

A Generic Multi Agents System for Multi Criteria Optimized Allocation of Applications on Heterogeneous Architectures

¹Saouli Rachida, ²P.R. Akil Mohamed and ³M.C. Henni Abderrazak

¹Department of Computer Science, BP 145, Mohamed Khider University, Algeria

²Groupe ESIEE, BP 99 2 BD Blaise Pascal, F 93162 Noisy le Grand cedex, France

³INI, Oued Smar, Alger 16000, Alegria

Abstract: We are interested in this research, by the optimized static allocation multi criteria in a real time distributed system when the tasks are subject to precedence's constraints. Within this framework it is necessary to suppose before execution, that all the possible scenarios of executions satisfy the temporal constraints while minimizing the cost and the size of material architecture, as well as the use at best of its resources. In this problem of resource allocation (placement and scheduling), which is NP-Complete, the satisfaction of several criteria can be contradictory. For the resolution of this problem, we propose in this study, a generic multi agent system, which is a dynamic component, coupled with a static strategy of scheduling in order to particularly integrating the criterion of load balancing. Thus, the need for a dynamic model appeared to us with the consideration of the heuristic based on *list scheduling*. An experimental Analysis was realized under programming parallel environment *PVM (Parallel Virtual Machine)* and shows the interest of our method. This for any heuristics using the dates of execution of the tasks (operations) in particular for method *AAA (Algorithm Architecture and Adequacy)* developed with the *INRIA* and which was the subject of several extensions.

Key words: Static placement/scheduling, load balancing, system distributed real time, multi agent systems

INTRODUCTION

The real time systems are founding in fields such as aeronautics, control of industrial processes or telemedicine also embarked systems are in systems of brakes control and engines. These critical systems, whose majority consists of treatments, must imperatively respect all their temporal constraints. A way to satisfy these real time constraints lies in the use of parallel machines multiprocessors, which are possibly heterogeneous. In the study of the real time distributed systems the problems of placement and scheduling are simultaneously encountered and if the model of the graph's algorithm is guided by precedence, it is the total execution time of the system which is considered not only or without^[1] load balancing. Thus within this framework we consider the list scheduling algorithms where, in each stage, a choice is made for the most advantageous placement (faster and satisfying a criterion) and for a given operation^[2]. This adapts perfectly to the systems subjected to temporal constraints. They make it possible to select one processor, for an operation given by primarily using two functions. They correspond to the start and the end dates

of the operation on the operator and load balancing is performing progressively. Then the algorithm maintains up to date two lists: one containing the ready tasks and the other unoccupied processors. It chooses a new task to assign with the free processor (minimal utilization ratio) for which imbalance after placement is minimal. The choice of the task to be scheduled is more difficult. It defines a priority between the tasks available to a given moment. This priority is a function of the temporal characteristics of the tasks or/and structural of the tasks graph and so that the expiries are respected. The selection criterion of a task, takes into account in this case the urgency of the task. In^[3], the attribution of a priority is according to the task's duration time and the maximum of its successors duration time, but this method gives satisfactory results when the communications are null. Extensions to this work^[4] duplicate tasks, what increase the processors use ratio. Other work based on a dating of the events; the rule giving the priority can take into account the duration of the task^[5] or its date of activation at the latest, without considering the constraints neither of precedence nor over resources. In^[6] according to the date of reception of the messages, the earliest ready task

on a given processor, is selected what reduces the choice of the processors and makes difficult the load balancing. In addition, the selection criteria of a task can be restricted by constraints of placement, which limits the selection of a task. These constraints can be related to the heterogeneous operators^[7] intended execute different operations (tasks) who's urgency to be scheduled, follows a function cost called pressure of scheduling. This function corresponds to a difference between the values of penalty and flexibility but without to consider the balancing of load. In^[8] the constraints of placement relate to the mechanisms of faults tolerance. Two criteria are taking into account and are varying dynamically with an order of evaluation, at each request for reconfiguration. Moreover, the heuristics based on these criteria gives a low having imbalance only, for configurations of the too strong constraints, related to the bonds available enter the nodes.

