

ACCU
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AN INTRODUCTION TO MULTITHREADING IN C++20

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Assumptions

- New project
- C++20 compiler and library

An introduction to multithreading in C++20

- Choosing your Concurrency Model
- Starting and Managing Threads
- Synchronizing Data

Choosing your Concurrency Model

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- Scalability
- Separation of Concerns

These reasons inform our choice of model.

Multithreading for Scalability

If you want Scalability, then Amdahl's law applies:

$$S = \frac{1}{1 - p + \frac{p}{n}}$$

S = Maximum speedup multiplier

p = Fraction of program that can be parallelized

n = Number of processors

Multithreading for Scalability

If you want Scalability, then Amdahl's law applies:

$$S = \frac{1}{1 - 0.9 + \frac{0.9}{n}}$$

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If you want Scalability, then Amdahl's law applies:

$$S = \frac{1}{1 - 0.9 + \frac{0.9}{1000}}$$

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Multithreading for Scalability

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$$9.91 = \frac{1}{1 - 0.9 + \frac{0.9}{1000}}$$

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Multithreading for Scalability

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$$9.999 = \frac{1}{1 - 0.9 + \frac{0.9}{100000}}$$

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Multithreading for Scalability

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$$99.9 = \frac{1}{1 - 0.99 + \frac{0.99}{100000}}$$

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Parallel Algorithms

Many standard library algorithms have parallel versions:

```
std::vector<MyData> data= ...;  
std::sort(  
    std::execution::par,  
    data.begin(), data.end(),  
    MyComparator{});
```

Independent Tasks

Split your work into many independent tasks and use a (non-standard) thread pool.

```
thread_pool tp;
```

```
void foo(){  
    execute(tp, []{ do_work(); });  
    execute(tp, []{ do_other_work(); });  
}
```

Separation of Concerns

- Raw performance not a priority
- Large sequential tasks that can run concurrently “in the background”

Dedicated Threads

Run each long-running task on its own thread.

```
std::jthread gui{[]{ run_gui(); });  
std::jthread printing{[]{ do_printing(); });
```

Starting and Managing Threads

Starting and Managing Threads

Cooperative Cancellation

Cooperative Cancellation

- GUIs often have “Cancel” buttons for long-running operations.
- You don't need a GUI to want to cancel an operation.
- Forcibly stopping a thread is undesirable

Cooperative Cancellation Types

C++20 provides `std::stop_source` and `std::stop_token` to handle cooperative cancellation.

Purely cooperative: if the target task doesn't check, nothing happens.

Cooperative Cancellation Usage

- 1 Create a `std::stop_source`

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- ❺ Periodically call `token.stop_requested()` to check
⇒ Stop the task if stopping requested

Cooperative Cancellation Usage

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- ❹ When you want the operation to stop call `source.request_stop()`
- ❺ Periodically call `token.stop_requested()` to check
⇒ Stop the task if stopping requested
- ❻ If you do not check `token.stop_requested()`, nothing happens

Cancellation Example

```
void stoppable_func(std::stop_token st){  
    while(!st.stop_requested()){  
        do_stuff();  
    }  
}
```

```
void stopper(std::stop_source source){  
    while(!done()){  
        do_something();  
    }  
    source.request_stop();  
}
```

Custom Cancellation

You can also use `std::stop_callback` to provide your own cancellation mechanism. e.g. to cancel some async IO.

```
Data read_file(  
    std::stop_token st,  
    std::filesystem::path filename ){  
    auto handle=open_file(filename);  
    std::stop_callback cb(st,[&]{ cancel_io(handle);});  
    return read_data(handle); // blocking  
}
```

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`std::async` can be used where you want a result.

`std::thread` should only be used if you have no choice.

std::jthread — Overview

Creating a `std::jthread` object starts the thread.

```
std::jthread t{my_func, arg1, arg2};
```

Runs `my_func(stop_token, arg1, arg2)` on the new thread.

std::jthread — Overview

Creating a `std::jthread` object starts the thread.

```
std::jthread t{my_func, arg1, arg2};
```

Runs `my_func(stop_token, arg1, arg2)` on the new thread.

Or runs `my_func(arg1, arg2)` on the new thread.

std::jthread — Basic API

std::jthread default constructor

Create an empty object with no thread

std::jthread x{Callable, Args...}

Create a new `std::stop_source` — `src`

Create a new thread running `Callable(src.get_token(), Args...)`
or `Callable(Args...)`

std::jthread destructor

Calls `src.request_stop()` and waits for the owned thread to finish

x.get_id()

Obtains the thread ID of the owned thread

x.join()

Wait for the owned thread to finish

`std::jthread` is a value type

`std::jthread` is a **handle**.

