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Deadline Constrained Cloud Computing Resources Scheduling Through An Ant Colony System Approach

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Abstract—Cloud computing resources scheduling is essential for executing workflows in the cloud platform because it relates to both the execution time and execution costs. In solving the problem of optimizing the execution costs while meeting deadline constraints, we developed an efficient approach based on ant colony system (ACS). For scheduling T tasks on R resources, an ant in ACS represents a solution with T dimensions, with each dimension being a task and the value of each dimension being an integer ranges in $[1, R]$ to indicate scheduling the task on which resource. With such solution encoding, the ant in ACS constructs a solution in T steps, with each step optimally selecting one resource from the R resources, according to both the pheromone and heuristic information. Therefore, the solution encoding is very simple and straight to reflect the mapping relation of tasks and resources. Moreover, the solution construct process is very natural to find optimal solution based on the encoding scheme. We have conducted extensive experiments based on workflows with various scales and various cloud resources. We compare the results with those of particle swarm optimization (PSO) and dynamic objective genetic algorithm (DOGA) approaches. The experimental results show that ACS is able to find better solutions with a lower cost than both PSO and DOGA do on various scheduling scales and deadline conditions.

Keywords— cloud computing, resource scheduling, deadline constrained, task scheduling, ant colony system

I. INTRODUCTION

Cloud computing has developed rapidly in recent years. According to the NIST's definition, cloud computing is "a model for enabling ubiquitous, convenient, on-demand network access to a shared pool of configurable computing resources that can be rapidly provisioned and released with minimal management effort or the interaction of service providers"[1].

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Therefore, cloud computing has lots of computing resources, e.g., virtual machine (VM), that users can lease these resources following their demand to execute the workflow [2][3][4].

Now in the era of "Big Data", the workflows frequently contain large scale of data that may need a large number of computing servers with cloud computing being considered as the best way to deal with such workflows. As is mentioned that the scale of data is large, so how to schedule those tasks to the proper resources is an important problem because good method can generate a scheduling scheme with high efficiency while keeping the cost low. As the workflow scheduling is a complex NP-hard problem, intelligent computing algorithm is a great approach to solving it. Many scientists have done some research on it. For example, the works by Chen and Zhang [5], Malawski *et al.* [6], Mao and Humphrey [7], and Rahman *et al.* [8] proposed evolutionary computation based algorithms to solve the resource scheduling problem. However, many of these researches do not consider the elasticity and heterogeneity of the resource in cloud computing. In addition, execution time is always considered as the only optimization objective neglecting the schedule cost. But in fact, the schedule cost should also be taken in to consideration because investment is an important factor in the business that cannot be ignored.

In 2014, a deadline based resource provisioning and scheduling algorithm was proposed by Rodriguez and Buyya [9]. The model attempts to find the solution that can meet the deadline constraint and at an optimal cost. It struck a balance between the cost and time to obtain maximum profit. Although the PSO approach they proposed has some promising results, there are still rooms for enhancement. The PSO approach makes use of the resource index to encode the resource. However, the index is just a symbol which does not represent any character of the resource, which leads to the flight of the PSO with certain blindness. Moreover, the PSO approach does not perform well in the situation of tight deadline for large scale workflow. Later, Li *et al.* [10] proposed to use renumber strategy to enhance the PSO and also extended the scheduling to multiobjective optimization [11].

In 2015, Chen *et al.* [12] proposed a dynamic objective genetic algorithm (DOGA) approach to solve the deadline based cloud resource scheduling model. In DOGA, the encoding problem of PSO has been solved. Moreover, DOGA uses dynamic objective strategy which focuses on execution time first, that is, to find the feasible solution to meet the deadline constraint, and subsequently focus on the execution cost after the feasible solution is found. Therefore, DOGA can find better results than PSO does. Nevertheless, DOGA still cannot obtain solution with execution cost small enough and fails to meet very tight deadline constraint. Moreover, the mutation and crossover are quite inefficiency because they are highly dependent on randomness.

In this paper, we proposed an ant colony system (ACS) based approach to solve the deadline based cloud resource scheduling model. In ACS, heuristic information is used to guide the search. In this paper, we make use of information such as the price of resource, the size of tasks and the topology structure of tasks. With heuristic information, the algorithm can give a good guidance during the construction of the solution. Compared to the random initialization of PSO and DOGA, our ACS approach can find a better solution even in the first generation with the guidance of heuristic value.

For solving the problem of scheduling T tasks on R resources, an ant in ACS represents a solution with T dimensions, with each dimension being a task and the value of each dimension being an integer ranges in $[1, R]$ to indicate scheduling the task on which resource. With such solution encoding, the ant in ACS constructs a solution in T steps, with each step optimally selecting one resource from the R resources, according to both the pheromone and heuristic information. Therefore, the solution encoding is very simple and straight to reflect the mapping relation of tasks and resources. Moreover, the solution construct process is very natural to find optimal solution based on the encoding scheme.