Then we consider that in the problem of resources allocation, the application of several criteria was not solve in the literature by traditional linear methods. Here we consider our model coupled particularly with heuristic developed at INRIA^[1,7], in order to integrate initially the load-balancing criterion not considered yet. The study represents the environment of simulation under PVM as well as the results obtained.

Multi Agent System Multi Criteria (SMA-MC): The methodology used, is basing on the concept of agent. Among the definitions for the concept of agent, we use the one that defines the agent as an autonomous entity, real or abstracted. It is able to act on itself and its environment. In a multi agent universe, it can communicate with other agents. The behavior is the consequence of its observations, its knowledge and interactions with other agents^[9].

Conceptual structures of agents: An agent is located in an environment. To model the structure of the agent, it is necessary to have a model of this environment. The latter can be in a state among a whole of states. It can change its state either in a spontaneous way or like result of the actions of the agent. The evolution of the environment is modeling differently, according to its characteristics, which one takes into account and simplifications that one is authorized^[10].

The characteristics of the environment influence the way in which one designs an agent because it is necessary to take account the environment's evolution and the capacity of the agent to seize this evolution.

The general model of the SMA

The system proposed is based on

A meta agent: from one placement/scheduling heuristic H_i , characterized by use of specifications models of tasks algorithm to allocate and architecture target of processors, the meta agent create (instanting) agents of system. It constitutes *accountancies* of each agent (sure knowledge that an agent has on the other agents of its environment). It establishes the model (*ENV*) of its environment, which corresponds to allocation model. It defines the whole of objectives to reach, as well as the set of the strategies using communication actions. We define the knowledge of the Meta agent as being the whole of the Meta rules, which make it possible to adapt heuristics of placement/scheduling to its SMA.

A generated SMA: where each agent corresponds to a processor composing the model of distributed architecture used in the considered heuristics. This fact by using the base of knowledge BC, the Meta agent generates the system of cognitive agents^[11], which act in thesame definite environment. Each agent will perceive the environment like dynamics and nondeterministic. The environment state can change after actions of other agents or of environment and the same action in a certain state will have different results according to the actions from the other agents.

Detailed description of the agent: To determine the agent's actions of this system, it is necessary to define them like their interactions^[12], with environment and agents. The definition of an agent bases: on the one hand of a universal definition of cognitive agents and on the other hand of a detailed definition corresponding to the logical model. This latter, bases on architecture BDI (Believe, Desire and Intention)^[11] and presented in the Fig. 1.

In Fig. 1, we represent the environment ENV by a plan surrounding the agents that are located there. Each

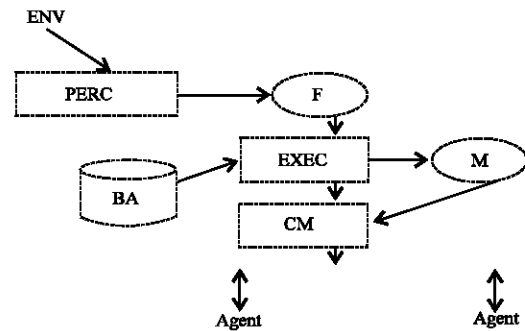


Fig. 1: The logical agent's model

function of the agent is representing by a rectangle surrounding its name. The set of knowledge of the agent (strategies: knowledge and objectives that are Desires and Intentions) corresponds to knowledge base BA. The result of functions modeling an agent is representing by an oval. In addition, double direction arrow represents interaction enters agents and the environment.

The functions of the agent's model locat in its environment are defining below:

PERC: $ENV \rightarrow F$ is the function, which perceives the model of the environment *ENV* and establishes the facts *F*, which are the *beliefs* of the agent.

EXEC: $SxFxB \rightarrow M$ is the kernel function, which allows the achievement of the objectives *B* and established the change(s) *M* on the environment. This is according to strategies *S* available to the agent, to established facts *F*.

CM: $MxC \rightarrow ENV$ is the function, which makes it possible the communication of the change (actions) on the environment according to the established accountants.

