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Abstract

This paper describes the design of the ACE object-oriented thread encapsulation class library. The architecture of this class library is presented from an end-user and internal design perspective and several key design issues are discussed. Readers should gain an understanding of the overall design approach, as well as the tradeoffs between various software quality factors such as performance, portability, and extensibility.

1 Introduction

Certain types of distributed applications benefit from using a concurrent model of execution to perform their tasks. Concurrency is particularly useful to improve performance and simplifying programming for network servers on multiprocessor platforms. For server applications, using threads to handle multiple client requests concurrently is often more convenient and less error-prone than the following design alternatives:

- Artificially serializing requests at a transport layer interface;
- Queueing requests internally and handling them iteratively;
- Forking a heavy-weight process for each client request.

This paper motivates and describes a C++ class library contained in the ADAPTIVE Communications Environment (ACE) [1]. ACE encapsulates and enhances the lightweight concurrency mechanisms provided both by Solaris 2.x threads [2] and POSIX Pthreads [3].

The material presented in this paper is intended for a technical audience interested in understanding the strategies and tactics of object-oriented (OO) concurrent programming using Solaris [2] and POSIX [3] threads. It is assumed that the reader is familiar with general OO design and programming techniques (such as design patterns [4], application frameworks [5], modularity, information hiding, and object modeling [6]), OO notations (such as OMT [7]), fundamental C++ programming language features (such as classes, inheritance, dynamic binding, and parameterized types [8]), basic UNIX systems programming concepts (such as process management, virtual memory, and interprocess communication [9]), and networking terminology (such as client/server architectures [10], RPC [11], CORBA [12], and TCP/IP [13, 14]).

This paper does not assume in-depth knowledge of concurrency, in general, or Solaris/POSIX multi-threading and synchronization mechanisms, in particular. An overview of concurrent programming and multi-threading is presented in Section 3. The overview defines key terminology and outlines the various alternative mechanisms available for concurrent programming on Solaris 2.x and POSIX pthreads.

This paper is organized as follows: Section 2 gives an overview of the goals of the ACE OS thread encapsulation library and outlines the OO architecture of the library components. Section 3 presents relevant background material on concurrent programming, in general, and the Solaris multithreading model, in particular. Section 4 presents an end-user perspective that motivates the design of the ACE thread encapsulation library, focusing on a "use case" example culled from a concurrent client/server application. Section 5 describes the public interfaces and internal design of the ACE threads encapsulation library in detail. Section 6 presents several examples that illustrate the OO components defined in Section 5. Finally, Section 7 presents concluding remarks.

2 Overview of the ACE OO Concurrency Mechanisms

2.1 Overall Goals

A distinct feature of modern operating systems (such as Solaris, OSF/1, Windows NT, and OS/2) compared to previous generations of SunOS is its integrated support for kernel-level and user-level multi-threading and synchronization.[1]

[1]This section focuses on Solaris 2.x threading and synchronization mechanisms for concreteness. However, most of the mechanisms, design principles, and interfaces are equivalent to POSIX Pthreads, as well.

However, the existing multi-threading and synchronization mechanisms shipped with these operating systems are relatively low-level APIs written in C. Developing applications using a mixture of C++ classes and low-level C APIs places an unacceptable burden on developers. Mixing these two styles within a single application leads to an "impedance" mismatch between object-oriented and procedural programming. Such a hybrid programming style is distracting and a chronic maintenance problem.

To avoid having each developer re-implement their own *ad hoc* C++ wrappers for OS threading mechanisms, the ACE toolkit provides a set of object-oriented concurrency components described in this paper. These ACE components provide a portable and extensible interface for concurrent programming. This interface simplifies thread management and synchronization mechanisms used to develop clients and servers. This interface has been ported to POSIX pthreads [3] and a Microsoft WIN32 [15] port is also underway.

2.1.1 Overall Requirements

In conjunction with the goal of encapsulating and simplifying the concurrency substrate of OS threading mechanisms, the ACE OO thread encapsulation class library is being developed in response to the following common application requirements.

- *Simplify program design* – by allowing multiple application tasks to proceed independently using conventional synchronous programming abstractions (such as CORBA remote method invocations);
- *Transparently improve performance* – by using the parallel processing capabilities of hardware platforms such as the SPARCcenter 1000 and 2000 shared memory symmetric multi-processors;
- *Explicitly improve performance* – by reducing data copying and by overlapping computation with communication;
- *Improve perceived response time* – for interactive applications (such as user interfaces or network management applications) by associating separate threads with different tasks or services in an application.

2.1.2 Design Goals

The ACE OO thread class library was developed to achieve the following design goals:

- Improve consistency of programming style by enabling developers to use C++ and OO consistently throughout their concurrent applications.
- Improve the portability and reusability of the underlying concurrency mechanisms.
- Reduce the amount of obtrusive changes to make applications thread-safe.
- Eliminate or minimize the potential for subtle synchronization errors.
- Enhance abstraction and modularity *without* compromising performance.

2.2 Architectural Overview of ACE OO Thread Encapsulation Components

Figure 1 is a Booch object model that illustrates the components in the ACE threads encapsulation class library. These components include the C++ classes and class categories described below.[2]

2.2.1 The ACE Locks Class Category

• **Mutex, Thread_Mutex, and Process_Mutex:** The `Mutex` classes provide a simple and efficient mechanism that serializes access to a shared resource (such as a file or object in shared memory). They encapsulate Solaris and POSIX synchronization variables (`mutex_t` and `pthread_mutex_t` and are described in Section 5.1.1.

• **RW_Mutex:** The `RW_Mutex` class is used to serialize access to shared resources whose contents are searched more than they are changed. It encapsulates the Solaris `rwlock_t` synchronization variable and is described in Section 5.1.3.

• **Semaphore:** The `Semaphore` class implements Dijkstra's "counting semaphore" abstraction, which is a general mechanism for serializing multiple threads of control. It encapsulates the Solaris `sema_t` synchronization variable and is described in Section 5.1.2.

• **Null_Mutex:** The `Null_Mutex` class provides a zero-overhead implementation of the locking interface used by the other C++ wrappers for synchronization. This class is described in Section 5.1.5.

• **Token:** The `Token` class provides a more general-purpose synchronization mechanism than a `Mutex`. For example, it implements "recursive mutex" semantics, where a thread that owns the token can reacquire it without deadlocking. In addition, threads that are blocked awaiting a `Token` are serviced in strict FIFO order as other threads release the token (in contrast, `Mutex` don't strictly enforce an acquisition order). This class is described in Section 5.1.6.

• **Recursive_Lock:** A `Recursive_Lock` extends the default Solaris locking semantics by allowing calls to `acquire` methods to be nested as long as the thread that owns the lock is the one that re-acquires it. It works with the `Mutex`, `RW_Mutex`, and `Semaphore` classes outlined above and is described in Section 5.1.4.

[2] All ACE classes are prefixed with `ACE_` to avoid polluting the global name space of programs. For brevity, this prefix has been omitted in all the following code.

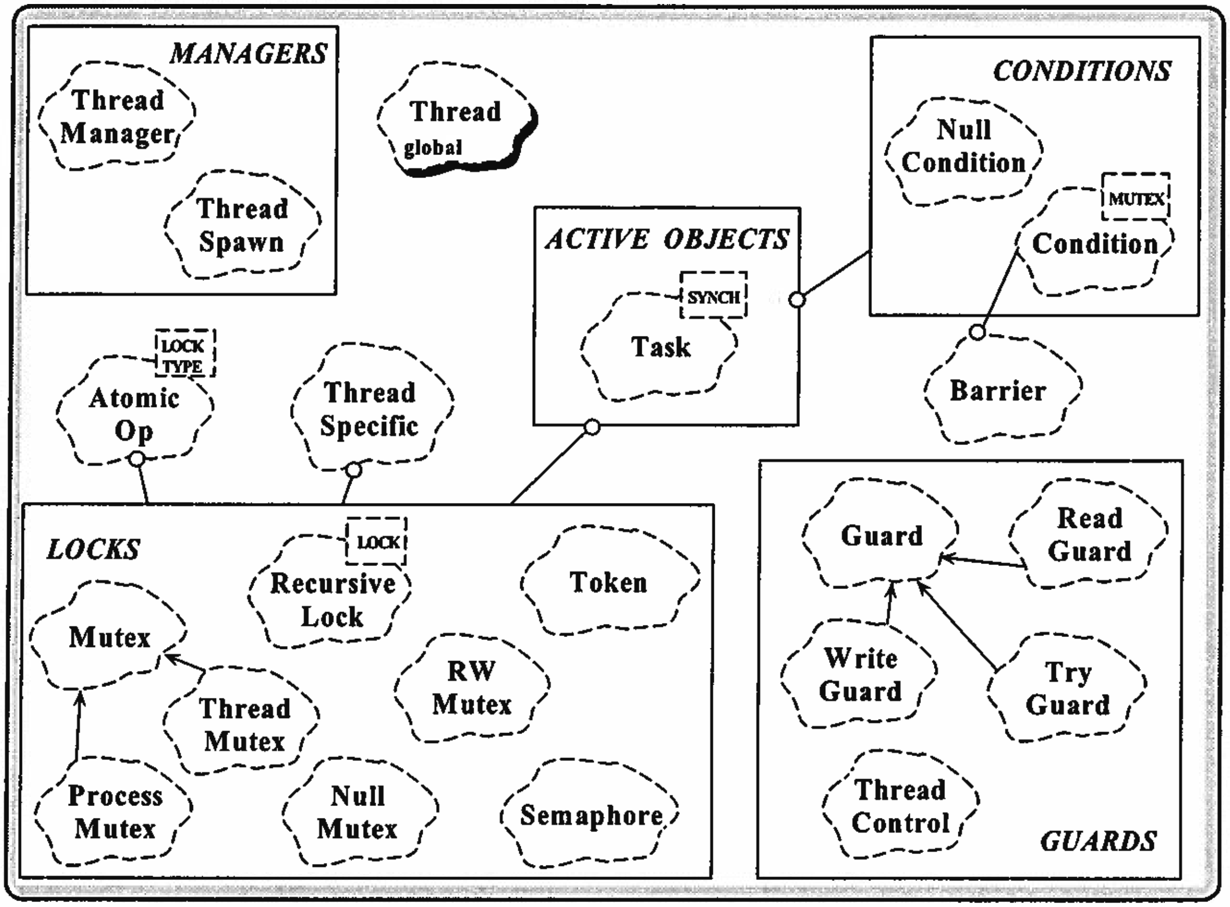

Figure 1: Object Model for ACE OO Thread Encapsulation Components

2.2.2 The ACE Guards Class Category

• **Guard, Try_Guard, Write_Guard, and Read_Guard:** these classes ensure that a lock is automatically acquired and released upon entry and exit to a block of C++ code, respectively. They are described in Section 5.2.1.

• **Thread_Control:** The `Thread_Control` class is used in conjunction with the `Thread_Manager` class to automate the graceful termination and cleanup of a thread's activities within its originating function. This class is described in Section 5.2.2.

2.2.3 The ACE Conditions Class Category

• **Condition:** The `Condition` class is used to block on a change in the state of a condition expression involving shared data. It encapsulates the Solaris `cond_t` synchronization variable and is described in Section 5.3.1.

• **Null_Condition:** The `Null_Condition` class provides a zero-overhead implementation of the `Condition` interface used for single-threaded applications. It is described in Section 5.3.2.

2.2.4 The ACE Managers Class Category

• **Thread_Manager:** The `Thread_Manager` class contains a set of mechanisms to manage groups of threads that collaborate to implement collective actions. This class is described in Section 5.4.1.

• **Thread_Spawn:** The `Thread_Spawn` class provides a standard utility that manages the creation of threads to handle requests from clients concurrently. This class is described in Section 5.4.2.

2.2.5 The ACE Active Objects Class Category

• **Task:** The `Task` class is the central mechanism in ACE for defining *active objects* [16, 17]. These active objects queue messages for input and output and perform user-defined message processing services in separate threads of control. This class is described in Section 5.5.1.

2.2.6 Miscellaneous ACE Concurrency Classes

• **Thread:** The `Thread` class encapsulates the Solaris `thr_*` and POSIX Pthreads [3] family of thread creation, termination, and management routines. This class is described in Section 5.6.1.

• **Atomic_Op:** The `Atomic_Op` class transparently parameterizes synchronization into basic arithmetic operations. This class is described in Section 5.6.2.

• **Barrier:** The `Barrier` class implements "barrier synchronization," which is particularly useful for many types of parallel scientific applications. This class is described in Section 5.6.3.

• **Thread_Specific:** The `Thread_Specific` class allows objects that are "physically" thread-specific (*i.e.*, private to a thread) to be accessed as though they were "logically" global to a program. This class is described in Section 5.6.4.

3 Background on Concurrent Programming and Multi-threading

Most UNIX systems programmers are familiar with traditional process management system calls (such as `fork`, `exec`, `wait`, and `exit`). There is less experience, however, with emerging multi-threading and synchronization mechanisms for UNIX (such as Solaris threads [2] or POSIX pthreads [3]). This section presents an overview of background material relevant to concurrent programming and Solaris threads. More detailed discussions of concurrent programming, and Solaris/POSIX threads appear in [2, 18, 19, 3].

3.1 Processes and Threads

A *process* is a collection of resources that enable the execution of program instructions. These resources include virtual memory, I/O descriptors, a run-time stack, signal handlers, user and group ids, and access control tokens. On earlier-generation UNIX systems (such as SunOS 4.x), processes were "single-threaded." In UNIX, operations in single-threaded programs are generally synchronous since control is always in either the program (*i.e.*, the user code) or in the operating system (via system calls). To some extent, the single-threaded nature of traditional UNIX processes simplifies programming since processes do not interfere with one another without explicit intervention by programmers.

However, many applications (particularly networking servers) are difficult to develop using single-threaded processes. For example, a single-threaded network file server must not block for extended periods of time handling one client request since the responsiveness for other clients would suffer. There are several common workarounds to avoid blocking in single-threaded servers:

- *Event demultiplexers/dispatcher* – one approach is to develop an event demultiplexer/dispatcher (such as the object-oriented Reactor framework [20]). This technique is widely used to manage multiple input devices in single-threaded user-interface frameworks. The main event demultiplexer/dispatcher detects an incoming event, demultiplexes the event to the appropriate event handler, and then dispatches an application-specific callback method associated with the event handler.

  The primary drawback with this approach is that long duration conversations must be developed as finite state machines. This approach becomes unwieldy as the number of states increase. In addition, since only non-blocking operations may be used, it is difficult to improve performance via techniques such as "I/O streaming" or schemes that benefit from locality of reference in data and instruction caches.

