Multiprocessor Systems

Multiprocessor System

- We will look at shared-memory multiprocessors
  - More than one processor sharing the same memory
- A single CPU can only go so fast
  - Use more than one CPU to improve performance
  - Assumes
    - Workload can be parallelised
    - Workload is not I/O-bound or memory-bound
- Disks and other hardware can be expensive
  - Can share hardware between CPUs

Types of Multiprocessors (MPs)

- UMA MP
  - Uniform Memory Access
  - Access to all memory occurs at the same speed for all processors.
- NUMA MP
  - Non-uniform memory access
  - Access to some parts of memory is faster for some processors than other parts of memory
- We will focus on UMA

Bus Based UMA

Simplest MP is more than one processor on a single bus connect to memory (a)

- Bus bandwidth becomes a bottleneck with more than just a few CPUs

Bus Based UMA

- Each processor has a cache to reduce its need for access to memory (b)
  - Hope is most accesses are to the local cache
  - Bus bandwidth still becomes a bottleneck with many CPUs

Cache Consistency

- What happens if one CPU writes to address 0x1234 (and it is stored in its cache) and another CPU reads from the same address (and gets what is in its cache)?
Cache Consistency

- Cache consistency is usually handled by the hardware.
  - Writes to one cache propagate to, or invalidate appropriate entries on other caches
  - Cache transactions also consume bus bandwidth

Bus Based UMA

- To further scale the number processors, we give each processor private local memory
  - Keep private data local on off the shared memory bus
  - Bus bandwidth still becomes a bottleneck with many CPUs with shared data
  - Complicate application development
    - We have to partition between private and shared variables

Bus Based UMA

- With only a single shared bus, scalability is limited by the bus bandwidth of the single bus
  - Caching only helps so much
- Alternative bus architectures do exist on high-end machines

UMA Crossbar Switch

- Pro
  - Any CPU can access any available memory without blocking
- Con
  - Number of switches required scales with $n^2$
    - 1000 CPUs need 1000000 switches

Summary

- Multiprocessors can
  - Increase computation power beyond that available from a single CPU
  - Share resources such as disk and memory
- However
  - Shared buses (bus bandwidth) limit scalability
    - Can be reduced via hardware design
    - Good cache locality together with private data where possible
- Question
  - How do we construct an OS for a multiprocessor?
    - What are the issues?
Each CPU has its own OS
- Statically allocate physical memory to each CPU
- Each CPU runs its own independent OS
- Share peripherals
- Each CPU (OS) handles its processes

**Issues**
- Each processor has its own scheduling queue
  - We can have one processor overloaded, and the rest idle
- Each processor has its own memory partition
  - We can cause one processor thrashing, and the others with free memory
  - No way to move free memory from one OS to another
- Consistency is an issue with independent disk buffer caches and potentially shared files

Master-Slave Multiprocessors
- OS (mostly) runs on a single fixed CPU
  - All OS tables, queues, buffers are present/manipulated on CPU 1
- User-level apps run on the other CPUs
  - And CPU 1 if there is spare CPU time
- All system calls are passed to CPU 1 for processing

**Issue**
- Master CPU can become the bottleneck
Symmetric Multiprocessors (SMP)

- OS kernel run on all processors
  - Load and resource are balance between all processors
  - Including kernel execution
- Issue: Real concurrency in the kernel
  - Need carefully applied synchronisation primitives to avoid disaster

Issue: Real concurrency in the kernel
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Symmetric Multiprocessors (SMP)

- One alternative: A single mutex that make the entire kernel a large critical section
  - Only one CPU can be in the kernel at a time
  - Only slightly better solution than master slave
  - Better cache locality
  - The "big lock" becomes a bottleneck when in-kernel processing exceed what can be done on a single CPU

Better alternative: identify largely independent parts of the kernel and make each of them their own critical section
- Allows more parallelism in the kernel
- Issue: Difficult task
  - Code is mostly similar to uniprocessor code
  - Hard part is identifying independent parts that don’t interfere with each other

