Process Scheduling

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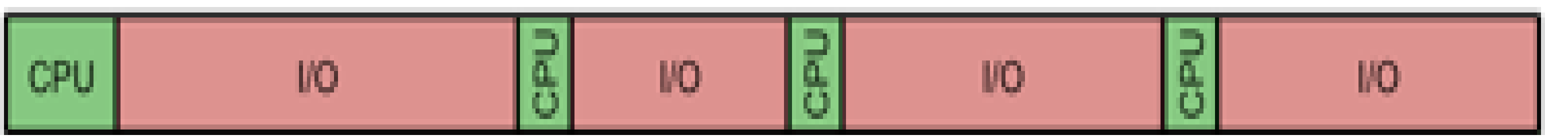
Process Behavior

- Most processes exhibit:
  - Large # of short CPU bursts between I/O requests
  - Small # of long CPU bursts between I/O requests
  - Interactive process: mostly short CPU bursts

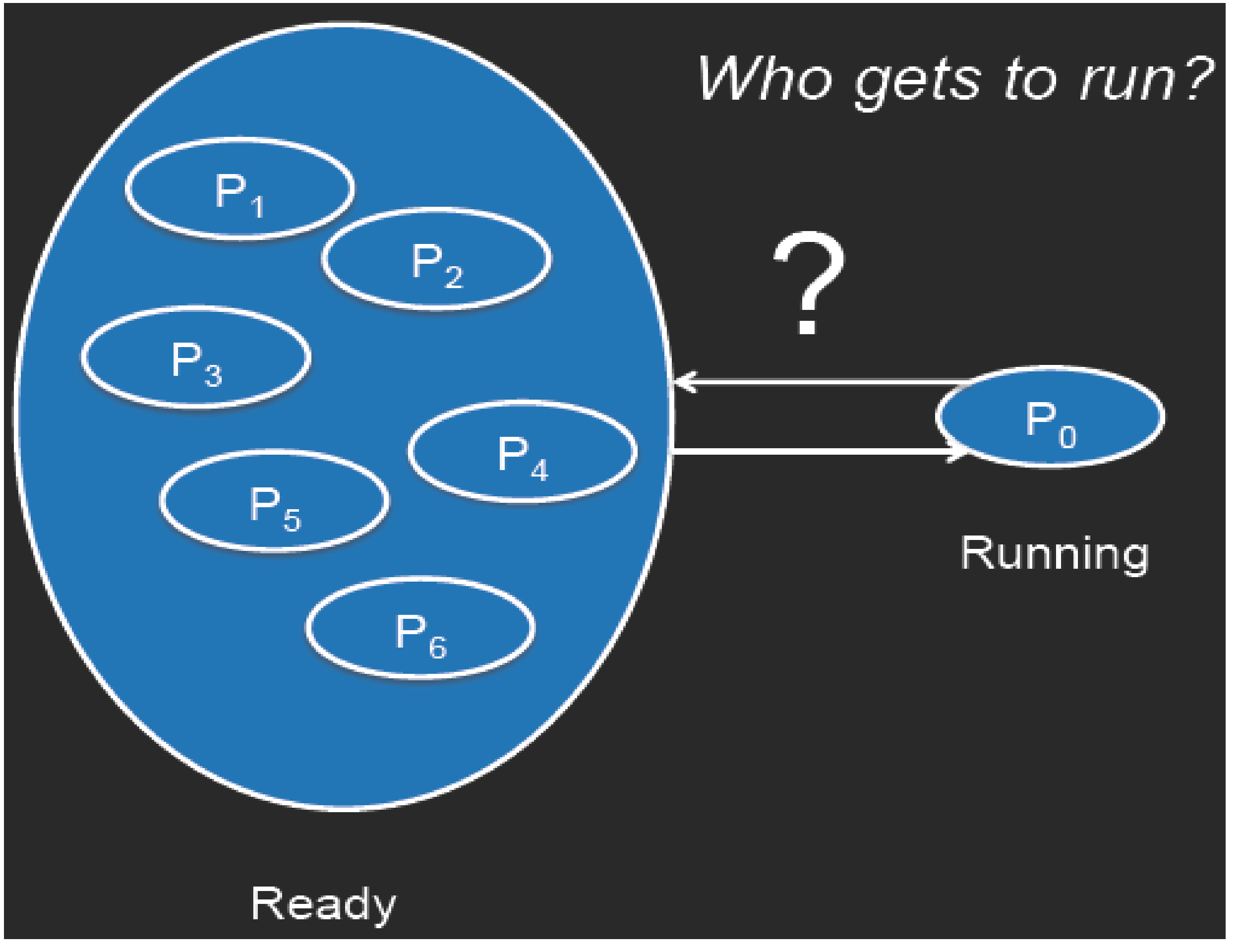


  - Compute process: mostly long CPU bursts

Scheduling

- Goal:
  - Maximize use of CPU & improve throughput
  - Let another process run when the current one is waiting on I/O
- Reality:
  - Some processes will use long stretches of CPU time
    - Preempt them and let another process run
  - More processes may want the CPU: keep them in the *ready list*
  - Perhaps all processes are waiting on I/O: nothing to run!

Scheduler



Scheduler

Two components

- *Scheduling algorithm*:
  - Policy: Makes the decision of who gets to run
- *Dispatcher*:
  - Mechanism to do the context switch

When does Scheduler Make Decision?

Four events affect the decision:

1. Current process goes from *running to waiting state*
2. Current process terminates
