does not need to handle any of the details of a concurrent implementation (access locks, messages, synchronizations, …)

A programming language which allows for those formulations is required!

- current language support: Ada, X10, Chapel, Fortress, Haskell, OCaml, …
Non-determinism

Non-determinism by interaction

Selective waiting in Occam2

ALT

Guard1
  Process1

Guard2
  Process2

...

- Guards are referring to boolean expressions and/or channel input operations.
- The boolean expressions are local expressions, i.e. if none of them evaluates to true at the time of the evaluation of the ALT-statement, then the process is stopped.
- If all triggered channel input operations evaluate to false, the process is suspended until further activity on one of the named channels.
- Any Occam2 process can be employed in the ALT-statement
- The ALT-statement is non-deterministic (there is also a deterministic version: PRI ALT).
Non-determinism by interaction

Selective waiting in Occam2

ALT

NumberInBuffer < Size & Append ? Buffer [Top]
SEQ
NumberInBuffer := NumberInBuffer + 1
Top := (Top + 1) REM Size
NumberInBuffer > 0 & Request ? ANY
SEQ
Take ! Buffer [Base]
NumberInBuffer := NumberInBuffer - 1
Base := (Base + 1) REM Size

• Synchronization on input-channels only (channels are directed in Occam2):
  - to initiate the sending of data (Take ! Buffer [Base]),
    a request need to be made first which triggers the condition: (Request ? ANY)

CSP (Communicating Sequential Processes, Hoare 1978) also supports non-deterministic selective waiting
Non-determinism

Non-determinism by interaction

Select function in POSIX

```c
int pselect(int n, fd_set *readfds, fd_set *writefds, fd_set *exceptfds,
            const struct timespec *ntimeout, sigset_t *sigmask);
```

with:

- `n` being one more than the maximum of any file descriptor in any of the sets.
- after return the sets will have been reduced to the channels which have been triggered.
- the return value is used as success / failure indicator.

The POSIX select function implements parts of general selective waiting:

- `pselect` returns if one or multiple I/O channels have been triggered or an error occurred.
  - Branching into individual code sections is not provided.
  - Guards are not provided.

After return it is required that the following code implements a sequential testing of all channels in the sets.
Selective Synchronization

Message-based selective synchronization in Ada

Forms of selective waiting:

```plaintext
select_statement ::= selective_accept | conditional_entry_call | timed_entry_call | asynchronous_select
```

... underlying concept: Dijkstra’s guarded commands

```plaintext
selective_accept implements ... 
  ... wait for more than a single rendezvous at any one time 
  ... time-out if no rendezvous is forthcoming within a specified time 
  ... withdraw its offer to communicate if no rendezvous is available immediately 
  ... terminate if no clients can possibly call its entries
```
Selective Synchronization

Message-based selective synchronization in Ada

```plaintext
selective_accept ::= select
                  [guard] selective_accept_alternative
                  { or [guard] selective_accept_alternative }
                  [ else sequence_of_statements ]
                  end select;

guard ::= when <condition> => selective_accept_alternative ::= accept_alternative |
         delay_alternative | terminate_alternative

accept_alternative ::= accept_statement [ sequence_of_statements ]
delay_alternative ::= delay_statement [ sequence_of_statements ]
terminate_alternative ::= terminate;

accept_statement ::= accept entry_direct_name [(entry_index)] parameter_profile [do
                   handled_sequence_of_statements]
                   end [entry_identifier]];
delay_statement ::= delay until delay_expression; | delay delay_expression;
```
Selective Synchronization

Basic forms of selective synchronization
(select-accept)

- If none of the entries have waiting calls the process is suspended until a call arrives.
- If exactly one of the entries has waiting calls this entry is selected.
- If multiple entries have waiting calls one of those is selected (non-deterministically). The selection can be prioritized by means of the real-time-systems annex.

The code following the selected entry (if any) is executed and the select statement completes.
Selective Synchronization

Basic forms of selective synchronization
(select-guarded-accept)

```plaintext
select
  when <condition> => accept ...
or
  when <condition> => accept ...
or
  when <condition> => accept ...
... end select;
```

- *If all conditions are ‘true’*
  - identical to the previous form.
- *If some condition evaluate to ‘true’*
  - the accept statement after those conditions are treated like in the previous form.
- *If all conditions evaluate to ‘false’*
  - Program_Error is raised.
  Hence it is important that the set of conditions covers all possible states.

This form is identical to
Dijkstra’s guarded commands.
Selective Synchronization

Basic forms of selective synchronization
(select-guarded-accept-else)

```
select
  when <condition> => accept ...
or
  when <condition> => accept ...
or
  when <condition> => accept ...
...
else
  <statements>
end select;
```

- If all currently open entries have no waiting calls or all entries are closed
  - The else alternative is chosen, the associated statements executed and the select statement completes.

- Otherwise one of the open entries with waiting calls is chosen as above.

This form never suspends the task.

This enables a task to withdraw its offer to accept a set of calls if no tasks are currently waiting.
Selective Synchronization

Basic forms of selective synchronization
(select-guarded-accept-delay)

```
select
  when <condition> => accept ...
or
  when <condition> => accept ...
or
  when <condition> => accept ...

... or ...
  when <condition> => delay [until] ...
    <statements>
or
  when <condition> => delay [until] ...
    <statements>

... end select;
```

- If none of the open entries have waiting calls before the deadline specified by the earliest open delay alternative
  
  This earliest delay alternative is chosen and the statements associated with it executed.

