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## Parallel & Distributed Real-Time Systems

Lecture #4

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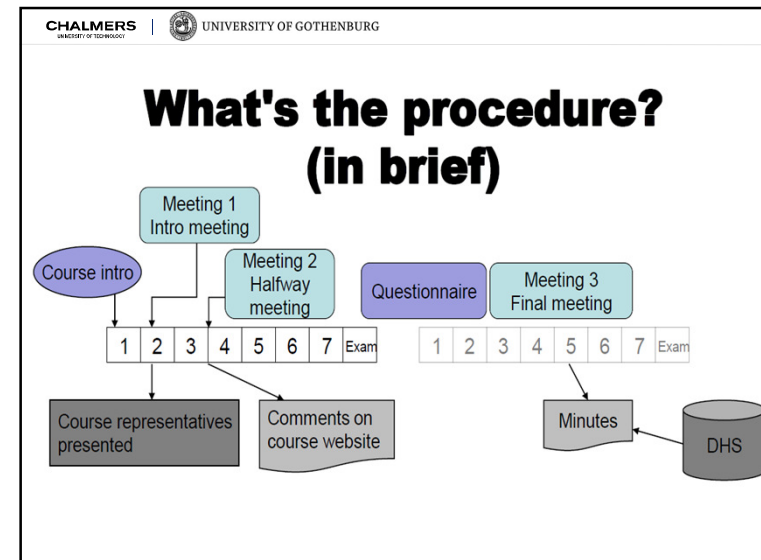
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## Course Evaluation Procedure

- Each course at Chalmers is evaluated with an **intro meeting**, a recommended **half-way meeting** and a **final meeting**.
- Questionnaires are sent out to all courses by the end of the exam week. And, can be answered until the end of Sw2 in the following Sp.
- When the questionnaires have closed, the final meeting is held.
- The final meeting is led by a programme representative.



**Scheduling**

Attempts to meet application constraints should be done in a proactive way through scheduling.

Schedule = resources + operations on a time line

**Scheduling**

Scheduling is used in many disciplines:  
 (a.k.a. "operations research")

- Production pipelines ("Ford's automotive assembly line")
  - Actors: workers + car parts
  - Goal: generate schedules that maximizes system throughput (cars per time unit)
  - Technique: job- and flow-shop scheduling
- Real-time systems
  - Actors: processors, data structures, I/O hardware + tasks
  - Goal: generate schedules that meet timing constraints (deadlines, periods, jitter)
  - Technique: priority-based task scheduling

**Scheduling**

Scheduling is used in many disciplines:  
 (a.k.a. "operations research")

- Classroom scheduling
  - Actors: classrooms, teachers, projectors + courses
  - Goal: generate periodic schedules within 7-week blocks
  - Technique: branch-and-bound algorithms
- Airline crew scheduling
  - Actors: aircraft, staff + routes
  - Goal: generate periodic schedules that minimizes the number of aircraft and staff used and fulfill union regulations for staff
  - Technique: advanced branch-and-bound algorithms

**Scheduling**


- A scheduling algorithm generates a schedule for a given set of tasks and a certain type of run-time system.
- The scheduling algorithm is implemented by a scheduler that decides in which order the tasks should be executed.
- Observe that the scheduler selects which task should be executed next, while the dispatcher starts the execution of the selected task.

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## Scheduling

A schedule is said to be feasible if it fulfills all application constraints for a given set of tasks.

A set of tasks is said to be schedulable if there exists at least one scheduling algorithm that can generate a feasible schedule.




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## Scheduling

A scheduling algorithm is said to be optimal with respect to schedulability if it can always find a feasible schedule whenever any other scheduling algorithm can do so.

A scheduling algorithm is said to be optimal with respect to a performance metric if it can always find a schedule that maximizes/minimizes that metric value.