3. Interrupt causes the scheduler to move a process from *running to ready:*
   - *scheduler decides it's time for someone else to run*
4. Current process goes from *waiting to ready*
   - I/O (including blocking events, such as semaphores) is complete

- Preemptive scheduler
- Cooperative (non-preemptive) scheduler
  - CPU cannot be taken away
- Run-to-completion scheduler (old batch systems)

Scheduling Algorithm Goals

- Be fair (to processes? To users?)
- Be efficient: Keep CPU busy … and don't spend a lot of time deciding!
- Maximize throughput: minimize time users must wait
- Minimize response time
- Be predictable: jobs should take about the same time to run when run multiple times
- Minimize overhead
- Maximize resource use: try to keep devices busy!
- Avoid starvation
- Enforce priorities
- Degrade gracefully: under heavy load

FCFS

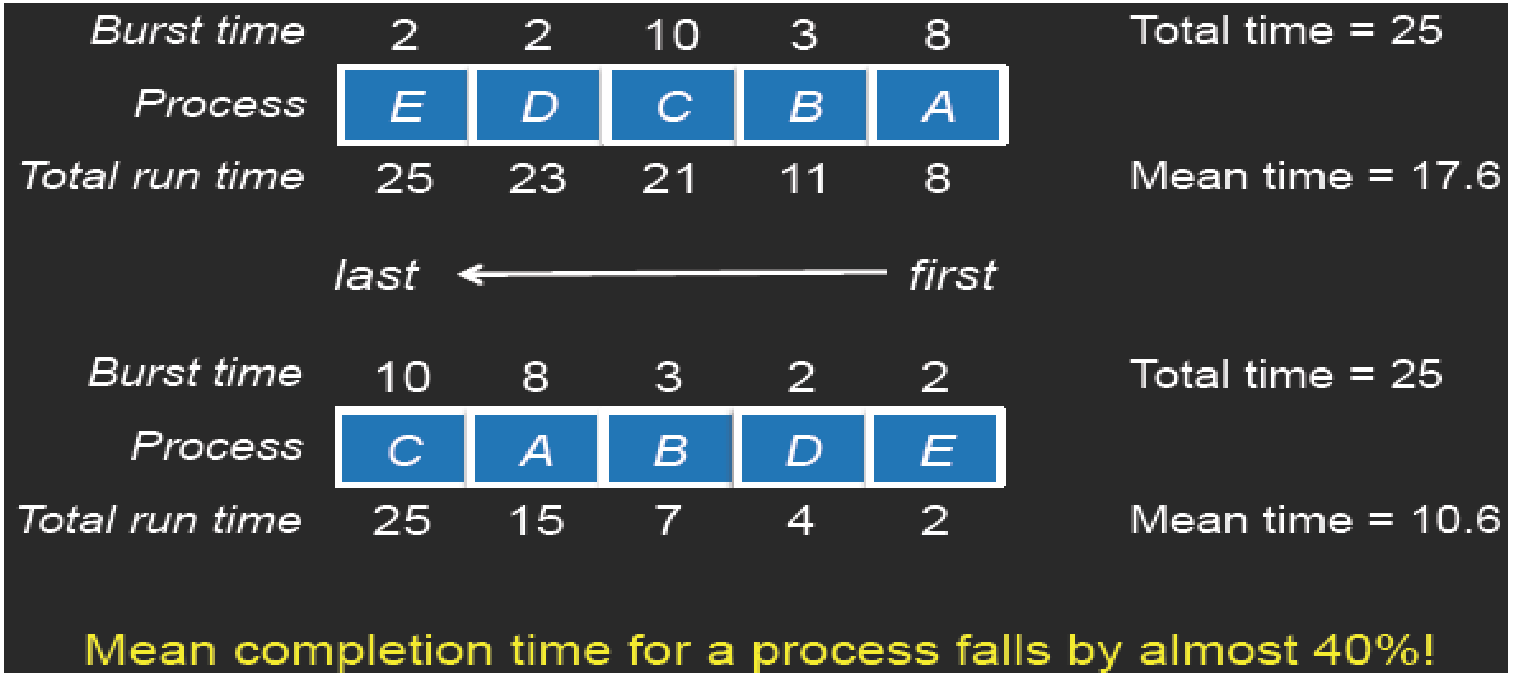
- Non-preemptive
- A process with a long CPU burst will hold up other processes
  - I/O bound jobs may have completed I/O and are ready to run: poor device utilization
  - Poor average response time