- *User-level co-routines* – another approach is to develop a non-preemptive, user-level co-routine package that explicitly saves and restores context information. This enables tasks to suspend their execution until another co-routine resumes them at a later point. The multi-tasking mechanisms on Windows 3.1 and the Mac System 7 OS are widely available systems that use this approach.

  In general, co-routines are complicated to use correctly since developers must manually perform task preemption by explicitly yielding the thread of control periodically. Moreover, each task must execute for a relatively short duration. Otherwise, clients may detect that requests are being handled sequentially rather than concurrently. Another limitation with co-routines is that application performance may be reduced if the OS blocks all services in a process whenever one task incurs a page fault. Moreover, the failure of a single task (*e.g.*, spinning in an infinite loop) may hang the entire process.

- *Multi-processing* – another approach for alleviating the complexity of single-threaded UNIX processes is to use the coarse-grained multi-processing capabilities provided by the `fork` and `exec` system calls. `Fork` spawns a separate child process that executes a task concurrently with its parent. It is possible for separate processes to collaborate directly by using mechanisms such as shared memory and memory-mapped files. On a local host, shared memory is a faster means of IPC than message passing since it avoids explicit data copying.

  However, the overhead and inflexibility of `fork` and `exec` makes dynamic process invocation prohibitively expensive and overly complicated for many applications. For example, the process management overhead for short-duration services (such as resolving the Ethernet number of an IP address, retrieving a disk block from a network file server, or setting an attribute in an SNMP MIB) is excessive. Moreover, it is difficult to exert fine-grain control over scheduling and process priority using `fork` and `exec`. In addition, processes that share C++ objects in shared memory segments must make non-portable assumptions about the placement of virtual table pointers.

Multi-threading mechanisms provide a more elegant, and sometimes more efficient, way to overcome the limitations with the traditional concurrent processing techniques described above. A thread is a single sequence of execution steps performed in the context of a process. In addition to an instruction pointer, a thread consists of other resources such as a run-time stack of function activation records, a set of general-purpose registers, and thread-specific data.

Conventional workstation operating systems (such as variants of UNIX [2, 21, 22] and Windows NT [15]) support the concurrent execution of multiple processes, each of which may contain 1 or more threads. A process serves as the unit of protection and resource allocation within a separate hardware protected address space. A thread serves as the unit of execution that runs within a process address space that is shared with 0 or more threads.

3.2 Benefits of Threads-based Concurrent Programming

It is often advantageous to implement concurrent applications that perform multiple tasks in separate threads rather than in separate processes for the following reasons:

- *Thread creation* – unlike forking a new processes, spawning a new thread does not require (1) duplicating the parent's address space memory, (2) setting up new kernel data structures, and (3) consuming an extra process slot in order to perform a subtask within a larger application.
- *Context switching* – Threads maintain minimal state information. Therefore, context switching overhead is reduced since less state information must be stored and retrieved. In particular, context switching between threads is less time consuming than context switching between UNIX heavyweight processes. This is due to the fact that TLB virtual address mappings not need be changed when switching between threads in the same process. Moreover, threads that run strictly in user-level do not incur any context switching overhead.
- *Synchronization* – It may not be necessary to switch between kernel-mode and user-mode when scheduling and executing an application thread. Thread-synchronization is less expensive than process-synchronization. For example, the entities being synchronized are often not global entities, but are localized. Global synchronization always involves the kernel, whereas the local (or "intra-process") synchronization used by application threads may require no kernel intervention.
- *Data Copying* – communicating between separate threads via shared memory is often much faster than using IPC message passing between separate processes since it avoids the overhead of explicit data copying. For example, cooperating database services that frequently reference common memory-resident data structures may be simpler and more efficient to implement via threads. In general, using the shared address space of a process to communicate between threads is easier and more efficient than using shared memory mechanisms (such as System V shared memory or memory-mapped files) to communication between processes.

3.3 Overview of Multi-Processing and Multi-threading on Solaris

This section summarizes relevant background material on the multi-processing (MP) and multi-threading (MT) mechanisms provided by Solaris 2.x. Details of other threading models and implementations (such as SGI, Sequent, OSF/1, and Windows NT) are somewhat different, though the basic concepts are very similar.

A traditional UNIX process is a relatively "heavyweight" entity that contains a single-thread of control. In contrast, the thread-based concurrency mechanisms available on Solaris 2.x are more sophisticated, flexible, and efficient (when used properly). As shown in Figure 2, the Solaris MP/MT architecture operates at 2 levels (kernel-space and user-space) and contains the following 4 components:

- *Processing elements* – which are the CPUs that execute user-level and kernel-level instructions. The semantics of the Sun MP/MT model are intended to work for both uni-processors and symmetrical multi-processors on shared memory hardware.
- *Kernel threads* – which are the fundamental entities that are scheduled and executed by the processing elements (PEs) in kernel space. The OS kernel maintains a small data structure and a stack for each kernel thread. Context switching between kernel threads is relatively fast since it does not require changing virtual memory information.
- *Lightweight processes (LWPs)* – which are associated with kernel threads. In Solaris 2.x, a UNIX process is no longer a thread of control. Instead, each process contains one or more LWPs. There is a 1-to-1 mapping between its LWPs and its kernel threads.[3] The kernel-level scheduler in Solaris uses LWPs (and thereby kernel threads) to schedule application tasks. An LWP contains a relatively large amount of state (such as register data, accounting and profiling information, virtual memory address ranges, and timers). Therefore, context switching between LWPs is relatively slow.

  For the time-sharing scheduler class (the default), the scheduler divides the available PE(s) among multiple active LWPs via *preemption*. With this technique, each LWP runs for a finite period of time (typically 10 milliseconds). After the time-slice of the current LWP has elapsed, the OS scheduler selects another available

[3] On the other hand, not every kernel thread has an LWP. For example, there are system threads (like the pagedaemon, NFS daemon, and the callout thread) that have a kernel thread and operate entirely in kernel space.

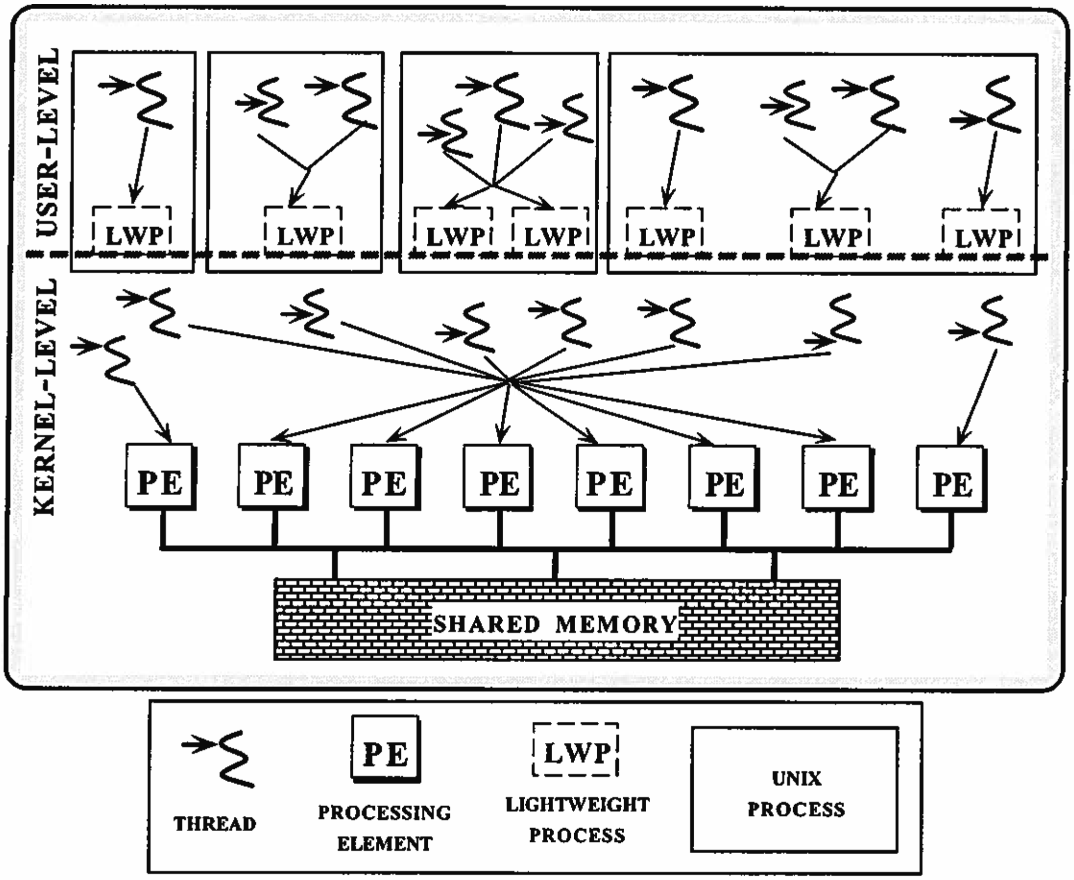

Figure 2: Solaris 2.x Multi-processing and Multi-threading Architecture

LWP, performs a context switch, and places the preempted LWP onto a queue. The kernel schedules LWPs using several criteria (such as priority, availability of resources, scheduling class, etc.). There is no fixed order of execution for LWPs in the time-sharing scheduler class.

- *Application threads* – Each LWP may be thought of as a "virtual PE," upon which application threads are scheduled and multiplexed by a user-level thread library. Each application thread shares its process address space with other threads, though it has a unique stack and register set. An application thread may spawn other application threads. Within a process, each of these application threads execute independently (though not necessarily in parallel depending on the hardware).

  Solaris 2.x provides a multi-level concurrency model that permits application threads to be spawned and scheduled using one of the following two modes:

  1. *Bound threads* – which map 1-to-1 onto LWPs and kernel threads. Bound threads permit independent tasks to execute in parallel on multiple PEs. Thus, if two application threads are running on separate LWPs (and thus separate kernel threads), they may execute in parallel (assuming they are running on a multiprocessor or using asynchronous I/O). Moreover, application threads may perform blocking system calls and handle page faults without impeding each other's progress.

     A kernel-level context switch is required to reschedule bound threads. Likewise, synchronization operations on bound threads require OS kernel intervention. Bound threads are most useful when an application is designed to take advantage of parallelism available on the hardware platform. Since each bound thread requires allocation of kernel resources, it may be inefficient to allocate a large number of bound threads.

  2. *Unbound threads* – which are multiplexed in an n-to-m manner atop one or more LWPs and kernel threads by a thread run-time library. This user-level library implements a non-preemptive, cooperative multi-tasking concurrency model. It schedules, dispatches, and suspends unbound threads, while minimizing kernel involvement. Compared with using application threads bound to LWPs, unbound application threads require less overhead to spawn, context switch, and synchronize.

  Depending upon the number of kernel threads that an application and/or library associates with a process, one or more unbound threads may execute on multiple PEs in parallel. Since each unbound thread does not allocate kernel resources, it is possible to allocate a very large number of unbound threads without significantly degrading performance.

3.4 Challenges of Concurrent Programming

On a multi-processor, more than one LWP may run in parallel on separate PEs. On a uni-processor, only one LWP will be active at any point in time. Regardless of the hardware platform, programmers must ensure that access to shared resources (such as files, databases records, network devices, terminals, or shared memory) is serialized to prevent *race conditions*. A race condition occurs when the order of execution of two or more concurrent LWPs leads to unpredictable and erroneous results (such as a database record being left in an inconsistent state). Race conditions may be eliminated by using the Solaris 2.x synchronization mechanisms described in Section 3.5. These mechanisms serialize access to critical sections of code that access shared resources.

In addition to the challenges of concurrency control, the following limitations arise when using multi-threading (rather than multi-processing or single-threaded, reactive event loops) to implement concurrent applications:

- *Robustness* – Executing all tasks via threads within a single process address space may reduce application robustness. This problem occurs since separate threads within the same process address space are not protected from one another. In order to reduce context switching and synchronization overhead, threads receive little or no protection from the hardware memory management unit (MMU).[4]

  Since threads are not protected, one faulty service in a process may corrupt global data shared by services running on other threads in the process. This, in turn, may produce incorrect results, crash an entire process, cause a network server to hang indefinitely, etc. A related problem is that certain UNIX system calls invoked in one thread may have undesirable side-effects on an entire process. For example, the `exit` system call has the side-effect of destroying all the threads within a process (`thr_exit` should be used to terminate only the current thread).

- *Access Privileges* – Another limitation with multi-threading is that all threads within a process share the same userid and access privileges to files and other protected resources. Therefore, to prevent accidental or intentional access to unauthorized resources, network services that base their security mechanisms on process ownership (such as the Internet `ftp` and `telnet` services) are typically implemented in separate processes.

- *Performance* – A common misconception is that multi-threading an application will automatically improve performance. In many circumstances, however, multi-threading does not improve performance. For example, compute-bound applications on a uni-processor [19] will not benefit from multi-threading since computation will not overlap communication. In addition, fine-grained locking causes high levels of synchronization overhead [23, 24]. This prevents applications from fully exploiting the benefits of parallel processing.

  There are some circumstances where multi-threading may improve performance significantly. For example, a multi-threading connection-oriented application gateway may benefit by being run on a multi-processor platform. Likewise, on a uni-processor, I/O-bound applications may benefit from multi-threading since computation is overlapped with communication and disk operations.

[4]An MMU protects separate process address spaces from accidental or malicious corruption by other active processes in the system.

3.5 Overview of Solaris 2.x Synchronization and Threading Mechanisms

This section outlines the synchronization and threading mechanisms available on Solaris 2.x. Solaris threads share various resources (such as open files, signal handlers, and global memory) within a single process address space. Therefore, they must utilize *synchronization mechanisms* to coordinate access to shared data, to avoid the race conditions discussed in Section 3.4. To illustrate the need for synchronization mechanisms, consider the following C++ code fragment:

```
typedef u_long COUNTER;
COUNTER request_count; // At file scope

void *run_svc (Queue<Message> *q)
{
  Message *mb; // Message buffer

  while (q->dequeue (mb)) > 0)
  {
    // Keep track of number of requests
    ++request_count;

    // Identify request and
    // perform service processing here...
  }
  return 0;
}
```

This code forms part of the main event-loop of a network daemon (such as an distributed database for medical images or a distributed file server). In the code, the main event-loop waits for messages to arrive from clients. When a message arrives, the main thread removes it from the message queue via its `dequeue` method. Depending on the type of message that is received, the thread then performs some type of processing (*e.g.*, image database query, file update, etc.). The `request_count` variable keeps track of the number of incoming client requests. This information might be used to update an attribute in an SNMP MIB.

The code shown above works fine as long as `run_svc` executes in a single thread of control. Incorrect results will occur on many multi-processor platforms, however, when run_svc is executed simultaneously by multiple threads of control running on different PEs. The problem here is that the code is not "thread-safe." Since auto-increment operations on the global variable request_count contain a race condition. Thus, different threads may increment obsolete versions of the request_count variable stored in their per-PE data caches.