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## Scheduling constraints

Examples of scheduling constraints:

- No processor sharing:
  - A processor can only execute one task at a time
  - This is a realistic assumption for any processor type being used in practice
  - Note: in case of multi-core processors, each core is viewed as a separate processor
- No dynamic task parallelism:
  - A task can only execute on one processor at a time
  - This is a realistic assumption for any programming model being used in practice

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## Scheduling constraints

Examples of scheduling constraints:

- Non-preemptive scheduling:
  - Once started, a task cannot be preempted by another task
  - This assumption is not so common in priority-based scheduling
- Greedy scheduling:
  - Once started, a task cannot be preempted by a lower-priority task
  - This assumption applies for all run-time systems used in practice
- No task migration:
  - A task can only execute on one given processor, or cannot change processor once it has started its execution
  - This is a realistic assumption for distributed systems, and is also enforced for some multi-core processor designs (e.g. AUTOSAR)

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## Scheduling constraints

Non-preemptive scheduling:

- Advantages:
  - Mutual exclusion can be automatically guaranteed
  - Results from WCET analysis correspond well with real WCET behavior
- Disadvantages:
  - Negative effect on schedulability
    - Scheduling decision takes effect only after a task has completed its execution
    - Once a task starts executing, all other tasks on the same processor will be blocked until execution is complete

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## Scheduling constraints

Preemptive scheduling:

- Advantages:
  - Schedulability is not negatively affected
    - Scheduling decisions can take effect as soon as the system state changes (even in the middle of task execution)
    - The capacities of task priorities can be used in full
- Disadvantages:
  - Mutual exclusion has to be guaranteed by e.g. semaphores (or similar constructs)
  - WCET analysis is more complicated since cache and pipeline contents will be affected by a task switch
  - Program security may be compromised (through so-called *covert channels*) if full preemption is allowed

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## Scheduling constraints

Greedy scheduling:

- Example: "traditional" static-priority scheduling (RM, DM)
  - Once a task starts executing, lower-priority tasks cannot grab the processor until execution is complete
- Advantages:
  - Scheduler relatively simple to implement
  - Supported by all run-time systems used in practice
- Disadvantages:
  - Schedulability is negatively affected:
    - Lower-priority tasks can starve and hence miss their deadlines

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## Scheduling constraints

Fair scheduling:

- Example: p-fair scheduling (Baruah et al. 1995)
  - Although a task has started executing, lower-priority tasks receive a guaranteed time quantum per time unit for execution
  - All tasks hence make some kind of progress per time unit
- Advantages:
  - Schedulability can be maximized on a multiprocessor system (assuming that task switch cost is negligible)
- Disadvantages:
  - Not supported by run-time systems used in practice
  - Poor schedulability when task switch cost is non-negligible
    - Fairness implies significantly more task switches than greediness

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## Scheduling algorithms

How much an oracle is the scheduling algorithm?

- Myopic scheduler:
  - Scheduling algorithm only knows about currently ready tasks.
  - Scheduling decisions are only taken whenever a new task instance arrives or a running task instance terminates.
- Clairvoyant scheduler:
  - Scheduling algorithm "knows the future"; that is, it knows in advance the arrival times of the tasks.
  - On-line clairvoyant scheduling is difficult to realize in practice.

"Predictions are always hard to make. In particular about the future."  
 (Yogi Berra)

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## Scheduling algorithms

When are schedules generated?

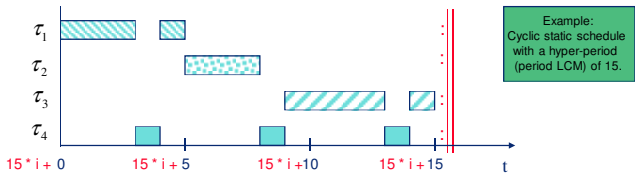
- Static scheduling:
  - Schedule generated "off-line" before the tasks becomes ready, sometimes even before the system is in mission.
  - Schedule consists of a "time table", containing explicit start and completion times for each task instance, that controls the order of execution at run-time.
- Dynamic scheduling:
  - Schedule generated "on-line" as a side effect of tasks being executed, that is, when the system is in mission.
  - Ready tasks are sorted in a queue and receive access to the processor and shared resources at run-time using conflict-resolving mechanisms.