Round-Robin Scheduling

- Preemptive: Process can not run for longer than a quantum (time slice)
- Performance depends on the time slice
  - Long time slice makes this similar to FCFS
  - Short time slice increases overhead % of context switching
- Advantages
  - Every process gets an equal share of the CPU
  - Easy to implement
  - Easy to compute average response time: *f(# processes on list)*
- Disadvantage
  - Giving every process an equal share isn't necessarily good
  - Highly interactive processes will get scheduled the same as CPU-bound processes

Shortest Remaining Time First Scheduling

- Sort jobs by anticipated CPU burst time
- Schedule shortest ones first
- Optimize average response time



Shortest Remaining Time First Scheduling

- Biggest problem: *we're optimizing with data we don't have!*
- All we can do is estimate
- Exponential average:

$$e_{n+1} = \alpha t_n + (1 - \alpha)e_n$$

- Algorithm can be preemptive or non-preemptive
- Preemptive version is:
  - Shortest remaining time first scheduling (vs. SJF)

Shortest Remaining Time First Scheduling

- Advantage
  - Short-burst jobs run fast
- Disadvantages
  - Long-burst (CPU intensive) jobs get a long mean waiting time
  - Rely on ability to estimate CPU burst length

Priority Scheduling

- Round Robin assumes all processes are equally important
- Not true
  - Interactive jobs need high priority for good response
  - Long non-interactive jobs get worse treatment (get the CPU less frequently): *this goal led us to SRTF*
  - Users may have different status (e.g., administrator)
- Priority scheduling algorithm:
  - Each process has a priority number assigned to it
  - Pick the process with the highest priority
  - Processes with the same priority are scheduled round-robin

Priority Scheduling

- Priority assignments:
  - Internal: time limits, memory requirements, I/O:CPU ratio, …
  - External: assigned by administrators
- Static & dynamic priorities
  - Static priority: priority never changes
  - Dynamic priority: scheduler changes the priority during execution
    - Increase priority if it's I/O bound for better interactive performance or to increase device utilization
    - Decrease a priority to let lower-priority processes run
    - Example: use priorities to drive SJF/SRTF scheduling