Example:
- Associate a mutex with independent parts of the kernel
- Some kernel activities require more than one part of the kernel
  - Need to acquire more than one mutex
  - Great opportunity to deadlock!!!
- Results in potentially complex lock ordering schemes that must be adhered to

Example:
- Given a "big lock" kernel, we divide the kernel into two independent parts with a lock each
  - Good chance that one of those locks will become the next bottleneck
  - Leads to more subdivision, more locks, more complex lock acquisition rules
  - Subdivision in practice is (in reality) making more code multithreaded

Real life Scalability Example

- Early 1990’s, CSE wanted to run 80 X-Terminals off one or more server machines
- Winning tender was a 4-CPU bar-fridge-sized machine with 256M of RAM
  - Eventual config 6-CPU and 512M of RAM
  - Machine ran fine in all pre-session testing
Real life Scalability Example

- Students + assignment deadline = machine unusable

To fix the problem, the tenderer supplied more CPUs to improve performance (number increased to 8)
- No change???

Eventually, machine was replaced with
- Three 2-CPU pizza-box-sized machines, each with 256M RAM
- Cheaper overall
- Performance was dramatically improved!!!!!
- Why?

Real life Scalability Example

- Paper:

  - The 4-8 CPU machine hit a bottleneck in the single threaded VM code
    - Adding more CPUs simply added them to the wait queue for the VM locks
  - The 2 CPU machines did not generate that much lock contention and performed proportionally better.

Lesson Learned

- Building scalable multiprocessor kernels is hard
- Lock contention can limit overall system performance

Multiprocessor Synchronisation

- Given we need synchronisation, how can we achieve it on a multiprocessor machine?
  - Unlike a uniprocessor, disabling interrupts does not work.
    - It does not prevent other CPUs from running in parallel
  - Need special hardware support

Recall Mutual Exclusion with Test-and-Set

<table>
<thead>
<tr>
<th>enter_region:</th>
</tr>
</thead>
<tbody>
<tr>
<td>TSL REGISTER <code>LOCK</code></td>
</tr>
<tr>
<td>CMP REGISTER <code>#0</code></td>
</tr>
<tr>
<td>JNE enter_region</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>leave_region:</th>
</tr>
</thead>
<tbody>
<tr>
<td>MOVE LOCK <code>#0</code></td>
</tr>
<tr>
<td>RET</td>
</tr>
</tbody>
</table>

Entering and leaving a critical region using the TSL instruction
Test-and-Set

- Hardware guarantees that the instruction executes atomically.
  - Atomically: As an indivisible unit.
  - The instruction can not stop half way through

Test-and-Set on SMP

- It does not work without some extra hardware support

![Diagram of CPU and Memory](image)

1. CPU 1 reads a 0
2. CPU 2 reads a 0
3. CPU 1 writes a 1
4. CPU 2 writes a 1

Test-and-Set on SMP

- A solution:
  - Hardware locks the bus during the TSL instruction to prevent memory accesses by any other CPU

![Diagram of CPU and Memory](image)

1. CPU 1 reads a 0
2. CPU 2 reads a 0
3. CPU 1 writes a 1
4. CPU 2 writes a 1

Test-and-Set on SMP

- Test-and Set is a busy-wait synchronisation primitive
  - Called a spinlock

- Issue:
  - Lock contention leads to spinning on the lock
    - Spinning on a lock requires bus locking which slows all other CPUs down
    - Independent of whether other CPUs need a lock or not
    - Causes bus contention

Reducing Bus Contention

- Read before TSL
  - Spin reading the lock variable waiting for it to change
  - When it does, use TSL to acquire the lock
- Allows lock to be shared read-only in all caches until its released
  - No bus traffic until actual release
- No race conditions, as acquisition is still with TSL

```c
start:
while (lock == 1);
r = TSL(lock)
if (r == 1)
goto start;
```
Reducing Bus Contention

- If lock fails, use exponential back-off algorithm
  - Wait a longer and longer time before trying again
  - 2 instructions, 4, 8, 16 etc
  - Up to a maximum
  - High maximum gives lower bus contention
  - Low maximum gives more responsive locks

```
start:
r = TSL(lock)
if (r == 1) {
  exp_wait();
goto start;
}
```

