5DV008 Computer Architecture Umeå University Department of Computing Science

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Topic 4: The Processor

Part A: Basic control

These slides are mostly taken verbatim, or with minor changes, from those prepared by

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of The Pennsylvania State University

[Adapted from *Computer Organization and Design, 4th Edition*, Patterson & Hennessy, © 2008, MK]

Key to the Slides

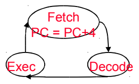
- The source of each slide is coded in the footer on the right side:
  - Irwin CSE331 = slide by Mary Jane Irwin from the course CSE331 (Computer Organization and Design) at Pennsylvania State University.
  - Irwin CSE431 = slide by Mary Jane Irwin from the course CSE431 (Computer Architecture) at Pennsylvania State University.
  - Hegner UU = slide by Stephen J. Hegner at Umeå University.

Review: MIPS (RISC) Design Principles

- Simplicity favors regularity
  - fixed size instructions
  - small number of instruction formats
  - opcode always the first 6 bits
- Smaller is faster
  - limited instruction set
  - limited number of registers in register file
  - limited number of addressing modes
- Make the common case fast
  - arithmetic operands from the register file (load-store machine)
  - allow instructions to contain immediate operands
- Good design demands good compromises
  - three instruction formats

The Processor: Datapath & Control

- Our implementation of the MIPS is simplified
  - memory-reference instructions: `lw, sw`
  - arithmetic-logical instructions: `add, sub, and, or, slt`
  - control flow instructions: `beq, j`
- Generic implementation
  - use the program counter (PC) to supply the instruction address and fetch the instruction from memory (and update the PC)
  - decode the instruction (and read registers)
  - execute the instruction

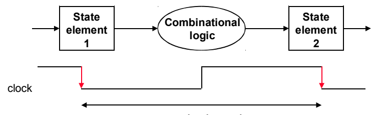


- All instructions (except `j`) use the ALU after reading the registers

How? memory-reference? arithmetic? control flow?

Aside: Clocking Methodologies

- The clocking methodology defines when data in a state element is valid and stable relative to the clock
  - State elements - a memory element such as a register
  - Edge-triggered – all state changes occur on a clock edge
- Typical execution
  - read contents of state elements -> send values through combinational logic -> write results to one or more state elements

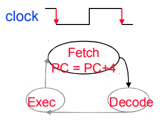


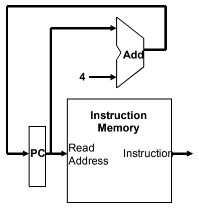
one clock cycle

- Assumes state elements are written on every clock cycle; if not, need explicit write control signal
  - write occurs only when both the write control is asserted and the clock edge occurs

Fetching Instructions

- Fetching instructions involves
  - reading the instruction from the Instruction Memory
  - updating the PC value to be the address of the next (sequential) instruction

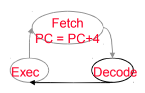


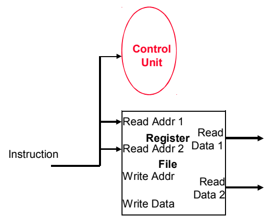


- PC is updated every clock cycle, so it does not need an explicit write control signal just a clock signal
- Reading from the Instruction Memory is a combinational activity, so it doesn't need an explicit read control signal

Decoding Instructions

- Decoding instructions involves
  - sending the fetched instruction's opcode and function field bits to the control unit



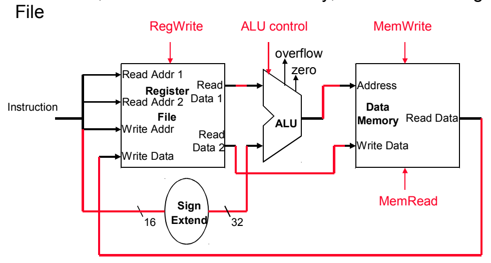


and

  - reading two values from the Register File
    - Register File addresses are contained in the instruction

