# Load Balancing & Termination Detection

Reading: PP Chapter 7

## Load-Balancing Rationale

## Load-Balancing Dichotomies

- Static Load-Balancing
  - Pre-planned
- Dynamic Load-Balancing
  - Adapts as computation progresses
  - Variations:
    - Centralized
    - Decentralized
      - Centralized control
      - Distributed control
- Communication-sensitive or not
- Generic vs. Application-Specific

## Static Load Balancing Methods

- Deterministic scheduling to minimize completion time, e.g. based on fixed **priority**
- Random *a priori* distribution
- Round robin (aka cyclic mapping: “deal” the load out to the processors)
- Recursive bisection: recursively split load into two, with half going to half the processors
- Simulated annealing, genetic programming

## Deterministic Scheduling

- Problem is NP-hard for all but the most trivial classes of assumptions.
- Assumes times of tasks (and communication) are known, which they often aren’t.
- Unexpected scheduling anomalies.

## Scheduling Anomalies (R.L. Graham, 1960’s)

- The following are expected to reduce overall execution time:
  - Reducing execution times of individual tasks
  - Relaxing precedence constraints between tasks
  - Adding more processors

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- The following are expected to reduce overall execution time:
  - Reducing execution times of individual tasks
  - Relaxing precedence constraints between tasks
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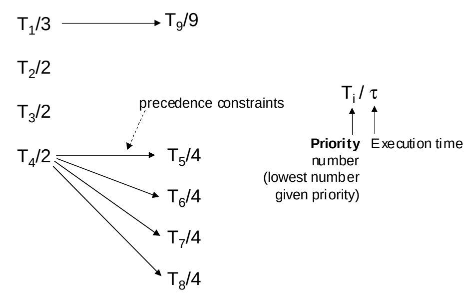
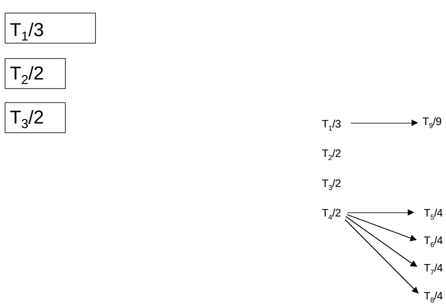
- For some algorithms, these can actually *increase* the execution time.

## Priority Scheduling Anomalies




## Consider Scheduling on 3 processors

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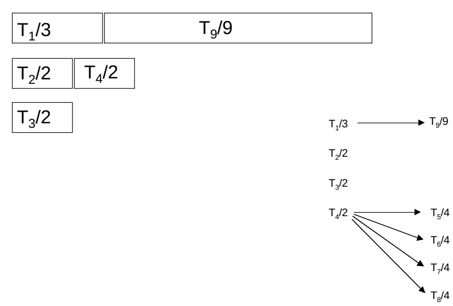


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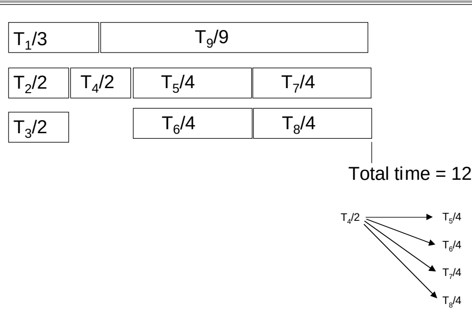
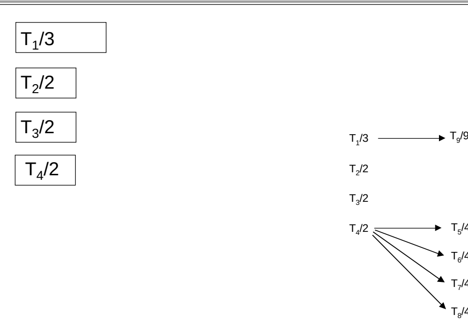