This phenomenon may be demonstrated by executing the C++ code in Example 1 below on a shared memory multi-processor running the Solaris 2.x operating system. Solaris 2.x allows multiple threads of control to execute in parallel on a shared memory multi-processor. The example shown below is a simplified version of the network daemon illustrated above:

Example 1

```
typedef u_long COUNTER;
static COUNTER request_count; // At file scope

void *run_svc (int iterations)
{
  for (int i = 0; i < iterations; i++)
    ++request_count; // Count # of requests

  return (void *) iterations;
}

typedef void *(*THR_FUNC)(void *);

// Main driver function for the
// multi-threaded server.

int main (int argc, char *argv[])
{
  int n_threads  =
    argc > 1 ? atoi (argv[1]) : 4;
  int n_iterations =
    argc > 2 ? atoi (argv[2]) : 1000000;

  thread_t t_id;

  // Divide iterations evenly among threads.
  int iterations = n_iterations / n_threads;

  // Spawn off N threads to run in parallel.
  for (int i = 0; i < n_threads; i++)
    thr_create (0, 0, THR_FUNC (&run_svc),
                (void *) iterations,
                THR_BOUND | THR_SUSPENDED,
                &t_id);

  // Resume all suspended threads
  // (threads id's are contiguous...)
  for (i = 0; i < n_threads; i++)
    thr_continue (t_id--);

  // Wait for all threads to exit.
  int status;
  while (thr_join (0, &t_id,
                   (void **) &status) == 0)
    cout << "thread id = " << t_id
         << ", status = " << status << endl;

  cout << n_iterations  << " = iterations\n"
       << request_count << " = request count"
       << endl;
  return 0;
}
```

The Solaris thr_create thread library routine is called *n_thread* times to spawn n new threads of control. In this example, each newly created thread executes the run_svc function, which is passed the value of iterations as its only argument. This value causes the run_svc routine to iterate $\frac{n\_iterations}{n\_threads}$ times.

Each thread is spawned using the THR_BOUND and THR_SUSPENDED flags. THR_BOUND informs the Solaris thread run-time library to bind the thread to a dedicated LWP. Each LWP may run in parallel on a separate PE in a multi-processor system. The THR_SUSPENDED flag creates each thread in the "suspended" state. This ensures that all threads are completely initialized before resuming the tests by calling thr_continue. The thr_continue function is a Solaris thread library routine that resumes the execution of suspended threads. Note that this example takes advantage of the fact that thread ids are allocated contiguously by Solaris in ascending order.

Once all threads have been resumed, the thr_join routine blocks the execution of the main thread. thr_join is similar to the UNIX wait system call – it reaps the status of exiting threads. thr_join will reap threads and return 0 until all the threads running run_svc have exited. When all other threads have exited, the main thread prints out the total number of iterations and the final value of request_count, and then exits the program.

Compiling this code into an executable a.out file and running it on 1 thread for 10,000,000 iterations produces the following results:

```
% a.out 1 10000000
thread id = 4, status = 1000000
10000000 = iterations
10000000 = request count
```

This result appears as expected. However, when executed on 4 threads for 10,000,000 iterations on a 4 PE machine, the program prints the following:

```
% a.out 4 10000000
thread id = 5, status = 1000000
thread id = 7, status = 1000000
thread id = 6, status = 1000000
thread id = 4, status = 1000000
10000000 = iterations
5000000  = request count
```

Clearly, something is wrong since the value of the global variable request_count is only one-half the total number of iterations. The problem here is that auto-increments on variable request_count are not being serialized properly.

In general, run_svc will produce incorrect results when executed in parallel on shared memory multi-processor platforms that do not provide *strong sequential order* cache consistency models. To enhance performance, many shared memory multi-processors employ *weakly-ordered* cache consistency semantics. For example, the V.8 and V.9 family of SPARC multi-processors provides both *total store order* and *partial store order* memory cache consistency semantics. With total store order semantics, reading a variable that is being accessed by threads on different PEs may not be serialized with simultaneous writes to the same variable by threads on other PEs. Likewise, with partial store order semantics, writes may also not be serialized with other writes. In either case, expressions that require more than a single load and store of a memory location (such as `foo++` or `i = i - 10`) may produce inconsistent results due to cache latencies across multiple PEs. To ensure that reads and writes of variables shared between threads are updated correctly, programmers must manually enforce the order that changes to these variables become globally visible.

A common technique for enforcing a strong sequential order on a *total store order* or *partial store order* shared memory multi-processor is to protect the increment of the `request_count` variable using a synchronization mechanism. Solaris 2.x provides several synchronization mechanisms. This paper describes C++ wrappers for the four primary synchronization mechanisms in Solaris 2.x: *mutexes*, *readers/writer locks*, *counting semaphores*, and *condition variables* [19]. ACE contains C++ wrappers (`Mutex`, `RW_Lock`, `Semaphore`, and `Condition`) that encapsulate these four Solaris 2.x synchronization mechanisms (`mutex_t`, `rwlock_t`, `sema_t`, and `cond_t`, respectively). In the remainder of Section 3 we outline the behavior of the Solaris synchronization mechanisms. Section 4 illustrates the use of C++ wrappers to simplify common synchronization variable usage and to improve program reliability.

3.5.1 Mutual Exclusion Locks

Mutex exclusion locks (commonly called "mutexes" or "binary semaphores") are used to protect the integrity of a shared resource that is accessed concurrently by multiple threads of control. A mutex serializes the execution of multiple threads by defining a critical section where only one thread executes its code at a time. Mutexes are simple (*e.g.*, only the thread owning a mutex may release it) and efficient (in terms of time and space).

One of the simplest and most efficient types of mutex is a "non-recursive" mutex (other types of mutexes are discussed in Section 4.4). Solaris 2.x implements non-recursive mutexes via the `mutex_t` data type and its corresponding `mutex_lock` and `mutex_unlock` functions. Non-recursive mutexes provide an efficient form of mutual exclusion. They define a critical section where only a single thread may execute at a time. They are non-recursive since the thread that currently owns a mutex may not reacquire the mutex without releasing it first. Otherwise, deadlock will occur immediately. As described in Section 5.1.4, the ACE OO thread encapsulation library provides the `Mutex` C++ wrapper to encapsulate non-recursive `mutex_t` semantics.

On Solaris 2.x, a thread may enter a critical section by invoking the `mutex_lock` function on a `mutex_t` variable. Any calls to this function will block until the thread that currently owns the lock has left its critical section. To leave a critical section, a thread invokes the `mutex_unlock` function on a `mutex_t` variable it currently owns. Calling `mutex_unlock` enables another thread that is blocked on the mutex to enter its critical section.

Operations on mutex variables in Solaris 2.x are implemented via adaptive spin-locks. Spin-locks ensure mutual exclusion by using an atomic hardware instruction. A spin-lock is a simple and efficient synchronization mechanism for certain types of short-lived resource contention, like auto-incrementing the global `request_count` variable illustrated in Example 1 above. An adaptive spin-lock polls a designated memory location using the atomic hardware instruction until one of the following conditions occur [2]:

- The value at this location is changed by the thread that currently owns the lock. This signifies that the lock has been released and may now be acquired by the spinning thread.
- The thread that is holding the lock goes to sleep. At this point, the spinning thread also puts itself to sleep to avoid unnecessary polling.

On a multi-processor, the overhead incurred by a spin-lock is relatively minor. Hardware-based polling does not cause contention on the system bus since it only affects the local PE caches of threads that are spinning on a mutex.

3.5.2 Readers/Writer Locks

Readers/writer locks behave similarly to mutexes. For example, the thread that acquires a readers/writer lock must also release it. Readers/writer mutexes help to improve concurrent execution when an object protected by the mutex is read far more often than it is written. Multiple threads may acquire the mutex simultaneously for reading, but only one thread may acquire the mutex for writing. Due to their additional overhead, readers/writer locks are intended primarily for data structures whose contents are read much more frequently than they are written. The Solaris implementation of readers/writer locks gives preference to writers (*i.e.*, if there are multiple readers and a single writer waiting on the lock the writer will acquire it first).

Solaris 2.x supports readers/writer mutexes via its `rwlock_t` type. As described in 5.1.3, the ACE thread library provides a class called `RW_Mutex` that encapsulates the semantics of `rwlock_t` within a C++ wrapper.

3.5.3 Counting Semaphores

Counting semaphores are conceptually non-negative integers that may be incremented and decremented atomically. If a thread tries to decrement a semaphore whose value equals zero the thread is suspended until another thread increments the semaphore.

Semaphores are less efficient than mutexes since they retain additional state and use sleep-locks, rather than spin-locks. However, they more general since they need not be acquired and released by the same thread that acquired them initially. This enables them to be used in asynchronous execution contexts (such as signal handlers).

Solaris 2.x supports for semaphores via its `sema_t` type. As described in Section 5.1.2, the ACE thread library provides a class called `Semaphore` that encapsulates the semantics of `sema_t` within a C++ wrapper.

3.5.4 Condition Variables

Condition variables provide a different flavor of locking than mutexes, readers/writer locks, and counting semaphores. These three other mechanisms make collaborating threads wait while the thread holding the lock executes code in a critical section. In contrast, a condition variable makes a thread wait until a condition expression involving shared data attains a particular state. When another cooperating thread indicates that the state of the shared data has changed the scheduler wakes up a thread that is suspended on that condition variable. The newly awakened thread then re-evaluate its condition expression and potentially resumes processing if the shared data has attained an appropriate state.

The condition expression waited for by a condition variable may be arbitrarily complex. In general, condition variables permit more complex scheduling decisions, compared with the other synchronization mechanisms. Condition variable synchronization is implemented using sleep-locks, which trigger a context switch and allow another thread to execute until the lock is acquired. As described in Section 3.5.1, mutexes are implemented using adaptive spin-locks. Spin-locks consume excessive resources if a thread must wait a long amount of time for a particular condition to become signaled.

Solaris 2.x supports condition variables via its `cond_t` type. As described in Section 5.3.1, the ACE thread library provides a class called `Condition` that encapsulates the semantics of `cond_t` within a C++ wrapper.

3.6 Process vs. Thread Synchronization Semantics

To increase flexibility and improve performance, Solaris 2.x provides two flavors of synchronization semantics that are optimized for either (1) threads that execute within the same process (*i.e.,* intra-process serialization) and (2) threads that execute in separate processes (*i.e.,* inter-process serialization). In Solaris 2.x, the USYNC_THREAD flag to the `*_init` functions of the synchronization mechanisms creates variables that are optimized for threads within a single processes. Likewise, the `USYNC_PROCESS` flag creates a synchronization variable that is valid across multiple processes. The latter type of synchronization mechanism is more general, though somewhat less efficient if all threads run within a single process.

3.7 Mutex Example

The following code illustrates how Solaris mutex variables may be used to solve the auto-increment serialization problem we observed earlier with `request_count`:

Example 2

```
typedef u_long COUNTER;
// At file scope
static COUNTER request_count;
// mutex protecting request_count (initialized
// to zero).
static mutex_t m;

void *run_svc (void *)
{
  for (int i = 0; i < iterations; i++)
  {
    mutex_lock (&m); // Acquire lock
    ++request_count; // Count # of requests
    mutex_unlock (&m); // Release lock
  }

  return (void *) iterations;
}
```

In the code above, m is a global variable of type `mutex_t`. In Solaris, any synchronization variable that is zero'd out is initialized using its default semantics. For example, the `mutex_t` variable m is always initialized to start out in the *unlocked* state. Therefore, the first time that `mutex_lock` is called it will acquire ownership of the lock. Any other thread that attempts to acquire the lock will be forced to wait (*e.g.,* by spinning) until the owner of the lock releases m.

Example 2 shown above solves the original synchronization problem, it suffers from the following drawbacks:

- *Inelegant and inconsistent* – the code mixes C functions with C++ objects, as well as different identifier naming conventions. Using a hybrid programming style is distracting and can become a maintenance problem.
- *Obtrusive* – the solution requires changing the source code. When developing a large software system, manually performing these types of changes leads to maintenance problems if all these changes are not made consistently.
- *Non-portable* – this code will only work with Solaris 2.x synchronization mechanisms. In particular, porting the code to use POSIX pthreads and Windows NT threads will require changing the locking code.
- *Error-prone* – It is easy for programmers to forget to call `mutex_unlock`. This will starve other threads that are trying to acquire the lock. Furthermore, deadlock will occur if the owner of the lock tries to reacquire a mutex it owns already.

  It is also possible that a programmer will forget to initialize the mutex variable. As mentioned above, in Solaris 2.x, a zero'd `mutex_t` variable is implicitly initialized. However, no such guarantees are made for `mutex_t` variables that are allocated as fields in dynamically allocated structures or classes. Moreover, other thread mechanisms (such as POSIX pthreads and Windows NT threads) do not make these guarantees and all synchronization objects must be initialized explicitly.

In Section 4 we will examine how the use of C++ wrappers helps to overcome these problem, by improving the functionality, portability, and robustness of Solaris synchronization mechanisms.

4 Simplifying Concurrent Programming with OO and C++

This section examines a use case to motivate and demonstrate the benefits of encapsulating Solaris concurrency mechanisms within C++ wrappers. This use case depicts a representative scenario that is based upon a production system [25]. Additional examples of the ACE OO thread encapsulation class library appear in Section 6, following the presentation the library interfaces in Section 5.

Many useful C++ classes have evolved incrementally by generalizing from solutions to practical problems that arise during system development. After the interface and implementation of a class have stabilized, however, this iterative process of generalizing classes over time is often de-emphasized. That is unfortunate since a major barrier to entry for object-oriented design and C++ is (1) learning and internalizing the process of *how* to identify and describe classes and objects and (2) understanding when and how to apply (or not apply) C++ features such as templates, inheritance, dynamic binding, and overloading to simplify and generalize their programs.

In an effort to capture the dynamics of C++ class design evolution, the following section illustrates the process by which object-oriented techniques and C++ idioms were incrementally applied to solve a surprisingly subtle problem. This problem arose during the development of a family of concurrent distributed applications that execute efficiently on both uni-processor and multi-processor platforms. This section focuses on the steps involved in generalizing from existing code by using templates and overloading to transparently parameterize synchronization mechanisms into a concurrent application. The infrastructure code is based on components in the ADAPTIVE Communication Environment (ACE) framework described in [1, 26, 20].

This example examines several C++ language features that solve the serialization problem presented in Section 3.5.1 more elegantly. As described in that section, the original solution was inelegant, non-portable, error-prone, and required obtrusive changes to the source code. This section illustrates a progression of C++ solutions that build upon insights from prior iterations in the design evolution.