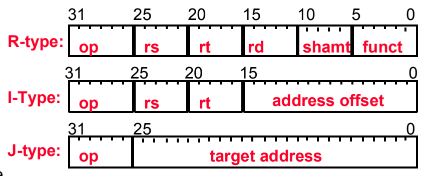
Executing Load and Store Operations

- Load and store operations involves
  - compute memory address by adding the base register (read from the Register File during decode) to the 16-bit signed-extended offset field in the instruction
  - store value (read from the Register File during decode) written to the Data Memory
  - load value, read from the Data Memory, written to the Register File



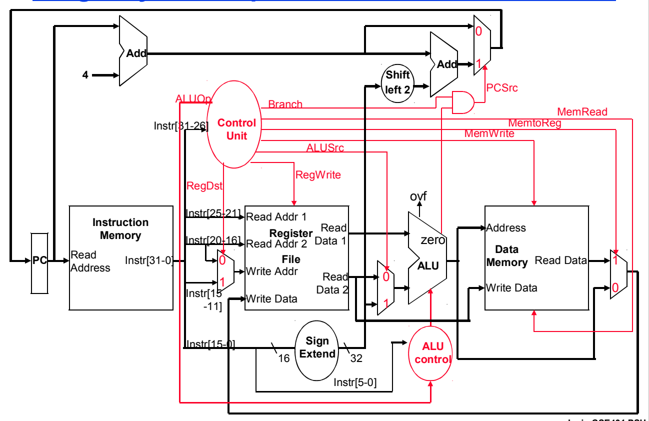
Adding the Control

- Selecting the operations to perform (ALU, Register File and Memory read/write)
- Controlling the flow of data (multiplexor inputs)

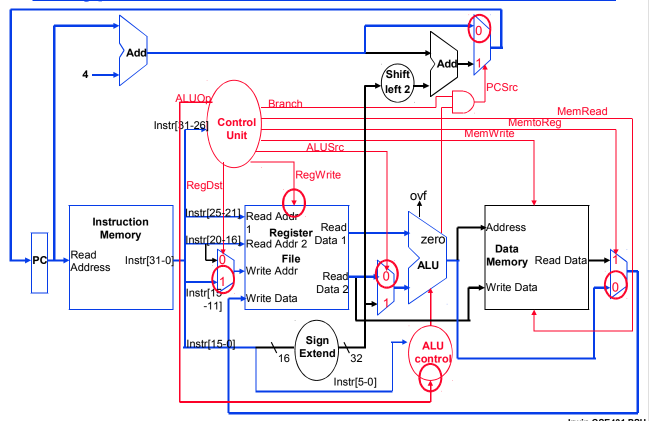


- Observations
  - op field always in bits 31-26
  - addr of registers to be read are always specified by the rs field (bits 25-21) and rt field (bits 20-16); for lw and sw rs is the base register
  - addr. of register to be written is in one of two places – in rt (bits 20-16) for lw; in rd (bits 15-11) for R-type instructions
  - offset for beq, lw, and sw always in bits 15-0