MCS Locks

- Each CPU enqueues its own private lock variable into a queue and spins on it
  - No contention
- On lock release, the releaser unlocks the next lock in the queue
  - Only have bus contention on actual unlock
  - No starvation (order of lock acquisitions defined by the list)

Other Hardware Provided SMP Synchronisation Primitives

- Atomic Add/Subtract
  - Can be used to implement counting semaphores
- Exchange
- Compare and Exchange
- Load linked; Store conditionally
  - Two separate instructions
    - Load value using load linked
    - Modify, and store using store conditionally
  - If value changed by another processor, or an interrupt occurred, then store conditionally failed
  - Can be used to implement all of the above primitives
  - Implemented without bus locking

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Spinning versus Switching

- Remember spinning (busy-waiting) on a lock made little sense on a uniprocessor
  - The was no other running process to release the lock
  - Blocking and (eventually) switching to the lock holder is the only option.
- On SMP systems, the decision to spin or block is not as clear.
  - The lock is held by another running CPU and will be freed without necessarily blocking the requestor

Spinning versus Switching

- Blocking and switching
  - to another process takes time
    - Save context and restore another
    - Cache contains current process not new
  - Adjusting the cache working set also takes time
  - TLB is similar to cache
  - Switching back when the lock is free encounters the same again
  - Spinning wastes CPU time directly
- Trade off
  - If lock is held for less time than the overhead of switching to and back
  ⇒ It’s more efficient to spin

Spinning versus Switching

- The general approaches taken are
  - Spin forever
  - Spin for some period of time, if the lock is not acquired, block and switch
    - The spin time can be
      - Fixed (related to the switch overhead)
      - Dynamic
        » Based on previous observations of the lock acquisition time
Preemption and Spinlocks

• Critical sections synchronised via spinlocks are expected to be short
  – Avoid other CPUs wasting cycles spinning
• What happens if the spinlock holder is preempted at end of holder’s timeslice
  – Mutual exclusion is still guaranteed
  – Other CPUs will spin until the holder is scheduled again
⇒ Spinlock implementations disable interrupts in addition to acquiring locks to avoid lock-holder preemption

Multiprocessor Scheduling

• Given $X$ processes (or threads) and $Y$ CPUs,
  – how do we allocate them to the CPUs

A Single Shared Ready Queue

• When a CPU goes idle, it take the highest priority process from the shared ready queue

Single Shared Ready Queue

• Pros
  – Simple
  – Automatic load balancing
• Cons
  – Lock contention on the ready queue can be a major bottleneck
    • Due to frequent scheduling or many CPUs or both
  – Not all CPUs are equal
    • The last CPU a process ran on is likely to have more related entries in the cache.

Affinity Scheduling

• Basic Idea
  – Try hard to run a process on the CPU it ran on last time

Two-level Scheduling

• Each CPU has its own ready queue
• Top-level algorithm assigns process to CPUs
  – Defines their affinity, and roughly balances the load
• The bottom-level scheduler:
  – Is the frequently invoked scheduler (e.g. on blocking on I/O, a lock, or exhausting a timeslice)
  – Runs on each CPU and selects from its own ready queue
    • Ensures affinity
  – If nothing is available from the local ready queue, it runs a process from another CPUs ready queue rather than go idle
Two-level Scheduling

• Pros
  – No lock contention on per-CPU ready queues in the (hopefully) common case
  – Load balancing to avoid idle queues
  – Automatic affinity to a single CPU for more cache friendly behaviour

Gang Scheduling

• We assumed thus far that processes (or threads) are independent
  – What happens if they are not?
    • Here A must wait until its next timeslice to get the message
    • Could go much faster if A's were scheduled together
    • Similar problems can occur with synchronisation between threads

Gang Scheduling

• The approach
  – Groups of related threads are scheduled together as a gang
  – All members of the gang run simultaneously, on different CPUs
  – All gang members start and end their time slice together