4.1 An Initial C++ Solution

A somewhat more elegant solution to the original problem is to encapsulate the existing Solaris `mutex_t` operations with a C++ wrapper, as follows:[5]

```
class Mutex
{
public:
  Mutex (int type = USYNC_THREAD) {
    mutex_init (&lock_, type, 0);
  }
  ~Mutex (void) {
    mutex_destroy (&lock_);
  }
  int acquire (void) {
    return mutex_lock (&lock_);
  }
  int release (void) {
    return mutex_unlock (&lock_);
  }

private:
  // Solaris 2.x serialization mechanism.
  mutex_t lock_;
};
```

One advantage of defining a C++ wrapper interface to mutual exclusion mechanisms is that application code now becomes more portable across OS platforms. For example, the following is an implementation of the Mutex class interface based on mechanisms in the Windows NT WIN32 API [15]:

```
class Mutex
{
public:
  Mutex (void) {
    InitializeCriticalSection (&lock_);
  }
  ~Mutex (void) {
    DeleteCriticalSection (&lock_);
  }
  int acquire (void) {
    EnterCriticalSection (&lock_); return 0;
  }
  int release (void) {
    LeaveCriticalSection (&lock_); return 0;
  }

private:
  // Win32 serialization mechanism.
  CRITICAL_SECTION lock_;
};
```

The use of the `Mutex` C++ wrapper class cleans up the original code somewhat, improves portability, and ensures that initialization occurs automatically when a `Mutex` object is defined, as shown in the code fragment below:

Example 3

```
typedef u_long COUNTER;
// At file scope.
static COUNTER request_count;
// Mutex protecting request_count.
static Mutex m;

void *run_svc (void *)
{
  for (int i = 0; i < iterations; i++)
  {
    m.acquire ();
    // Count # of requests.
    ++request_count;
    m.release ();
```

[5] In this paper, many examples of C++ classes are shown with the methods implemented within the class definition. This style is for exposition purposes only and should not be used when developing applications.

```
    }

    return (void *) iterations;
}
```

However, the C++ wrapper approach does not solve all the problems identified in Section 3.5.1. In particular, it does not solve the problem of forgetting to release the mutex (which still requires manual intervention by programmers). In addition, using class `Mutex` still requires obtrusive changes to the original non-thread-safe source code.

4.2 Another C++ Solution

A straightforward way to ensure locks will be released automatically is to use the semantics of C++ class constructors and destructors. The following utility class uses these language constructs to automate the acquisition and release of a mutex:

```
class Guard
{
public:
  Guard (const Mutex &m): lock_ (m) {
    lock_.acquire ();
  }
  ~Guard (void) {
    lock_.release ();
  }

private:
  const Mutex &lock_;
}
```

A `Guard` defines a "block" of code over which a `Mutex` is acquired and then released automatically when the block is exited. It employs a C++ idiom idiom commonly known as "constructor as resource acquisition – destructor as resource release" [8, 27, 6].

As shown in the code above, the constructor of a `Guard` class acquires the lock on the `Mutex` object automatically when an object of the class is created. Likewise, the destructor of a `Guard` class automatically unlocks the `Mutex` object when the object goes out of scope.

Note that the `lock_` data member of class `Guard` is a reference to a `Mutex` object. This avoids the overhead of creating and destroying an underlying Solaris `mutex_t` variable every time the constructor and destructor of a `Guard` are executed.

By making a slight change to the code, we now guarantee that a `Mutex` is acquired and released automatically:

Example 4

```
typedef u_long COUNTER;
// At file scope.
static COUNTER request_count;
// Mutex protecting request_count.
static Mutex m;

void *run_svc (void *)
{
  for (int i = 0; i < iterations; i++)
  {
    {
      // Automatically acquire the mutex.
      Guard monitor (m);

      ++request_count;
      // Automatically release the mutex.
    }
    // Remainder of service processing omitted.
  }
}
```

However, this solution still has not fixed the problem with obtrusive changes to the code. Moreover, adding the extra '{' and '}' curly brace delimiter block around the `Guard` is inelegant and error-prone. A maintenance programmer might misunderstand the importance of the curly braces and remove them, yielding the following code:

```
  for (int i = 0; i < iterations; i++)
  {
    Guard monitor (m);

    ++request_count;
    // Remainder of service processing omitted.
  }
```

Unfortunately, this "curly-brace elision" has the side-effect of eliminating all concurrent execution within the application by serializing the main event-loop. Therefore, all computations that would have executed in parallel within that section of code will be serialized unnecessarily.

4.3 An Improved C++ Solution

To solve the remaining problems in a transparent, unobtrusive, and efficient manner requires the use of two additional C++ features: parameterized types and operator overloading. We use these features to provide a template class called `Atomic_Op`, a portion of which is shown below (the complete interface appears in Section 5.6.2):

```
template <class TYPE>
class Atomic_Op
{
public:
  Atomic_Op (void) { count_ = 0; }
  Atomic_Op (TYPE c) { count_ = c; }
  TYPE operator++ (void) {
    Guard monitor (lock_);
    return ++count_;
  }
  operator TYPE () {
    Guard monitor_ (lock_);
    return count_;
  }
  // Other arithmetic operations omitted...

private:
  Mutex lock_;
  TYPE count_;
};
```

The `Atomic_Op` class redefines the normal arithmetic operations (such as `++`, `--`, `+=`, etc.) on built-in data types to make these operations work atomically. In general, any class that defines the basic arithmetic operators will work with the

Atomic_Op class due to the "deferred instantiation" semantics of C++ templates.

Since the Atomic_Op class uses the mutual exclusion features of the Mutex class, arithmetic operations on objects of instantiated Atomic_Op classes now work *correctly* on a multi-processor. Moreover, C++ features (such as templates and operator overloading) allow this technique to work *transparently* on a multi-processor, as well. In addition, all the method operations in Atomic_Op are defined as inline functions. Therefore, an optimizing C++ compiler will generate code that ensures the run-time performance of Atomic_Op is no greater than calling the mutex_lock and mutex_unlock function directly.

Using the Atomic_Op class, we can now write the following code, which is almost identical to the original non-thread safe code (in fact, only the typedef of COUNTER has changed):

Example 5

```
typedef Atomic_Op<u_long> COUNTER;
// At file scope
static COUNTER request_count;

void *run_svc (void *)
{
  for (int i = 0; i < iterations; i++)
  {
    // Actually calls Atomic_Op::operator++()
    ++request_count;
  }
}
```

By combining the C++ constructor/destructor idiom for acquiring and releasing the Mutex automatically, together with the use of templates and overloading, we have produced a simple, yet remarkably expressive parameterized class abstraction. This abstraction operates correctly and atomically on an infinite family of types that require atomic operations. For example, to provide the same thread-safe functionality for other arithmetic types, we simply instantiate new objects of the Atomic_Op template class as follows:

```
Atomic_Op<double> atomic_double;
Atomic_Op<Complex> atomic_complex;
```

4.4 Extending Atomic_Op by Parameterizing the Type of Mutual Exclusion Mechanism

Although the design of the Atomic_Op and Guard classes described above yield correct and transparently thread-safe programs, there is still room for improvement. In particular, note that the type of the Mutex data member is hard-coded into the Atomic_Op class. Since templates are available in C++, this design decision represents an unnecessary restriction that is easily overcome. The solution is to parameterize Guard and add another type parameter to the template class Atomic_Op, as follows:

```
template <class LOCK>
class Guard
{
  // Basically the same as before...

private:
  // new data member change.
  const LOCK &lock_;
};

template <class LOCK, class TYPE>
class Atomic_Op
{
  TYPE operator++ (void)
  {
    Guard<LOCK> monitor (lock_);
    return ++count_;
  }
  // ...

private:
  LOCK lock_; // new data member
  TYPE count_;
};
```

Using this new class, we can make the following simple change at the beginning of the source file:

```
typedef Atomic_Op <Mutex, u_long> COUNTER;
// At file scope.
COUNTER request_count;

// ... same as before
```

4.5 Design Rationale and Performance Issues

Before making the changes described above, it is worthwhile to analyze the motivation for using templates to parameterize the type of mutual exclusion mechanism used by a program is beneficial. After all, just because C++ supports templates does not make them useful in all circumstances. In fact, parameterizing and generalizing the problem space via templates without clear and sufficient reasons may increase the difficulty of understanding and reusing C++ classes.

The use of templates in the Atomic_Op class raises several issues. The first is "what is the run-time performance penalty for all the added abstraction?" The second question is "instead of templates, why not use inheritance and dynamic binding to emphasize uniform mutex interface and to share common code?" The third is "aren't the synchronization properties of the program being obscured by using templates and overloading?" Several of these questions are related and this section discusses tradeoffs involving different design alternatives.

4.5.1 Performance

The primary reason why templates are used for the Atomic_Op class involve run-time efficiency. Once expanded by an optimizing C++ compiler during template instantiation, the additional amount of run-time overhead is minimal or non-existent. In contrast, inheritance and dynamic binding incur overhead at run-time in order to dispatch virtual method calls.

Figure 3 illustrates the performance exhibited by the mutual exclusion techniques used in Examples 2 through 5

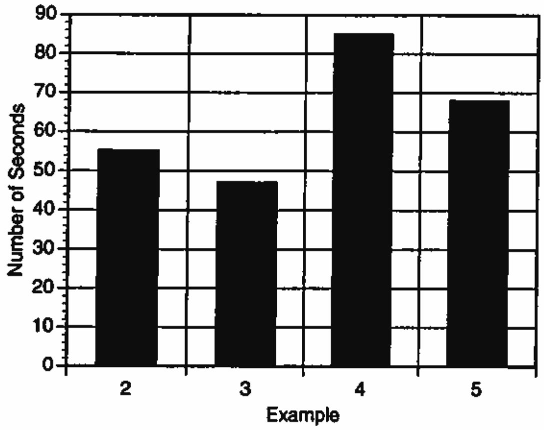

Figure 3: Number of Seconds Required to Process 10,000,000 Iterations

above.[6] This figure depicts the number of seconds required to process 10 million iterations, divided into 2.5 million iterations per-thread. The test examples were compiled using the `-O4` optimization level of the Sun C++ 3.0.1 compiler. Each test was executed 10 times on an otherwise idle 4 PE Sun SPARCserver 690MP. The results were averaged to reduce the amount of spurious variation (which proved to be insignificant).

Example 2 uses the Solaris `mutex_t` functions directly. Example 3 uses the C++ `Mutex` class wrapper interface. Surprisingly, this implementation consistently performed better than Example 1, which used direct calls to the underlying Solaris mutex functions. Example 4 uses the `Guard` helper class inside of a nested curly brace block to ensure that the `Mutex` is released automatically. This version required the most time to execute. Finally, Example 5 uses the `Atomic_Op` template class, which is only slightly less efficient than using the Solaris mutex functions directly. More aggressively optimizing C++ compilers would reduce the amount of variation in the results.

Table 1 indicates the number of micro-seconds (*u*secs) incurred by each mutual exclusion operation for Examples 2 through 5. Recall that each loop iteration requires 2 mutex operations (one to acquire the lock and one to release the lock). Example 2 is used as the baseline value since it uses the underlying Solaris primitives directly. The third column of Examples 3 through 5 are normalized by dividing their values by Example 2.

4.5.2 Portability

One motivation for parameterizing the type of mutual exclusion mechanism is to increase portability across OS platforms. Templates decouple the formal parameter class name "`Mutex`" from the actual name of the class used to provide

[6] Example 1 is the original erroneous implementation that did not use any mutual exclusion operations. Although it operates extremely efficiently (approximately 0.09 seconds to process 10,000,000 iterations), it produces results that are totally incorrect!

Example	*u*secs per operation	Ratio
Example 2	2.76	1
Example 3	2.35	0.85
Example 4	4.24	1.54
Example 5	3.39	1.29

Table 1: Serialization Time for Different Examples

mutual exclusion. This is useful for platforms that already use the symbol `Mutex` to denote an existing type or function. By using templates, the `Atomic_Op` class source code would not require any changes when porting to such platforms.

However, a more interesting motivation arises from the observation that there are actually several different flavors of mutex semantics one might want to use (either in the same program or across a family of related programs). Each of these mutual exclusion flavors share the same basic acquire and release protocol, but they possess different serialization and performance properties. Section 5.1.1 presents a number of mutual exclusion mechanisms that have proven to be useful in practice.

4.5.3 Transparency

One argument *against* using templates to parameterize synchronization is that the level of transparency hides the mutual exclusion semantics of the program. Whether this is considered a "bug" or a "feature" depends on how one believes that concurrency and synchronization should be integrated into a program. For class libraries that contain basic building-block components (such as the `Map_Manager` described in Section 5.1.1), allowing synchronization semantics to be parameterized is often desirable since this enables developers to *precisely* control and specify the concurrency semantics that they want. The alternatives to this strategy are (1) don't use class libraries if multi-threading is used (which obviously limits functionality), (2) do all the locking outside the library (which may be inefficient or unsafe), or (3) hard-code the locking strategy into the library implementation (which is also inflexible and potentially inefficient). All these alternatives are antithetical to principles of reuse in object-oriented software systems.

4.5.4 Evaluating the Tradeoffs

Selecting an appropriate design strategy for developing a class library that supports concurrency depends on several factors. For example, certain library users may welcome simple interfaces that hide concurrency control mechanisms from view. In contrast, other library users may be willing to accept more complicated interfaces in return for additional control and increased efficiency. A layered approach to class library design may satisfy both groups of library users. Using this design approach, the lowest layers of the class library export most or all of the parameterized types as template arguments. The higher layers provide reasonable default type values and provide an easier-to-use application developer's programming interface.

The new "default template argument" feature recently adopted by the ANSI C++ committee facilitates the development of class libraries that satisfy both types of library users. This feature allows library developers to specify common default types as arguments to template class and function definitions. For example, the following modification to template class `Atomic_Op` provides it with typical default template arguments:

```
template <class LOCK = Mutex,
          class TYPE = u_long>
class Atomic_Op
{
// Same as before
};

// ...

#if defined (MT_SAFE)
// Default is Mutex and u_long.
typedef Atomic_Op COUNTER;
#else
// Don't serialize.
typedef Atomic_Op<Null_Mutex> COUNTER;
#endif /* MT_SAFE */
COUNTER request_count;
```

Due to the complexity that arises from incorporating concurrency into applications, C++ templates are quite useful for reducing redundant development effort. However, as with any other language feature, it is possible to misuse templates and needlessly complicate a system's design and implementation (not to mention increasing the compile and link times). One heuristic to use when deciding whether to use parameterized types is to keep track of when existing code is about to be duplicated in a way that only modifies the data types. If there is another reasonable scenario that would require yet a third version that only differs by types, this indicates that generalizing the original code to use templates may be worthwhile.

