### 9. Sustainable multiprocessor

scheduling of sporadic task systems (or: how an inexact schedulability test might be better)

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### Weakness

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Real systems differ from models
Clock and timer inaccuracies
Blocking / non-preemption
Execution time variation
Differences must not invalidate test (!)
Solution

Use pessimistic assumptions

Real-time systems

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### Goals

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- Our notion of what is "pessimistic" should be consistent with the analysis that underlies the schedulability test
- The test should be monotonic with respect to any workload parameters that are considered to be bounds on actual values

Real-time systems

# Predictability [Ha & Liu, 1994] For arbitrary job sets on multiprocessors, if the scheduling algorithm is *work-conserving* <sup>1</sup>), preemptive, global (with migration), with fixed job priorities Job completion times are monotonically related to job execution times Hence it is safe to consider only upper bounds for job execution times in schedulability tests This is <u>not true</u> for non-preemptive scheduling A scheduling algorithm is *work conserving* if processors are not idle while tasks eligible for execution are not able to execute on other processors

Real-time system:

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## How?

- Actual/nominal?
  Actual maximum job execution time < C<sub>p</sub> or
  Value C<sub>i</sub> used by scheduler is reduced
- Per job/task?

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- $\Box$  C<sub>i</sub> reduced differently for each job, or
- $\square C_i reduced for all jobs of task$
- Use in scheduling decisions, or not?

 These may or may not make a difference in sustainability, depending on context

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# Longer inter-arrival times Sustainability is built into the sporadic workload model Der-job or per-task □ Actual, nominal too for algorithms that do not make use of T<sub>i</sub> in scheduling decisions Global FTP, EDF, EDZL are sustainable w.r.t. longer inter-arrival times

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