The rest of this paper is organized as follows. Section II presents some background introductions of the deadline based model [9] and fitness evaluation. Section III presents the ACS approach. Section IV presents the experimental results. Finally, Section V presents the conclusion.

II. BACKGROUND

A. The Workflow Scheduling Model

Fig. 1 is an example of a workflow model. The tasks of the workflow have the topology structure, for example, t_2 cannot be executed until t_1 's execution is finished. Moreover, a parent's task needs to transfer data to its child tasks when they are executed in different resources. We represent the time to transfer data in the link between parent task and child task.

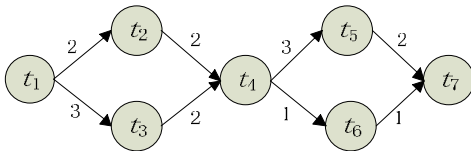


Fig. 1. A simple workflow model

Two objectives 'total execution time' (TET) and 'total execution cost' (TEC) are defined in Eqs. (1) and Eqs. (2).

$$TET = \max \{ET_{t_i} \mid t_i \in T\} \quad (1)$$

$$TEC = \sum_{j=1}^{|R|} (C_{r_j} \times (LET_{r_j} - LST_{r_j})) \quad (2)$$

where ET_{t_i} represents the 'end time' that the task t_i ends its execution. C_{r_j} represents the cost to lease the resource r_j for a unit of time. LST_{r_j} represents the 'lease start time' of r_j while LET_{r_j} represents the 'lease end time' of r_j . TET is calculated by the end time of the task which ends its execution lastly. TEC is calculated by the sum of the cost to lease every resource while the cost to lease every resource is calculated by multiplying the cost of the resource by its lease time.

The model's goal is to minimize the cost and to meet the deadline constraint. The formulation of the optimization objective is shown in Eqs. (3) and Eqs. (4).

$$\text{Minimize } TEC \quad (3)$$

$$TET < \text{deadline} \quad (4)$$

B. Scheduling Scheme

In ACS, the encode scheme of an ant uses the index of the task and resource to encode the solution. Every dimension represents the corresponding task and its value represents the resource it runs on. A simple example of encoding with 7 tasks and 3 resources is shown in Fig. 2.

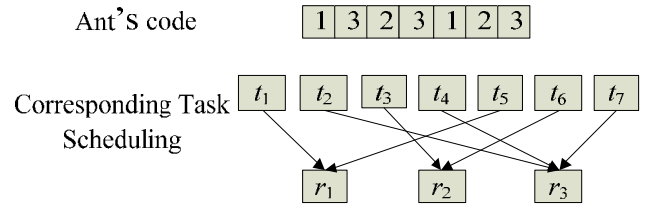


Fig. 2. An example of ACS encoding for workflow scheduling

C. Fitness Evaluation

As we use Eqs. (3) and Eqs. (4) to evaluate an ant's fitness, a function should be declared to obtain TEC and TET . Before we declare the function, we first define some data needed for the function. We define the array *exetime* to represent the execution time, for example, $exetime[i][j]$ represents the time needed for task t_i to run on the resource r_j . We also define the array *transfertime* to represent the time needed for the parent task to transfer data to its child, for example, $transfertime[i][j]$ represents the time needed for task t_i to transfer data to task t_j . Fig. 3 shows example of *transfertime* and *exetime* arrays, generated based on Fig. 1 and Fig. 2.

Since all the relevant variables are identified, we can obtain the workflow scheduling. Fig. 4 shows the workflow scheduling generated from Fig. 2 and Fig. 3.

	t_1	t_2	t_3	t_4	t_5	t_6	t_7		r_1	r_2	r_3
$transfertime = t_4$	0	2	3	0	0	0	0	} $exetime = t_4$	1	6	4
	0	0	0	2	0	0	0		4	5	6
	0	0	0	2	0	0	0		3	6	8
	0	0	0	0	3	1	0		2	2	3
	0	0	0	0	0	0	2		3	1	4
	0	0	0	0	0	0	1		3	2	6
	0	0	0	0	0	0	0		5	6	8

Fig. 3. An example of *transfertime* and *exetime* in a workflow

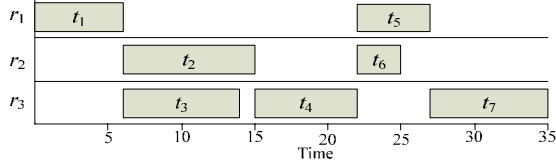


Fig. 4. Example of workflow scheduling.