## Consider Scheduling on 4 processors



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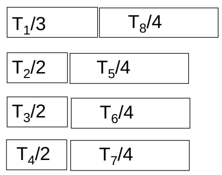


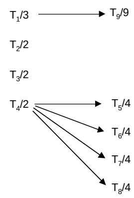


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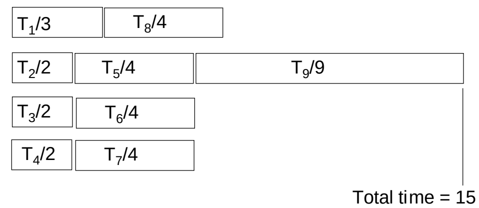
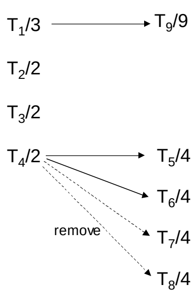
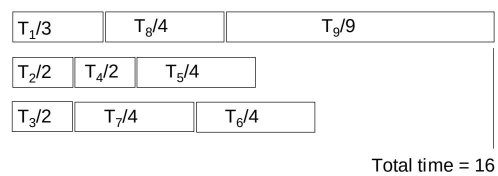



## Consider Relaxing Constraints




## Consider the relaxed constraints on 3 processors




## Cause of Anomalies

- Obviously the anomalies are caused by the use of the **priority rule** in scheduling:
  - This rule is cheap to implement (O(n)).
  - It does not take into account optimizations that would be possible by violating strict priority.
- In general, finding true optimum would entail a search, which tends to be much more expensive.

## Bounds on Anomalies

- Let ‘ designate times for system with relaxed constraints and shorter individual times. Then
- Time(m)/ Time(m’) $\leq$ 1 + (m-1)/m’, where m’ $\geq$ m are numbers of processors.

- Example: Time(2)/Time(3) $\leq$ 4/3.
- Worst case: Time(m)/Time(m’) < 2.

## More on Scheduling

- Later, when we discuss real-time.

## Dynamic Load-Balancing

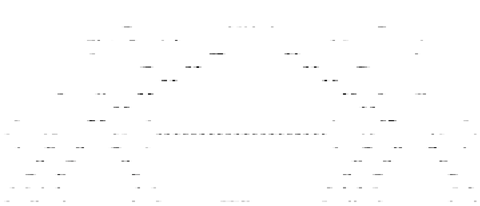
- Centralized: Processors go to a centralized work pool to get more work (e.g. in the work pool model). Also called **self-scheduling**.
- Decentralized: The work is distributed by some other method

## Pro’s and Con’s of Centralized

## Decentralized

- Distributed pool
  - Processors go to pool to get work
  - Processors distribute extra work to pools
  - May necessitate rebalancing
- Push or Pull (“Fully-distributed”)
  - Push: Heavily-loaded processors push their work onto other processors.
  - Pull: Lightly-loaded processors go to other processors to get work.

## Distributed Pool



## Tree Method
(e.g. Keller, Lindstrom, & Patil 1979)

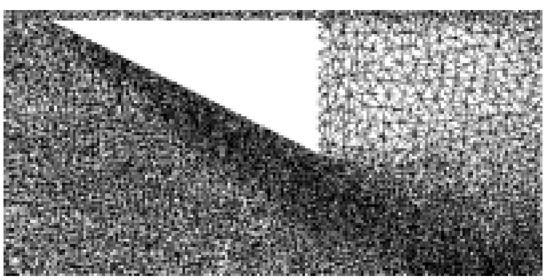
## Gradient Method
(Lin & Keller 1987)

- Tasks are like molecules of a fluid.
- Fluid flows from high-pressure to low-pressure areas.
- Intelligent switches in processing elements can multiplex load balancing along with communication traffic.
- Distributed pressure metric steers along shortest path to under-loaded node.
- Parallel

