Non continuous allocation Algorithm for Increasing the Utilization Processor in Multi-Computers Network

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Abstract: Processor allocation is responsible for selecting a set of processors in order to run parallel work on them, while job schedule is responsible for determination of executing works. Job Schedule selects the next job for execution based on stated policy and then the processor allocation algorithm finds the free processors for the selected work. Until now, several continuous and non continuous techniques have been given for processor allocation in mesh multi-computers networks. Continuous allocation methods always try to allocate a free continuous sub-mesh with the same requested dimensional structure to the parallel input job. For this reason, it produces the internal fragmentation in the processors network. Non continuous allocation algorithms were produced with the aim of removing processors fragmentation. In discontinuous allocation algorithms, message interference between different jobs and strugle to get communication resources increases network communication overheads due to the increase in path length passed by the message. This communication overhead is highly dependent on to the manner of free sub-meshes allocation and the manner of recording by the algorithm. This reasearch, a non continuous allocation algorithm called Efficient and Quick Non-Continuous Allocation (EQNA) algorithm has been presented for a two-dimensional mesh network with C programming language. The efficiency of this algorithm compared via simulator tool ProcSimity with other continuous and non continuous allocation algorithms . Simulation results indicate improved Utilization Processor in the given algorithm.

Introduction

In large multi-computers, using an allocation algorithm in particular and an efficient scheduled algorithm is very crucial to have maximum computing power. If input job cannot be executed upon the arrival due to lack of processor and or other jobs, it will be transferred to the waiting line. When some processors are allocated to a job, this job keeps the processors with itself until completion of work. After completion, job is gone out the system and the processors become free for other tasks. Most of the continuous and non continuous allocation algorithms have been designed for two-dimensional mesh network. Mesh network has been the most favorite network among other networks for implementation of parallel computers with distributed memory due to simplicity, scalability, regularity and easy implementation and has been used in several machines such as: iWARP, IBMBlueGene / L and DeltaTouchstone [1]. Minimization of allocation time in Grid multi-computers is a fundamental issue because the main purpose of parallel execution is to minimize the total time that a job spends upon the entry to the exit moment in the system. With increase in system size, time for finding sub-meshes for the allocation to input job may be equal to the job execution time. Hence, development of strategies for minimizing search time (which is also called time allocation) is very important. Methods of processor allocation can be divided into two general categories: continuous and discontinuous. In continuous allocation methods, a set of free continuous processors available in the network is allocated to execute the input job. Allocation method as shown in [2,3] results in high fragmentation. Excessive fragmentation degrades performance parameters of the system. In order to resolve the fragmentation that occurred in the continuous allocation, discontinuous allocation methods were proposed. Discontinuous allocation is able to execute a job on several sub-meshes smaller than that the input job has requested and will not wait to release a continuous sub-mesh. Although a discontinuous allocation increases conflicts between messages in the system, it increases processors utilization in using the system processors and reduces the problem of fragmentation .Method of allocation operations has a direct impact on algorithm performance in discontinuous allocation algorithms

proposed [4]. It should be noted that, processors fragmentation operation must be conducted in a way that the processors allocated to a job have necessary continuity because this continuity has a crucial role in decreasing communication overhead and maintains useful efficiency of system resources. For those discontinuous allocation algorithms presented for two-dimensional meshes, it should be mentioned that processor allocation operation is not conducted based on continuous free sub-meshes available in the network but it has been used predefined local models or mathematical that reduce the efficiency of these algorithms. A discontinuous allocation algorithm that is called Efficient and Quick non-continuous allocation algorithm (EQNA) has been proposed for a two-dimensional mesh network [5,6, 7].

EQNA algorithm combines the advantages of both continuous and discontinuous allocation methods. For example, the advantage of continuous allocation is to eliminate the communication overhead between processors assigned to a job that is also deeply considered in this algorithm. This algorithm has the capability of complete detection and reduction of allocation overhead. This quality is achieved by maintaining the maximum continuity between the processors assigned to a job.