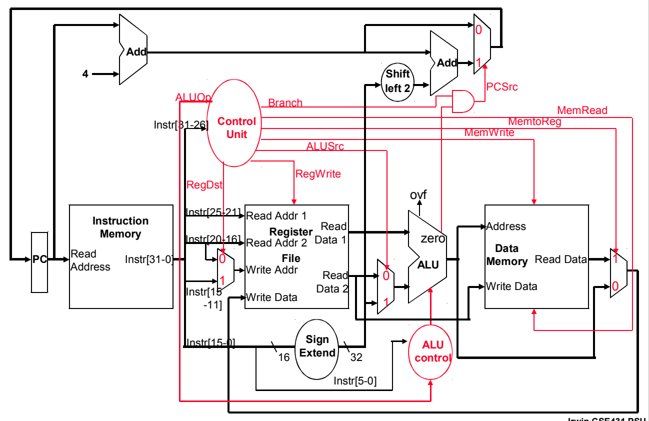
Single Cycle Datapath with Control Unit



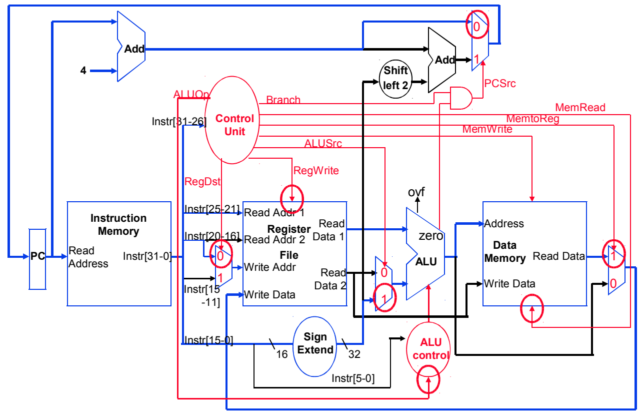
R-type Instruction Data/Control Flow



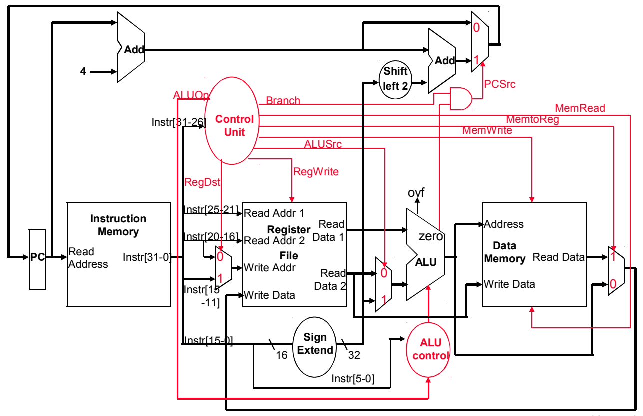
Load Word Instruction Data/Control Flow



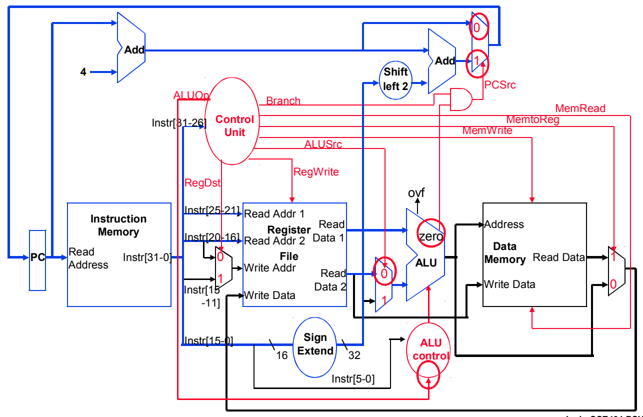
Load Word Instruction Data/Control Flow



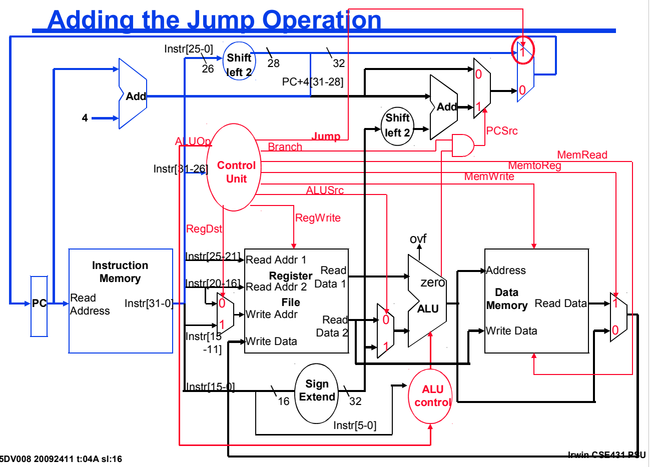
Branch Instruction Data/Control Flow



Branch Instruction Data/Control Flow



Adding the Jump Operation



Instruction Times (Critical Paths)