5 Public Interfaces and Internal Design

This section describes the public interfaces and relevant internal design aspects of components in the ACE OO thread encapsulation library. The ACE components are divided into the following groups:

- C++ wrappers for locking mechanisms (described in Section 5.1).
- C++ wrappers for Solaris 2.x thread functions (described in Section 5.6.1).
- Higher-level thread management classes (described in Section 5.4.1).

A use case example of the ACE OO thread components was presented in Section 4. The remainder of this section presents a more comprehensive discussion of the public interfaces, functionality, and internal design of ACE. Where appropriate, this section depicts private portions of the C++ wrapper classes in order to illustrate how the wrappers are mapped onto Solaris 2.x threading and synchronization mechanisms.

5.1 The ACE Locks Class Category

The ACE C++ wrappers provide a portable, type-safe, object-oriented interface to Solaris and POSIX OS synchronization mechanisms described in Section 3.5. The following bullets outline the primary benefits of these ACE C++ wrappers:

- **Improve correctness:** by automating the initialization of synchronization objects that appear as fields in C++ classes and structs, as well as by guaranteeing that locks are acquired and released automatically.
- **Uniform synchronization interface:** all the C++ wrappers for Solaris 2.x synchronization provide a uniform interface for acquiring and releasing various types of locks. In particular, all components in the ACE Locks class category support four common methods: `acquire`, `try_acquire`, `release`, and `remove`. This uniformity makes it possible to use the lock classes as type parameters in conjunction with other ACE synchronization components (such as those defined in Section 5.2.1, 5.6.2, and 5.1.4).
- **More intuitive error reporting:** the Solaris 2.x synchronization functions use a non-standard mechanism for returning errors to callers. In contrast, the ACE wrappers use a more standard approach that returns -1 if a failure occurs, along with setting `errno` to indicate the cause of the failure.
- **Simplify common usage pattern:** the wrappers simplify common usage patterns for the Solaris 2.x synchronization mechanisms. The code shown illustrates this point by using the ACE C++ wrappers for Solaris `mutex_t` and `cond_t` to implement a simple version of Dijkstra's counting semaphores (*i.e.*, P and V are equivalent to `acquire` and `release`, respectively).

```
class Semaphore
{
public:
  Semaphore (int initial_value)
    : count_nonzero_ (lock_) {
    // Automatically acquire lock.
    Guard<Mutex> monitor (lock_);

    count_ = initial_value;
   // Automatically release the lock
  }

  // Block the thread until the semaphore
  // count becomes greater than 0,
  // then decrement it.

  void acquire (void) {
    // Automatically acquire lock
    Guard<Mutex> monitor (lock_);

    // Wait until semaphore is available.
    while (count_ == 0)
      count_nonzero_.wait ();
```

```
    count_ = count_ - 1;
    // Automatically release the lock
  }

  // Increment the semaphore, potentially
  // unblocking a waiting thread.

  void release (void) {
    // Automatically acquire lock
    Guard<Mutex> monitor (lock_);

    // Allow waiter to continue.
    if (count_ == 0)
      count_nonzero_.signal ();

    count_ = count_ + 1;
    // Automatically release the lock
  }

private:
  Mutex lock_;
  Condition<Mutex> count_nonzero_;
  u_int count_;
};
```

Note how the constructor for the `Condition` object `count_nonzero_` binds the `Mutex` object `lock_` together with the `Condition` object. This simplifies the `Condition::wait` calling interface. In contrast, the underlying Solaris `cond_t` `cond_wait` interface requires a mutex to be passed as a parameter on every call to `wait`.

Solaris 2.x provides a built-in implementation of counting semaphores (see the discussion in Section 3.5.3). However, the POSIX Pthreads [3] threads library does *not* include a semaphore. Therefore, the class shown above both illustrates the use of ACE C++ wrappers and documents a portable `Semaphore` implementation for POSIX Pthreads in the ACE thread encapsulation library.

5.1.1 The Mutex Classes

The `Mutex` class provides a simple and efficient mechanism that serializes access to a shared resource. It encapsulates the Solaris `mutex_t` synchronization variable. The class definition for `Mutex` is shown below:

```
class Mutex
{
public:
  // Initialize the mutex.
  Mutex (int type = USYNC_THREAD);

  // Implicitly destroy the mutex.
  ~Mutex (void);

  // Explicitly destroy the mutex.
  int remove (void);

  // Acquire lock ownership (wait
  // for lock to be released).
  int acquire (void) const;

  // Conditionally acquire lock
  // (i.e., don't wait for lock
  // to be released).
  int try_acquire (void) const;

  // Release lock and unblock
  // the next waiting thread.
  int release (void) const;

private:
  mutex_t lock_;
};
```

The `Thread_Mutex` and `Process_Mutex` classes simply inherit from `Mutex` and use its constructor to create the appropriate type of mutex, as follows:

```
class Thread_Mutex : public Mutex
{
public:
  Thread_Mutex (void): Mutex (USYNC_THREAD);
};

class Process_Mutex : public Mutex
{
public:
  Thread_Mutex (void): Mutex (USYNC_PROCESS);
};
```

5.1.2 The Semaphore Class

The `Semaphore` class implements Dijkstra's "counting semaphore" abstraction, which is a general mechanism for serializing multiple threads of control. It encapsulates the Solaris `sema_t` synchronization variable. The `Semaphore` class interface is shown below:

```
class Semaphore
{
public:
  // Initialize the semaphore,
  // with default value of "count".
  Semaphore (u_int count,
             int type = USYNC_THREAD,
             void * = 0);

  // Implicitly destroy the semaphore.
  ~Semaphore (void);

  // Explicitly destroy the semaphore.
  int remove (void);

  // Block the thread until the semaphore count
  // becomes greater than 0, then decrement it.
  int acquire (void) const;

  // Conditionally decrement the semaphore if
  // count greater than 0 (i.e., won't block).
  int try_acquire (void) const;

  // Increment the semaphore, potentially
  // unblocking a waiting thread.
  int release (void) const;

private:
  sema_t semaphore_;
};
```

5.1.3 The RW_Mutex Class

The `RW_Mutex` class is used to serialize access to resources whose contents are searched more than they are changed. It encapsulates the Solaris `rwlock_t` synchronization variable. The `RW_Mutex` interface is shown below:

```
class RW_Mutex
{
public:
  // Initialize a readers/writer lock.
  RW_Mutex (int type = USYNC_THREAD,
            void *arg = 0);

  // Implicitly destroy a readers/writer lock.
  ~RW_Mutex (void);

  // Explicitly destroy a readers/writer lock.
  int remove (void);

  // Acquire a read lock, but
  // block if a writer hold the lock.
  int acquire_read (void) const;

  // Acquire a write lock, but
  // block if any readers or a
  // writer hold the lock.
  int acquire_write (void) const;

  // Conditionally acquire a read lock
  // (i.e., won't block).
  int try_acquire_read (void) const;

  // Conditionally acquire a write lock
  // (i.e., won't block).
  int try_acquire_write (void) const;

  // Unlock a readers/writer lock.
  int release (void) const;

private:
  rwlock_t lock_;
};
```

Note that POSIX Pthreads does not provide a `rwlock_t` type. To ensure code portability, ACE provides an `RW_Mutex` implementation based on existing POSIX synchronization wrappers such as `Mutex` and `Condition`.

5.1.4 The Recursive_Lock Class

A `Recursive_Lock` extends the default Solaris non-recursive locking semantics. It allows calls to `acquire` methods to be nested as long as the thread that owns the lock is the one that re-acquires it. It works with the `Mutex`, `RW_Mutex`, and `Semaphore` classes.

By default, Solaris provides non-recursive mutexes and readers/writer locks. These semantics are too restrictive in certain circumstances. Therefore, ACE provides support for recursive locks via the `Recursive_Lock` class. Recursive locks are particularly useful for callback-driven C++ frameworks [28, 20], where the framework event-loop performs a callback to user-defined code. Since the user-defined code may subsequently re-enter framework code via a method entry point, recursive locks are useful to prevent deadlock from occurring on locks held within the framework during the callback.

The following C++ template class implements recursive lock semantics for the Solaris 2.x synchronization mechanisms (note that POSIX Pthreads provides recursive mutexes in the thread library):

```
template <class LOCK>
class Recursive_Lock
{
public:
  // Initialize a recursive lock.
  Recursive_Lock (int type = USYNC_THREAD,
                  void *arg = 0);

  // Implicitly release a recursive lock.
  ~Recursive_Lock (void);

  // Explicitly release a recursive lock.
  int remove (void);

  // Acquire a recursive lock (will increment
  // the nesting level and not deadlock if
  // owner of the lock calls this method more
  // than once).
  int acquire (void) const;

  // Conditionally acquire a recursive lock
  // (i.e., won't block).
  int try_acquire (void) const;

  // Releases a recursive lock (will not
  // release lock until nesting level == 0).
  int release (void) const;

private:
  // This is the lock that actually suspends
  // other waiting threads.
  LOCK lock_;

  // Protects thread id and nesting level.
  LOCK mutex_;

  // Current owner of the lock.
  thread_t thr_id_;

  // Current nesting level of the recursion.
  int nesting_level_;
};
```

`Recursive_Lock` may be instantiated with any C++ synchronization wrapper (*e.g.*, `Mutex`, `RW_Mutex`, `Semaphore`) that conforms to the `acquire/release` C++ wrapper interface. This example illustrates yet another benefit of using C++ wrappers: they promote interface conformance by adapting gratuitously incompatible interfaces (such as Solaris 2.x semaphores and mutexes). This is an example of the Adapter pattern from [4].

The following code illustrates the implementation of the methods in the `Recursive_Lock` class:

```
Recursive_Lock::Recursive_Lock (void)
  : nesting_level_ (0), thr_id_ (0) {}

// Acquire a recursive lock (will increment
// the nesting level and not deadlock if
// owner of lock calls method more than once).

int
Recursive_Lock::acquire (void) const
{
  thread_t t_id = Thread::self ();

  mutex_.acquire ();

  // Check if we already hold the lock, if so
  // simply increment the nesting level.
  if (thr_id_ == t_id) {
    ++nesting_level_;
```

```
      mutex_.release ();
      return 0;
    }
    else {
      mutex_.release ();

      int result = lock_.acquire ();
      if (result == 0) {
        thr_id_ = t_id;
        nesting_level_ = 0;
      }
      return result;
    }
}

// Releases a recursive lock.

int
Recursive_Lock::release (void) const
{
  mutex_.acquire ();
  // Don't release the lock until nesting
  // level drops to 0.
  if (nesting_level_ > 0) {
    --nesting_level_;
    mutex_.release ();
    return 0;
  }
  else {
    thr_id_ = 0;
    mutex_.release ();
    return lock_.release ();
  }
}
```

The following is an example of Recursive_Locks based on a variation of the Atomic_Op COUNTER presented in Section 4. In the example, Atomic_Op is called by multiple recursive function calls within a single thread:

```
// Counter is a recursive lock.
typedef Atomic_Op< Recursive_Lock <Mutex> >
        COUNTER;
// Keep track of the recursion depth.
static COUNTER recursion_depth;

int factorial (int n)
{
  if (n <= 1) {
    cout << "recursion depth = "
         << recursion_depth << endl;
    return n;
  }
  else {
    // First call acquires lock, subsequent
    // calls increment nesting level.
    recursion_depth++;
    return factorial (n - 1) * n;
  }
}
```

The use of a Recursive_Lock prevents deadlock from occurring when the recursion_depth counter is incremented. Although this illustrates recursive lock behavior, it is a poor example. A program executing factorial in multiple threads would produce unpredictable results since recursion_depth is a global various that would be modified serially by multiple threads of control! A more appropriate (and less expensive) locking strategy in this case would use the Thread-Specific Storage pattern [29] described in Section 5.6.4.

5.1.5 The Null_Mutex Class

The Null_Mutex class provides a zero-overhead implementation of the general locking interface shared by the other C++ wrappers for Solaris synchronization. The interface and trivial implementation for Null_Mutex is shown below:

```
class Null_Mutex
{
public:
  Null_Mutex (void) {}
  ~Null_Mutex (void) {}
  int remove (void) { return 0; }

  int acquire (void) const { return 0; }
  int try_acquire (void) const { return 0; }
  int release (void) const { return 0; }
};
```

As shown in the code above, the Null_Mutex class implements the acquire and release methods as "no-op" inline functions that are removed completely by a compiler optimizer. Section 6 illustrates the use of the Null_Mutex.

5.1.6 The Token Class

This class provides a more general-purpose synchronization mechanism than Mutexes. For example, it implements "recursive mutex" semantics, where a thread that owns the token can reacquire it without deadlocking. In addition, threads that are blocked awaiting a Token are serviced in strict FIFO order as other threads release the token. In contrast, Mutexes don't strictly enforce an acquisition order.

The interface for the Token class is shown below:

```
class Token
{
public:
  // Initialization and termination.
  Token (int = USYNC_THREAD, void * = 0);
  ~Token (void);

  // Acquire the token, sleeping until it is
  // obtained or until <timeout> expires.
  // If some other thread currently holds
  // the token then <sleep_hook> is called
  // before our thread goes to sleep.

  int acquire (void (*sleep_hook)(void *),
               void *arg = 0,
               Time_Value *timeout = 0);

  // This behaves just like the previous
  // <acquire> method, except that it
  // invokes the virtual function called
  // <sleep_hook> that can be overridden
  // by a subclass of Token.
  int acquire (Time_Value *timeout = 0);

  // This should be overridden by a subclass
  // to define the appropriate behavior before
  // <acquire> goes to sleep.  By default,
  // this is a no-op...
  virtual void sleep_hook (void);

  // An optimized method that efficiently
  // reacquires the token if no other threads
  // are waiting.  This is useful for if you
```

```
    // don't want to degrad the quality of
    // service if there are other threads
    //  waiting to get the token.
    int renew (int requeue_position = 0,
               Time_Value *timeout = 0);

    // Become interface-compliant with other
    // lock mechanisms (implements a
    // non-blocking <acquire>).
    int tryacquire (void);

    // Shuts down the Token instance.
    int remove (void);

    // Relinquish the token.  If there are any
    // waiters then the next one in line gets it.
    int release (void);

    // Return the number of threads that are
    // currently waiting to get the token.
    int waiters (void);

    // Return the id of the current thread that
    // owns the token.
    thread_t current_owner (void);
};
```

5.2 The ACE Guards Class Category

5.2.1 The Guard Classes

Compared with the C-level Solaris mutex APIs, the `Mutex` wrapper described in Section 5.1.1 provides an elegant interface for synchronizing multiple threads of control. However, `Mutex` is potentially error-prone since it is possible to forget to call the `release` method (shown in Section 3.7). This may occur either due to programmer negligence or due to the occurrence of C++ exceptions.