EQNA algorithm is capable to be applied in both two- and three-dimensional mesh multi-computers networks. In this paper, EQNA algorithm performance has been compared using simulations with discontinuous allocation algorithms known as Paging (0) and MBS. These two algorithms have been selected because of the best performance among other algorithms [8]. EQNA algorithm has been compared to FF continuous algorithm in order to show superiority of discontinuous allocation to continuous allocation with respect to the problem of fragmentation in continuous allocation. At first, previous studies related to the processor allocation algorithms in mesh networks will be reviewed. In review of literature, studies conducted on improvement in efficiency of allocation algorithms will be investigated and the manner of these algorithms performances will be summarized. EQNA discontinuous allocation algorithm will be described and the manner of allocation this algorithm will be exemplified and EQNA algorithm and implemented continuous and discontinuous allocation algorithms have been compared from the viewpoint of several important parameters in performance. And finally, results of the previous studies are discussed[9,10].

Research objectives

Processor allocation in distributed memory multi-computer with distributed memory especially those that are based mesh, In recent years, many studies have found that their several examples of commercial and experimental parallel machines used sharing space for allocating processors. Previous research suggests that continuous and discontinuous allocation algorithms still have not found a good way and a new allocation algorithm is needed.

Algorithms that are currently assigned to a processor are presented for three-dimensional lattices, full recognition feature to have sub-mesh but the ability to withstand the heavy overhead cost allocation is achieved that paid allocating and freeing the CPU to perform. Allocation overhead associated with increased mesh size, in the past algorithm increased [11].

In the case of discontinuous allocation algorithms are presented for two-dimensional mesh it should be said these algorithms have several serious problems such that it can be both internal and external fragmentation, and interference within the network named. None of these algorithms based on AMD sub-mesh free allocation continuous operation of the network, but where there are no pre-defined patterns or mathematical models are used.

For example, ANCA is divided into two parts, labor input if the allocation was successful for each of the sectors these two sections are also divided into two equal parts. MBS [12] used as input into the base and four sub-mesh sized based on 4 Assigns. Allocation based on profile pages, which are usually independent of the application is determined, the network is partitioned. Thus, these algorithms may have a great free sub-mesh, it may not be able to allocate the time for completion of such parameters would affect the system performance.

The main focus of this study is present a new way and efficient in the field discontinuous and continuous allocation for mesh multi-computer that current assignment is to overcome the limitations of existing methods and be able to utilize the advantages of both methods.

A method that keeps higher affinity compared with the previous allocation algorithms, among the processors allocated to a task. This reduces the number of sub-mesh assigned to a task and hence the path traveled by messages on the decline. The reduction pathway, leading to lower communication overhead in the network and consequently decreases the completion time of the job will entail.

Review of literature

Definitions and methods of continuous and discontinuous allocation used for multi-computers mesh networks have been reviewed in this section.

Definitions

A two-dimensional mesh M (w, h) is a rectangle of nodes with dimensions of $w \times h$ where w is width and h is the height of the rectangle. Each node of mesh is a processor that is known with the address of its characteristics. A node in column and row b has the coordinate of $\langle a, b \rangle$ where $0 \le a < w$ and $0 \le b < h$. Node $\langle i, j \rangle$ that is not in borderlines of mesh approximates and connects directly with other four nodes: $\langle i \pm 1, j \rangle$ and $\langle i, j \pm 1 \rangle$ so that $0 < i < w - 1$ and $0 < j < h - 1$. In borderlines, each node approximates and connects to other two or three nodes according to its situation.

Definition 1: two-dimensional sub-mesh S (a, b) in the mesh M (w, h) is a subnet M (a, b) that $0 \le a \le w$ and $0 \le b \le h$. When a job requests a sub-mesh with dimensions $a \times b$, this job is expressed via T (a, b). Address for sub-mesh S is known by its end and base node that is a four-parameters variable as $\langle x, y, x', y' \rangle$ where, $< x, y >$ shows the lower left corner and $\langle x', y' \rangle$ shows the upper right corner of sub-mesh S. it is clear that $a = x' - x + 1$ and $b = y' - y + 1$ and base node of sub-mesh, is $\langle x, y \rangle$ and the sub-mesh area is the number of nodes inside it that is equal to $a \times b$.