The strategies of each agent are the set of rules, which, allow to make a change on the environment and to perform interactions (SI) with the agents of its accountancies. An interaction allows generating a new model of the state of the environment (S1), sending tasks since and from other agents (S2), sending messages information or a new decision (S3) and modifying the model of environment (S4).

The interaction between the agents of this model is realizing according to their accountancies. The agents concerned with this interaction are those, which satisfy the same constraints on the placement/scheduling, or bound by a neigh board's relation. This interaction is performing with the use of a master agent, which is supervising execution of the slave agents' functions. The master maintains, for a certain time theobjectives until their achievements (limited obligation) by slave agents of the system. The result of the perception of environment implies the possibility that the selected objective can be still realizable, or possibly changes by another according to the result of actions performed on theenvironment. In this case, the takeover by a master agent implies master slave relations with the agents of the system, by guiding their actions and their wait, as well as the resolution of possible conflict generated by the mechanisms of decisions of each agent slave.

The criterion of load balancing and the methodology

AAA: Within the framework of real time distributed applications, the methodology AAA (Algorithm,

Architecture, Adequacy) developed with the INRIA heuristic (H_A)^[7] takes into account all the steps of the development of an application, of its high level specification until the execution of the code in the components. An optimized allocation is obtaining by transformation of graphs. It corresponds to one static placement/scheduling of elements of the algorithm on target distributed and heterogeneous architecture. The latter is modeled by a directed graph constituting a network of automates. The set of the nodes of a graph, defining in this case a processor, is of four types: operator, transfer, memories and bus. The required solution bases on the latency, which is in direct relationship to minimization of the communication's cost and corresponds in this case to the length of the critical path of the allocation graph. This methodology bases on a preliminary characterization of the elements of the graph of algorithm and architecture (maximum execution times of the operations on each operator able to execute it ...). It makes it possible to predict the behavior of the application and to build its executive distributed and optimized. Nevertheless, the predictions off lines, in particular the duration time of the operations on the operators of architecture, can be deviated of the real values at the execution time. Indeed these durations, which are at worst case, do not adapt to the data (changes) of execution what can land the system in degradation: an important imbalance in the use of the resources, a not respectedlatency implying a static adaptation and new execution of the allocation.

The definition of the objective (criterion) of load balancing is relating to the improvement of the establishment in heuristics H_A considered. The latter bases on a cost function, which evaluates the urgency to schedule an operation so that the higher it is for an operator, more the value of corresponding flexibility is small and more the critical path is lengthened (penalty). It is thus a question of scheduling each operation candidate on each operator able to execute it and retain the operator minimizing the function cost used. Our system makes it possible to integrate the objective defined according to Fig. 2.

The SMA-MC generates the corresponding SMA and the Meta Agent establishes:

- The slave agents *sl* and the main agent.
- The accountancies of each agent while basing on the constraints of placements.
- The model of the environment state *ENV* that corresponds to the diagram of the allocation sequence,

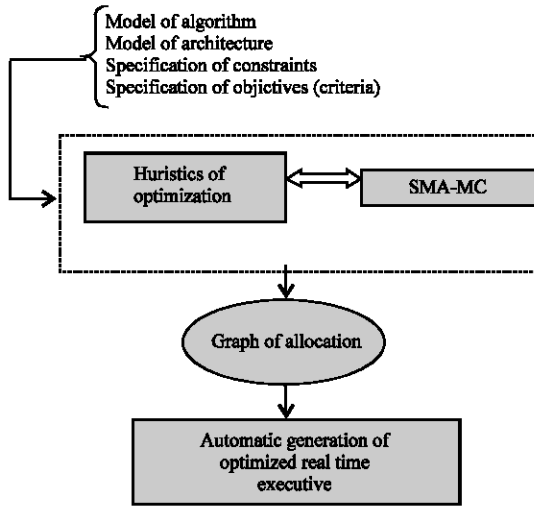


Fig. 2: Mixed system of optimized allocation

- The objectives considered (load balancing) and the strategies (sets of rules or methods) for their realization.