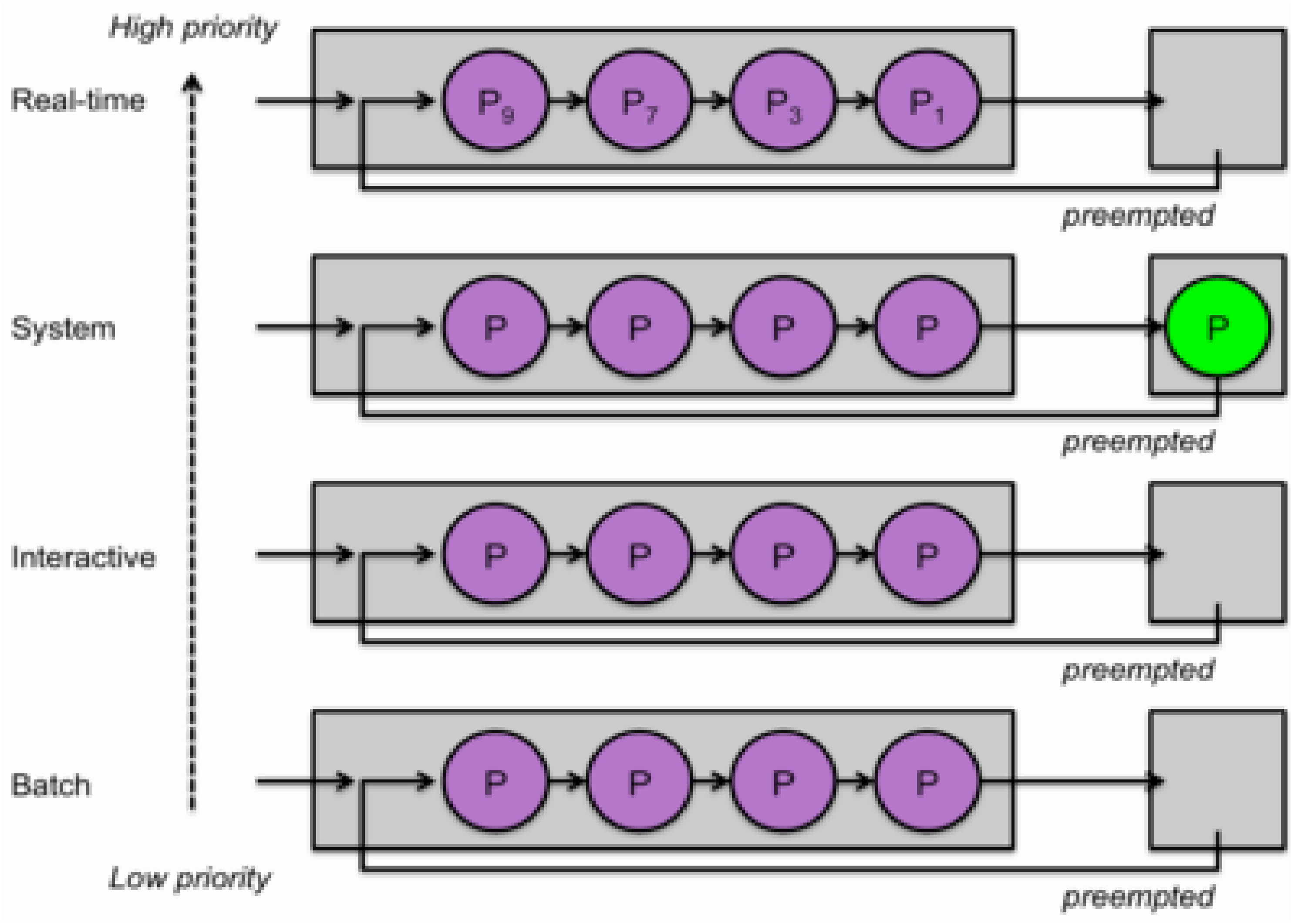
Priority Scheduling: dealing with starvation

- Starvation
  - Process is blocked indefinitely
  - Steady stream of higher-priority processes keeps it from being scheduled
- Dealing with starvation: Process aging
  - Gradually increase the priority of a process so that eventually its priority will be high enough so it will be scheduled to run
  - Then bring it down again

Multilevel Queue

- Priority classes
  - Examples: System processes, interactive processes, slow interactive processes, background non-interactive processes
  - Each priority class gets its own queue
  - Processes are permanently assigned to a specific queue
- Goals
  - Priority scheduler with queues per priority level
  - Each queue may have a different scheduling algorithm
  - Quantum is increased at each lower priority level
    - Lower-priority processes tend to be compute bound