Definition 2: Busy sub-mesh β is a sub-mesh that all its nodes are assigned to a job at that moment. A set of busy sub-meshes B is the set that set includes all the busy sub-meshes available in the network that is called busy list. For example, in figure (1), three busy sub-meshes exist in network M (6, 6); therefore, $B = \{\beta_1, \beta_2, \beta_3\}$ where $\beta_1 = \langle 0,0,1,2 \rangle$, $\beta_3 = \langle 4,3,5,5 \rangle$, $\beta_2 = \langle 2,0,3,1 \rangle$ are the members of this set.

Definition 3: Coverage sub-mesh for busy sub-mesh β is expressed according to the input T that is a sub-mesh that none of its nodes can be selected as the basis node of a free sub-mesh for allocation to job T with respect to busy sub-mesh $\vartheta_{\beta,T}$. Coverage sub-mesh $\vartheta_{\beta,T}$ is equal to $\langle x_c, y_c, x', y' \rangle$ for $\beta \langle x, y, x', y' \rangle$ and the job β where, $y_c = \max(0, y - b + 1)$ and $x_c = \max(0, x - a + 1)$. A according to the input job T, coverage set C_T is a collection of coverage sub-meshes for the job T where, $C_T = \{\vartheta_{\beta,T} | \beta \in B\}$. For example, for the input job T (3, 2) in figure (1), we have: $\vartheta_{\beta_1,T} = \langle 0,0,1,2 \rangle$، $\vartheta_{\beta_2,T} = \langle 0,0,3,1 \rangle$ ،$\vartheta_{\beta_3,T} = \langle 2,2,5,5 \rangle$ ، $C_T = \{\langle 2,2,5,5 \rangle, \langle 0,0,3,1 \rangle, \langle 0,0,1,2 \rangle\}$

Definition 4: According to the input job T, reject δ_T sub-mesh is a sub-mesh including some processors that is a sub-mesh that none of its processors can be regarded as the basis node of a free sub-mesh for allocation to job T with respect to its dimensions. There are two reject sub-meshes for each T: horizontal (δ_{TH}) and (δ_{TV}) vertical. It is simple to calculate them i.e. $\delta_{TV} = \langle a', 0, w, h \rangle$ and $\delta_{TH} = \langle 0, b', w, h \rangle$ and $a' = w - a + 1$ and $b' = h - b + 1$

where, $w \times h$ is sub-mesh size. A set of reject sub-meshes Δ_T is calculated by adding δ_{TH} and δ_{TV}. For example, $\delta_{TH} = \langle 0,5,5,5 \rangle$ and $\delta_{TV} = \langle 4,0,5,5 \rangle$ in figure (1).
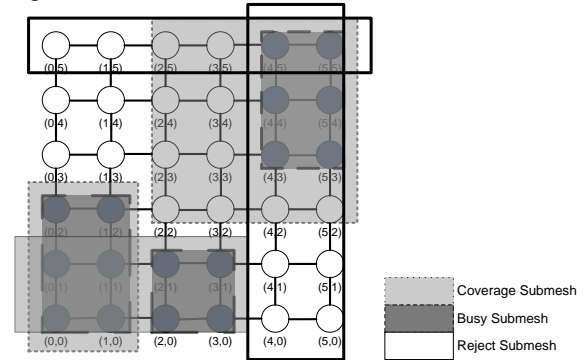

Fig .(1) An example of allocation for T (3, 2)

Continuous allocation Algorithms
Continuous allocation has been proposed for mesh multi-computers networks. Most previous studies have been focused on reducing the negative effects of fragmentation of processors on the system efficiency due to the continuous allocation. Some known solutions will be described below.

First-Fit(FF)/ Best-Fit (BF) Algorithm
First-Fit/ Best-Fit algorithms were proposed to improve the efficiency of the sliding frame. First-Fit algorithm is implementable on the sub-mesh with any size as sliding frame and can allocate a sub-mesh with the requested size correctly. This algorithm keeps bit map of the status of mesh free and allocated nodes in the array called busy array and according to the job given for allocation, look for busy array algorithm for creating an array called coverage array. Coverage array has been produced by scanning all busy arrays from left to right and top to bottom and returns the address of the first free node found in coverage array as a base node for allocation. Best-Fit method is similar to First-Fit but it returns a node as a job basis node where its sub-mesh has the most allocated neighbors. The simulation results show that First-Fit method is better than Best-Fit. In First-Fit/ Best-Fit, whole mesh must be scanned to find the base node. Therefore, it is the time complexity of algorithm O (N) where N is the number of processors. First-Fit method has not a complete diagnosis. Another drawback of this algorithm is high overhead due to the array manipulation that decreases the popularity of this algorithm, especially in the large meshes.

