

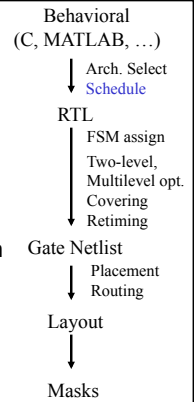
ESE535: Electronic Design Automation

Day 8: February 11, 2015
Scheduling Introduction



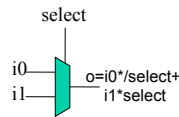
Today

- Scheduling
 - Basic problem
 - Variants
 - List scheduling approximation



General Problem

- Resources are not free
 - Wires, io ports
 - Functional units
 - LUTs, ALUs, Multipliers,
 - Memory access ports
 - State elements
 - memory locations
 - Registers
 - Flip-flop
 - loadable master-slave latch
 - Multiplexers (mux)

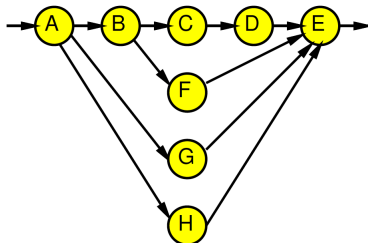


Trick/Technique

- Resources can be shared (reused) in time
- Sharing resources can reduce
 - instantaneous resource requirements
 - total costs (area)
- **Pattern:** scheduled operator sharing

Example

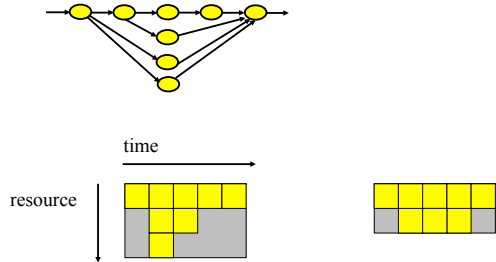
Assume unit delay operators.
How many operators do I need to evaluate this computation in ~5 time units?



Sharing

- Does not have to increase delay
 - w/ careful time assignment
 - can often reduce peak resource requirements
 - while obtaining original (unshared) delay
- **Alternately:** Minimize delay given fixed resources

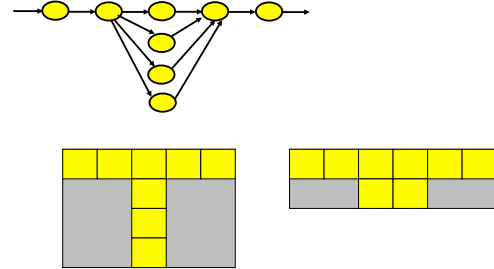
Schedule Examples



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More Schedule Examples



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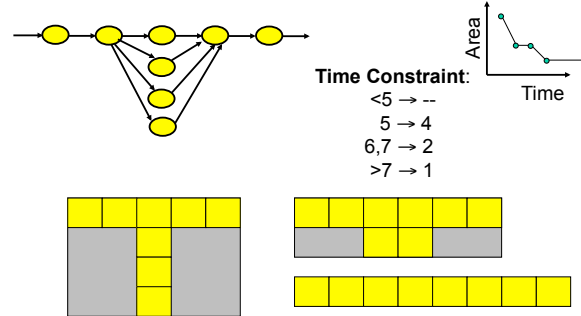
Scheduling

- **Task:** assign time slots (and resources) to operations
 - **time-constrained:** minimizing peak resource requirements
 - *n.b.* time-constrained, not always constrained to minimum execution time
 - **resource-constrained:** minimizing execution time

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Resource-Time Example



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Scheduling Use

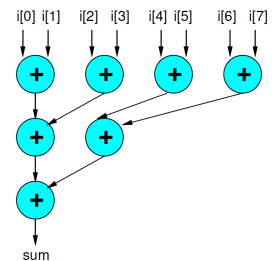
- Very general problem formulation
 - HDL/Behavioral → RTL
 - Register/Memory allocation/scheduling
 - Instruction/Functional Unit scheduling
 - Processor tasks
 - TDMA, bus scheduling, static routing
 - Routing (share channel)

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Preclass 2

- Schedule onto two adders
- Does the number of cycles depend on $i[7], i[6], \dots, i[0]$?
- How many cycles?