Obtain *TEC* and *TET*

Input: array $ant[T]$ represents a solution
Output: *TEC* and *TET*
Void Obtain_*TEC*_*TET*()
{
 $R = \emptyset, TEC = 0, TET = 0$
 for $i=0$ to $i=T-1$
 if t_i has no parents
 $ST_{t_i} = LET_{r_{ant[i]}}$
 else
 $ST_{t_i} = \max(\max\{ET_{t_p} : t_p \in \text{parents}(t_i)\}, LET_{r_{ant[i]}})$
 end if
 $exe = exetime[i][ant[i]]$
 $transfer = 0$;
 for each child t_c of t_i
 if t_c is not mapped to $r_{ant[i]}$
 $transfer += transfertime[i][c]$
 end if
 end for each
 $PT_{ant[i]}^{r_{ant[i]}} = exe + transfer$
 $ET_{t_i} = PT_{ant[i]}^{r_{ant[i]}} + ST_{t_i}$
 if $r_{ant[i]} \notin R$
 $R = R \cup \{r_{ant[i]}\}$
 $LST_{r_{pos[i]}} = ST_{t_i}$
 end if
 $LET_{r_{pos[i]}} = ET_{t_i}$
 end for each
 $TET = \max\{ET_{t_i} : t_i \in T\}$
 $TEC = \sum_{i=1}^{|R|} C_i * (LET_{r_i} - LST_{r_i})$
}

Fig. 5. The pseudo-code to calculate *TEC* and *TET*

The pseudo-code to calculate *TEC* and *TET* is shown in Fig. 5, which is also found in our previous paper [12]. The first step is to initialize *TET*, *TEC*, and *R*. *R*, which is initialized as \emptyset , represents the set of resource that the workflow leases during the execution. Next, every coordinate i is iterate through. For task t_i , the resource is obtained from executing the array $ant[i]$. For t_i 's start time ST_{t_i} , the value is determined by the following criteria, that is, if t_i has no parent, ST_{t_i} is equal to $LET_{r_{ant[i]}}$. And if t_i has parent t_p , t_i 's ST_{t_i} is equal to the time after t_p end its execution. t_i 's processing time PT_{t_i} is equal to execution time exe plus the time that t_i use to transfer data to its child, named *transfer*. The end time of t_i , ET_{t_i} , is calculated by ST_{t_i} plus PT_{t_i} . If $r_{ant[i]}$ isn't in the set of *R*, which means $r_{ant[i]}$ hasn't been leased, the lease start time of $r_{ant[i]}$ $LST_{r_{ant[i]}}$, is equal to ST_{t_i} while the lease end time $LET_{r_{ant[i]}}$ is the end time of t_i . Finally, *TEC* and *TET* can be obtained through Eqs. (1) and (2).

III. ACS APPROACH

A. Solution Encoding

ACS was proposed by Dorigo and Gambardella in 1997, inspired by the foraging behavior of ants [13]. The ACS algorithm is designed to solve discrete combinational optimization problem (COP), e.g., the traveling salesman problem (TSP). In this paper, we find that the cloud resource scheduling problem for workflow execution is a kind of COP that is much suitable solved by ACS. Comparing to the process of using ACS for TSP, every task selects its execution resource similar to that every city select its path to the next city. As shown in Fig. 6, an ant represents a solution, denoting which resource is executed on for each task. In our proposed ACS approach, it has similar algorithmic structure to traditional ACS for TSP that our ACS selects the optimal resource for each task step by step.

According to the illustration of Fig. 6, ACS uses integer to encode the solution. As shown in Fig. 2, the coordinate i 's value represents the resource that t_i runs on. For example, $dim_i=j$ represents that t_i runs on the resource r_j . Therefore, in Fig. 6, task t_1 is scheduled on r_2 , tasks t_2 and t_3 are scheduled on r_1 , task t_4 is scheduled on r_3 , task t_5 is scheduled on r_m , while task t_n is scheduled on r_2 .

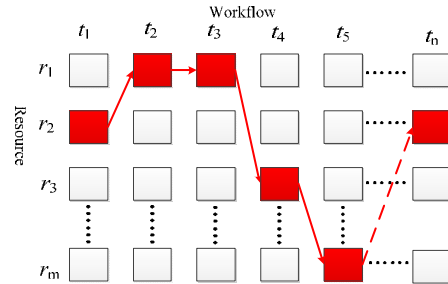


Fig. 6. Illustration of a solution of an ant in search.