Multilevel Queue



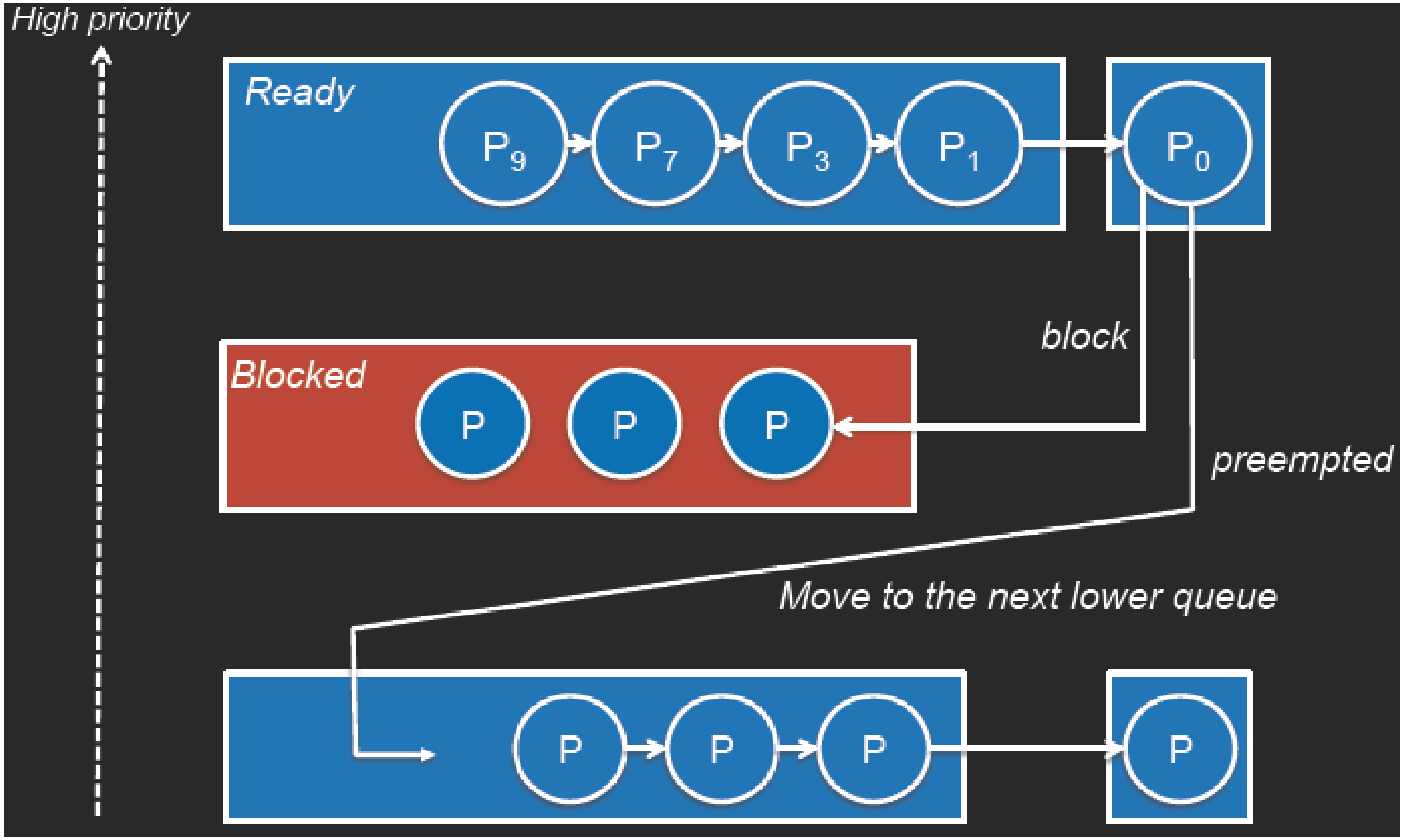
Multilevel Feedback Queue

Goals

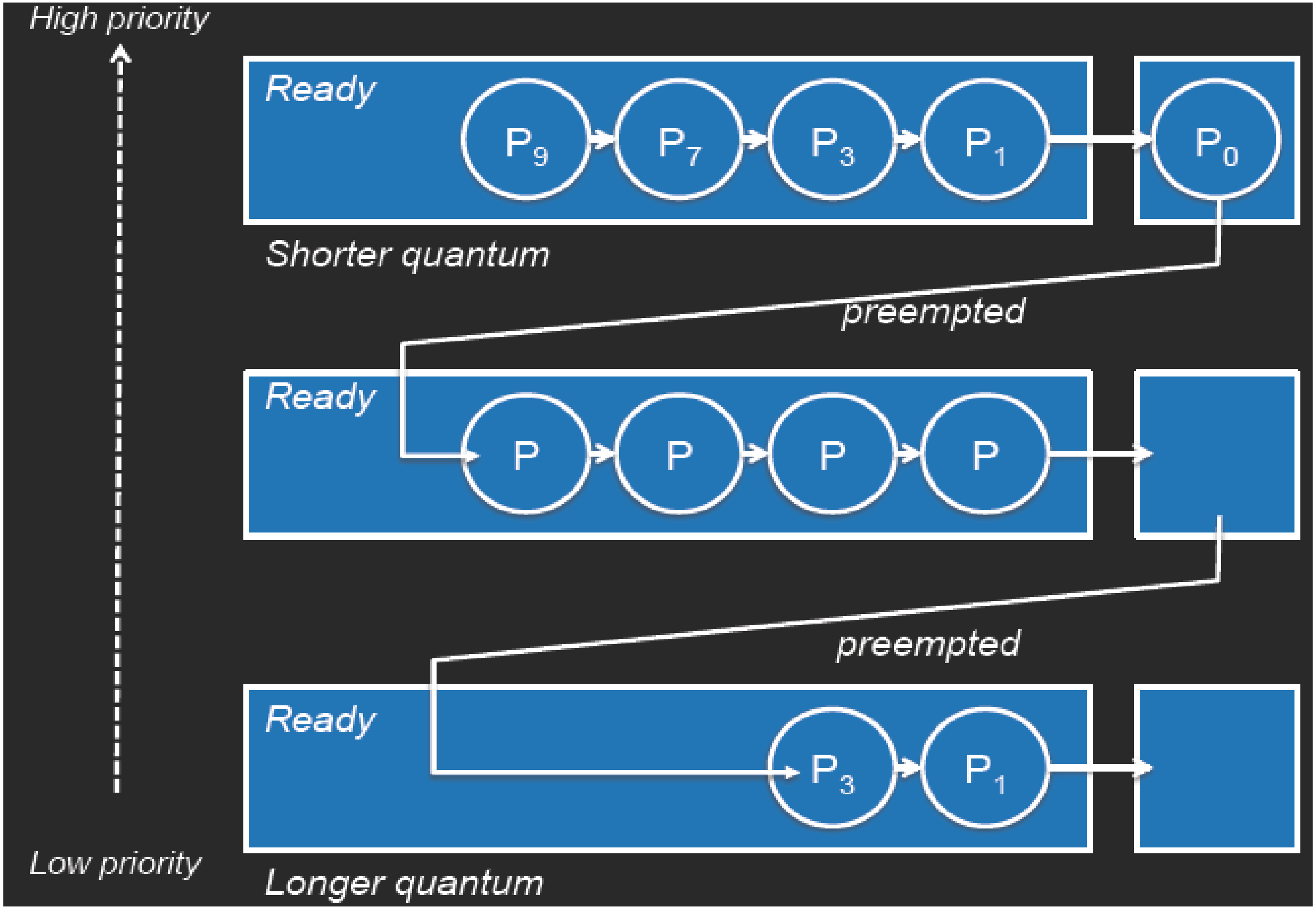
- *Allow processes to move between queues*
- Separate processes based on CPU burst behavior
  - I/O-bound processes will end up on higher-priority queues
  - If a process does not finish its quantum then it will stay at the same level, otherwise it moves to a lower level
- Quantum is increased at each lower priority level
  - Lower-priority processes tend to be compute bound
- Processes that wait too long may be moved to a higher-priority queue (aging)
- Each queue may have a different scheduling algorithm