Discontinuous allocation Algorithms
With the developments in routing techniques such as wormhole switching, delayed communication had a

fewer sensitivity to distances between nodes. These developments led to a more acceptable form of discontinuous allocation in networks with large diameters such as mesh. in a case of sufficient processors for allocation, discontinuous allocation does not seek for data execution and necessarily a continuous pattern. Some non continuous allocation methods will be examined here.

Paging allocation Algorithm
Paging allocation method divides the whole mesh into pages that are sub-meshes with equal sizes and in length 2^{size_index} is larger than or is equal to zero. A page is regarded as an allocation unit. To determine the type of navigation, pages are identified by the same index. Page sizes are expressed by paging(*size index*) . For example, Paging (2) means the pages that composed of sub-meshes with dimensions 4×4. If a job asks for a sub-mesh with dimensions $a \times b$, the number of required pages is calculated by the formula $\left\lceil (a \times b)/P_{size} \right\rceil$ where, Psize is the page size. This algorithm maintains free pages in a list and in a case of request; it allocates from this list and returns it to the list when releasing the page. If in a case of *size index=0,* there is no fragmentation but there is fragmentation with increase in *size index*, time complexity of algorithm is $O(a \times b)$.

Multiple Buddy Systems (MBS) Algorithm
 Binary shape of this algorithm is a developed form of [8]. This method divides mesh network into a square and non-overlapped sub-meshes with dimensions of 2 square. If a job asks for a processor P, this request is converted to the request in base 4. In this way, $P = d_k \times (2^k \times 2^k) + \cdots + d_0 \times (2^0 \times 2^0)$ so that $d_0 \dots d_k \in \{0,1,2,3\}$. Algorithm tries to allocate $d_i \times (2^i \times 2^i)$ according to the available resources. If some blocks do not exist, the algorithm breaks repeatedly the larger blocks and converts them to four smaller partners in order to achieve its intended size.
Four-partners blocks will be $(2^j \times 2^j)$ and four blocks will be $(2^{j-1} \times 2^{j-1})$. In a case of sufficient processors, algorithm is always successful because the smallest part that can be allocated is block 1×1 . Consequently, there will be no fragmentation. Time complexity of this algorithm is O (N) where N is the number of processors in system.
Continuous allocation for mesh multi-computer networks has been proposed. Most previous studies on the negative effects of fragmentation on system performance processors, which arise due to the continuous allocation, has been focused. In the following we describe some approaches are known.An example of processor allocation strategies

have been proposed for two-dimensional mesh multi-computer of Two Dimensional Buddy System (2DBS) , "frame sliders" (FS), "adaptive dynamics" (AS), and the 'allocation of first choice "(FF) and the" best choice "(BF) DBS2 has a very simple structure, but only about a foot square mesh system is implemented and the fragmentation   has many internal and external.
FS method on mesh systems can be implemented with any size, but due to the lack of full recognition sub-mesh, the cause is external fragmentation. The "frame sliders" for its relevance to the desired length and width sub-mesh very incomplete and therefore lots of free sub-mesh ignores the network. AS method is able to efficiently use the rotation of the system when the primary mode of operation was not successful allocation, improve.
In this method, a task for which allocation requests sub-mesh a*b, b*a sub-mesh can be allocated. Time allocation methods for AS compared with the FS longer, because the AS, dynamics processors in the network mesh with the movement as a CPU, along the vertical is done, the FS of the jump size width sub-mesh requested to use will. FF and BF methods are also fully recognized, because these two dimensions do not consider the rotated position.
Examples of discrete methods include random allocation , the allocation-page, multi-assist technique (MBS), Adaptive Non-Contiguous Allocation (ANCA) , adaptive and dynamic allocation of combination multi-assist (AS & MBS) and page variables . In practice, random fragmentation problem goes away, but the interactions between the jobs to be created in a relationship. The degree of coherence among the processors allocated to a page dedicated to the preservation and continuity of the pages with larger size increases. The page size is much larger than the amount of internal fragmentation becomes greater. With emerged MBS system performance increasing compared to the previous solution was found, but MBS also has disadvantages.
For example, despite a sub-mesh joined MBS in the network is equal to or greater than sub-mesh was also asked, In most cases, it was not able to allocate a smaller sub-mesh And apart from that used for the allocation and increases the communication overhead. ANCN incoming requests to Section 2i, the ith iteration splits. At each step, the algorithm tries to find sub-mesh to allocate a request, and if unsuccessful sub-mesh in half and re-scan it.
One of the major drawbacks of this method is that the network does not pay attention to the big sub-mesh and the algorithm always tries to allocate its fragments that do not necessarily cut the pieces in this great free sub-meshnot included and subsequently as a result of a division operation is