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Preclass 3

- Schedule onto:
 - 2 adders (+)
 - 2 incrementer (++)
 - 2 comparator (>)
- `sum=0;`
- `for(j=0;i[j]>0;j++)`
- `sum+=i[j];`
- Does the number of cycles depend on `i[7], i[6], ... i[0]` ?
- How many cycles?

Two Types (1)

- **Data independent**
 - graph static
 - resource requirements and execution time
 - independent of data
 - schedule statically
 - maybe bounded-time guarantees
 - typical ECAD problem

Two Types (2)

- **Data Dependent**
 - execution time of operators variable
 - depend on data
 - flow/requirement of operators data dependent
 - if cannot bound range of variation
 - must schedule online/dynamically
 - cannot guarantee bounded-time
 - general case (*i.e.* halting problem)
 - typical "General-Purpose" (non-real-time) OS problem

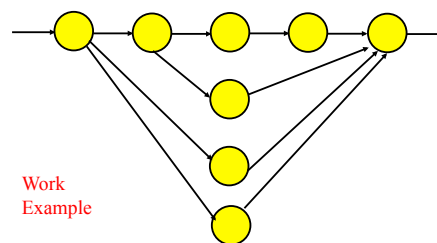
Unbounded Resource Problem

- Easy:
 - compute ASAP schedule
 - *i.e.* schedule everything as soon as predecessors allow
 - will achieve minimum time
 - won't achieve minimum area
 - (meet resource bounds)

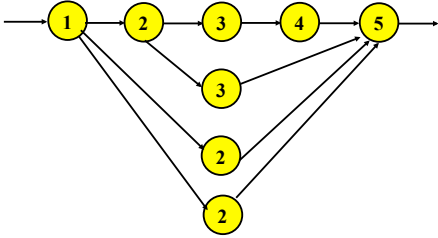
ASAP Schedule As Soon As Possible (ASAP)

- For each input
 - mark input on successor
 - if successor has all inputs marked, put in visit queue
- While visit queue not empty
 - pick node
 - update time-slot based on latest input
 - Time-slot = $\max(\text{time-slot-of-inputs})+1$
 - mark inputs of all successors, adding to visit queue when all inputs marked

ASAP Example



ASAP Example

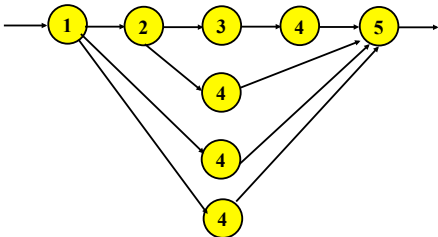


Also Useful to Define ALAP

- As Late As Possible
- Work backward from outputs of DAG
- Also achieve minimum time w/ unbounded resources

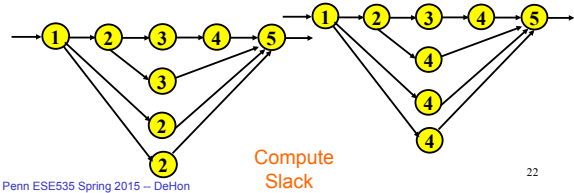
Rework Example

ALAP Example

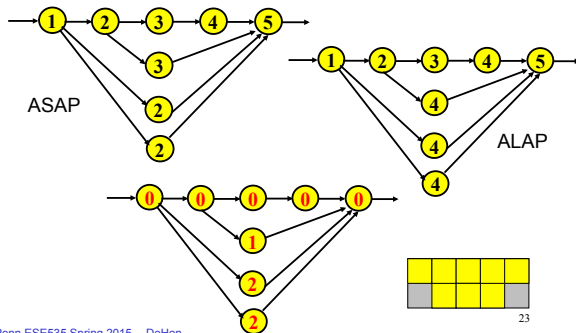


ALAP and ASAP

- Difference in labeling between ASAP and ALAP is *slack* of node
 - Freedom to select timeslot
 - **Class theme:** exploit freedom to reduce costs
- If ASAP=ALAP, no freedom to schedule