It is **movable** $\Rightarrow$

- Ownership can be transferred
- Can be stored in containers (e.g. `std::vector<std::jthread>`)
- no need to use `new`

Threads: Callables and Arguments

The callable and arguments are **copied** into storage local to the new thread.

This helps avoid dangling references and race conditions.

Use `std::ref` when you really want a reference. Or use a lambda.

std::jthread destructor semantics

The destructor will request stop and wait for the thread to finish:

```
void thread_func(  
    std::stop_token st,  
    std::string arg1,int arg2){  
    while(!st.stop_requested()){  
        do_stuff(arg1,arg2);  
    }  
}  
  
void foo(std::string s){  
    std::jthread t(thread_func,s,42);  
    do_stuff();  
} // destructor requests stop and joins
```

Cancellation and `std::jthread`

`std::jthread` integrates with `std::stop_token` to support cooperative cancellation.

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- Starting a thread with `std::jthread` implicitly creates a `std::stop_source`.
- A stop token obtained from `source.get_token()` is passed to your thread function as an **optional** first parameter.
- Destroying a `std::jthread` calls `source.request_stop()` and `thread.join()`.

The thread still needs to check the stop token passed in to the thread function.

std::jthread — Cancellation API

Given

```
std::jthread x{some_callable};
```

```
x.get_stop_source()
```

obtain the stop source for the thread

```
x.get_stop_token()
```

obtain a stop token for the thread

```
x.request_stop()
```

equivalent to `x.get_stop_source().request_stop()`

Synchronization facilities

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Unsynchronized access to a memory location from more than thread, where at least one thread is writing.

All data races are undefined behaviour $\Rightarrow$ we need synchronization.

Synchronization facilities

C++ provides a bunch of synchronization facilities:

- Latches
- Barriers
- Futures
- Mutexes
- Semaphores
- Atomics

Latches

Latches

`std::latch` is a single-use counter that allows threads to wait for the count to reach zero.

- ❶ Create the latch with a non-zero count
- ❷ One or more threads decrease the count
- ❸ Other threads may wait for the latch to be signalled.
- ❹ When the count reaches zero it is permanently signalled and all waiting threads are woken.

Latch API

```
std::latch x{count}
```

Create a latch with the specified count

```
x.count_down()
```

Decrease the count. Trigger latch if count reaches zero

```
x.wait()
```

Wait for the latch to be triggered.

```
x.arrive_and_wait()
```

`x.count_down()` then `x.wait()`

Waiting for tasks with a latch

```
void foo(){
    unsigned const thread_count=...;
    std::latch done(thread_count);
    std::vector<std::optional<my_data>> data(thread_count);
    std::vector<std::jthread> threads;
    for(unsigned i=0;i<thread_count;++i)
        threads.push_back(std::jthread([&,i]{
            data[i]=make_data(i);
            done.count_down();
            do_more_stuff();
        }));
    done.wait();
    process_data(data);
}
```

Synchronizing Tests with Latches

Using a latch is great for multithreaded tests:

- ❶ Set up the test data
- ❷ Create a latch
- ❸ Create the test threads
⇒ The first thing each thread does is
`test_latch.arrive_and_wait()`
- ❹ When all threads have reached the latch they are unblocked to run their code

Barriers

Barriers

`std::barrier<>` is a reusable barrier.

Synchronization is done in **phases**:

- ❶ Construct a barrier, with a non-zero count and a **completion function**
 - ❷ One or more threads arrive at the barrier
 - ❸ Some of these threads wait for the barrier to be signalled
 - ❹ When the count reaches zero, the barrier is signalled, the **completion function** is called and the count is reset
- 

Barrier API

```
std::barrier<task_type> x{count, task}
```

Create a barrier with the specified count and completion function

```
auto arrival_token=x.arrive()
```

Decrease the count. Trigger completion phase if count reaches zero

```
x.wait(arrival_token)
```

Wait for the completion phase to be complete.

```
x.arrive_and_wait()  
x.wait(x.arrive())
```

```
x.arrive_and_drop()
```

Decrease the count permanently (and potentially trigger completion phase)

without waiting.

Barriers and Loops

Barriers are great for loop synchronization between parallel tasks.

The **completion function** allows you to do something between loops: pass the result on to another step, write to a file, etc. It is run on **one of the participating threads**.

Barrier Example

```
unsigned const num_threads=...;  
void finish_task();
```

```
std::barrier<std::function<void()>> b(  
    num_threads, finish_task);
```

```
void worker_thread(std::stop_token st, unsigned i){  
    while(!st.stop_requested()){  
        do_stuff(i);  
        b.arrive_and_wait();  
    }  
}
```

Futures

Futures

Futures provide a mechanism for a one-shot transfer of data between threads.