performed. If the size of the pieces finally come to an end operations mesh is a large increase communication overhead. AS & MBS algorithm in terms of response time and service time is the same MBS, However, AS & MBS increased overhead allocation problem in large mesh networks. The page variable assignment, allocation unit allocation unit is larger than a CPU but can also be used as MBS and ANCA. Consequently, a variable assignment page in large networks, the time required to reach a final decision.

Rsearch Algorithm; Efficient and Quick Non-Continuous Allocation algorithm(EQNA) for Utilization

Suppose that the input job T (3, 2) has been given to the system and we can do the allocation by use of EQNA algorithm. It is clear form figure (1) that busy sub-meshes include $\beta_2 = \langle 2, 0, 3, 1 \rangle$, $\beta_1 = \langle 0, 0, 1, 2 \rangle$ and $\beta_3 = \langle 4, 3, 5, 5 \rangle$ that were allocated in mesh network M (6, 6). According to the busy sub-meshes and the input job T, the coverage sub-meshes will be $C_T = \{\langle 2,2,5,5\rangle, \langle 0,0,3,1\rangle, \langle 0,0,1,2\rangle\}$ and the reject orizontal and vertical areas are $\delta_{TH} = \langle 0, 5, 5, 5 \rangle$، $\delta_{TV} = \langle 4, 0, 5, 5 \rangle$

The main idea for EQNA algorithm is to collect information from available rows in sub-mesh network via the coverage sub-meshes made of the busy sub-meshes. From this information, we can determine in the shortest time whether there is a node in a row for allocation to the input job T as the base node. This information is merely obtained by the comparison of the coverage sub-meshes and the rows and minimizes the comparisons in search spaces and finally allocation time and waiting time a great degree.

For algorithm performance, it is necessary to introduce a one-dimensional array called *last-covered*, which keeps the very right node covered in each (*x-coordinate*) row in the mesh network. In this article, a set of connected nodes in a row of mesh net is called a piece that begins from the very left node in the row (It is usually zero in definitions). If all the nodes in a piece belong to one of the coverage sub-meshes C_T, then that piece is called "coverage piece". In array j of array *last covered[j]* where, $1 \le j \le b' - 1$, it keeps x-coordinate of the last node of coverage piece in the row j. At the beginning, algorithm calculates reject sub-meshes Δ_T after determination of the coverage sub-meshes according to the dimensions of the input job and eliminates it from whole search domain. Then, we arrange the coverage sub-meshes according to their coordinate Xc of base node parameters in an ascending form and then calculate the values of arrays *last-covered* by the *last-covered* function. If there is no coverage piece in the *j* row, the value of *last-covered[j]* will be zero. For example,

the values of *last-covered[j]* for $\int=0,1,2,3,4$ will be *(3,3,5,0,0)* respectively.