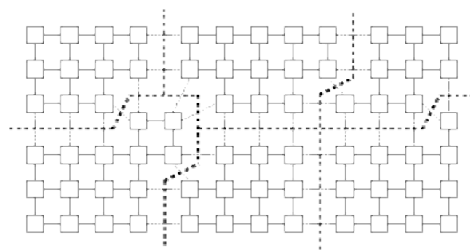
## Other Methods

- ACWN method (Kale', 1988)
- Seed-in-the-wind method
- Application-specific methods:
  - Partitioning using grids and graphs:
    - PIC computations
    - FEM computations

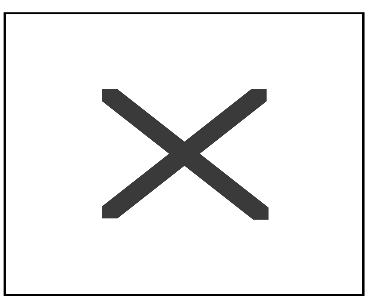
## FEM mesh example



## Decentralized Load-Balancing for a Grid Problem
(from Foster's DBPP)



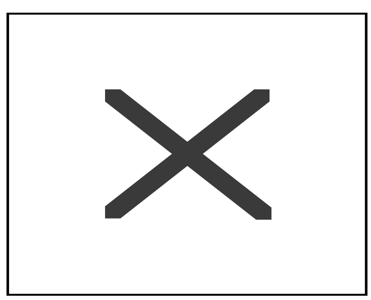
## Load Distribution without Load Balancing (Physical grid, 16x32 procs)



Processor time-distribution histogram

diverse

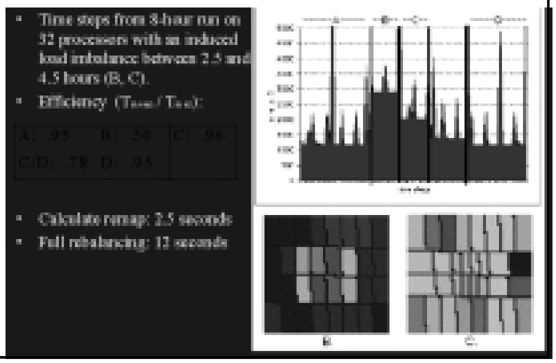
## Load Distrubution with Load Balancing (cyclic-mapping algorithm)



Processor time-distribution histogram

more uniform

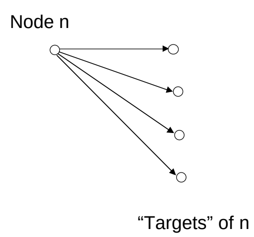
Example of dynamic load balancing in an atmospheric model: rebalancing a “hot spot”: http://www-unix.mcs.anl.gov/~michalak/daoslides/




## Example from PP sec. 7.4

- Single-source shortest path on a directed graph
- Find the distances from a designated node to all other nodes
- Possibilities:
  - Dijkstra’s algorithm
  - Moore’s algorithm

## Nomenclature




## Dijkstra vs. Moore

- Dijkstra’s algorithm:
  - Upper bounds on distance-from-source are maintained for all nodes.
  - Nodes are “retired” in succession, starting with the source. When a node is retired, its upper bound is provably the shortest path from the source.
  - Each time a node is retired, the distance-from-source upper bounds of its unretired targets are updated.
  - The unretired node with the smallest distance is the next chosen for retirement.

## Sequential Timing for Dijkstra

- n (number of nodes) iterations, each iteration has to find min of up to n unretired nodes and update up to n targets: $O(n^2)$
- If the graph is “sparse”, meaning a constant upper bound on fan-out for all graphs, then the update step is O(1). Finding min can be done in O(log n), so for the sparse case: O(n log n)

## Dijkstra vs. Moore

- Moore’s algorithm:
  - Upper bounds on distances are maintained.
  - Nodes are visited by selecting from a queue, initially containing the single source.
  - As a node is visited, the upper bounds on its targets are updated. If an update results in an improvement, the node is re-enqueued.

## Sequential timing for Moore

- Each enqueuing may entail updating of up to n nodes.
- Claim: A node won't be enqueued more than $O(n^2)$ times.
- Therefore this algorithm is $O(n^3)$.