Multilevel Feedback Queue

- Pick the process from the head of the highest priority queue



Multilevel Feedback Queue



Multilevel Feedback Queue

- Advantage
  - Good for separating processes based on CPU burst needs
  - Let I/O bound processes run often
  - Give CPU-bound processes longer chunks of CPU
  - No need to estimate interactivity! (Estimates were often flawed)
- Disadvantages
  - Priorities get controlled by the system.
    - A process is considered important because it uses a lot of I/O
  - Processes whose behavior changes may be poorly scheduled
  - System can be gamed by scheduling bogus I/O

Symmetric multiprocessor scheduling

- SMP: each processor has access to the same memory and devices.
- Processor affinity
  - Try to reschedule a process onto the same CPU
  - Cached memory & TLB lines may be present on the CPU's cache
- Types of affinity
  - Hard : force a process to stay on the same CPU
  - Soft affinity: best effort, but the process may be rescheduled on a different CPU
    - Load balancing: ensure that CPUs are busy
    - It's better to run a job on another CPU than wait
    - If the run queue for a CPU is empty, get a job from another CPU's run queue: *pull migration*
    - Check load periodically: if not balanced, move jobs. *Push migration*

Hierarchy of symmetric multiprocessors

- Multiple processors
- Multiple cores
  - Shared caches among cores (e.g., Intel i7 cores share L3 cache)
- Hyperthreading
  - Presented as two cores to the operating system
  - Memory stall: CPU has to wait (e.g., to get data on a cache miss)
  - When the issuing logic can no longer schedule instructions from one thread and there are idle functional units in the CPU core, it will try to schedule a suitable instruction from the other thread.
- Good schedulers will know the difference

Linux Scheduler

- Linux 1.2: Round Robin scheduler (fast & simple)
- Linux 2.2: Scheduling classes
  - Classes: Real-time, non-real-time, non-preemptible
  - Support for symmetric multiprocessing
- Linux 2.4: O(N) scheduler
  - Iterates over every task at each scheduling event
  - If a time slice was not fully used, 1/2 of the remaining slice was added to the new time slice for the process.
  - "goodness" metric decided who goes next
  - One queue (in a mutex): no processor affinity

Linux 2.6 O(1) scheduler goals

- Addressed three problems
  - Scalability: O(1) instead of O(n) to not suffer under load
  - Support processor affinity
  - Support preemption

Linux 2.6 O(1) scheduler

- One *runqueue* per CPU: 140 priority lists serviced round robin
  - Two priority ranges: 0-99 for real-time; 100-140 for others
  - *High priority processes get a longer quantum!*
  - If a process uses its time slice, it will not get executed until all other processes exhaust their quanta
- *runqueue* data structure:
  - Two arrays sorted by priority value:
    - **Active: all tasks with time remaining in their slices**
    - **Expired: all tasks that used up their time slice**
  - Scheduler chooses the highest priority task from the active queue
  - When the active queue is empty, the expired queue becomes active