The duration times used: In our method, the strategies of the agent base on a principal characteristic, which relates to the rule of using exact durations of operations on the operators and not an approximation with the average duration, as it is the case in heuristics H_A considered. Indeed let us recall that in the static allocation, if the exact durations can be possibly deviated of the real values at the execution time, the approximate values will only increase these deviations. These execution times correspond to an approximate time calculated for each O_i operation, by an average compared to the number n of Op_j operators able to execute it according to the expression:

$$\Delta_{app}(O_i) = 1/n \sum \Delta(O_i, Op_j) \text{ such as}$$

$\Delta(O_i, Op_j)$ is the exact duration characterized in H_A .

In addition, the earliest end date $E(O_i)$ of an operation O_i corresponds:

$E(O_i) = S(O_i) + \Delta_{app}(O_i)$ such as $S(O_i)$ is the earliest start date which is the greatest date E of its predecessors.

From these dates, the critical path R of the graph of algorithm is the duration of the longest path:

$$R = \text{Max} [E(O_i)]$$

The consequence of using the exact durations in our method, is that we characterize each operation O_i by a start date $S(O_i, Op_j)$ on each operator Op_j .

The principle: the approach proposed aims to balance the loads of the operators to each stage of the heuristics of scheduling. For this, we based on the principle of the dynamic method of balancing SID (Sender Initiative diffusion). However, we have modifying the quantity ($= 1$) of operations to be negotiated for a new scheduling. We have regarding the field of scheduling as being constraints of placement. Finally, we have adding the execution kernel EXEC, to take into account the precedence of the operations. It is thus a question of negotiating the migration of only one operation among those allocated with an agent overloaded according to the following mechanism:

- Perceive scheduling information.
- Each agent estimates its local load: An overloaded agent disseminates information of balancing to the agents of its. Accepted operation generates a minimal scheduling path, which does not lengthen the critical path with this stage.
- Resolve conflict and decision of the scheduling of the selected operations.

The result of the perception PERC (ENV) of the environment makes it possible to establish facts for each agent slave: his local load, the length of local scheduling, as well as the average load in a number of allocated operations defined by:

$\Sigma \text{load} (sl)/n$ where n is the number of agents slaves sl pertaining to the accountancies.

The set of the rules of agents' strategies is applying by kernel function EXEC defined below by the functions EXEC1 and EXEC2 of each agent and makes it possible to evaluate its load LU compared to a value (threshold) preset by using the average of the loads:

Any overloaded agent communicates to its group, the preceding operation maximum earliest end date E_{max} . This date corresponds to each operation allocated to him (according EXEC1).

Any discharged agent tests the operation, which does not lengthen critical path R_n with this stage, based in the exact duration time and the local scheduling path R_{local} (according EXEC2).

Using information received from each agent slave, the master agent applies the actions of change SI of environment. Therefore, for any operation concerned with the action of (new) allocation, a slave will be select after resolution of conflict. The decision of the master is according to whether this operation generates a new minimal local way R_{nouv} on a slave.

The resolution of conflict relates to the case where a several slave agents select the same operation and in this study, the chosen operation is that which checks:

Min (Rn-Rnouv) such as Rn is the path obtained from stage n of the heuristics.

Function 1: EXEC1 (F, B, S)

Require: LPRED {lists of operations scheduled with its preceding ones}

Require: Q {list of the operations scheduled on the agent overloaded}

Require: LCRIT {list of operation in critical path}

Ensure : Emax

Ensure: M {actions's communication}

If (LU-Moy_{load})>threshold then

For all O such that operator (O) = sl do

Emax = maximum (LPRED)

{The maximum earliest end date of the precedents operations}

End For

M = (S3, Emax (Q)) {return the list of Emax of each operation locally scheduled}

End If

If Oi in LCRIT then

Emax = maximum (LPRED (Oi))

{Operation Oi scheduled with this stage}

M = (S3, Emax (Oi))

{Return Emax of the precedent of Oi}

End If

Function 2 EXEC2 (F,B,S)

Require: Q {list of scheduled operations on the overloaded agent}

Require: Emax

Require: Δ (O, sl) {exact duration time of each operation O scheduled on agent sl}