B. Initialization of Pheromone

In traditional ACS for TSP, the calculation of τ_0 , which is the initial value of pheromone, is $\tau_0 = 1 / (D \times C^{DD})$, where D is the number of city and C^{DD} is the route generated by greedy algorithm. In our cloud computing scheduling model, we set the number of task, which is $|T|$, as D . We first use greedy algorithm to obtain a solution $S_g[i]$ by Eq. (5). Then we calculate the *TEC* of $S_g[i]$ and use it as C^{DD} . As a result, τ_0 is calculated by Eq. (6).

$$S_g[i] = \sum_{i=0}^{|T|-1} \arg \min (exetime(i, j) \times C[j]) \quad (5)$$

$$\tau_0 = 1 / (|T| \times TEC_{S_g}) \quad (6)$$

The τ_0 is the initial value of all the pheromone $\tau(i, j)$ that deployed on every (task, resource) pair.

C. Construction of Solution

After initializing all the pheromone $\tau(i, j)$ with the value of τ_0 , ACS goes to the solution construction process for all the ants.

In this process, ants will construct their solutions in parallel, which means all the ants will select resource for t_0 , in the first step, then all the ants go to the second step to select resource for t_1 , and so on, until the $|T|^{th}$ step for all the ants selecting resource for $t_{|T|-1}$.

In each step, every ant will select resource for the corresponding task in two ways, exploitation and exploration, which is shown in Eq. (7). For t_i , we will first generate a random number $q \in [0, 1]$, if $q \leq q_0$, the ant will do exploitation, that is, the ant will greedily select the high pheromone value and heuristic value. Otherwise, the ant will select the resource by roulette wheel selection. The formulation of roulette wheel selection is shown in Eq. (8), where $p(i, j)$ represents the probability for t_i to select r_j .

$$r_{t_i} = \begin{cases} \arg \max \{ [\tau(i, j)] \times [\eta(i, j)]^\beta \} & q \leq q_0 \\ \text{Roulette Wheel Selection} & q > q_0 \end{cases} \quad (7)$$

$$p(i, j) = \frac{[\tau(i, j)] \times [\eta(i, j)]^\beta}{\sum_{j=0}^{|R|-1} [\tau(i, j)] \times [\eta(i, j)]^\beta} \quad (8)$$

Herein, the $\tau(i, j)$ is the pheromone value between the task t_i and the resource r_j . The $\eta(i, j)$ is the heuristic information value between the task t_i and the resource r_j that indicating the desirable of scheduling the task t_i on the resource r_j . In order to obtain the heuristic information value, we consider the cost for execute time. The cost for execute time of scheduling the task t_i on the resource r_j is calculated as:

$$exe_cost = exetime[i][j] \times C[j] \quad (9)$$

Therefore, the $\eta(i, j)$ is calculated as:

$$\eta[i][j] = \frac{1}{exe_cost} \quad (10)$$

D. Pheromone Updating Rules

1) Global Updating Rule

After every generation, we will change the pheromone value of the globally best solution. The formulation is shown in Eq. (11), where ρ is the evaporation rate and $\Delta\tau_b(i, j)$ is calculated by Eq. (12).

$$\tau(i, j) = (1 - \rho) \times \tau(i, j) + \rho \times \Delta\tau_b(i, j), \quad \forall (i, j) \in S_{best} \quad (11)$$

$$\Delta\tau_b(i, j) = 1 / TEC_{best} \quad (12)$$

2) Local Updating Rule

During the construction of the solution, the pheromone value changes as volatilization occurs due to both the new pheromone amount deposited by ants on the route and to pheromone evaporation. For example, an ant choses r_j for t_i , the route (i, j) 's pheromone value will volatilized. The formulation is shown in Eq. (13), where ξ is volatilization rate.

$$\tau(i, j) = (1 - \xi) \times \tau(i, j) + \xi \times \tau_0 \quad (13)$$

E. Flowchart of the ACS

To facilitate software programing of our algorithm, if the solution's *TET* is larger than the deadline, we define the *TEC* as 1,000,000, a figure that far exceeds the feasible solution's *TEC*. We identify that the algorithm cannot find a solution if a feasible solution is not found within 10000 generations.

The whole flowchart of using ACS to optimally schedule the cloud tasks on cloud resources is shown in Fig. 7.