Procedure Submesh Allocation

{

Step 1.*flag←false*. /* flag representing the orientation */

Step 2.*Job_Size= a × b*

Step 3. Decide the orientation of *T* as follows, and determine
the reject set.

if (*flag = false*)

then$T \leftarrow T(w, h)$, $a' \leftarrow a\text{-}w + 1$, $b' \leftarrow b\text{-}h + 1$

else$T \leftarrow T(h, w)$, $a' \leftarrow a\text{-}h + 2$, $b \leftarrow b\text{-}w + 1$

Step 4. Based on current B and T, determine $\vartheta_{\beta,T}$ and Last_covered[j] $(1 \le j \le b' - 1) \leftarrow 0$

For each $\beta\langle x, y, x', y'\rangle$, determine

$\vartheta_{\beta,T}\langle x_c, y_c, x', y'\rangle$

Arrange $\vartheta_{\beta,T}$ s in the increasing order of x_c

For each $\vartheta_{\beta,T}$ (starting from one whose x_c is smallest)

If ($y_c < b'$)

For each row j $(y_c \le j \le \min(y', b' - 1))$

If($x_c \le$ last_covered[j] $+ 1 \le x'$)then last_covered[j] $\leftarrow x'$

Step 5.

$j \leftarrow 1$

while (j <b' AND *last_covered[j]* $+ 1 \ge a'$) /* no freesubmesh is found in the j th row */

$j \leftarrow j + 1$

if (j = b') /* no free submesh found in that orientation */

if (*flag = false*)

then *flag←true* and go back to Step 3

else$i \leftarrow$ (*last_covered[j]* $+ 1$) and go to Step 6. /*a freesubmesh is found */

Step 6.

If (*flag = false*)

then$S \leftarrow <i, j, i + w\text{-}1, j + h\text{-}1>$

else$S \leftarrow <i, j, i + h\text{-}1, j + w\text{-}1>$

Allocate S to T and add S to *B*.

Return success

For example, in figure (1) $\beta_2 = \langle 2,0,3,1\rangle$, $\beta_1 = \langle 0,0,1,2\rangle$ and $\beta_3 = \langle 4,3,5,5\rangle$ and the input job T=(3 , 2) and b'-1=4 , then the *last-covered* is calculated as follows: *last_covered[j] (j=0,1, 2, 3,4)= 0*

By using three coverage sub-meshes β_3 وβ_2، β_1 we get three sub-meshes $\vartheta_{\beta1,T} = \langle 0, 0, 1, 2 \rangle$, $\vartheta_{\beta2,T} = \langle 0, 0, 3, 1 \rangle$ and $\vartheta_{\beta3,T} = \langle 2, 2, 5, 5 \rangle$ then we arrange them as, $\vartheta_{\beta1,T}$, $\vartheta_{\beta2,T}$ and $\vartheta_{\beta3,T}$.

According to the $\vartheta_{\beta1,T}$, the values *last-covered[j]* for j=0, 1, 2 equals 2. For j=0,1 the values of *last-covered[j]* for $\vartheta_{\beta3,T}$ equals to 3 and with the quantity

of *last-covered [2]* is changed and equals to 5. Final value , for 5 element last_covered (left to right) is: (0,*0,5,3,3)* .

As it can be seen, if a node belong to sub-meshβ, it belongs certainly to sub-mesh $\complement_T$. There for, for determining the dependency of a node, we need to examine coverage sub-meshes. And *last-covered* has the necessary information in this regard. By examining the values of this array, we can determine whether a node exists to allocation to a job. Now, we have b=5 and a=4 for allocating a node to the job according to fig.1 and because $last\_covered[j](1 \leq j \leq 3) + 1 \geq a'$, the result of value j is equal to 4. Then, because $last\_covered[4] + 1 < a'$, node$\langle 1,4 \rangle$ can be allocated to the job T as a base node. Note that EQNA algorithm is more time-saving in compared to other methods.

 Procedure   EQNA_Allocate (a,b)

{
Total_Allocated=0
Job_Size= $a \times b$
 Step1. if (number of free processors<Job_Size)
                 Return failure.
 Step2. if (there is a free S(x,y) suitable for S(a,b))
         {
Allocateit using Submesh Allocation *contiguous allocation algorithm.*
          return success.
         }
Step3. $\alpha = a$ and $\beta = b$
Step4. Subtract 1 from max (α, β) if max >1
Step5. if(Total_allocated + $(a \times b)$ >Job_Size go to step4
Step6. if there is a free S (x,y) suitable for $S(a \times b)$
         {
         allocate it using Submesh Allocation.
         Total_allocated = Total_allocated+ $(a \times b)$.
         }
Step7. if (Total_allocated = Job_Size)
                 return success.
         else
                 go to Step4.
}end procedure