Ensure: M {actions's communications}

If (LU-Moy_{load})<0 then

For all O in Q do

If (Emax (O)<Rlocal)

and (Rlocal+Δ (O, sl)<Rn) then

Rnouv = Rlocal + Δ (O, sl)

min (O) = MINIMUM (Rnouv) {retain operation which doesn't lengthen critical path}

End If

If (Emax (O)>Rlocal) and (Emax (O) +

Δ (O, sl)<Rn) then

Rnouv = Emax (O)+Δ (O, sl)

min (O) = MINIMUM (Rnouv)

End if

End for

M = (S3, min (O)) {local path min generated}

End if

Experimental analysis under PVM: PVM (Parallel Virtual Machine) is a communication system, made up of a library

and a demon. It makes the communications independent of the operating system, where applications use whole machines, potentially heterogeneous and inter-connected by a communication network, like only one computer. Execution applications on pvm distribute tasks on one or more computers constituting the parallel machine. Each task of the virtual machine can emit an unspecified number of messages toward any other task of the machine. Thus, pvm library consists of two principal parts. The first one, which is independent of the operating system, gathers all the functions of management of the tasks pvm and of the groups as well as the high-level communication functions. The second, moreover low level, includes the transfer's functions of the packages on the network, recognizes the system of the host machine and adapts to his architecture. XPVM is the X-Windows version of pvm; it is a representation of machine PVM with the name (s) and type (s) of computer (s) composing it. This menu of window make it possible to control the tasks (menu Tasks), to control the machines (menu Hosts), to stop pvm (menu Reset, Quit, Halt) like having of the assistance (menu Help).

We have realized our simulation by using xpvm under a host Linux: the principal task (level n0) is the task xpvm, which enabled us to activate the execution of the system's agents. In level n1, a group of tasks, main agent (T-M) and k agents slaves (T-sl), are creating and synchronizing with mechanism of barrier. This later makes it possible to block all the agents on this level, until the specified number of agents in simulation was been activated, while arriving at the same point of equivalence. In addition, it allows a dynamically manage of addition other members (agents) to the group. The spawn associates in this level an identifier (TID) with each task created (T-M, T-SL) and which will make it possible pvm to recognize it in the virtual machine.

In addition, we used an index me of membership of the group to identify each task agent member, value 0 allows to initially launching the execution of the main agent (T-M) of our system. The execution scheme (level n2) realized in our method is presented in Fig. 3.

Restrictions were been made because of indeterminism in the creation of the tasks pvm. Then we have limiting our tests to a scenario of extreme imbalance where all operations are been scheduled on only one slave agent. This is why a reduced number (2) of slave agents, was considered. Simulation uses a file test of entries using allocations graphs examples, generated by the heuristics considered. This determines the perception function, realized in this diagram by the main agent. The files tests are been structured in tables, which characterize for each operation, the date's values below:

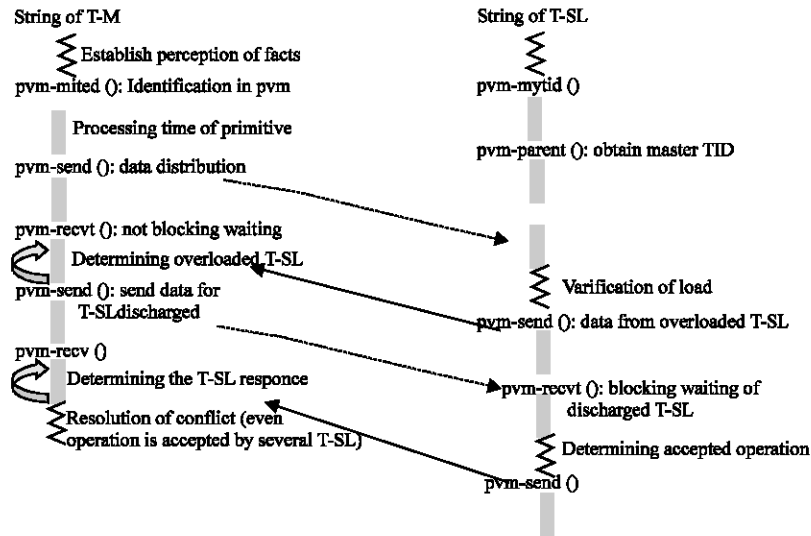


Fig. 3: Model of the agents' execution

- Earliest start date S of scheduled operation on allocated agent.
- Precedents operations of scheduled operations.
- Exact duration of operations on agents.
- Average duration time in the group.