- What is the clock cycle time assuming negligible delays for muxes, control unit, sign extend, PC access, shift left 2, wires, setup and hold times except:
  - Instruction and Data Memory (200 ps)
  - ALU and adders (200 ps)
  - Register File access (reads or writes) (100 ps)

Instr.	I Mem	Reg Rd	ALU Op	D Mem	Reg Wr	Total
R-type						
load						
store						
beq						
jump						

Instruction Critical Paths

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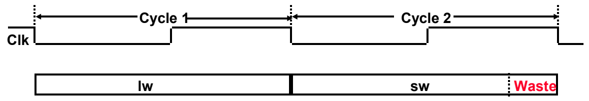
Instr.	I Mem	Reg Rd	ALU Op	D Mem	Reg Wr	Total
R-type	200	100	200		100	600
load	200	100	200	200	100	800
store	200	100	200	200		700
beq	200	100	200			500
jump	200					200

Single Cycle Disadvantages & Advantages

- Uses the clock cycle inefficiently – the clock cycle must be timed to accommodate the slowest instruction
  - especially problematic for more complex instructions like floating point multiply



- May be wasteful of area since some functional units (e.g., adders) must be duplicated since they can not be shared during a clock cycle

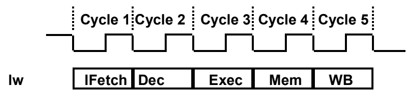
but

- Is simple and easy to understand

How Can We Make It Faster?

- Start fetching and executing the next instruction before the current one has completed
  - Pipelining – (all?) modern processors are pipelined for performance
  - Remember *the* performance equation:
    CPU time = CPI * CC * IC
- Under *ideal* conditions and with a large number of instructions, the speedup from pipelining is approximately equal to the number of pipe stages
  - A five stage pipeline is nearly five times as fast because the CC is nearly five times as fast
- Fetch (and execute) more than one instruction at a time
  - Superscalar processing – stay tuned

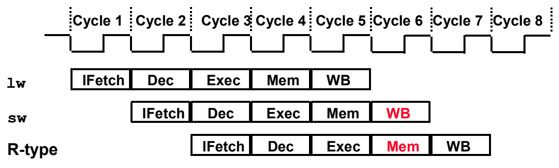
The Five Stages of Load Instruction



- IFetch: Instruction Fetch and Update PC
- Dec: Registers Fetch and Instruction Decode
- Exec: Execute R-type; calculate memory address
- Mem: Read/write the data from/to the Data Memory
- WB: Write the result data into the register file

A Pipelined MIPS Processor

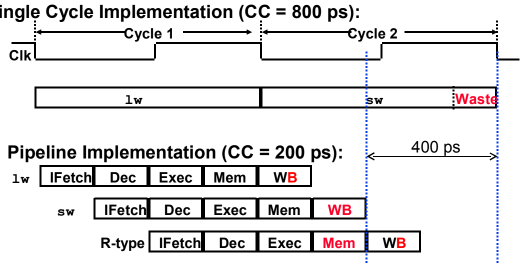
- Start the next instruction before the current one has completed
  - improves throughput - total amount of work done in a given time
  - instruction latency (execution time, delay time, response time - time from the start of an instruction to its completion) is *not* reduced



- clock cycle (pipeline stage time) is limited by the **slowest** stage
  - for some stages don't need the whole clock cycle (e.g., WB)
  - for some instructions, some stages are wasted cycles (i.e., nothing is done during that cycle for that instruction)

Single Cycle versus Pipeline

Single Cycle Implementation (CC = 800 ps):



Pipeline Implementation (CC = 200 ps):