Therefore, to improve application robustness, the ACE synchronization facilities leverage off the semantics of C++ class constructors and destructors to ensure that `Mutex` locks will be automatically acquired and released. ACE provides a family of classes called `Guard`, `Try_Guard`, `Write_Guard`, and `Read_Guard` that ensure a lock is automatically acquired and released upon entry and exit to a block of C++ code, respectively.

The `Guard` class is the most basic guard mechanism and is defined as follows:

```
template <class LOCK>
class Guard
{
public:
  // Automatically acquire the lock.
  Guard (const LOCK &m): lock_ (m) {
    lock_.acquire ();
  }

  // Implicitly release the lock.
  ~Guard (void) {
    lock_.release ();
  }

  // Explicitly release the lock.
  int remove (void) const {
    return lock_.remove ();
  }

  // Explicitly acquire the lock.
  int acquire (void) const {
    return lock_.acquire ();
  }

  // Conditionally acquire the lock
  // (i.e., won't block).
  int try_acquire (void) const {
    return lock_.try_acquire ();
  }

  // Explicitly release the lock.
  int release (void) const {
    return lock_.release ();
  }

private:
  const LOCK &lock_;
}
```

An object of the `Guard` class defines a "block" of code over which a lock is acquired and then released automatically when the block is exited. Note that this mechanism will work for the `Mutex`, `RW_Mutex`, and `Semaphore` synchronization wrappers.

The `Read_Guard` and `Write_Guard` classes have the same interface as the `Guard` class. However, their `acquire` methods read locks and write locks, respectively.

The `Guard` class constructor shown above will block until the lock is acquired. There are cases where non-blocking acquires are necessary. Therefore, ACE provides the `Try_Guard` class, which inherits from `Guard` but uses the lock's `try_acquire` method rather than `acquire`. Callers may then use `Try_Guard`'s `locked` method to test atomically whether the lock was actually acquired or not.

```
template <class LOCK>
class Try_Guard : public Guard<LOCK>
{
public:
  // Automatically acquire the lock.
  Try_Guard (const LOCK &m): lock_ (m) {
    this->result_ = this->lock_.try_acquire ();
  }

  // Implicitly release the lock.
  ~Try_Guard (void) {
    if (this->result_ != -1)
      this->lock_.release ();
  }

  // 1 if locked, 0 if can't acquire lock
  // (errno will contain the reason for this).
  int locked (void) {
    return this->result_ != -1;
  }

private:
  int result_;
};
```

5.2.2 The Thread_Control Class

The `Thread_Control` class is used in conjunction with the `Thread_Manager` class to automate the graceful termination and cleanup of a thread's activities within its originating function. For example, `Thread_Control`'s constructor stores state information. This information automatically removes the thread from an associated Thread_Manager when the function used to invoke the thread originally terminates. This technique works correctly regardless of (1) which path through the function is executed and (2) whether exceptions are thrown. In this respect, the Thread_Control class behaves like the Guard utility class presented in Section 5.2.1.

The interface for the Thread_Control class is presented below:

```
class Thread_Control
{
public:
  // Initialize the thread control object.
  // If INSERT != 0, then register the thread
  // with the Thread_Manager.
  Thread_Control (Thread_Manager *, int add = 0);

  // Implicitly kill the thread on exit and
  // remove it from its associated Thread_Manager
  ~Thread_Control (void);

  // Explicitly kill the thread on exit and
  // remove it from its associated Thread_Manager.
  void *exit (void *status);

  // Set the exit status (and return status).
  void *set_status (void *status);

  // Get the current exit status.
  void *get_status (void);
};
```

5.3 The ACE Conditions Class Category

5.3.1 The Condition Class

The Condition class is used to block on a change in the state of a condition expression involving shared data. It encapsulates the Solaris cond_t synchronization variable. The Condition class interface is presented below:

```
template <class MUTEX>
class Condition
{
public:
  // Initialize the condition variable.
  Condition (const MUTEX &m,
             int type = USYNC_THREAD,
             void *arg = 0);

  // Implicitly destroy the condition variable.
  ~Condition (void);

  // Explicitly destroy the condition variable.
  int remove (void);

  // Block on condition, or until absolute
  // time-of-day has elapsed. If abstime
  // == 0 use blocking wait().
  int wait (Time_Value *abstime = 0) const;

  // Signal one waiting thread.
  int signal (void) const;

  // Signal *all* waiting threads.
  int broadcast (void) const;

private:
  cond_t      cond_;
  // Reference to mutex lock.
  const MUTEX &mutex_;
};
```

5.3.2 The Null_Condition Class

The Null_Condition class is a zero-cost implementation of the Condition interface described above. It's methods are all implemented as no-ops. This is useful for cases where mutual exclusion is simply not needed (*e.g.*, a particular program or service will *always* run in a single thread of control and/or will not contend with other threads for access to shared resources). The reason for having Null* classes is to allow applications to parameterize the type of synchronization they require *without* requiring changes to the application code. The Null_Condition class interface is presented below:

```
template <class MUTEX>
class Null_Condition
{
public:
  Null_Condition (const MUTEX &m,
                  int type = 0,
                  void *arg = 0) {}
  ~Null_Condition (void) {}
  int remove (void) { return 0; }
  int wait (Time_Value *abstime = 0) const {
    errno = ETIME; return -1;
  }
  int signal (void) const {
    errno = ETIME; return -1;
  }
  int broadcast (void) const {
    errno = ETIME; return -1;
  }
};
```

The Null_Condition class is identical in spirit to the Null_Mutex class described in Section 5.1.5.

5.4 The ACE Thread Managers Class Category

5.4.1 The Thread_Manager Class

The Thread_Manager class contains a set of mechanisms to manage groups of threads that collaborate to implement collective actions. For example, the Thread_Manager class provides mechanisms (such as suspend_all and resume_all) that allow any number of participating threads to be suspended and resumed atomically. The Thread_Manager class also shields applications from many incompatibilities between different flavors of multithreading mechanisms (such as POSIX threads, CMA threads, and Solaris threads).

The interface of the Thread_Manager class is illustrated below:

```
class Thread_Manager
{
public:
  // Initialize the thread manager.
```

```
  Thread_Manager (int size);

  // Implicitly destroy thread manager.
  ~Thread_Manager (void);

  // Initialize the manager with room
  // for SIZE threads.
  int open (int size = DEFAULT_SIZE);

  // Release all resources.
  int close (void);

  // Create a new thread.
  int spawn (THR_FUNC,
             long, thread_t * = 0,
             void *stack = 0,
             size_t stack_size = 0);

  // Create N new threads.
  int spawn_n (int n, THR_FUNC,
               void *args, long flags);

  // Clean up when a thread exits.
  void *exit (void *status);

  // Blocks until there are no
  // more threads running.
  void wait (void);

  // Resume all stopped threads.
  int resume_all (void);

  // Suspend all threads.
  int suspend_all (void);

  // Send signum to all stopped threads.
  int kill_all (int signal);

private:
  // ...
};
```

5.4.2 The Thread_Spawn Class

The Thread_Spawn class provides a standard utility that manages the creation of threads to handle requests from clients concurrently. This class behaves as a "thread factory", accepting connections from clients and spawning threads "on-demand" to run the service specified by a user-supplied service handler (SVC_HANDLER).

The interface for the Thread_Spawn class is presented below:

```
template <class SVC_HANDLER,
          class PEER_ACCEPTOR,
          class PEER_ADDR>
class Thread_Spawn
  : public Acceptor <SVC_HANDLER,
                     PEER_ACCEPTOR,
                     PEER_ADDR>
{
public:
  // = Initialization methods.
  Thread_Spawn (Thread_Manager *tm,
                Reactor *);
  virtual int open (const PEER_ADDR &sia,
                    Reactor *);
protected:

  virtual int handle_input (int fd);
  // Template method that accepts connection
  // and spawns a thread.

  virtual int handle_close (int fd, Reactor_Mask);
  // Called when this factory is closed down.

  virtual SVC_HANDLER *make_svc_handler (void);
  // Factory method that creates an appropriate
  // SVC_HANDLER *.

  virtual int thr_flags (void);
  // Returns the flags used to spawn a thread.
};
```

Note how this classes inherits from the ACE Acceptor class, which is a generic factory for passively connecting clients and creating service handlers [30].

5.5 The ACE Active Objects Class Category

5.5.1 The Task Class

The Task class is the central mechanism in ACE for creating user-defined *active objects* [16] and *passive objects* that process application messages. An ACE Task can perform the following activities:

- Can be dynamically linked;
- Can serve as an endpoint for I/O operations;
- Can be associated with multiple threads of control (i.e., become a so-called "active object");
- Can store messages in a queue for subsequent processing;
- Can execute user-defined services.

The Task abstract class defines an interface that is inherited and implemented by derived classes in order to provide application-specific functionality. It is an abstract class since its interface defines the pure virtual methods (open, close, put, and svc) described below. Defining Task as an abstract class enhances reuse by decoupling the application-independent components provided by the Stream class category from the application-specific subclasses that inherit from and use these components. Likewise, the use of pure virtual methods allows the C++ compiler to ensure that a subclass of Task honors its obligation to provide the following functionality:

- *Initialization and Termination Methods* – Subclasses derived from Task must implement open and close methods that perform application-specific Task initialization and termination activities. These activities typically allocate and free resources such as connection control blocks, I/O handles, and synchronization locks.

  Tasks can be defined and used either together with Modules or separately. When used with Modules they are stored in pairs: one Task subclass handles read-side processing for messages sent upstream to its Module layer and the other handles write-side processing messages send downstream to its Module layer.

The open and close methods of a Module's write-side and read-side Task subclasses are invoked automatically by the ASX framework when the Module is inserted or removed from a Stream, respectively.

- *Application-Specific Processing Methods* – In addition to open and close, subclasses of Task must also define the put and svc methods. These methods perform application-specific processing functionality on messages. For example, when messages arrive at the head or the tail of a Stream, they are escorted through a series of inter-connected Tasks as a result of invoking the put and/or svc method of each Task in the Stream.

  A put method is invoked when a Task at one layer in a Stream passes a message to an adjacent Task in another layer. The put method runs *synchronously* with respect to its caller, *i.e.*, it borrows the thread of control from the Task that originally invoked its put method. This thread of control typically originate either "upstream" from an application process, "downstream" from a pool of threads that handle I/O device interrupts [31], or internal to the Stream from an event dispatching mechanism (such as a timer-driven callout queue used to trigger retransmissions in a connection-oriented transport protocol Module).

  If an ACE Task executes as a *passive object* (*i.e.*, it always borrows the thread of control from the caller), then the Task::put method is the entry point into the Task and serves as the context in which Task executes its behavior. In contrast, if an ACE Task executes as an *active object* the Task::svc method is used to perform application-specific processing *asynchronously* with respect to other Tasks. Unlike put, the svc method is not directly invoked from an adjacent Task. Instead, it is invoked by a separate thread associated with its Task. This thread provides an execution context and thread of control for the Task's svc method. This method runs an event loop that continuously waits for messages to arrive on the Task's Message Queue (see next bullet).

  Within the implementation of a put or svc method, a message may be forwarded to an adjacent Task in the Stream via the put_next Task utility method. Put_next calls the put method of the next Task residing in an adjacent layer. This invocation of put may borrow the thread of control from the caller and handle the message immediately (*i.e.*, the synchronous processing approach illustrated in Figure 4 (1)). Conversely, the put method may enqueue the message and defer handling to its svc method that is executing in a separate thread of control (*i.e.*, the asynchronous processing approach illustrated in Figure 4 (2)). As discussed in [1], the particular processing approach that is selected has a significant impact on performance and ease of programming.

- *Message Queueing Mechanisms* – In addition to the open, close, put, and svc pure virtual method interfaces, each Task also contains a Message Queue. A Message Queue is a standard component in ACE that is used pass information between Tasks. Moreover, when a Task executes as an active object, its Message Queue is used to buffer a sequence of data messages and control messages for subsequent processing in the svc method. As messages arrive, the svc method dequeues the messages and performs the Task subclass's application-specific processing tasks.

  Two types of messages may appear on a Message Queue: simple and composite. A simple message contains a single Message Block and a composite message contains multiple Message Blocks linked together. Composite messages generally consist of a *control* block followed by one or more *data* blocks. A control block contains bookkeeping information (such as destination addresses and length fields), whereas data blocks contain the actual contents of a message. The overhead of passing Message Blocks between Tasks is minimized by passing pointers to messages rather than copying data.

  Message Queues contain a pair of high and low water mark variables that are used to implement layer-to-layer flow control between adjacent Modules in a Stream. The high water mark indicates the amount of bytes of messages the Message Queue is willing to buffer before it becomes flow controlled. The low water mark indicates the level at which a previously flow controlled Task is no longer considered to be full.

The interface of the Task class is provided below:

```
template <class SYNCH>
class Task : public Service_Object
{
public:
  // Initialization/termination methods.
  Task (Thread_Manager *thr_mgr = 0,
        Message_Queue<SYNCH> *mp = 0);
  virtual int open (void *flags = 0) = 0;
  virtual int close (u_long = 0) = 0;

  // Transfer msg into the queue to handle
  // immediate processing.
  virtual int put (Message_Block *,
                   Time_Value *tv = 0) = 0;

  // Run by a daemon thread to handle
  // deferred processing.
  virtual int svc (void) = 0;

protected:
  // Turn the task into an active object..
  int activate (long flags);

  // Routine that runs the service routine
  // as a daemon thread.
  static void *svc_run (Task<SYNCH> *);

  // Tests whether a message can be enqueue
  // without blocking.
  int can_put (Message_Block *);
```

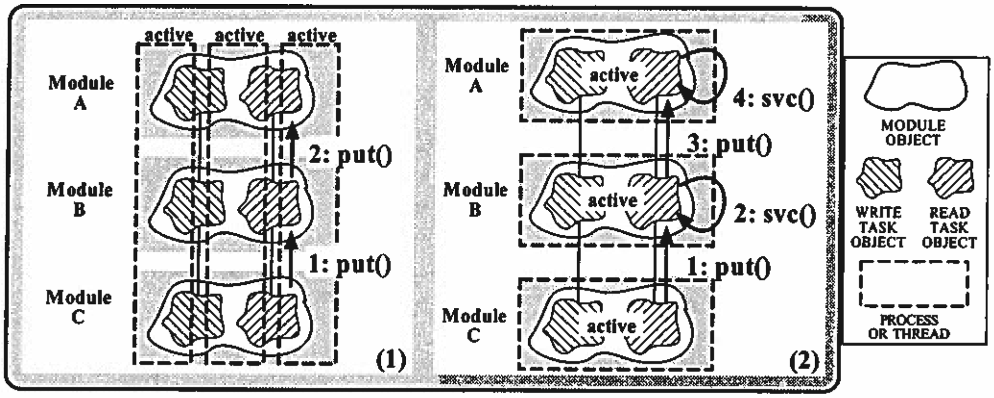

Figure 4: Alternative Methods for Invoking put and svc Methods

```
// Insert message into the message list.
int putq (Message_Block *, Time_Value * = 0);

// Extract the first message from the list.
int getq (Message_Block *&, Time_Value * = 0);

// Return a message to the queue.
int ungetq (Message_Block *,
            Time_Value * = 0);

// Transfer message to the adjacent Task
// in a Stream.
int put_next (Message_Block *,
              Time_Value * = 0);

// Turn the message back around.
int reply (Message_Block *,
           Time_Value * = 0);

// Task utility routines to identify names.
const char *name (void) const;
Task<SYNCH> *sibling (void);
Module<SYNCH> *module (void) const;

// Check if queue is a reader.
int is_reader (void);
// Check if queue is a writer.
int is_writer (void);

// Special routines corresponding to
// certain message types.
int flush (u_long flag);

// Manipulate watermarks.
void water_marks (IO_Cntl_Msg::IO_Cntl_Cmds,
                  size_t);
```

5.6 Miscellaneous ACE Concurrency Classes

5.6.1 The Thread Class Utility

The Thread class utility encapsulates the Solaris and POSIX Thr_* family of thread creation, termination, and management routines within C++ wrappers. This class provides a common interface that is mapped onto either POSIX Pthreads or Solaris threads.

