ASSIGNMENT 3 - Modifying the CFS scheduler

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Code (test.c) -

Using omp_get_wtime() we get elapsed wall clock time in seconds. The time is measured per thread. We need to include the omp.h package.

To show the difference between using soft real time guarantee and not using it, I have used two while loops.

First while loop for with the soft real time guarantee. For each loop a child process is created and it's corresponding parent's rtnice is increased using the syscall call rtnice. Here every loop or every child created have a specific soft real time guarantee given.

Then we print each process' execution time.

Second while loop for without the soft real time guarantee. For each loop a child process is created

Then we print each process' execution time.

Code(rtnice.c)

If the pid is wrong then an error is send else we search for the pid in the task-struct Correspondingly, we then intiatize the rtnice to the soft-real guarantee provided. If the soft-real guarantee is less than 0, error is send.

Changes made-

These changes are made in the linux-5.9.1/kernel/sched/fair.c

- 1.) entity_before We compare the rt_nice of inputted sched_entities. When both are zero, then comparison is according to the vruntimes.
- 2.)update_curr Now we check if rt_nice of any sched_entity >0 then the rt_nice gets updated rather than the vruntime.

We have also intitialized the rt_nice in the linux-3.19_new/kernel/sched/core.c.

INPUT-

I have hardcored, the inputs which can be changed.

We need to provide the pid, which is generated using getpid() after fork.

Also, along with it, the soft real time guarantee is needed.

OUTPUT-

The execution time of the processes are stated.

First for with the soft real time guarantee, the execution time is stated which should be less than for without the soft real time guarantee in most of the cases.

SAMPLE TEST CASE OR SCRIPT-

WITH THE SOFT REAL GUARANTEE-

Pid is already generated, if to specify otherwise for error we can give it as <0.

Also, for the 4 guarantees, I have provided one as -1 to show error.

Others are provided in the screenshot.

NOTE: The values can be changed in the file.

ERROR HANDLING-

- 1)When the pid <0 an error is shown.
- 2) when the soft real time guarantee is <0 error is shown.

SCREENSHOTS-