In EQNA algorithm, when a parallel job is chosen for the processor allocation, the algorithm begins to search for a mesh in order to find a suitable sub-mesh for the input job. If the requested sub-mesh is found, it will be allocated to the job and the allocation process will be ended. Otherwise, the largest free sub-mesh which can be placed in S (a, b) will be allocated to it. Then the algorithm will search for the largest sub-mesh whose dimensions do not exceed the previous allocated sub-mesh provided that the number of the allocated processors does not exceed the quantity $a \times b$ The last phase is repeated until

$a \times b$ processors are allocated. For example, take into account the mesh situation M (6, 6) which is shown in figure (1) and then suppose that the input job has asked for a sub-mesh with the dimensions 6×2 As we see in the figure, there are no free 6×2 sub-meshes. Therefore, EQNA algorithm of the free $\langle 0, 3, 3, 4 \rangle$ and $\langle 4, 0, 5, 1 \rangle$ sub-meshes are allocated to it as we will explain. First, the algorithm subtracts one unit from the largest angle of the requested sub-mesh; and the result will be sub-mesh 5×2 which does not exist again. The process of subtraction goes on until the sub-mesh 4×2 is obtained which does exist. Then, the algorithm while expressing that the quantity of the processors should not exceed 6×2, will try to choose the sub-mesh whose dimensions does not exceed the previous allocated sub-mesh (4×2) . In this example, $[(4 \times 2) + (4 \times 2)] > (6 \times 2)$ consequently,   the algorithm subtracts one unit from the largest angle of the sub-mesh $(4 \times 2)$and the result of the sub-mesh will be (3×2) . But again, $[(4 \times 2) + (3 \times 2)] > (6 \times 2)$, the subtraction goes on until the summation of the angles of the sub-mesh is less than the dimensions of the allocated submesh or equals the intended processors (6×2) . In this example, (2×2) sub-mesh is obtained which is available in the system. Then, the sub-mesh$\langle 4,0,5,1 \rangle$ is allocated to the job and the process is finished.

Algorithms results comparison for Utilization

Here, we represent the results of the simulation of some continuous and non-continuous allocation methods such as Paging (0)**,** MBS and First-Fit (FF). We perform the algorithm of the allocation and release of these methods with the C language, and as similate it by the as similation software ProcSimity which is a tool for as similating processor allocation and priority given to the job in multi-computers systems .

The mesh model which is used in assimilation is a square mesh with the length of L. The way of producing and entering of jobs are supposed to be of powered distribution and are serviced in the form of FCFS. The time of doing is supposed as the form of powered distribution with the average amount of a time unit. Two kinds of distributions are used for the way of producing the length and the width of the job. The first one is the monotonous distribution on [1, L] in which the length and width of the job are produced separately. The second one is the powered distribution in which the length and the width of the job are produced in the powered form and with the average of half of the entire mesh. These distributions are the ones which are used in most assimilations . Each assimilator is based on a perfect implementation of 1000 jobs. The results of assimilation on a

sufficient number of implementation are averaged. Thus, their reliability is %90 and the error is less than %5. The inter-communication network uses a crawling procedure and an XY routing. Sending fleet data between two adjacent nodes takes a time unit and *t1* time unit is spent for finding the route of the fleet between two nodes. The message length is shown as $[\mathbf{1}, \mathbf{L}]$. The allocated processors use one of the current communication models. The first model is the *all to one* model. In this model, a processor which is randomly chosen from a job sends the data packs to all of the processors of that job. As it has been said in [8, 11, 12], the number of the messages produced by a given job has a powered distribution of an average quantity of *num-mes*. The second communication model is called the *all to all* model in which each allocated processor to a job sends the data packs to all the processors of that job. This communication model creates much message communication involvement in the network and this is the weakness of non- continuous allocation algorithms.