- `std::async` — launch a task that returns a value
- `std::promise` — explicitly set a value
- `std::packaged_task` — wrap a task that returns a value

All of these give you a `std::future<T>` for the result.

std::future<T> — Basic API

`std::future<T>` default constructor

Create an empty object with no state

`f.valid()`

Check if the future has state

`f.wait()`

Wait for the data to be ready

`f.wait_for(duration)`

Wait for the data to be ready for the specified duration

`f.wait_until(time_point)`

Wait for the data to be ready until the specified time

`x.get()`

Wait for the data and retrieve it

Using futures

Futures provide blocking waits and polling for data:

```
void blocking(std::future<int> f){  
    f.wait(); // can be omitted  
    do_stuff(f.get()); // blocks until ready  
}
```

```
void polling(std::future<int> f){  
    if(f.wait_for(0s) == std::future_status::ready){  
        do_stuff(f.get());  
    }  
}
```

`std::promise<T>` — Basic API

`std::promise<T>` default constructor

Create an object with an empty state

`p.valid()`

Check if the promise has state

`p.set_value()`

Set the value in the state

`p.set_exception(ex_ptr)`

Set the exception in the state

`p.get_future()`

Get the `std::future<T>` for the state

Passing data with Futures

```
std::promise<MyData> prom;  
std::future<MyData> f=prom.get_future();
```

```
std::jthread thread1{[f=std::move(f)]{  
    do_stuff(f.get());  
}};
```

```
std::jthread thread2{[&prom]{  
    prom.set_value(make_data());  
}};
```

Passing exceptions with Futures

```
std::promise<MyData> prom;  
std::future<MyData> f=prom.get_future();  
  
std::jthread thread1{[f=std::move(f)]{  
    do_stuff(f.get()); // throws my_exception  
}};  
  
std::jthread thread2{[&prom]{  
    prom.set_exception(  
        std::make_exception_ptr(my_exception{}));  
}};
```

Launching tasks with `std::async`

`std::async` can be used to create threads.

```
// Call func(arg1,arg2) on a new thread
auto f=std::async(std::launch::async,
    func,arg1,arg2);
```

- `f.get()` will return the result of the call to `func`
- `f` owns the thread. Similar to `jthread` — the destructor will wait for the thread to exit.

`std::future<T>` is one-shot

After calling `f.get()`, a `std::future` no longer holds a value.

```
std::promise<MyData> prom;  
std::future<MyData> f=prom.get_future();
```

```
do_stuff(f.get());  
assert(!f.valid());  
f.get(); // error, will throw
```

std::shared_future<T>

`std::shared_future` allows multiple threads to receive the same result.

```
std::promise<MyData> prom;  
std::shared_future<MyData> f=  
    prom.get_future().share();
```

```
std::jthread thread1{[f]{ do_stuff(f.get()); } };  
std::jthread thread2{[f]{ do_stuff(f.get()); } };
```

Mutexes

Mutexes

Mutex: **M**utual **E**xclusion

A mutex is a means of **preventing** concurrent execution.

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A mutex is a means of **preventing** concurrent execution.

⇒ we should use them as sparingly as possible.

C++ Mutexes

C++ provides 6 mutex types. For most code that is 5 too many.

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- `std::mutex` $\Leftarrow$ Use this one
- `std::timed_mutex`
- `std::recursive_mutex`
- `std::recursive_timed_mutex`
- `std::shared_mutex`
- `std::shared_timed_mutex`

Locking mutexes

Locking and unlocking is done via RAII types.

- `std::scoped_lock` $\Leftarrow$ use this one
- `std::unique_lock`
- `std::lock_guard`
- `std::shared_lock`

Locking example

```
int some_data;  
std::mutex some_data_mutex;  
  
void add_to_data(int delta){  
    std::scoped_lock lock(some_data_mutex); // locks  
    some_data+=delta;  
} // unlocks mutex in lock destructor
```

Locking multiple mutexes

```
class account
{
    std::mutex m;
    currency_value balance;
public:
    friend void transfer(account& from, account& to,
        currency_value amount)
    {
        std::scoped_lock lock_from(from.m);
        std::scoped_lock lock_to(to.m);
        from.balance -= amount;
        to.balance += amount;
    }
};
```

Locking multiple mutexes

Thread 1	Thread 2
Calls <code>transfer(a1, a2, v1)</code>	Calls <code>transfer(a2, a1, v2)</code>
Locks <code>a1.m</code>	Locks <code>a2.m</code>
Tries to lock <code>a2.m</code> <i>Blocks</i>	Tries to lock <code>a1.m</code> <i>Blocks</i>

DEADLOCK

Locking multiple mutexes

```
class account
{
    std::mutex m;
    currency_value balance;
public:
    friend void transfer(account& from, account& to,
        currency_value amount)
    {
        std::scoped_lock locks(from.m, to.m);
        from.balance -= amount;
        to.balance += amount;
    }
};
```

Waiting for Data

Waiting for Data

How do you wait for data to be ready?