- Otherwise one of the open entries with waiting calls is chosen as above.

This enables a task to withdraw its offer to accept a set of calls if no other task is calling after some time.
Selective Synchronization

Basic forms of selective synchronization
(select-guarded-accept-terminate)

select
    when <condition> => accept ...
or
    when <condition> => accept ...
or
    when <condition> => accept ...
...
or
    when <condition> => terminate;
...
end select;

terminate cannot be mixed with else or delay

- If none of the open entries have waiting calls and none of them can ever be called again
  The terminate alternative is chosen, i.e. the task is terminated.

This situation occurs if:
  ... all tasks which can possibly call on any of the open entries are terminated.
  or ... all remaining tasks which can possibly call on any of the open entries are waiting on select-terminate statements themselves and none of their open entries can be called either. In this case all those waiting-for-termination tasks are terminated as well.
Selective Synchronization

Message-based selective synchronization in Ada

Forms of selective waiting:

```
select_statement ::= selective_accept | conditional_entry_call | timed_entry_call | asynchronous_select
```

... underlying concept: Dijkstra’s guarded commands

`conditional_entry_call` and `timed_entry_call` implements ... 

... the possibility to withdraw an outgoing call. 

... this might be restricted if calls have already been partly processed.
Selective Synchronization

Conditional entry-calls

conditional_entry_call ::= 
select 
  entry_call_statement [sequence_of_statements]
else 
  sequence_of_statements
end select;

- If the call is not accepted immediately
  The else alternative is chosen.

Example:

select
  Light_Monitor.Wait_for_Light;
  Lux := True;
else
  Lux := False;
end;
Selective Synchronization

Timed entry-calls

timed_entry_call ::= 
  select
    entry_call_statement
    [sequence_of_statements]
  or
    delay_alternative
end select;

Example:
  select
    Controller.Request (Some_Item);
    ------ process data
  or
    delay 45.0; ------ seconds
    ------ try something else
end select;

• If the call is not accepted before the deadline specified by the delay alternative
  ℹ️ The delay alternative is chosen.

This is e.g. useful to withdraw an entry call after some specified time-out.

There is only one entry-call and one delay alternative.
Selective Synchronization

Message-based selective synchronization in Ada

Forms of selective waiting:

select_statement ::= selective_accept |
                   conditional_entry_call |
                   timed_entry_call |
                   asynchronous_select

... underlying concept: Dijkstra’s guarded commands

asynchronous_select implements ...

... the possibility to escape a running code block due to an event from outside this task.
(outside the scope of this course ☞ check: Real-Time Systems)
Sources of Non-determinism

As concurrent entities are not in “lockstep” synchronization, they “overtake” each other and arrive at synchronization points in non-deterministic order, due to (just a few):

- Operating systems / runtime environments:
  - Schedulers are often non-deterministic.
  - System load will have an influence on concurrent execution.
  - Message passing systems react load depended.

- Networks & communication systems:
  - Traffic will arrive in an unpredictable way (non-deterministic).
  - Communication systems congestions are generally unpredictable.

- Computing hardware:
  - Timers drift and clocks have granularities.
  - Processors have out-of-order units.

- … basically: Physical systems (and computer systems connected to the physical world) are intrinsically non-deterministic.
Non-determinism

Correctness of non-deterministic programs

Partial correctness:
\[(P(I) \land \text{terminates}(\text{Program}(I,O)) \Rightarrow Q(I,O))\]

Total correctness:
\[P(I) \Rightarrow (\text{terminates}(\text{Program}(I,O) \land Q(I,O)))\]

Safety properties:
\[(P(I) \land \text{Processes}(I,S)) \Rightarrow \square Q(I,S)\]
where \(\square Q\) means that \(Q\) does always hold

Liveness properties:
\[(P(I) \land \text{Processes}(I,S)) \Rightarrow \Diamond Q(I,S)\]
where \(\Diamond Q\) means that \(Q\) does eventually hold (and will then stay true)
and \(S\) is the current state of the concurrent system
Non-determinism

Correctness of non-deterministic programs

Correctness predicates need to hold true
irrespective of the actual sequence of interaction points.

or

Correctness predicates need to hold true
for all possible sequences of interaction points.

Therefore correctness predicates need to be based on invariants,
i.e. invariant predicates which are independent of the potential execution sequences,
yet support the overall correctness predicates.
Correctness of non-deterministic programs

For example (in verbal form):
“Mutual exclusion accessing a specific resource holds true, for all possible numbers, sequences or interleavings of requests to it”

An invariant would for instance be that the number of writing tasks inside a protected object is less or equal to one.

Those invariants are the only practical way to guarantee (in a logical sense) correctness in concurrent / non-deterministic systems.

(as enumerating all possible cases and proving them individually is in general not feasible)
Correctness of non-deterministic programs

Concrete:

Every time you formulate a non-deterministic statement like the one on the left you need to formulate an invariant which holds true whichever alternative will actually be chosen.

This is very similar to finding loop invariants in sequential programs.
Summary

Non-Determinism

- Non-determinism by design:
  - Benefits & considerations

- Non-determinism by interaction:
  - Selective synchronization
  - Selective accepts
  - Selective calls

- Correctness of non-deterministic programs:
  - Sources of non-determinism
  - Predicates & invariants