The interface of the Thread class is provided below:

```
typedef void *(*THR_FUNC)(void *);

class Thread
{
public:
  // Spawn N new threads, which execute
  // "func" with argument "arg".
  static int spawn_n (size_t n, THR_FUNC func,
                      void *arg, long flags,
                      void *stack = 0,
                      size_t stack_size = 0);

  // Spawn a new thread, which executes
  // "func" with argument "arg".
  static int spawn (THR_FUNC,
                    void *arg, long,
                    thread_t * = 0,
                    void *stack = 0,
                    size_t stack_size = 0);

  // Wait for one or more threads to exit.
  static int join (thread_t, thread_t *,
                   void **);

  // Suspend the execution of a thread.
  static int suspend (thread_t);

  // Continue the execution of a
  // previously suspended thread.
  static int resume (thread_t);

  // Send signal signum to the thread.
  static int kill (thread_t, int signum);

  // Return the unique ID of the thread.
  static thread_t self (void);

  // Yield the thread to another.
  static void yield (void);

  // Exit current thread, returning "status".
  static void exit (void *status);

  // Set LWP concurrency level of the process.
  static int setconcurrency (int new_level);

  // Get LWP concurrency level of the process.
  static int getconcurrency (void);

  static int sigsetmask (int how,
                         const sigset_t *set,
                         sigset_t *oset = 0);
  // Change and/or examine calling thread's
  // signal mask.
```

```
  static int keycreate (thread_key_t *keyp,
                        void (*)(void *value));
  // Allocates a <keyp> that is used to
  // identify data that is specific to each
  // thread in the process. The key is global
  // to all threads in the process.

  static int setspecific (thread_key_t key,
                          void *value);
  // Bind value to the thread-specific data
  // key, <key>, for the calling thread.

  static int getspecific (thread_key_t key,
                          void **valuep);
  // Stores the current value bound to <key>
  // for the calling thread into the location
  // pointed to by <valuep>.
};
```

5.6.2 The Atomic_Op Class

The `Atomic_Op` class transparently parameterizes synchronization into basic arithmetic operations.

```
template <class LOCK, class TYPE>
class Atomic_Op
{
public:
  // Initialize count_ to 0.
  Atomic_Op (void);

  // Initialize count_ to c.
  Atomic_Op (TYPE c);

  // Atomically increment count_.
  TYPE operator++ (void);

  // Atomically increment count_ by inc.
  TYPE operator+= (const TYPE inc);

  // Atomically decrement count_.
  TYPE operator-- (void);

  // Atomically decrement count_ by dec.
  TYPE operator-= (const TYPE dec);

  // Atomically compare count_ with rhs.
  TYPE operator== (const TYPE rhs);

  // Atomically check if count_ >= rhs.
  TYPE operator>= (const TYPE rhs);

  // Atomically check if count_ > rhs.
  TYPE operator> (const TYPE rhs);

  // Atomically check if count_ <= rhs.
  TYPE operator<= (const TYPE rhs);

  // Atomically check if count_ < rhs.
  TYPE operator< (const TYPE rhs);

  // Atomically assign rhs to count_.
  void operator= (const TYPE rhs);

  // Atomically return count_.
  operator TYPE ();

private:
  LOCK lock_;
  TYPE  count_;
};
```

5.6.3 The Barrier Class

The `Barrier` class implements "barrier synchronization," which is particularly useful for many types of parallel scientific applications. This class allows `count` number of threads to synchronize their completion (so-called "barrier synchronization"). The implementation uses a "sub-barrier generation numbering" scheme to avoid overhead and to ensure that all threads exit the barrier correct.

```
class Barrier
{
public:
  // Initialize the barrier to
  // synchronize count threads.
  Barrier (u_int count,
           int type = USYNC_THREAD,
           void *arg = 0);

  // Block the caller until all count threads
  // have called wait() and then allow all
  // the caller threads to continue in parallel.
  int wait (void);
};
```

5.6.4 The Thread_Specific Class

The `Thread_Specific` class allows objects that are "physically" thread-specific (*i.e.*, private to a thread) to be accessed as though they were "logically" global to a program. The underlying pattern that this class is based upon is described in [29].

The following is the public interface of the ACE `Thread_Specific` class:

```
template <class TYPE>
class Thread_Specific
{
public:
  // If caller passes a non-NULL ts_obj *
  // this is used to initialize the
  // thread-specific value.  Thus, calls
  // to operator->() will return this value.
  Thread_Specific (TYPE *ts_obj = 0);

  // Get the thread-specific object for the key
  // associated with this object.  Returns 0
  // if the data has never been initialized,
  // otherwise returns a pointer to the data.
  TYPE *ts_object (void);

  // Use a "smart pointer" to obtain the
  // thread-specific object associated with
  // the key.
  TYPE *operator-> ();
};
```

6 Using the ACE OO Thread Encapsulation Library

This section presents several examples that illustrate the use of the key features in the ACE threading library. Refer back to the interfaces described in Section 5 to determine the behavior of the ACE concurrency components.

6.1 A Map Manager for Message Demultiplexing

Often, selecting a mutual exclusion mechanism with the appropriate semantics depends on the context in which a class is being used. The following example illustrates the interface and implementation of a "map manager" component in the general ACE toolkit [32]. This component is typically used in a network server to map external identifiers (such as port numbers or connection ids) onto internal identifiers (such as pointers to queues where messages are stored when outgoing links to a satellite become flow controlled). A portion of the Map_Manager interface and implementation are shown below:

```
template <class EXT_ID,
          class INT_ID,
          class LOCK>
class Map_Manager
{
public:
  // Associate EXT_ID with the INT_ID.
  int bind (EXT_ID ext_id,
            const INT_ID *int_id)
  {
    Guard<LOCK> monitor (lock_);
    // ...
  }

  // Break any association of EXT_ID.
  int unbind (EXT_ID ext_id)
  {
    Guard<LOCK> monitor (lock_);
    // ...
  }

  // Locate INT_ID associated with EXT_ID and
  // pass out parameter via INT_ID.
  // If found return 0, else -1.
  int find (EXT_ID ext_id, INT_ID &int_id)
  {
    Guard<LOCK> monitor (lock_);

    if (locate_entry (ext_id, int_id)
      // ext_id is successfully located.
      return 0;
    else
      return -1;
  }

private:
  LOCK lock_;
  // ...
};
```

One advantage of this approach is that the lock_ will be released regardless of which execution path exits a method. For example, lock_ is released properly if either arm of the if/else statement returns from the find method. In addition, this "constructor/destructor as resource acquisition/release" idiom also properly releases the lock_ if an exception is raised during processing in the definition of the locateEntry helper method. This is useful since the C++ exception handling mechanism is designed to call all necessary destructors upon exit from a block in which an exception is thrown. Note that had we written the definition of find using explicit calls to acquire and release the lock_, *i.e.*:

```
int find (EXT_ID ext_id, INT_ID &int_id)
{
  lock_.acquire ();

  if (locateEntry (ext_id, int_id)
  {
    // ext_id is successfully located.
    lock_.release ();
    return 0;
  }
  else
  {
    lock_.release ();
    return -1;
  }
}
```

the find method logic have been more contorted and less space efficient. In addition, there is no guarantee that lock_ would be released if an exception was thrown in the locateEntry method.

The type of LOCK that the Map_Manager template class is instantiated with depends upon the particular structure of parallelism in the program code when it is used. For example, in some situations it is useful to declare:

```
typedef Map_Manager <Addr, TCB, Mutex>
        MAP_MANAGER;
```

and have all calls to find, bind, and unbind automatically serialized. In other situations, it is useful to turn off synchronization without touching any existing library code by using the Null_Mutex class:

```
typedef Map_Manager <Addr, TCB, Null_Mutex>
        MAP_MANAGER;
```

In yet another situation, it may be the case that calls to find are *far* more frequent than bind or unbind. In this case, it may make sense to use the RW_Mutex readers/writer lock:

```
typedef Map_Manager <Addr, TCB, RW_Mutex>
        MAP_MANAGER;
```

Through the use of C++ wrappers and templates, we can create a highly-portable, platform-independent mutual exclusion class interface that does not impose arbitrary syntactic constraints on our use of different synchronization mechanisms. By using templates to parameterize the type of locking, little or no application code must change to accommodate new synchronization semantics. As always, however, the selection of an appropriate synchronization mechanism should be guided by thorough profiling and empirical measurements.

6.2 A Thread-safe Message Queueing Mechanism

This example illustrates the use of the ACE Condition wrapper (which encapsulates the Solaris and Pthreads cond_t condition variable mechanism) and the ACE Mutex wrapper (which encapsulates the Solaris and Pthreads mutex_t mutual exclusion mechanism).

The code is extracted from the Message_Queue class, which is contained in the Task class described in Section 5.5.1. A Message_Queue can parameterized by the type of synchronization policy needed to achieve the desired level of concurrency control. By default, the level of concurrency control is "thread-safe," as defined by the MT_Synch class in the ACE Synch.h file:

```
class MT_Synch
{
public:
  typedef Condition<Mutex> CONDITION;
  typedef Mutex MUTEX;
};
```

If MT_Synch is used to instantiate Message_Queue, all public methods will be thread-safe, with the corresponding overhead that implies. In contrast, if the Null_Synch class is used to instantiate Message_Queue, all public methods will not be thread-safe, and there will be no additional overhead. Null_Synch is also defined in Synch.h, as follows:

```
class Null_Synch
{
public:
  typedef Null_Condition<Null_Mutex> CONDITION;
  typedef Null_Mutex MUTEX;
};
```

An example use of Message_Queue appeared in the run_svc function at the beginning of Section 3.5. Message_Queue is modeled after the message queueing and buffer management facilities provided by System V STREAMS [33] and BSD UNIX [34].

An ACE Message_Queue is composed of one or more Message_Blocks that are linked together by prev_ and next_ pointers. In addition, a Message_Block may also be linked to a chain of other Message_Blocks. This structure enables efficient manipulation of arbitrarily-large messages *without* incurring a great deal of memory copying overhead.

```
// The contents of a message are represented
// internally by a Message_Block.

class Message_Block
{
public:
  Message_Block (size_t size,
                 Message_Type type = MB_DATA,
                 Message_Block *cont = 0,
                 char *data = 0);
  // ...
};

// A Message_Queue is a thread-safe queueing
// facility for messages.  Note the use of
// the C++ "traits" idiom to combine both the
// Condition and Mutex types into a single
// template parameter.

template <class SYNCH = MT_Synch>
class Message_Queue
{
public:
  // Default high and low water marks.
  enum
  {
    // 0 is the low water mark.
    DEFAULT_LWM = 0,
    // 1 K is the high water mark.
    DEFAULT_HWM = 4096,
    // Message queue was active
    // before activate() or deactivate().
    WAS_ACTIVE   = 1,
    // Message queue was inactive
    // before activate() or deactivate().
    WAS_INACTIVE = 2
  };

  // Initialize a Message_Queue.
  Message_Queue (size_t hwm = DEFAULT_HWM,
                 size_t lwm = DEFAULT_LWM);

  // Destroy a Message_Queue.
  ~Message_Queue (void);

  /* Checks if queue is full/empty. */
  int is_full (void) const;
  int is_empty (void) const;

  // Enqueue and dequeue a Message_Block *.
  int enqueue_tail (Message_Block *new_item,
                    Time_Value *tv = 0);
  int enqueue_head (Message_Block *new_item,
                    Time_Value *tv = 0);
  int dequeue_head (Message_Block *&first_item,
                    Time_Value *tv = 0);

  // Deactivate the queue and wakeup all threads
  // waiting on the queue so they can continue.
  int deactivate (void);

  // Reactivate the queue so that threads can
  // enqueue and dequeue messages again.
  int activate (void);

private:
  // Routines that actually do the enqueueing
  // and dequeueing (assumes locks are held).
  int enqueue_tail_i (Message_Block *);
  int enqueue_head_i (Message_Block *);
  int enqueue_head_i (Message_Block *&);

  // Check the boundary conditions.
  int is_empty_i (void) const;
  int is_full_i (void) const;

  // Implement activate() and deactivate()
  // methods (assumes locks are held).
  int deactivate_i (void);
  int activate_i (void);

  // Pointer to head of Message_Block list.
  Message_Block *head_;
  // Pointer to tail of Message_Block list.
  Message_Block *tail_;
  // Lowest number before unblocking occurs.
  int low_water_mark_;
  // Greatest number of bytes before blocking.
  int high_water_mark_;
  // Current number of bytes in the queue.
  int cur_bytes_;
  // Current number of messages in the queue.
  int cur_count_;
  // Indicates that the queue is inactive.
  int deactivated_;

  // C++ wrapper synchronization primitives
```

```
  // for controlling concurrent access.
  SYNCH::MUTEX     lock_;
  SYNCH::CONDITION notempty_cond_;
  SYNCH::CONDITION notfull_cond_;

};
```