## PP 7.4 uses the Moore Algorithm

- A work pool model is used.
- A work unit is a node to be visited.
- The work pool is therefore the same as the queue.
- The work pool can be centralized or distributed.

## Distributed Moore Algorithm

- The authors suggest one process per node, which maintains the upper bound on the node.
- When the node is updated, it will notify the processes of its target nodes, so that they can similarly update.
- So there is no actual queue, just processes waiting for updates.

## Termination Issue

- With the distributed Moore algorithm, there is the issue of determining when the computation is done.
- Sufficient conditions are:
  - Every process must be idle.
  - There can be no messages in transit.
- Why only sufficient?

## Termination Issue

- Why only sufficient?
- In general, but not for Moore's algorithm, the system might have the answer but there are still non-idle processes or live messages.
- One way to address is to have a master process notify the others to shut down, e.g. by sending a high-priority message.
- There would need to be a way of ignoring messages arriving after the shutdown, and shutdown would have to acknowledge to the master.

## PP 7.3 Distributed Termination

- Acknowledgment messages method
  - Messages originally emanate from a single node.
  - Sending a message **that makes a node active** imposes an implicit tree structure on the processes.
  - Normally all messages are acknowledged, but a parent is acknowledged only **when the child goes from active to idle**.
  - When all of a node's children have acknowledged and there is no more processing, the node becomes idle itself.
  - The computation is done when the original node becomes idle.

## PP 7.3 Distributed Termination

- Ring Termination Method
  - Processes are arranged in a virtual ring structure, $P_0$, …., $P_{n-1}$
  - When $P_0$ terminates, it sends a ready-to-shutdown token to $P_1$.
  - When $P_i$ receives a token, it holds it until it terminates, then passes it to $P_{i+1 (\mathrm{mod}\ n)}$.
  - When $P_0$ receives a token, all $P_i$ have terminated.
  - $P_0$ then sends a shut-down to all processes.

## PP 7.3 Distributed Termination

- Ring Termination Method previously described assumes a process cannot be reactivated once it has terminated.
- In a work pool model, termination is analogous to the local pool being empty.
- But then we'd have a situation where a "terminated" process gets reactivated.
- How can we detect global termination in such a situation

## PP 7.3 Distributed Termination

- Ring Termination with Reactivation
  - If terminated $P_i$ receives a reactivation message from $P_j$, j > i, and has not yet received a ready-to-shutdown token, then there is no problem.
  - However, if $P_i$ has already received such a token and passed it on, the pending shutdown has to be ignored.

## Ring Termination with Reactivation

- Processes and tokens are colored black or white.
- Black signifies pending shutdown, white signifies absolute shutdown.
- $P_0$ becomes white and sends a white token to the right.
- If $P_i$ is white, it passes the token unchanged.
- If $P_i$ is black, it changes it to black.
- If $P_0$ receives a white token, then final shutdown takes place. If it receives a black one, it again sends a white token.

## All-Sources Shortest Paths

- Repeated parallel matrix multiplication
  - starting with connection matrix + I (using + min rather than + *):
  - log n matrix multiples, each $O(n^3)$ $\rightarrow O((n^3 \log n)/p)$.

## All-Sources Shortest Paths

- Parallel Floyd's method
  - Triply-nested loops, O(n) iterations each
  - **Middle** nest can be done in parallel
    - After each outer iteration, broadcast to all processors
    - $t_{comp}*n^3/p + t_{comm}*n^2$
  - Inner **two** nests can be done in parallel
    - $t_{comp}*n^3/p + t_{comm}*n^2/\mathrm{sqrt}(p)$

## All-Sources Shortest Paths

- Multiple Dijkstra's algorithms can be run in parallel for different sources.
- There is no communication cost.
- However, multiple sequential Dijkstra for dense graphs is slower than a sequential Floyd.
- If communication is expensive, or the graph is sparse, this could be a win.

## Exercise

- How would you parallelizing a single Dijkstra?