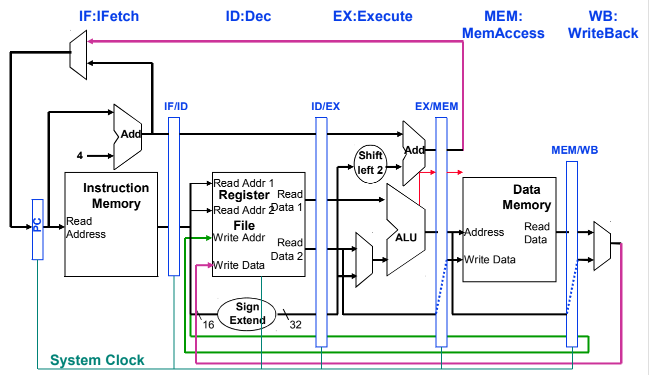
- To complete an entire instruction in the pipelined case takes 1000 ps (as compared to 800 ps for the single cycle case). Why ?
- How long does each take to complete 1,000,000 adds ?

Pipelining the MIPS ISA

- What makes it easy
  - all instructions are the same length (32 bits)
    - can fetch in the 1st stage and decode in the 2nd stage
  - few instruction formats (three) with symmetry across formats
    - can begin reading register file in 2nd stage
  - memory operations occur only in loads and stores
    - can use the execute stage to calculate memory addresses
  - each instruction writes at most one result (i.e., changes the machine state) and does it in the last few pipeline stages (MEM or WB)
  - operands must be aligned in memory so a single data transfer takes only one data memory access

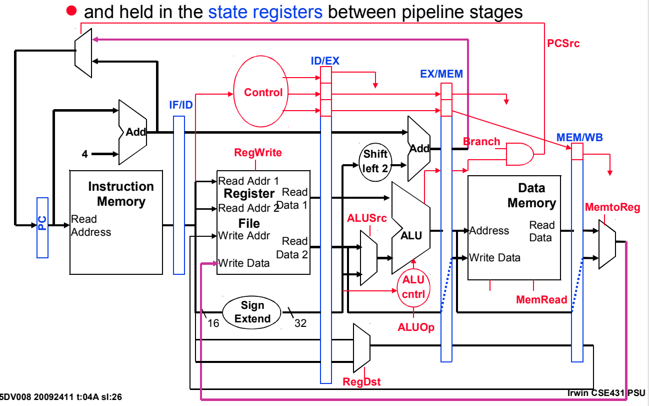
MIPS Pipeline Datapath Additions/Mods

- State registers between each pipeline stage to isolate them



MIPS Pipeline Control Path Modifications

- All control signals can be determined during Decode
  - and held in the state registers between pipeline stages

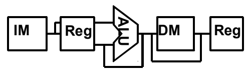


Pipeline Control

- IF Stage: read Instr Memory (always asserted) and write PC (on System Clock)
- ID Stage: no optional control signals to set

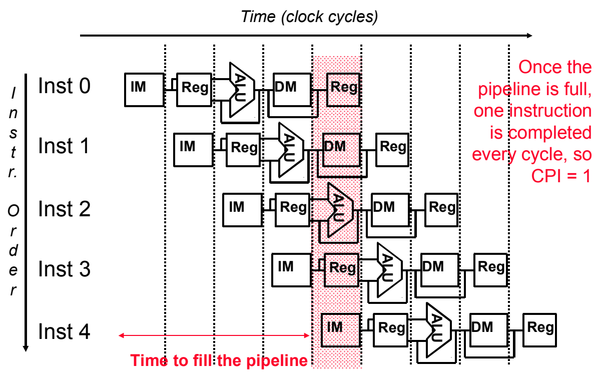
	EX Stage				MEM Stage			WB Stage	
	Reg Dst	ALU Op1	ALU Op0	ALU Src	Brch	Mem Read	Mem Write	Reg Write	Mem toReg
R	1	1	0	0	0	0	0	1	0
`lw`	0	0	0	1	0	1	0	1	1
`sw`	X	0	0	1	0	0	1	0	X
`beq`	X	0	1	0	1	0	0	0	X

Graphically Representing MIPS Pipeline



- Can help with answering questions like:
  - How many cycles does it take to execute this code?
  - What is the ALU doing during cycle 4?
  - Is there a hazard, why does it occur, and how can it be fixed?