Linux 2.6 O(1) scheduler

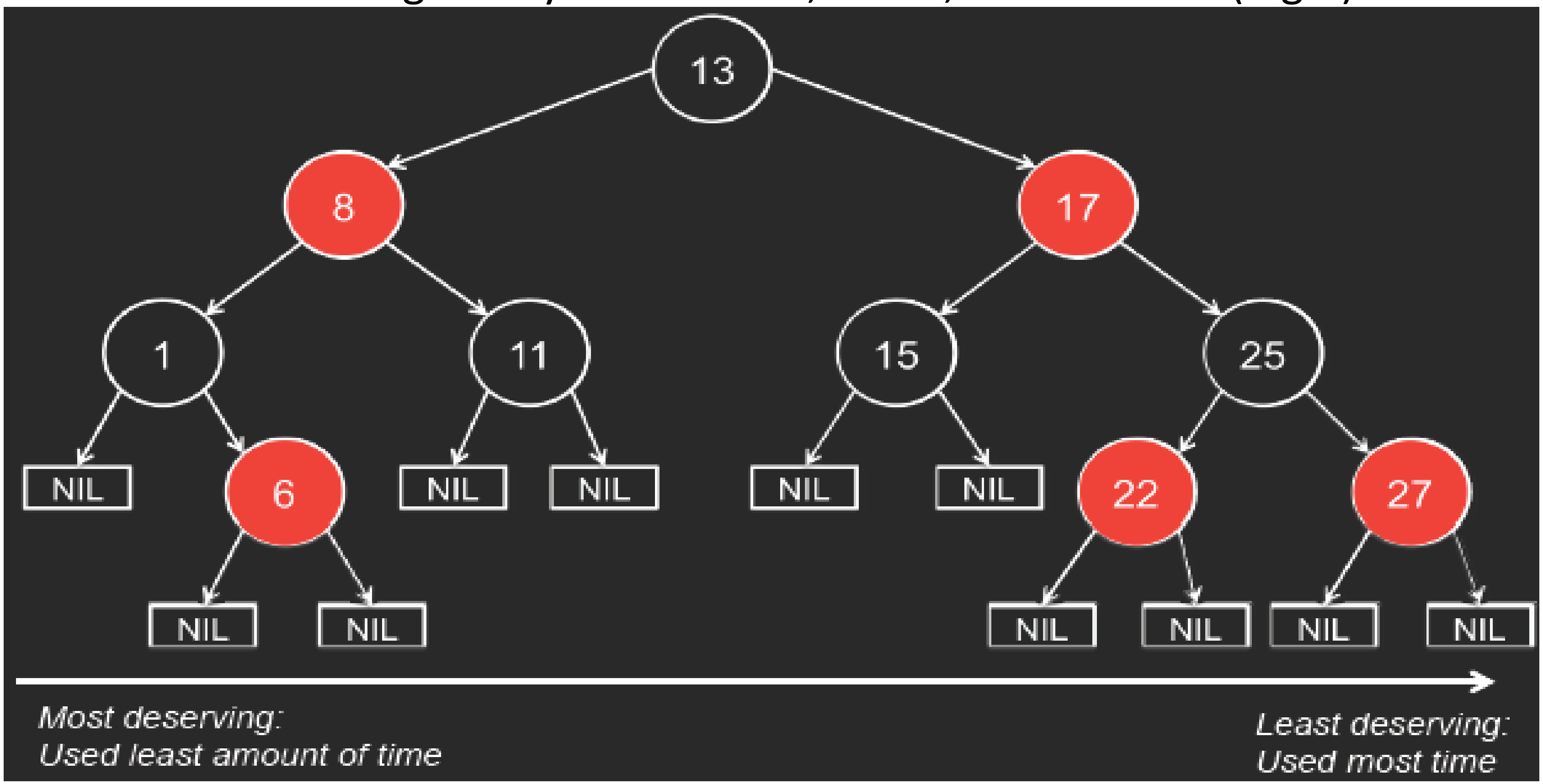
- Real-time tasks: static priorities
- Non real-time tasks: dynamic priorities
  - I/O-bound processes get priority increased by up to 5 levels
  - CPU-bound processes get priority decreased up to 5 levels
  - Interactivity determined by %sleep : %compute time ratio
- SMP load balancing
  - Every 200ms, check if CPU loads are unbalanced
  - If so, move tasks from a loaded CPU to a less-loaded one
  - If a CPU's runqueue is empty, move from the other runqueue
- Downside of O(1) scheduler
  - A lot of code with complex heuristics

Linux Completely Fair Scheduler

- Latest scheduler (introduced in 2.6.23)
- Goal: give a “fair” amount of CPU time to tasks
- Keep track of time given to a task (“virtual runtime”)
  - Also use “sleeper fairness”: tasks get a “fair” share of the CPU even if they sleep from time to time
- Priorities
  - Used as a decay factor for the time a task is permitted to execute
  - Allowable time decreases for low priority tasks

Linux Completely Fair Scheduler

- No run queues
- Time-sorted read-black tree instead of a run queue (spent cpu time as a key)
  - Self-balancing binary tree: search, insert, & delete in O(log n)



CFS: picking a process

- Scheduling decision:
  - Pick the leftmost task
- When a process is done:
  - Add execution time to the per-task run time count
  - Insert the task back in the queue
- Heuristic: *decay factors*
  - Determine how long a task can execute
  - Higher priority tasks have lower factors of decay.
  - Avoids having run queues per priority level

Acknowledgements

- Some of slides are adapted from Paul Krzyzanowski