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## Static scheduling

Off-line schedule generation:

- Simulate dynamic scheduling
  - Record a run-time behavior (linear time complexity)
- Apply a search heuristic (e.g., a branch-and-bound algorithm)
  - Find a feasible schedule (if one exists) by considering all possible execution scenarios (NP-complete problem)

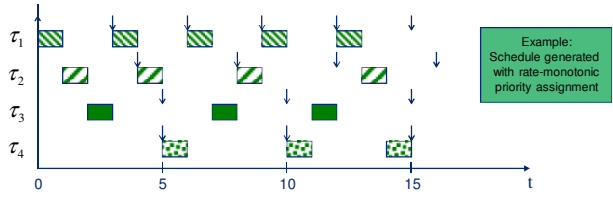


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## Dynamic scheduling

On-line schedule generation:

- Mechanisms for resolving conflicts
  - Priorities possibly combined with time quanta
  - Feasibility of schedule must be checked off-line by making predictions on how the conflicts are resolved at run-time



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## Dynamic scheduling

**Rate-monotonic scheduling (RM):**

- Uses static priorities
  - Priority is determined by task frequency (rate)
  - Tasks with higher rates (i.e., shorter periods) are assigned higher priorities
- Theoretically well-established (for single-processor systems)
  - Sufficient schedulability test can be performed in linear time (under certain simplifying assumptions)
  - Exact schedulability test is an NP-complete problem
  - RM is optimal among all scheduling algorithms that uses static priorities under the assumption that  $D_i = T_i$  for all tasks (shown by C. L. Liu & J. W. Layland in 1973)

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## Dynamic scheduling

**Deadline-monotonic scheduling (DM):**

- Uses static priorities
  - Priority is determined by task deadline
  - Tasks with shorter (relative) deadlines are assigned higher priorities
  - Note: RM is a special case of DM, with  $D_i = T_i$
- Theoretically well-established (for single-processor systems)
  - Exact schedulability test is an NP-complete problem
  - DM is optimal among all scheduling algorithms that uses static priorities under the assumption that  $D_i \leq T_i$  for all tasks (shown by J. Y.-T. Leung & J. Whitehead in 1982)

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## Dynamic scheduling

**Earliest-deadline-first scheduling (EDF):**

- Uses dynamic priorities
  - Priority is determined by how critical the process is at a given time instant
  - The task whose absolute deadline is closest in time receives the highest priority
- Theoretically well-established (for single-processor systems)
  - Exact schedulability test can be performed in linear time (under certain simplifying assumptions)
  - EDF is optimal among all scheduling algorithms that uses dynamic priorities under the assumption that  $D_i = T_i$  for all tasks (shown by C. L. Liu & J. W. Layland in 1973)

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## Dynamic scheduling

**Example: RM versus EDF**

$\tau_1 : (C_1 = 2, T_1 = 5)$   
 $\tau_2 : (C_2 = 4, T_2 = 7)$

The figure shows two Gantt charts. The top chart is for Rate-Monotonic (RM) scheduling. Task 1 (light blue) is scheduled in a periodic pattern with period 5. Task 2 (dark green) is scheduled in a periodic pattern with period 7. A red circle and arrow point to the first instance of task 2, which starts at t=7 but misses its deadline at t=7. The bottom chart is for Earliest-Deadline-First (EDF) scheduling. Task 1 is scheduled in a periodic pattern with period 5. Task 2 is scheduled in a periodic pattern with period 7. The first instance of task 2 starts at t=0 and finishes at t=7, meeting its deadline.

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## Handling shared resources

When tasks are no longer independent (i.e., they access shared software/hardware objects for which mutual exclusion is enforced) the scheduler must be extended with special mechanisms.

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## Handling shared resources

Priority inversion phenomenon:

priority (H) > priority (M) > priority (L)  
 H and L share mutex resource R

Blocking time for H **not bounded** by execution of critical region

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## Handling shared resources

Resolving resource conflicts:  
 (while also avoiding priority/deadline inversion)

- Off-line resource scheduling:
  - Intelligent algorithms that are configured to generate schedules with no need for conflict resolution at run-time.
  - Examples: branch-and-bound (B&B) algorithms
- On-line resource access protocols:
  - Blocking protocols using dynamic adjustments of task priorities.
  - Examples: Priority Inheritance Protocol, Deadline Inheritance Protocol, Priority Ceiling Protocol, Immediate Ceiling Priority Protocol, Stack Resource Policy
  - Non-blocking protocols using retry loops.
  - Examples: lock-free and wait-free object sharing

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## Handling shared resources

Priority Inheritance Protocol: (Sha, Rajkumar & Lehoczky, 1990)

- Basic idea: When a task  $\tau_i$  blocks one or more higher-priority tasks, it temporarily assumes (inherits) the highest priority of the blocked tasks.