The result of simulation relates to the determination of the operation and the new operator (agent slave) of scheduling in a stage of the heuristic. Indeed, in our case, we use the exact duration over the slave and not the average duration as in heuristic H_A , to test the acceptance of an operation by, a slave. Let us recall that they are here operators modeled by agents. An agent is overload according to following rules:

R1: If (local load-average load in the group) > threshold (=1) then process corresponding to the imbalance generated by H_A in the allocation.

R2: If (an operation belonging to the critical path was scheduled with this stage) then process corresponding to temporal imbalance because of use of average duration in H_A .

Process is the consequence of application of the rules R1 or R2, which allows the agent discharged to determine the operation of which it can be its new agent (operator) of scheduling.

Application of rule R2: That is to say, the sequence of scheduling Fig. 4a generated by heuristics H_A such as operations O_i : (A, B, C, D) scheduled on two operators Op1 and Op2 and characterized by:

Table 1: Evaluation of balancing exact duration time values Δ (then starting date S) to obtain the same duration time's average Δ_{app}

	Δ :				S:			
	Δ_A	Δ_B	Δ_C	Δ_D	S_A	S_B	S_C	S_D
sl1	1	5	1	1	0	1	1	6
sl2	1	3	1	1	0	1	1	4

- Diagram of precedence: PRED (B) =PRED (C) =A and PRED (D) = C,B
- Average durations times:

$$\Delta_{app}(A) = \Delta_{app}(C) = \Delta_{app}(D) = 1 \Delta_{app}(B) = 4$$

Evaluation of balancing by our system: We have establish in Table1, exact duration time values Δ (then starting date S) to obtain the same duration time's average Δ_{app} :

Our method relates to the stage of scheduling operation B that belongs to the critical path and its flexibility is null. Thus, what determined its urgency to be scheduled by H_A . After it's scheduling and with this stage, in our method it is the slave agent sl2, which will be concerned and applied the rule R2 by using the exact durations such as:

$$\text{Min}(\Delta(B, sl1), \Delta(B, sl2)) = 3 \text{ and } \text{Emaxpred} > \text{Rlocal}_{sl2} = (1 > 0)$$

What implies $Rn - (\text{Emaxpred} + 3) > 0$: the critical path Rn corresponding to this stage, does not increase. This agent (sl2) will accept operation B. Here Emaxpred is the end date of the operation A, which is the preceding operation of B. Recall that these values (Emax) are calculated and transmitted in our method, by the agent overloads and used by the slave discharges to test if the operation can be scheduled in it.

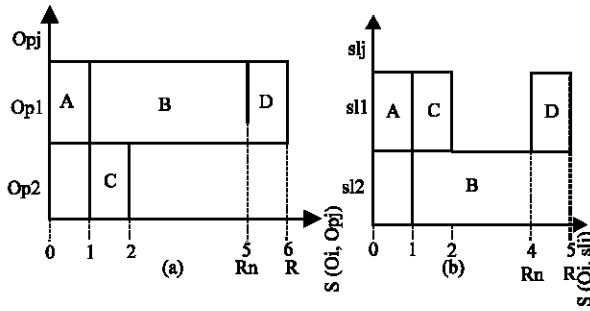


Fig. 4: Diagram temporal before (a) and after load balancing (b)

Table 2: Exact duration times Δ and starting date S values

	Δ :			S :		
	Δ_A	Δ_B	Δ_C	S_A	S_B	S_C
sl1	1	4	1	0	1	5
sl2	1	4	1	0	1	5

Figure 4b presents the result of the primitive pvm-send () generated by the agent sl2. It shows the consequence of this result on the following stages of scheduling of operations C and D.