In both models, the processors allocated to a job in a linear array are recorded and are numbered by a network row scanning in the array. The processor as similator choses the starting point and the destination from this array and then determines the starting point and the destination coordinates by a record. The system on which the assimilation is done is a (16×16) mesh in which the $t_s = 3$ time unit and the fleet is $P_{len} = 8$ and the *num-mes=5*

The parameter chosen for comparison is: *mean system utilization*. The average optimum use of the system is the percentage of using system processors during the implementation; and it is estimated as follows:

$$\text{System Utilization} = \sum_{i=1}^{t} \frac{w \times h - n_i}{(w \times h) \times t} \qquad (1)$$

In this formula n_i is the number of free processors of the system in time i and t is the total spent time, and $w \times h$ is the number of the system processors. System loading is an independent parameter in the system which has an invert relation with the *mean inter-arrival of jobs* and is estimated as follows:

$$\lambda = \frac{N \times T_e}{\text{System Load} \times P} \qquad (2)$$

In this formula F is the total number of the processors and the jobs are entered into the system by the potation distribution and the rate of the λ in the time unit. N is the average number of the wanted processors by each job, and T_e is the average powered distribution of the implementation time.

Utilization

Fig.(2) and Fig.(3)   have shown the average productivity of system resources in the allocation algorithms EQNA, MBS, Paging (0) and FF for both communicating models and job size distribution. The assimilation results in these figures are obtained in the system's heavy load. The heavy load, i.e. the waiting line of the system is rapidly filled and causes the allocation algorithm to reach the highest level of using the system's resources. For both job size distributions of non-continuous allocation algorithms they found an average productivity quantity of %71 to %76, but the continuous method FF could not go beyond %50, and this was because doing EQNA operation by other allocation algorithms for both of job size distributions showed a better performance. Also, it has been shown that the allocation is continuously done and after that fragmentation occurred that prevents a good allocation. The average productivity of system resources for non-continuous algorithms for both job size distributions is almost equal and this is because both of these algorithms have the same power in reducing the fragmentation. When the numbers of free processors of the system were equal or more than to the requested processors, these algorithms always do the job allocation successfully.
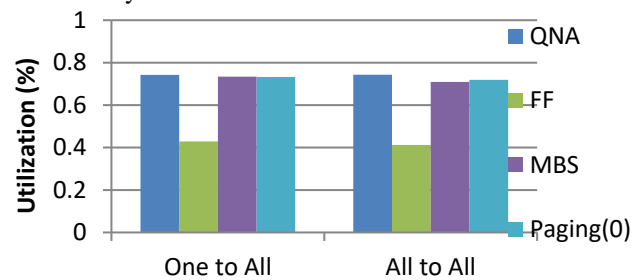

Fig. (2) The optimum use of system resources in continuous and non-continuous methods for both communicating models with monotonous distribution of job dimensions in 16 * 16 sub mesh
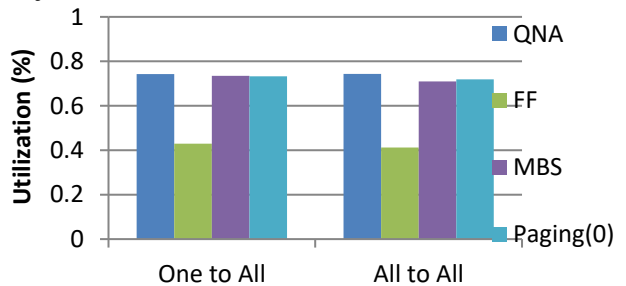

Fig. (3) The optimum use of system resources in continuous and non-continuous methods for both communicating models with powered distribution of job dimensions in 16 * 16 sub mesh

Conclusion

The Utilization of EQNA was compared with the of continuous and non continuous algorithms. The results of assimilations shown that EQNA in spite of

the available communicating in the net, it has been resulted of interference of different jobs messages with each other; it increasing the Utilization to a great extent. EQNA also efficiently takes advantage of the system's resources while keeping maximum consistency and preventing internal and external fragmentation.

Also, the results considerably shown that EQNA with respect to job completion time which is an important parameter of Utilization has superior to known allocation methods such as FF, MBS and Paging (0). Further more; the experiences prove that EQNA also has a better performance in comparison to the previous continuous and non-continuous allocation techniques when the packs are longer and the sub meshes systems have larger dimensions. It is expected that this procedure practically keeps its Utilization because when the sub mesh dimension get larger, it increasing the needs of the programs such as the number of the required processors as well. results of this study can be an effective step to develop super computer.

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11/2/2024