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COURSE NAME : 19CSB201 – OPERATING SYSTEMS

II YEAR/ IV SEMESTER

UNIT – II Process Scheduling And Synchronization

Topic: Process Synchronization: Semaphores

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Semaphores

A semaphore is a variable or abstract **data type used to control access to a common resource** by multiple threads and avoid critical section problems in a concurrent system such as a multitasking operating system. Semaphores are a type of synchronization primitive.

A semaphore S is an integer variable that, apart from initialization, is accessed only through two standard atomic operations: **wait() and signal() .**

definition of wait() is as follows:

```
wait(S) {
    while (S <= 0)
        ; // busy wait
    S--;
}
```

The definition of signal() is as follows:

```
signal(S) {
    S++;
}
```

Semaphore Usage

Operating systems often distinguish between **counting and binary semaphores**.

The value of a counting semaphore can range over an unrestricted domain.

The value of a binary semaphore can range only between 0 and 1. Thus, binary semaphores behave similarly to mutex locks.

Counting semaphores

Counting semaphores can be used to control access to a given resource consisting of a finite number of instances. The semaphore is initialized to the number of resources available. Each process that wishes to use a resource performs a wait() operation on the semaphore (thereby decrementing the count). When a process releases a resource, it performs a signal() operation (incrementing the count). When the count for the semaphore goes to 0, all resources are being used. After that, processes that wish to use a resource will block until the count becomes greater than 0.

In process P1 , we insert the statements

```
S1;
signal(synch);
```

In process P_2, we insert the statements

```
wait(synch);
S2;
```

Because synch is initialized to 0, P2 will execute S2 only after P1 has invoked signal(synch) , which is after statement S1 has been executed.

Semaphore Implementation

To implement semaphores under this definition, we define a semaphore as follows:

```
typedef struct {
    int value;
    struct process *list;
} semaphore;
```

Now, the wait() semaphore operation can be defined as

```
wait(semaphore *S) {
        S->value--;
        if (S->value < 0) {
                add this process to S->list;
                block();
        }
}
```

and the signal() semaphore operation can be defined as

```
signal(semaphore *S) {
        S->value++;
        if (S->value <= 0) {
                remove a process P from S->list;
                wakeup(P);
        }
}
```

The **block()** operation suspends the process that invokes it.

The **wakeup(P)** operation resumes the execution of a blocked process P.

These two operations are provided by the operating system as basic system calls.

Deadlocks and Starvation

- The implementation of a semaphore with a waiting queue may result in a **situation where two or more processes are waiting indefinitely** for an event that can be caused only by one of the waiting processes. The event in question is the execution of a signal() operation. When such a state is reached, these processes are said to be **deadlocked**.

To illustrate this, consider a system consisting of two processes, P_0 and P_1, each accessing two semaphores, S and Q, set to the value 1:

P_0	P_1
`wait(S);`	`wait(Q);`
`wait(Q);`	`wait(S);`
.	.
.	.
.	.
`signal(S);`	`signal(Q);`
`signal(Q);`	`signal(S);`

Suppose that P_0 executes `wait(S)` and then P_1 executes `wait(Q)`. When P_0 executes `wait(Q)`, it must wait until P_1 executes `signal(Q)`. Similarly, when P_1 executes `wait(S)`, it must wait until P_0 executes `signal(S)`. Since these `signal()` operations cannot be executed, P_0 and P_1 are deadlocked.

starvation

- Another problem related to deadlocks is indefinite blocking or **starvation**, a situation in which processes **wait indefinitely** within the semaphore. Indefinite blocking may occur if we remove processes from the list associated with a semaphore in LIFO (last-in, first-out) order

Priority Inversion

- A scheduling challenge arises when a **higher-priority process needs** to read or modify kernel **data that are currently being accessed by a lower-priority process**—or a chain of lower-priority processes. Since kernel data are typically protected **with a lock**, the higher-priority process will have to wait for a lower-priority one to finish with the resource. The situation becomes more complicated if the lower-priority process is preempted in favor of another process with a higher priority.

As an example, assume we have three processes— L, M, and H —whose priorities follow the order **L < M < H**. Assume that process H requires resource R, which is currently being accessed by process L. Ordinarily, process H would wait for L to finish using resource R. However, now suppose that process M becomes runnable, thereby preempting process L. Indirectly, a process with a lower priority—process M—has affected how long process H must wait for L to relinquish resource R.

This problem is known as **priority inversion**. It occurs only in systems with more than two priorities, so one solution is to have only two priorities.

Typically these systems solve the problem by implementing a **priority-inheritance protocol**. According to this protocol, all processes that are accessing resources needed by a higher-priority process inherit the higher priority until they are finished with the resources in question. When they are finished, their priorities revert to their original values. In the example above, a priority-inheritance protocol would allow process L to temporarily inherit the priority of process H, thereby preventing process M from preempting its execution. When process L had finished using resource R, it would relinquish its inherited priority from H and assume its original priority. Because resource R would now be available, process H —not M—would run next.

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THANK
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