The implementation of the Message_Queue class is shown below. Note how this class utilizes the OO pattern whereby public methods acquire locks and private methods assume that locks are held.

```
// Create an empty message list and
// initialize the Condition objects (note
// that Mutex lock_ is automatically
// created by its default constructor...).

template <class SYNCH>
Message_Queue::Message_Queue (size_t hwm,
                              size_t lwm)
  : notfull_cond_ (lock_),
    notempty_cond (lock_)
{
  // ...
}

// Check if queue empty (does not hold locks).

template <class SYNCH> int
Message_Queue<SYNCH>::is_empty_i (void) const
{
  return cur_bytes_ <= 0 && cur_count_ <= 0;
}

// Check if queue is full, i.e., it has more
// than high_water_mark_ bytes in it...
// (does not hold locks).

template <class SYNCH> int
Message_Queue<SYNCH>::is_full_i (void) const
{
  return cur_bytes_ > high_water_mark_;
}

/* Check if queue is empty (holds locks) */

template <class SYNCH> int
Message_Queue<SYNCH>::is_empty (void) const
{
  Guard<SYNCH::MUTEX> monitor (lock_);
  return is_empty_i ();
}

/* Check if queue is full (holds locks) */

template <class SYNCH> int
Message_Queue<SYNCH>::is_full (void) const
{
  Guard<SYNCH::MUTEX> monitor (lock_);
  return full ();
}

// Deactivate the queue and wakeup all threads
// waiting on the queue so they can continue.
// No messages are removed from the queue.
// Any other operations called until the queue is
// activated again will immediately return -1 with
// <errno> == ESHUTDOWN.  Returns WAS_INACTIVE if
// queue was inactive before the call and
// WAS_ACTIVE if queue was active before the call.

template <class SYNCH> int
Message_Queue<SYNCH>::deactivate (void)
{
  ACE_MT (Guard<SYNCH::MUTEX> m (this->lock_));
  return this->deactivate_i ();
}

// Implementation of the public deactivate()
// method (assumes locks are held).

template <class SYNCH> int
Message_Queue<SYNCH>::deactivate_i (void)
{
  int current_status = this->deactivated_
    ? WAS_INACTIVE : WAS_ACTIVE;

  // Wake up all the waiters.
  this->notempty_cond_.broadcast ();
  this->notfull_cond_.broadcast ();

  this->deactivated_ = 1;
  return current_status;
}

// Reactivate the queue so that threads can
// enqueue and dequeue messages again.  Returns
// WAS_INACTIVE if queue was inactive before
// the call and WAS_ACTIVE if queue was active
// before the call.

template <class SYNCH> int
Message_Queue<SYNCH>::activate (void)
{
  ACE_MT (Guard<SYNCH::MUTEX> m (this->lock_));
  return this->activate_i ();
}

template <class SYNCH> int
Message_Queue<SYNCH>::activate_i (void)
{
  int current_status =
    this->deactivated_ ? WAS_INACTIVE : WAS_ACTIVE;
  this->deactivated_ = 0;
  return current_status;
}

// Queue new item at the front of the list.

template <class SYNCH> int
Message_Queue<SYNCH>::enqueue_head
  (Message_Block *new_item, Time_Value *tv)
{
  Guard<SYNCH::MUTEX> monitor (lock_);

  if (this->deactivated_) {
    errno = ESHUTDOWN;
    return -1;
  }

  // Wait while the queue is full.

  while (is_full_i ()) {
    // Release the lock_ and wait for
    // timeout, signal, or space becoming
    // available in the list.
    if (notfull_cond.wait (tv) == -1) {
      if (errno == ETIME)
        errno = EWOULDBLOCK;
      return -1;
    }
    if (this->deactivated_) {
      errno = ESHUTDOWN;
      return -1;
    }
  }
```

```
    // Actually enqueue the message at the
    // head of the list.
    int list_was_empty
      = enqueue_head_i (new_item);

    if (list_was_empty > 0)
      // Tell any blocked threads that the
      // queue has a new item!
      notempty_cond.signal ();

    return list_was_empty;
  }

  // Queue new item at the end of the list.
  // If tv == 0, the caller will block until
  // action is possible, else will wait for
  // amount of time in *tv).  Calls will return,
  // however, when queue is closed, when a signal
  // occurs, or if the time specified in tv
  // elapses (and errno = EWOULDBLOCK).

  template <class SYNCH> int
  Message_Queue<SYNCH>::enqueue_tail
    (Message_Block *new_item, Time_Value *tv)
  {
    Guard<SYNCH::MUTEX> monitor (lock_);

    if (this->deactivated_) {
      errno = ESHUTDOWN;
      return -1;
    }
    // Wait while the queue is full.

    while (is_full_i ()) {
      // Release the lock_ and wait for
      // timeout, signal, or space becoming
      // available in the list.
      if (notfull_cond.wait (tv) == -1) {
        if (errno == ETIME)
          errno = EWOULDBLOCK;
        return -1;
      }
      if (this->deactivated_) {
        errno = ESHUTDOWN;
        return -1;
      }
    }

    // Actually enqueue the message at
    // the end of the list.
    int list_was_empty
      = enqueue_tail_i (new_item);

    if (list_was_empty > 0)
      // Tell any blocked threads that
      // the queue has a new item!
      notempty_cond.signal ();

    return list_was_empty;
  }

  // Dequeue the front item on the list
  // and return it to the caller.

  template <class SYNCH> int
  Message_Queue<SYNCH>::dequeue_head
    (Message_Block *&first_item, Time_Value *tv)
  {
    Guard<SYNCH::MUTEX> monitor (lock);

    // Wait while the queue is empty.
```

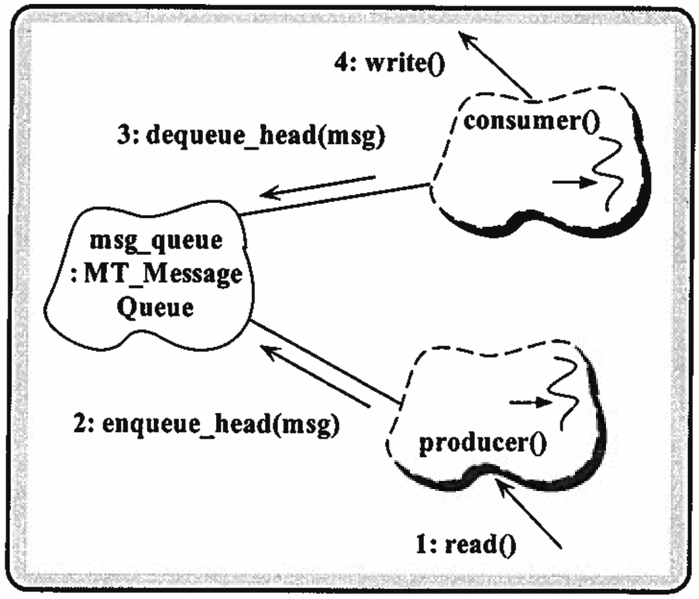

Figure 5: Concurrent Producer and Consumer

```
    while (is_empty_i ()) {
      // Release the lock_ and wait for
      // timeout, signal, or a new message
      // being placed in the list.

      if (notempty_cond.wait (tv) == -1) {
        if (errno == ETIME)
          errno = EWOULDBLOCK;
        return -1;
      }
      if (this->deactivated_) {
        errno = ESHUTDOWN;
        return -1;
      }
    }

    // Actually dequeue the first message.
    int list_was_full
      = dequeue_head_i (first_item);

    if (list_was_full > 0)
      // Tell any blocked threads that
      // the queue is no longer full.
      notfull_cond.signal ();

    return list_was_full;
  }
```

The following code illustrates an ACE implementation of the classic "bounded buffer" program using a Message_Queue. The program uses two threads to concurrently copy stdin to stdout. Figure 5 illustrates the relations between the ACE components that run concurrently. The producer thread reads data from the stdin stream, creates a message, and then queues the message in the Message_Queue. The consumer thread dequeues the message and writes it to stdout. To save space, most of the error checking has been omitted.

```
#include "Message_Queue.h"
#include "Thread_Manager.h"
```

```
typedef Message_Queue<MT_Synch> MT_Message_Queue;

// Global thread manager.
static Thread_Manager thr_mgr;

// Read data from stdin into a message and queue
// the message for the consumer.  A NULL pointer
// is enqueued when there is no more data to
// read.  The consumer then knows to exit.

static void *
producer (MT_Message_Queue *msg_queue)
{
  // Insert thread into thr_mgr.
  Thread_Control tc (&thr_mgr);
  char buf[BUFSIZ];

  for (int n; ; ) {
    // Allocate a new message.
    Message_Block *mb
      = new Message_Block (BUFSIZ);

    n = read (0, mb->rd_ptr (), mb->size ());
    if (n <= 0) {
      // Shutdown message to the other
      // thread and exit.
      mb->length (0);
      msg_queue->enqueue_tail (mb);
    }

    // Send the message to the other thread.
    else {
      mb->wr_ptr (n);
      msg_queue->enqueue_tail (mb);
    }
  }

  // The destructor of Thread_Control removes
  // the exiting thread from the
  // Thread_Manager automatically.
  return 0;
}

// The consumer dequeues a message from the
// Message_Queue, writes the message to the
// stderr stream, and deletes the message.
// The producer sends a NULL pointer to informs
// the consumer to stop reading and exit.

static void *consumer
  (MT_Message_Queue *msg_queue)
{
  Message_Block *mb = 0;
  // Insert thread into thr_mgr.
  Thread_Control tc (&thr_mgr);
  int result = 0;

  // Keep looping, reading a message out
  // of the queue, until we timeout or get a
  // message with a length == 0, which signals
  // us to quit.

  for (;;)
    {
      result = msg_queue->dequeue_head (mb);
      if (result == -1)
        return -1;

      int length = mb->length ();

      if (length > 0)
        ::write (1, mb->rd_ptr (), length);

      delete mb;

      if (length == 0)
        break;
    }

  // The destructor of Thread_Control removes
  // the exiting thread from the
  // Thread_Manager automatically.
  return 0;
}

// Spawn off two threads that copy
// stdin to stdout.

int main (int argc, char *argv[])
{
  // Use the thread-safe instantiation
  // of Message_Queue.
  Message_Queue msg_queue;

  thr_mgr.spawn (THR_FUNC (producer),
                 (void *) &msg_queue,
                 THR_NEW_LWP | THR_DETACHED);
  thr_mgr.spawn (THR_FUNC (consumer),
                 (void *) &msg_queue,
                 THR_NEW_LWP | THR_DETACHED);

  // Wait for producer/consumer threads to exit.
  thr_mgr.wait ();
  return 0;
}
```

6.3 A Concurrent Network Database Server

The following example illustrates a concurrent network database server developed using the ACE thread management components. Client requests trigger the server to lookup "employees" by their unique numerical ID. If there is a match, the name is returned to the client.

Each client request to the server is run in parallel. This example illustrates the use of the `Thread_Manager` and the `Thread_Control` classes. In addition, it also illustrates the use of the ACE C++ wrapper classes for sockets [35].

The code shown below is intentionally simplified for this example and does not represent how a highly robust and efficient implementation would be developed. For example, a production implementation would place an upper-bound on the number of spawned bound threads to avoid consuming large amounts of kernel resources. In addition, a production implementation would clearly use a more sophisticated database scheme.

```
#include "SOCK_Acceptor.h"
#include "Thread_Manager.h"

// Per-process thread manager.
Thread_Manager thr_mgr;

// Function called when a new thread is created.
// This function is passed a connected client
// SOCK_Stream, which it uses to receive a
// database lookup request from a client.

static void *
lookup_name (SOCK_Stream new_stream)
{
```

```
  // Local thread control object.
  Thread_Control tc (&thr_mgr);

  enum {
    // Maximum line we'll read from a client.
    MAXLINE     = 255,
    // Maximum size of employee name.
    EMPNAMELEN = 512
  };

  // Simple read-only database.
  static struct
    {
      int emp_id;
      const char emp_name[EMPNAMELEN];
    } emp_db[] =
      {
        123, "John Wayne Bobbit",
        124, "Cindy Crawford",
        125, "O. J. Simpson",
        126, "Bill Clinton",
        127, "Rush Limbaugh",
        128, "Michael Jackson",
        129, "George Burns",
        0, ""
      };

  int n;
  int emp_id;
  int found;
  char recvline[MAXLINE];
  char sendline[MAXLINE];

  n = new_stream.recv (recvline, MAXLINE)
  emp_id = atoi (recvline);
  found = 0;

  for (int index = 0;
       found == 0 && emp_db[index].emp_id;
       index++)
    if (emp_id == emp_db[index].emp_id) {
      found = 1;
      n = sprintf (sendline, "%s",
                   emp_db[index].emp_name);
    }

  if (found == 0)
    n = sprintf (sendline, "%s", "ERROR");

  new_stream.send (sendline, n + 1, 0);
  new_stream.close ();

  // The destructor of Thread_Control removes the
  // exiting thread from the Thread_Manager
  // automatically.
  return 0;
}

// Default port number.
static const int default_port = 5000;

int
main (int argc, char *argv[])
{
  // Port number of server.
  u_short port = argc > 1
    ? atoi (argv[1]) : default_port;

  // Internet address of server.
  INET_Addr addr (port);

  // Passive-mode listener object.
  SOCK_Acceptor server (addr);

  // Connected client.
  SOCK_Stream new_stream;

  // Wait for a connection from a client
  // (this illustrates a concurrent server).

  for (;;) {
    // Accept a connection from a client.
    server.accept (new_stream);

    // Spawn off a thread-per client request.
    thr_mgr.spawn (THR_FUNC (lookup_name),
                   new_stream,
                   THR_BOUND | THR_DETACHED);
  }
  // NOTREACHED
  return 0;
}
```

7 Concluding Remarks

This paper motivates and describes the object-oriented thread encapsulation class library provided in ACE. The ACE thread class library provides several benefits to developers:

- Improve the consistency of programming style by enabling developers to use C++ and OO throughout their concurrent applications.
- Reduce the amount of obtrusive changes to make applications thread-safe. For example, utility classes in the library (such as `Atomic_Op`, `Mutex`, `RW_Mutex`, `Semaphore`, and `Condition`) improve the portability and reusability of the underlying Solaris 2.x concurrency mechanisms.
- Eliminate or minimize the potential for subtle synchronization errors. Several of the ACE thread library classes (such as `Guard` and `Thread_Control`) ensure that resources (such as locks and library data structures) are allocated and released properly, even if exceptions occur.
- Enhance abstraction and modularity *without* compromising performance. Using C++ language features (such as inline functions and templates) ensures that the additional functionality provided by the ACE OO thread library does not reduce efficiency significantly.

The ACE OO thread encapsulation library has been used on a number of commercial projects. These products include the Ericsson EOS family of telecommunication switch monitoring applications, Bellcore ATM switch management software, the network management subsystem and core infrastructure subsystem of the Motorola Iridium global personal communications system, and enterprise-wide electronic medical imaging systems at Kodak and Siemens.

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