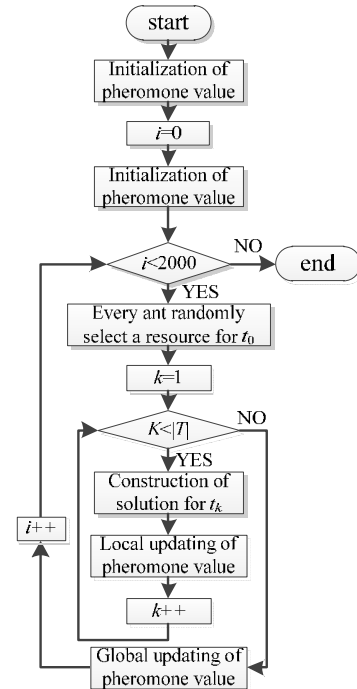


Fig. 7. Flowchart of ACS

IV. EXPERIMENTS AND COMPARISONS

In our experiment, for every type of resource r_j , we define its processing capability (cap_j) as $Random(1,10)$ and its cost per unit time as $Normal(cap_j,0.1)$. Where $Normal(a, b)$ represents the random value generated by the normal (Gaussian) distribution with mean a and standard deviation b . For every task t_i , we define its size t_{i_size} as $Random(10,30)$ while its *exetime* on r_j is defined as $Normal(t_{i_size}/cap_j,0.1)$. We calculate $transfertime[i][child(i)]$ by Eq. (14) while during our experiment, bandwidth is 20.

$$\begin{aligned} transfertime[i][child(i)] \\ = Random(0.1,1) \times t_{i_size} / bandwidth \end{aligned} \quad (14)$$

Topology Structure Generation

```

for  $i = 0$  to  $|T|-1$ 
   $P_{child} = 0.1 + 0.2 * (i/|T|)$ 
  for  $k = i+1$  to  $|T|$ 
    if  $Random(0,1) < P_{child}$ 
       $t_k$  is the child of  $t_i$ 
    end if
  end for each
end for each

```

Fig. 8. Algorithm for generating a topological structure

In cloud computing, the tasks are assumed to have a complex topological structure. We design an algorithm shown in Fig. 8 to generate the topological structure of the tasks where the tasks can be executed successively. For such task t_i , its child tasks' index is greater than i . We set a parameter P_{child} to be the probability that a task t_k to be the child of t_i . P_{child} increases with the incensement of i , in order to generate a balance structure. Fig. 8 is similar to the one in [12] except the difference in the probability settings of P_{child} .

We use 3 different scales of workflow to do our experiment — small, medium and large. Small workflow has 50 tasks. Medium workflow has 100 tasks. Large workflow has 200 tasks. The type of resource is set to be 6, the same as in [9].

In PSO approach, according to [9], $c_1=c_2=2.0$, $\omega=0.5$, and the population is 100. While in DOGA approach, we follow the proposals in [12] as $P_c=0.8$ and $P_m=0.002$ when setting TET as optimization objective and $P_c=0.15$ and $P_m=0.008$ when setting TEC as optimization objective. The population is also set as 100.

In ACS approach, the parameters are shown in Table I.

Population	10	ρ	0.1
α	1	ξ	0.1
β	5	q_0	0.9

A. Comparison with Same Evolutionary Generation

The three algorithms may require many generations to find a feasible solution, named $FGEN$. If $FGEN > 10000$, we regard that the algorithm cannot find a solution. Otherwise, we let the algorithm to run 2000 more generations after finding a feasible solution to search for the best solution with smallest TEC . We

ran the 3 algorithms under different deadline constraints and compared the results of TEC . We have also plotted the convergence curves of the TEC metric along the 2000 generations for all the three algorithms (see Fig. 9 to Fig. 14). The X-axis means generation, named GEN and the Y-axis means TEC . To reduce the randomness effect, we executed the three algorithms 30 times on each instance and use the average result for comparisons. S_DEV represents the standard deviation of the 30 independent tests. The comparison of 3 algorithms in 3 different scales of workflow is shown subsequently via a table and two figures. The better results in the tables are marked with **boldface**.

1) Small Scale of Workflow

The results of small scale of workflow are shown in Table II, Fig. 9 and Fig. 10. In the table we can see that in small scale of workflow, ACS perform well in generating a better solution with a smaller TEC and meeting a tight deadline constraint. But DOGA shows better stability with smaller standard deviation. While in the figures, we can see that the convergence speed of ACS is the fastest to obtain smaller TEC value.

Table II the Comparison of Small Scale of Workflow with the Same Evolutionary Generation

Deadline		PSO	DOGA	ACS
150	TEC	1723.16	1524.56	1288.4
	S_DEV	36.26	23.4	126.14
120	TEC	1733.65	1538.10	1336.65
	S_DEV	23.69	19.75	65.00