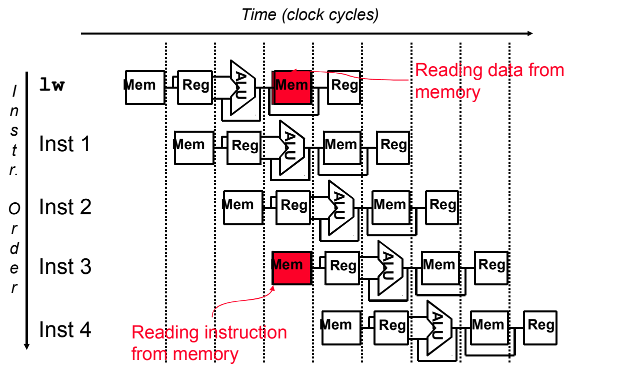
Why Pipeline? For Performance!


Time (clock cycles)
I n s t r. O r d e r
Inst 0
Inst 1
Inst 2
Inst 3
Inst 4
IM
Reg
ALU
DM
Reg
Time to fill the pipeline
Once the pipeline is full, one instruction is completed every cycle, so CPI = 1

Can Pipelining Get Us Into Trouble?

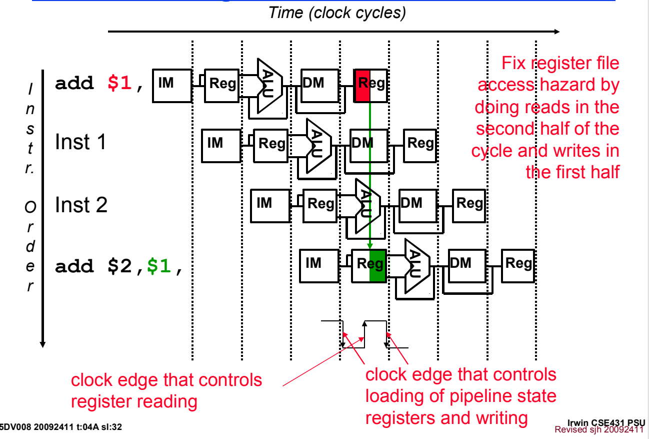
- Yes: Pipeline Hazards
  - structural hazards: attempt to use the same resource by two different instructions at the same time
  - data hazards: attempt to use data before it is ready
    - An instruction's source operand(s) are produced by a prior instruction still in the pipeline
  - control hazards: attempt to make a decision about program control flow before the condition has been evaluated and the new PC target address calculated
    - branch and jump instructions, exceptions
- Can usually resolve hazards by waiting
  - pipeline control must detect the hazard
  - and take action to resolve hazards

A Single Memory Would Be a Structural Hazard



❑ Fix with separate instr and data memories (I$ and D$)

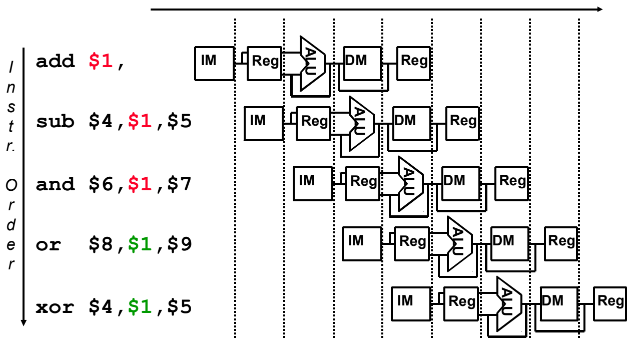
How About Register File Access?