ASAP, ALAP, Difference



Two Bounds

Bounds

- Useful to have bounds on solution
- Two:
 - CP: Critical Path
 - Sometimes call it “Latency Bound”
 - RB: Resource Bound
 - Sometimes call it “Throughput Bound” or “Compute Bound”

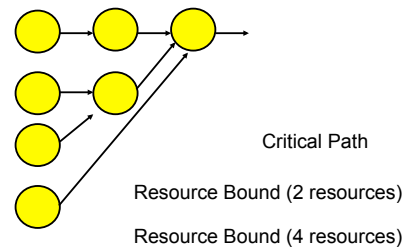
Critical Path Lower Bound

- ASAP schedule ignoring resource constraints
 - (look at length of remaining critical path)
- Certainly cannot finish any faster than that

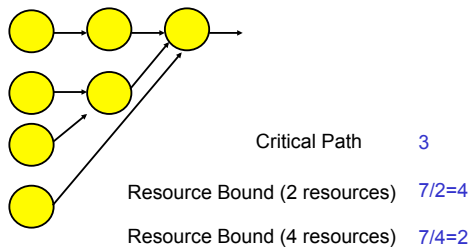
Resource Capacity Lower Bound

- Sum up all capacity required per resource
- Divide by total resource (for type)
- Lower bound on remaining schedule time
 - (best can do is pack all use densely)
 - Ignores schedule constraints

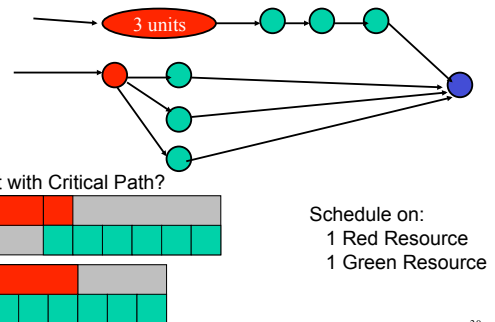
Example



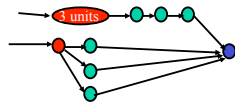
Example



Why hard?

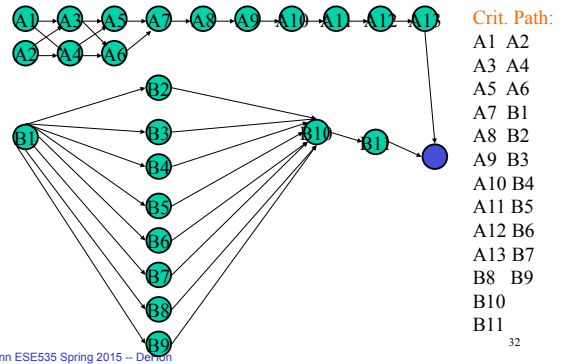


General

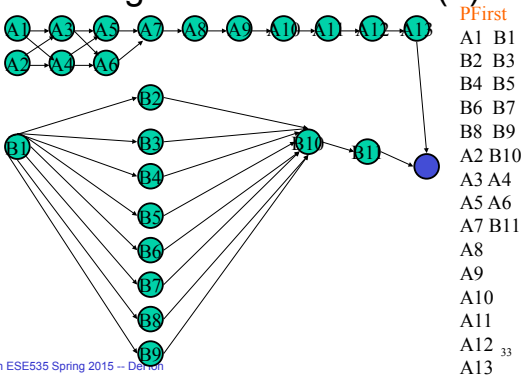


- When selecting, don't know
 - need to tackle **critical path**
 - need to run task to **enable work** (parallelism)
- Can generalize example to single resource case