Busy wait?

```
std::mutex m;  
std::optional<Data> data;  
  
void busy_wait(){  
    while(true){  
        std::scoped_lock lock(m);  
        if(data.has_value()) break;  
    }  
    process_data();  
}
```

Busy waiting is bad

Busy waiting:

- Consumes CPU time waiting
- Wastes electricity
- Delays the notification

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`std::condition_variable` provides notifications to avoid busy waiting.

Condition Variables optimize waiting

```
std::mutex m;  
std::condition_variable cond;  
std::optional<Data> data;  
  
void cv_wait(){  
    std::unique_lock lock(m);  
    cond.wait(lock, []{return data.has_value();});  
    process_data();  
}
```

Condition Variable notifications

`std::condition_variable` must be notified.

```
void cv_notify(){  
    {  
        std::scoped_lock lock(m);  
        data = make_data();  
    }  
    cond.notify_one();  
}
```

Cancelling Waits

Handling cancellation with busy waits is easy:

```
void busy_wait(std::stop_token token){  
    while(true){  
        if(token.stop_requested()) return;  
        std::scoped_lock lock(m);  
        if(data.has_value()) break;  
    }  
    process_data();  
}
```

For condition variables we need

`std::condition_variable_any`.

Cancelling Condition Variable Waits

```
std::condition_variable_any cond;

void cv_wait(std::stop_token token){
    std::unique_lock lock(m);
    if(!cond.wait(lock, token,
        []{return data.has_value();}))
        return;
    process_data();
}
```

Semaphores

Semaphores

A semaphore represents a number of available “slots”. If you **acquire** a slot on the semaphore then the count is decreased until you **release** the slot.

Attempting to acquire a slot when the count is zero will either block or fail.

A thread may release a slot without acquiring one and vice versa.

Semaphores II

Semaphores can be used to build just about any synchronization mechanism, including latches, barriers and mutexes.

See [The Little Book Of Semaphores](#).

Mostly you are better off using the higher level structures.

A **binary semaphore** has 2 states: 1 slot free or no slots free. It can be used as a mutex.

Semaphores in C++20

C++20 has `std::counting_semaphore<max_count>`
`std::binary_semaphore` is an alias for `std::counting_semaphore<1>`.

As well as **blocking** `sem.acquire()`, there are also `sem.try_acquire()`, `sem.try_acquire_for()` and `sem.try_acquire_until()` functions that fail instead of blocking.

Semaphore Example

```
std::counting_semaphore<5> slots(5);  
  
void func(){  
    slots.acquire();  
    do_stuff(); // at most 5 threads can be here  
    slots.release();  
}
```

Atomics

Atomics

Atomic variables are the lowest level of synchronization primitive.

In C++ they are written `std::atomic<T>`.

T must be **Trivially copyable**, and **Bitwise comparable**.

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In C++ they are written `std::atomic<T>`.

`T` must be **Trivially copyable**, and **Bitwise comparable**.

Except `T` can also be `std::shared_ptr<U>` or `std::weak_ptr<U>`.

Lock free or not?

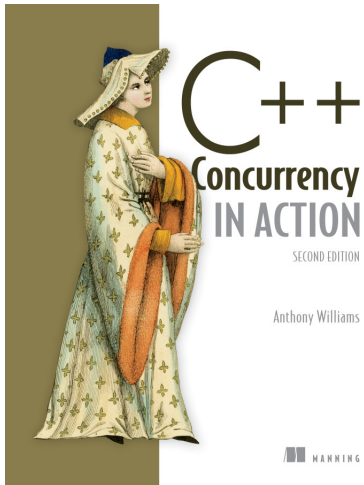
`std::atomic<T>` may not be lock-free — may use an internal mutex.

`std::atomic_flag`, `std::atomic_signed_lock_free` and `std::atomic_unsigned_lock_free` are only guaranteed lock-free types.

Only most platforms `std::atomic<integral-type>` and `std::atomic<T*>` are lock-free.

Can query with `std::atomic<T>::is_always_lock_free`.

My Book



C++ Concurrency in Action
Second Edition

Covers C++17 and the
first Concurrency TS
C++20 Addendum coming soon!

cplusplusconcurrencyinaction.com

Questions?

Summary

Summary

- Avoid managing your own threads if you can
- Use `std::jthread` for threads
- Use `std::stop_token` for cancellation
- Use `std::future`, `std::latch` and `std::barrier` where you can
- Use `std::mutex` almost everywhere else
- Use `std::atomic` in rare cases