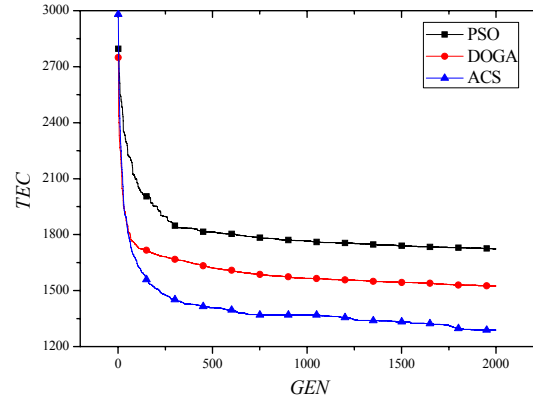


Fig. 9. The result on small scale of data, deadline=150

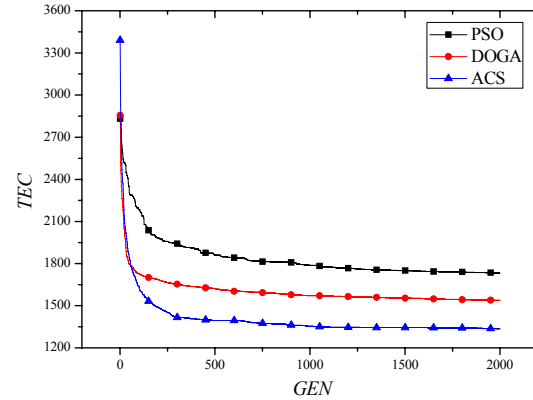


Fig. 10. The result on small scale of workflow, deadline=120

2) Medium Scale of Workflow

The results of medium scale of workflow are shown in Table III, Fig. 11, and Fig. 12. In the table we can see that the gap between ACS and other two algorithms is bigger and ACS has greater stability than the other two algorithms. From the figures, we can conclude that ACS also has the fastest convergence speed to reach a feasible solution quicker.

Table III The Comparison of Medium Scale of Workflow with The Same Evolutionary Generations

Deadline		PSO	DOGA	ACS
700	<i>TEC</i>	5128.70	3702.41	3289.45
	<i>S DEV</i>	561.71	119.79	87.93
600	<i>TEC</i>	5184.48	3762.09	3351.18
	<i>S DEV</i>	387.53	85.44	59.61

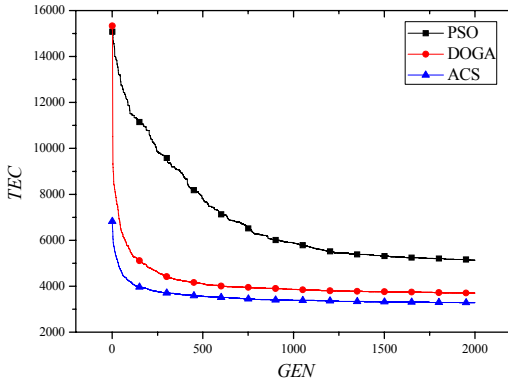


Fig. 11. The result on medium scale of workflow, deadline=700

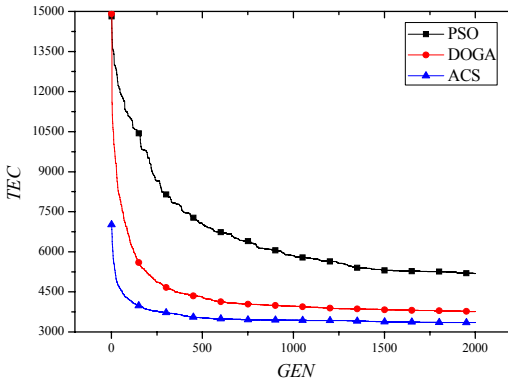


Fig. 12. The result on medium scale of workflow, deadline=600

3) Large Scale of Workflow

The results of large scale of workflow are shown in Table IV, Fig. 13, and Fig. 14. With the growing scale of workflow, ACS shows greater ability in solving the problem. In the table and figures, in terms of stability, *TEC* solution and convergence speed, ACS is better than the other two algorithms.

Table IV The Comparison of Large Scale of Workflow with The Same Evolutionary Generations

Deadline		PSO	DOGA	ACS
1200	<i>TEC</i>	24043.5	15396.68	14384.8
	<i>S DEV</i>	4544.3	1478.1	549.47
1000	<i>TEC</i>	28468.8	15961.69	14498.5
	<i>S DEV</i>	6567.5	1029.5	527.07