Application of the rule R1: We illustrate in this example, the application of the rule R1 by our method. It is about the stage after scheduling of three no critical operations O_i : (A,B,C) characterized by:

- A diagram of precedence given by:

$$\text{PRED}(B) = A, \text{PRED}(C) = B$$
- The Table 2 below of exact duration times Δ and starting date S values

Figure 5 a presents the temporal diagram of the sequence of scheduling obtained by heuristics H_A . Fig. 5b presents the result of our method after the application of the rule R1 for this stage. It is thus the agent sl1, which is overload such as:

$(Lu_{sl1} - \text{average load}) = 3 - (3/2) > 1$. Operation A is that accepted by the agent sl2, for it generates a local path minimal (Rlocal) on this agent.

Thus let us note that the improvement of the heuristics, by the integration of the criterion of load balancing allows a better use of operators and/or a profit in the length of scheduling sequence, if the operation concerned with balancing is characterized by a smaller exact duration. Possibly if the rules R1 and R2 are not applied, a decision can related to the reduction of the size of architecture according to operators' which are allocated with no operation.

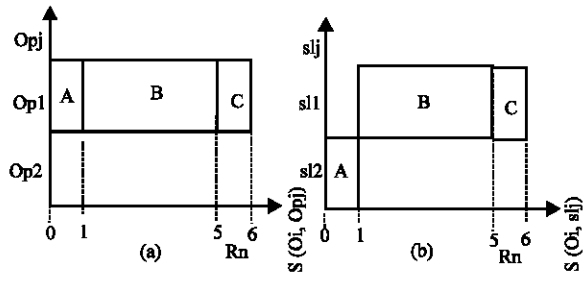


Fig. 5: Diagram temporal before (a) And after load balancing (b)

CONCLUSION

We considered in this work that the problem of the integration of several criteria, to each stage of the placement/scheduling heuristics, is presented in the form of an open system (parallel, asynchronous, indeterminism). We propose in this work a mixed system, which cohabits a dynamic model based cooperative agent with a static model of allocation. Initially, the criterion of load balancing was introducing with taking into account, precedence over operations. These latter are connecting to real time distributed systems that base on the assumption of synchronism extremely related to the logical successions of events and decisions. The system that we propose is generic which, through the Meta agent will try to learn in the past and to found, which and if a criterion is to performing at each stage of the heuristic. These remain then to solve the problem of the adaptation of the multi agent system for heuristics H_A , or others in order to introduce well other criteria not taken into account such as the degree of freedom^[7], the fault-tolerance.

REFERENCES

1. Vicard, A., 1999. Formalization and optimization of distributed real time embarked systems. Ph.D Thesis. University of Paris-XIII, Galileo institute.
2. Munteau Traian and Talbi El Ghazali, 1991. Method of static processes placement on parallel architectures. TSI V.10. n.
3. Wu and Sweeting, 1993. Heuristic Algorithms for task Assignment and Scheduling in Processor Network. Parallel Computing, n20, pp: 1-14.
4. Yang and Gerasoilis, 1993. List Scheduling With and Without Communication Delays. Parallel Computing, n19, pp: 1321-1344.
5. Shirazi, Wang, 1990. Analysis and evaluation of heuristic method for static task scheduling. J. Parallel and Distributed Computing. N.10, pp: 222-232.

6. Shepard Gagné, 1991. A Pre Run Time Scheduling algorithm for hard real time systems. IEEE transactions on software. 17. n7, pp: 669-677.
7. Thierry Grand Pierre, 2000. Modeling of heterogeneous parallel architectures for automatic generating an optimized real time distributed executives. Ph.D Thesis. Paris XI Orsay University.
8. Lanet, J., 1995. Tasks allocation in a distributed system. RTS 95, Paris, pp: 222-231.
9. Jacques Ferber, 1995. Multi agent systems towards a collective intelligence. Intl. Edn.
10. Florea Adina, Daniel Kayser and Stefan Pentiu, 2002. Agents Intelligents. Web course. Polytechnic University of Bucharest.
11. Jean Pierre Müller, 2000. Organizational Modeling multi agent systems. S.E of ARCo.
12. LU and Carey, 1986. Load balanced allocation in locally distributed computer systems. Computer Science Technical Report 633. University of Wisconsin.