Advantage:

- Prevents medium-priority tasks from preempting  $\tau_i$  and prolonging the blocking duration experienced by higher-priority tasks.

Disadvantage:

- **May deadlock:** priority inheritance can cause deadlock
- **Chained blocking:** the highest-priority task may be blocked once by every other task executing on the same processor.

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## Handling shared resources

**Priority Ceiling Protocol:** (Sha, Rajkumar & Lehoczky, 1990)

- Basic idea: Each resource is assigned a priority ceiling equal to the priority of the highest-priority task that can lock it. Then, a task  $\tau_i$  is allowed to enter a critical region only if its priority is higher than all priority ceilings of the resources currently locked by tasks other than  $\tau_i$ . When the task  $\tau_i$  blocks one or more higher-priority tasks, it temporarily inherits the highest priority of the blocked tasks.

**Advantage:**

- No **deadlock**: priority ceilings prevent deadlocks
- No **chained blocking**: a task can be blocked at most the duration of one critical region.

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## Handling shared resources

**Priority Ceiling Protocol:** priority (H) > priority (M) > priority (L)  
 H sequentially accesses resources  $R_1$  and  $R_2$   
 M accesses resource  $R_3$   
 L accesses resource  $R_3$  and nests  $R_2$

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## Handling shared resources

**Distributed PCP:** (Rajkumar, Sha & Lehoczky, 1988)

- All critical regions associated with the same global resource are bound to a specified synchronization processor.
- A task "migrates" to the synchronization processor to execute the critical region (using remote-procedure calls)
  - Advantage: deadlock-free algorithm
  - Disadvantage: large overhead for message-passing protocol
- All critical regions associated with the same global resource are executed at a priority equal to the semaphore's priority ceiling
  - short blocking times

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## Handling shared resources

**Lock-Free and Wait-Free Object Sharing:**

If several tasks attempt to access a lock-free object concurrently, and if a subset of these tasks stop taking steps, then one of the remaining tasks completes its access in a finite number of steps.

If several tasks attempt to access a wait-free object concurrently, and if a subset of these tasks stop taking steps, then each of the remaining tasks complete their access in a finite number of steps.



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## Handling shared resources

**Lock-Free Object Sharing:** (Anderson et al., 1996)

- Basic idea: The lock-free object sharing scheme is implemented using "retry loops". Object accesses are implemented using *test-and-set* or *compare-and-swap* instructions typically found in modern RISC processors.
- Advantage:
  - Resource accesses are non-blocking
  - Deadlock-free
  - Avoids priority inversion
  - Requires no kernel-level support
- Disadvantage:
  - Potentially unbounded retry loops

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## Handling shared resources

**Wait-Free Object Sharing:** (Anderson et al., 1997)

- Basic idea: The wait-free object sharing scheme is implemented using a "helping" strategy where one task "helps" one or more other tasks to complete an operation. Before beginning an operation, a task must announce its intentions in an "announce variable". While attempting to perform its own operations, a task must also help any previously-announced operation (on its processor) to complete execution.
- Advantage:
  - Non-blocking, deadlock-free, and priority-inversion-free
  - Requires no kernel-level support
  - Precludes waiting dependencies among tasks

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## Handling shared resources

**Non-existence of optimal on-line shared-resource scheduler:** (Mok, 1983)

When there are mutual exclusion constraints in a system, it is impossible to find an optimal on-line scheduling algorithm (unless it is clairvoyant).

**Complexity of shared-resource feasibility test:** (Mok, 1983)

The problem of deciding feasibility for a set of periodic tasks which use semaphores to enforce mutual exclusion is NP-hard.

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## End of lecture #4