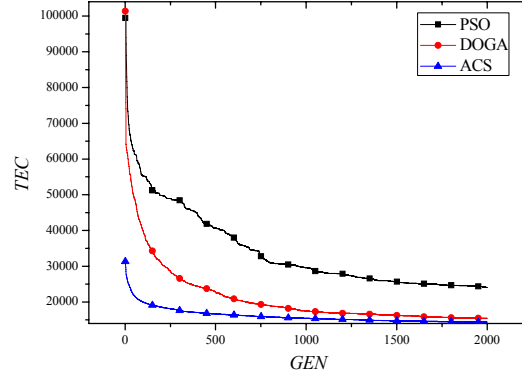


Fig. 13. The result on large scale of workflow, deadline=1200

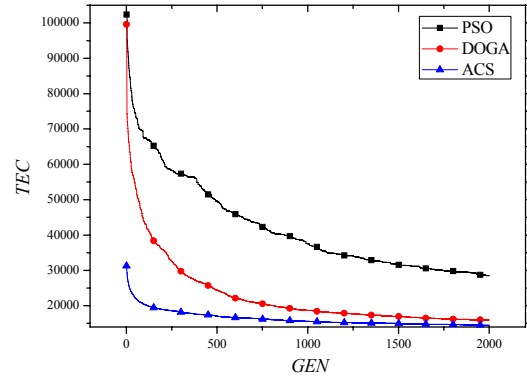


Fig. 14. The result on large scale of workflow, deadline=1000

B. Comparison with Same Execution Time

As the population of ACS is far smaller than that of PSO and DOGA, ACS may have better execution time efficiency. But the operation of ACS in every generation has higher complexity than other two algorithms. In order to show the efficiency of ACS more directly, we set the same executing time as 60 seconds to do the experiments.

Similarly, we performed 30 independent experiments for every algorithm. We again compare the results for *TEC* and *S DEV* of the 3 algorithms under different deadline constraints and plotted the convergence curves on the *TEC* metric along the 60 seconds of three algorithms. The X-axis means executing time, named *Time* and the Y-axis means *TEC*.

1) Small Scale of Workflow

The results of small scale of workflow are shown in Table V, Fig.15, and Fig.16. As the scale of workflow is small, all 3 algorithms have good convergence speed. However, ACS generated a solution with smaller *TEC*. With the guidance of heuristic value, ACS can find a better solution in the first generation.

Table V Comparison of Small Scale of Workflow with the Same Execution Time

Deadline		PSO	DOGA	ACS
150	<i>TEC</i>	1662.27	1429.55	1261.55
	<i>S DEV</i>	30.55	24.00	136.61
120	<i>TEC</i>	1647.73	1404.43	1337.51
	<i>S DEV</i>	31.95	10.24	79.53

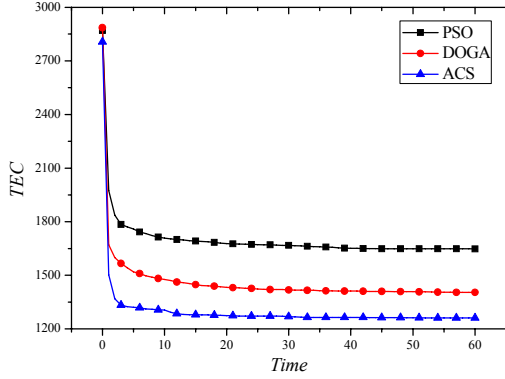


Fig. 15. The result on small scale of workflow, deadline=150 with the same execution time

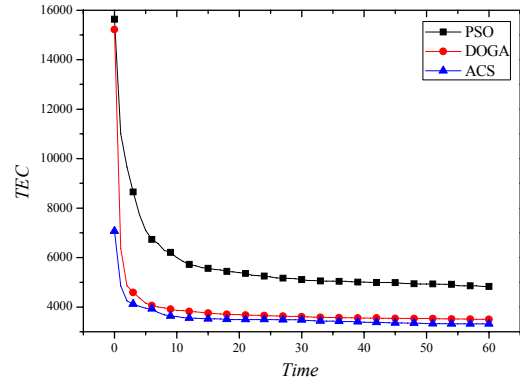


Fig. 18. The result on medium scale of workflow, deadline=600 with the same execution time

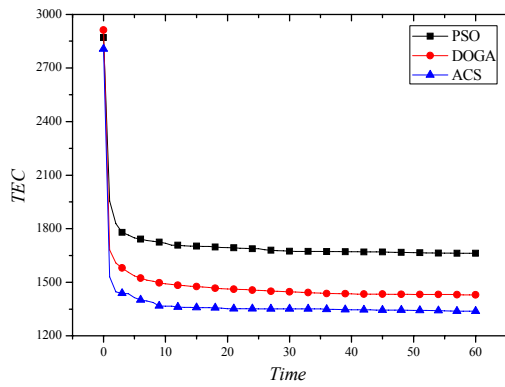


Fig. 16. The result on small scale of workflow, deadline=150 with the same execution time

2) Medium Scale of Workflow

The results of medium scale of workflow are shown in Table VI, Fig.17, and Fig.18. ACS is also able to generate a solution with the smallest *TEC*.