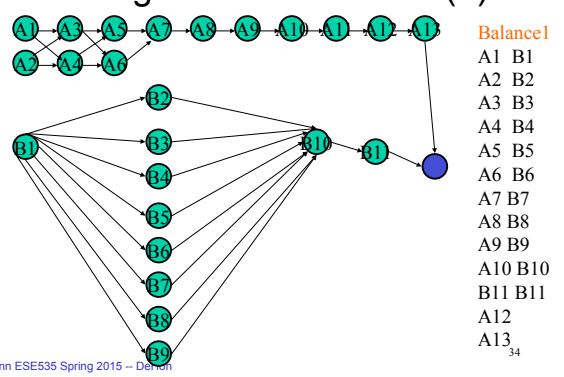
Single Resource Hard (1)



Single Resource Hard (2)



Single Resource Hard (4)



List Scheduling

Greedy Algorithm → Approximation

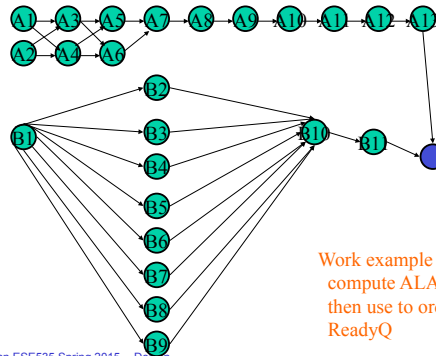
List Scheduling (basic algorithm flow)

- Keep a ready list of "available" nodes
 - (one whose predecessors have already been scheduled)
 - Like ASAP queue
 - But won't necessary process in FIFO order
- While there are unscheduled tasks
 - Pick an unscheduled task and schedule on first available resource after its predecessors
 - Put any tasks enabled by this one on ready list

List Scheduling

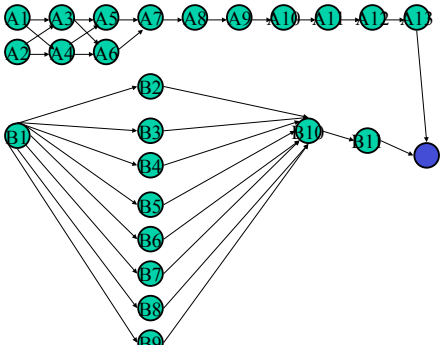
- Greedy heuristic
- **Key Question:** How prioritize ready list?
 - What is dominant constraint?
 - least slack (worst critical path) → LPT
 - LPT = Longest Processing Time first
 - enables work
 - utilize most precious (limited) resource
- So far:
 - seen that no single priority scheme would be optimal

List Schedule by LPT



Work example
compute ALAP
then use to order
ReadyQ

LPT Schedule



LPT:
A1 A2
A3 A4
A5 A6
A7 B1
A8 B2
A9 B3
A10 B4
A11 B5
B6 B7
B8 B9
A12 B10
A13 B11

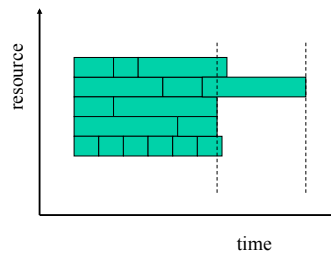
List Scheduling

- Use for
 - resource constrained
 - time-constrained
 - give resource target and search for minimum resource set
- Fast: $O(N) \rightarrow O(N \log(N))$ depending on prioritization
- Simple, general
- Good for upper bound – results is achievable
- Not always optimal
- How good?

Approximation

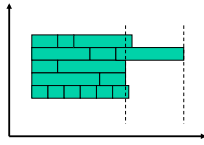
- Can we say how close an algorithm comes to achieving the optimal result?
- Technically:
 - If can show
 - $\text{Heuristic}(\text{Prob}) / \text{Optimal}(\text{Prob}) \leq \alpha \quad \forall \text{Prob}$
 - Then the Heuristic is an α -approximation

Scheduled Example Without Precedence



How bad is this schedule?

