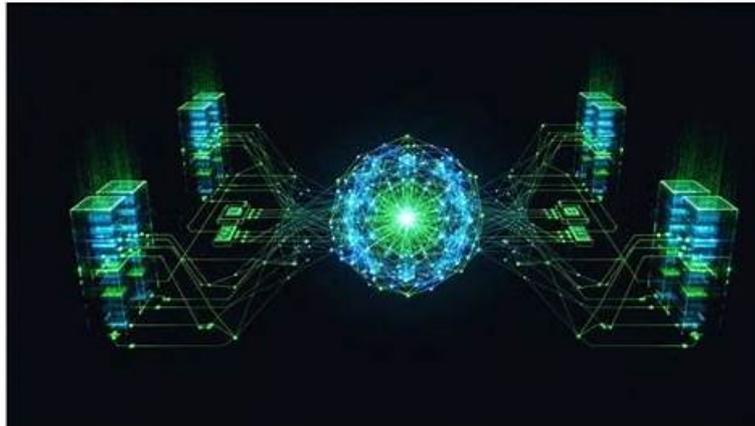


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NVIDIA AI Infrastructure Sample Questions (Q299-Q304):

NEW QUESTION # 299

You are deploying a security application that leverages the BlueField DPIJ to perform deep packet inspection (DPI) on network traffic.

Your application requires access to the raw packet data, including the Ethernet headers. Which of the following programming models or APIs is most suitable for accessing raw packet data on the BlueField DPU with minimal overhead?

- A. Using libpcap to capture packets from the network interface.
- B. Using the 'tcpdump' command and parsing its output.
- C. Using standard Linux socket APIs (e.g., 'socket()', 'recvfrom()') in user space.
- D. Using Netfilter hooks in the Linux kernel to intercept packets.
- E. using DPDK (Data Plane Development Kit) with the BlueField DPU's PMD (Poll Mode Driver).

Answer: E

Explanation:

DPDK provides a framework for high-performance packet processing in user space, bypassing the kernel's networking stack. The BlueField DPU's PMD (Poll Mode Driver) allows DPDK applications to directly access the network interface with minimal overhead. This is ideal for DPI applications that need to process a large volume of packets at high speed. Standard socket APIs and Netfilter hooks involve kernel intervention, which can introduce significant overhead. Libpcap is a packet capture library, not designed for high-performance packet processing. 'tcpdump' is a command-line tool, not a programming API.

NEW QUESTION # 300

You are tasked with troubleshooting a performance bottleneck in a multi-node, multi-GPU deep learning training job utilizing Horovod.

The training loss is decreasing, but the overall training time is significantly longer than expected. Which of the following monitoring approaches would provide the most insight into the cause of the bottleneck?

- A. Using 'nvidia-smi' on each node to monitor GPU utilization and memory usage.
- B. Monitoring network bandwidth utilization on each node using 'iftop' or 'iperf3'
- C. Using 'Shtop' to monitor CPU utilization on each node.
- **D. Enabling Horovod's timeline and profiling features to visualize the communication patterns and identify synchronization bottlenecks.**
- E. Analyzing the training loss curve to identify potential issues with the model architecture or hyperparameters.

Answer: D

Explanation:

Horovod's timeline and profiling tools are specifically designed to visualize communication patterns and identify bottlenecks in distributed training jobs. While 'nvidia-smi' and network monitoring can provide useful information, they don't give the holistic view of communication overhead that Horovod's tools provide. Loss curve analysis helps with model-related issues, not distributed training bottlenecks. 'htop' isn't related to network or GPU specific issues in distributed processing.

NEW QUESTION # 301

You have a Kubernetes cluster with nodes running different versions of the NVIDIA driver. You need to ensure that your containerized AI applications are always compatible with the specific driver version running on the node where they are scheduled. How can you achieve this driver version compatibility in a cloud-native way?

- A. Manually create different container images for each driver version and use node selectors to schedule the correct image on the appropriate nodes.
- B. Implement a webhook that inspects the node labels and injects the appropriate NVIDIA libraries into the pod at runtime.
- C. Use the NVIDIA driver capabilities to detect the driver version at runtime and dynamically load the correct libraries.
- D. Use a shared volume to mount drivers into a container.
- **E. Use the NVIDIA Operator to automatically manage driver installations and updates on the nodes, ensuring a consistent driver version across the cluster.**

Answer: E

Explanation:

The NVIDIA Operator is designed to manage the lifecycle of NVIDIA drivers and related components within a Kubernetes cluster, including automated installations, updates, and version management. This ensures a consistent and compatible driver version across all nodes, simplifying application deployment and management. The operator is the cloud-native approach to managing the NVIDIA stack. Option A is manual and inflexible. Option B relies on proper NVIDIA Driver setup on the host. Option D is a complex undertaking. Option E is insecure.

NEW QUESTION # 302

You have installed the NVIDIA Container Toolkit and are attempting to run a container with GPU support. However, the 'docker run' command fails with an error indicating that the NVIDIA runtime is not found. You have already verified that the NVIDIA Container Toolkit is installed, and the Docker daemon has been restarted. What is the most likely cause of this error?

- A. The system doesn't have a GPU.

- B. The '/etc/docker/daemon.json' file is missing or has incorrect configuration settings related to the NVIDIA runtime.
- C. The container image is corrupted and needs to be rebuilt.
- D. The NVIDIA driver version is incompatible with the CUDA version specified in the container image.
- E. The 'nvidia-container-runtime' package is not installed.

Answer: B

Explanation:

The most likely cause is an issue with the '/etc/docker/daemon.json' file (A). This file configures Docker's runtime settings, including specifying the NVIDIA runtime. If the file is missing or has incorrect entries, Docker will not be able to find the NVIDIA runtime. While driver incompatibility (B) can cause issues, it typically manifests as runtime errors within the container, not a failure to find the runtime itself. 'nvidia-container-runtime' might be a required package depending on the installation method. A missing GPU is unlikely since the Toolkit would likely fail to install, although this is also an error that can prevent the NVIDIA runtime from being started.

NEW QUESTION # 303

You're configuring a RoCEv2 network for your AI infrastructure. Which UDP port number range is commonly used for RoCEv2 traffic, and why is it important to be aware of this?

- A. 1024-49151 , the registered port range, for general application use.
- B. Any UDP port number can be used without issue.
- C. 49152-65535, the dynamic/private port range, to avoid conflicts with other services.
- D. 0-1023, because these are well-known ports.
- E. 4791 , which is reserved for VXLAN.

Answer: C

Explanation:

RoCEv2 commonly uses the dynamic/private port range (49152-65535). This avoids potential conflicts with well-known or registered ports used by other services. Knowing this range is crucial for configuring firewalls and network policies to allow RoCEv2 traffic to flow freely.

NEW QUESTION # 304

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