Table VI The Comparison of Medium Scale of Workflow with the Same Execution Time

Deadline		PSO	DOGA	ACS
150	<i>TEC</i>	4794.67	3448.55	3282.95
	<i>S DEV</i>	301.58	103.81	146.20
120	<i>TEC</i>	4829.50	3498.95	3315.83
	<i>S DEV</i>	358.43	90.24	89.87

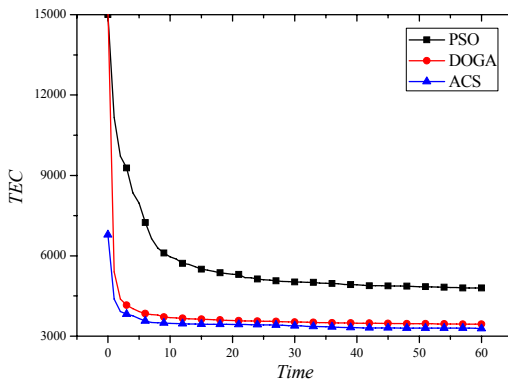


Fig. 17. The result on medium scale of workflow, deadline=700 with the same execution time

3) Large Scale of Workflow

The results of large scale of workflow are shown in Table VII, Fig. 19, and Fig.20. In this case, ACS performed better both in terms of stability and the time taken to find a feasible solution.

Table VII Comparison of Large Scale of Workflow with the Same Execution Time

Deadline		PSO	DOGA	ACS
150	<i>TEC</i>	24134.82	16803.40	14850.3
	<i>S DEV</i>	5931.42	1119.96	656.65
120	<i>TEC</i>	28035.01	16224.48	15102.00
	<i>S DEV</i>	4780.08	1279.56	798.85

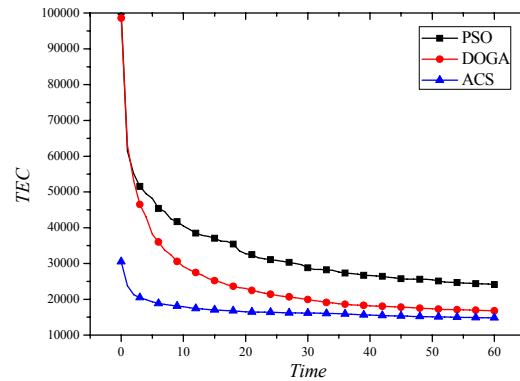


Fig. 19. The result on large scale of workflow, deadline=1200 with the same execution time

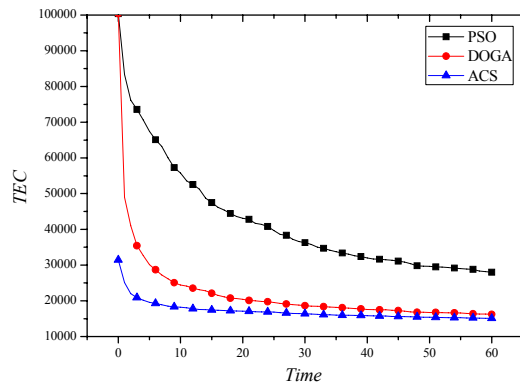


Fig. 20. The result on large scale of workflow, deadline=1200 with the same execution time

C. Analysis of the Result

1) Convergence

In the case of small scale of workflow, the convergence speed of the three algorithms is nearly the same. But with the increasing scale of workflow, ACS has better convergence speed than PSO and DOGA. This is helped by the heuristic value of ACS to finding a good solution in the first generation.

2) TEC

In the 3 different scales of data, ACS can generate a better solution with smaller TEC value than PSO and DOGA do. The performance of ACS increases considerably with the increasing scale of workflow when compared with the other two algorithms.

3) Efficiency

In the 3 different scales of workflow, from the Fig. 9~Fig. 20, we can conclude that in most of the cases, ACS can find a solution with smaller TEC within the first few evolutionary generations and seconds.

V. CONCLUSION

In this paper, we have developed an ant colony system based approach to the resource scheduling problem of cloud computing under a cost-minimization and deadline-constrained model. The model has unrestricted availability and can meet the needs of business organizations. Deficiencies of this model encountered by PSO [9] and DOGA [12] approaches have been improved. The experiments under various scheduling scales and deadline constraints show that the ACS is able to find a better solution with a smaller TEC than PSO and DOGA do.

Future work will be concerned with enhancing the stability of the ACS, while the use of other evolutionary computation algorithms such as differential evolution [14][15], artificial bee colony [16], enhanced PSOs [17][18], and brain storm optimization [19] will be investigated. Moreover, dynamic and multi-objective characteristics will be studied using relevant algorithms [20][21].

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