Observe



- \exists optimal length L
- No idle time up to start of last job to finish
- start time of last job $\leq L$
- last job length $\leq L$
- Total LS length $\leq 2L$
- What can say about optimality?
- Algorithm is within factor of 2 of optimum

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Results

- Scheduling of identical parallel machines has a 2-approximation
 - *i.e.* we have a polynomial time algorithm which is guaranteed to achieve a result within a factor of two of the optimal solution.
- In fact, for precedence unconstrained there is a 4/3-approximation
 - *i.e.* schedule Longest Processing Time first

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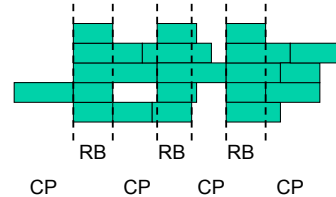
Recover Precedence

- With precedence we may have idle times, so need to generalize
- Work back from last completed job
 - two cases:
 - entire machine busy
 - some predecessor in critical path is running
- Divide into two sets
 - whole machine busy times
 - critical path chain for this operator

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Precedence



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Precedence Constrained

- Optimal Length $>$ All busy times
 - Optimal Length \geq Resource Bound
 - Resource Bound \geq All busy
- Optimal Length $>$ This Path
 - Optimal Length \geq Critical Path
 - Critical Path \geq This Path
- List Schedule = This path + All busy times
- List Schedule $\leq 2 * (\text{Optimal Length})$

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Conclude

- Scheduling of identical parallel machines with precedence constraints has a 2-approximation.

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Tightening

- How could we do better?
- What is particularly pessimistic about the previous cases?
 - List Schedule = This path + All busy times
 - List Schedule $\leq 2 * (\text{Optimal Length})$

Tighten

- LS schedule \leq Critical Path+Resource Bound
- LS schedule \leq $\text{Min}(\text{CP}, \text{RB}) + \text{Max}(\text{CP}, \text{RB})$
- Optimal schedule \geq $\text{Max}(\text{CP}, \text{RB})$
- LS/Opt $\leq 1 + \text{Min}(\text{CP}, \text{RB}) / \text{Max}(\text{CP}, \text{RB})$
- The more one constraint dominates
 - the closer the approximate solution to optimal
 - ↳ (EEs think about 3dB point in frequency response)

Tightening

- Example of
 - More information about problem
 - More internal variables
 - ...allow us to state a tighter result
- 2-approx for any graph
 - Since CP may = RB
- Tighter approx as CP and RB diverge

Multiple Resource

- Previous result for homogeneous functional units
- For heterogeneous resources:
 - also a 2-approximation
 - Lenstra+Shmoys+Tardos, Math. Programming v46p259
 - (not online, no precedence constraints)

Bounds

- Precedence case, Identical machines
 - no polynomial approximation algorithm can achieve better than 4/3 bound
 - (unless P=NP)
- Heterogeneous machines (no precedence)
 - no polynomial approximation algorithm can achieve better than 3/2 bound

Summary

- Resource sharing saves area
 - allows us to fit in fixed area
- Requires that we schedule tasks onto resources
- General kind of problem arises
- We can, sometimes, bound the “badness” of a heuristic
 - get a tighter result based on gross properties of the problem
 - approximation algorithms often a viable alternative to finding optimum
 - play role in knowing “goodness” of solution

Relate HMC

- How does this relate to our mapping for Heterogeneous multicontext computing array?

Big Ideas:

- Exploit freedom in problem to reduce costs
 - (slack in schedules)
- Use dominating effects
 - (constrained resources)
 - the more an effect dominates, the “easier” the problem
- Technique: Approximation

Admin

- Reading on web for Monday
 - Same reading for today and Monday
- Assignment 4 Due Thursday