Time (clock cycles)
Instr. Order
add $1,
Inst 1
Inst 2
add $2,$1,
IM
Reg
ALU
DM
Fix register file access hazard by doing reads in the second half of the cycle and writes in the first half
clock edge that controls register reading
clock edge that controls loading of pipeline state registers and writing

Register Usage Can Cause Data Hazards

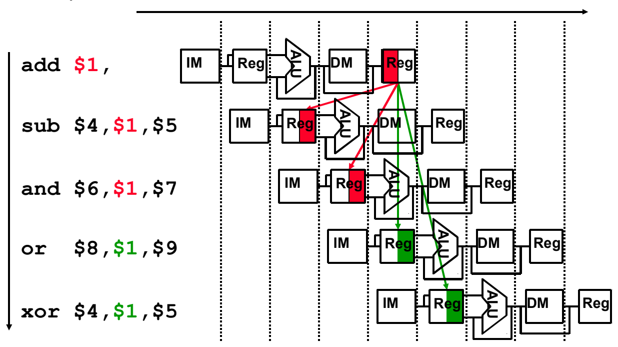
❑ Dependencies backward in time cause hazards



❑ Read before write data hazard

Register Usage Can Cause Data Hazards

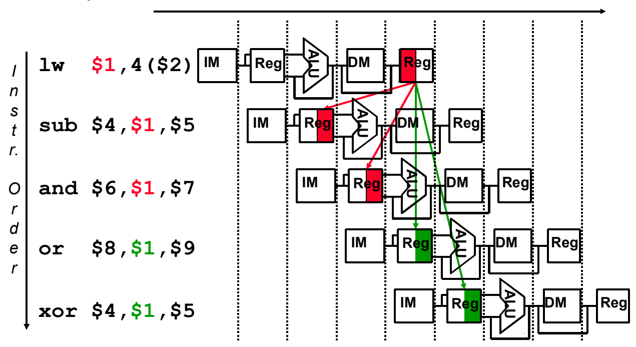
- Dependencies backward in time cause hazards



- Read before write data hazard

Loads Can Cause Data Hazards

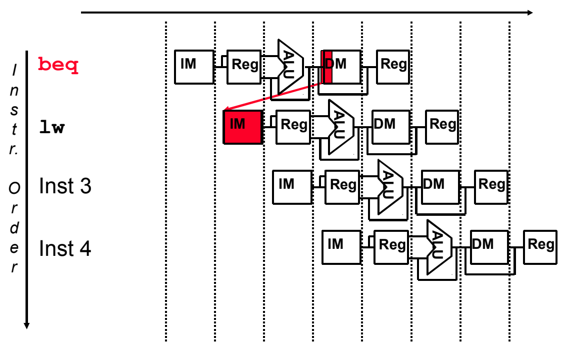
- Dependencies backward in time cause hazards



- Load-use data hazard

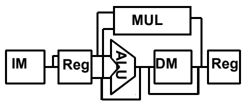
Branch Instructions Cause Control Hazards

- Dependencies backward in time cause hazards

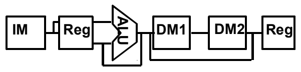


Other Pipeline Structures Are Possible

- What about the (slow) multiply operation?
  - Make the clock twice as slow or …
  - let it take two cycles (since it doesn't use the DM stage)

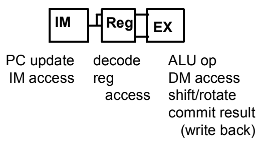


- What if the data memory access is twice as slow as the instruction memory?
  - make the clock twice as slow or …
  - let data memory access take two cycles (and keep the same clock rate)

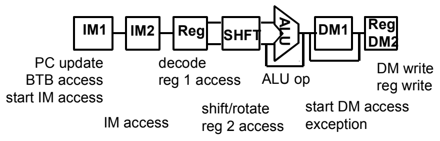


Other Sample Pipeline Alternatives

- ARM7



- XScale



Summary

- All modern day processors use pipelining
- Pipelining doesn't help latency of single task, it helps throughput of entire workload
- Potential speedup: a CPI of 1 and fast a CC
- Pipeline rate limited by slowest pipeline stage
  - Unbalanced pipe stages makes for inefficiencies
  - The time to "fill" pipeline and time to "drain" it can impact speedup for deep pipelines and short code runs
- Must detect and resolve hazards
  - Stalling negatively affects CPI (makes CPI less than the ideal of 1)