

tricky3.447Processor tasks on Exceptionssection\*.70



Computer Architecture  
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# Chapter 1

## Introduction

This document is the note I have written during and outside of the course, all the information here is directly taken from the course, slides, etc... However mistake can happen, if you see some mistake or see something that is not clear, feel free to ping an issue on the github, or email/telegram me. **Disclaimer** in this course, when we say *high-level language* we mean a language that is compiled/interpreted for instance: `c` is a high-level language here.

### 1.0.1 Content of the course

The course is divided into three parts:

- **Part I: Processors and ISA**

What is a processor? How can we design one? How do programs look like when they are executed?

- **Part II: I/Os and Exceptions**

What is around a processor to make a full computer? How the processor exchanges information with the rest of the world?

- **Part III: Memory Hierarchy**

Processors are fast and memory is slow -how can one combine the two? How can one protect the data users in memory

- **Part IV: Instruction-Level Parallelism**

What makes a good processor? How real processors achieve ever increasing performances?

- **Part V: Multiprocessors**

What are the basic challenges of connecting many processors together? What changes from a single processor system?

- **Part VI: Rudiments of Hardware Security**

How can a hacker exploit what we have built in the previous parts to attack a system? How physics helps jeopardizing security?

**Literature**

The course will have two books for the literature which are the same as the one for fds :

1. Digital Design: Principles and Practices John F. Wakerly
2. Computer organization and design: The hardware software interface David A. Patterson,  
John L. Hennessy

# Chapter 2

## Processors and instruction set architecture

### 2.1 Instruction set architecture

The goal for the beginning of this course is to go from "high-level" perspective to the bottom of the iceberg. First let us look at a piece of code (`c`):

```
int data = 0x00123456;
int result = 0;
int mask = 1;
int count = 0;
int temp = 0;
int limit = 32;
do{
    temp = data & mask;
    result = result + temp;
    data = data >> 1;
    count = count + 1;
} while (count != limite);
```

Here we can see that we have variable with expressive names (that we can choose). each variable has a type, the computation we are doing `result + temp` looks like a mathematic formula, the control flow we are using is very intuitive.

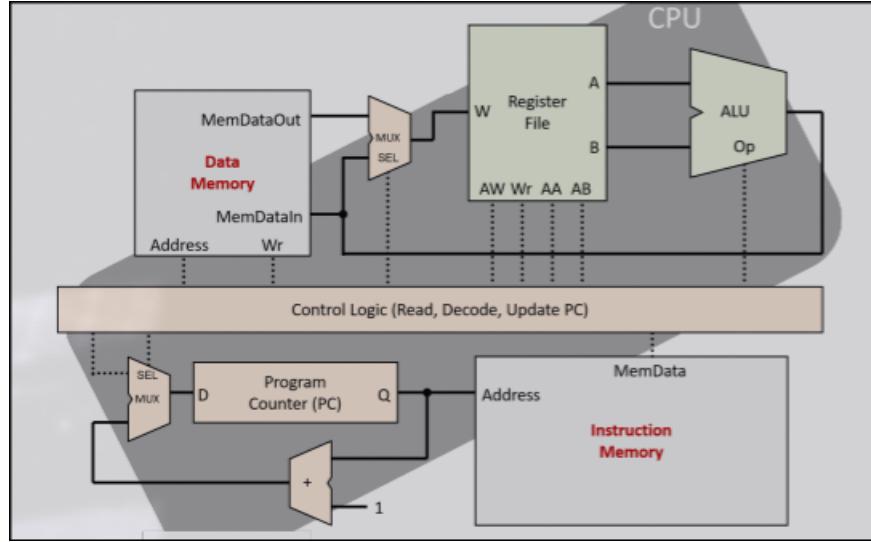
In the case of those high-level language, we have an "unlimited" number of variables which supports any type.

If we wanted to convert this code into Assembly code we would have this:

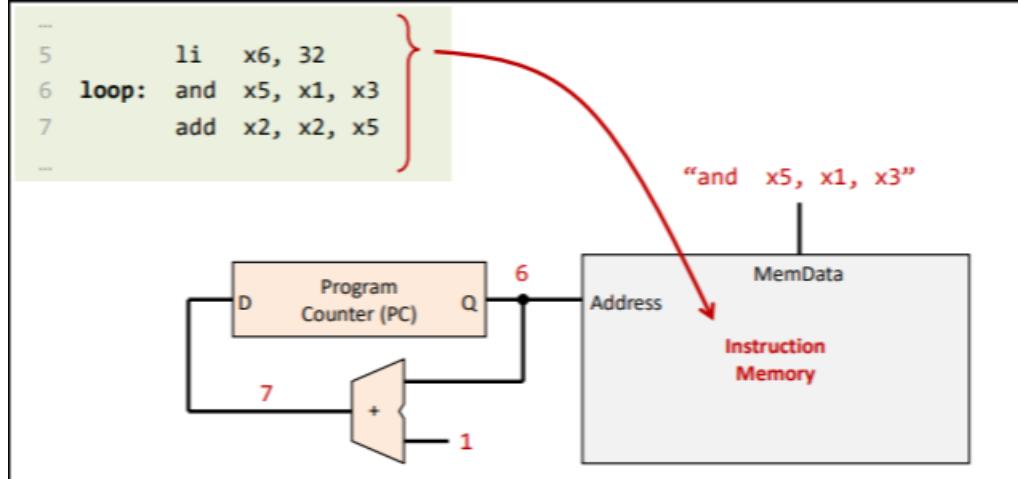
```
li x1, 0x00123456
    li x2, 0
    li x3, 1
    li x4, 0
    li x5, 0
    li x6, 32
loop:
    and x5, x1, x3
    add x2, x2, x5
    srl x1, x1, 1
    addi x4, x4, 1
    bne x4, x6, loop
```

As we can see we have a much more rigid format: we really have a sequence of numbered instructions that is executed line by line. For each instruction, we have an *opcode* that defines the effect of the instruction. Each *variable* has a fixed name and we only have one form of control flow. The question to ask is why did we do that?

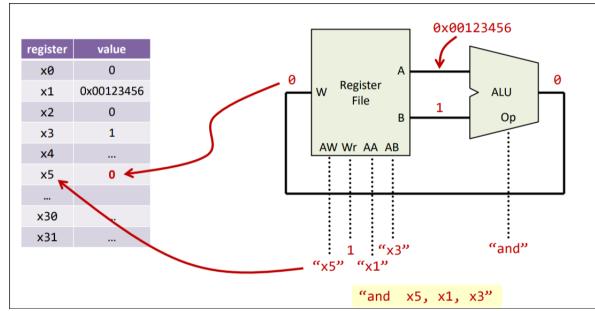
The answer of this question lies in the architecture of the processor:



how it works: the processor fetches the instruction at the address of the program counter (PC) and launches it to the control logic

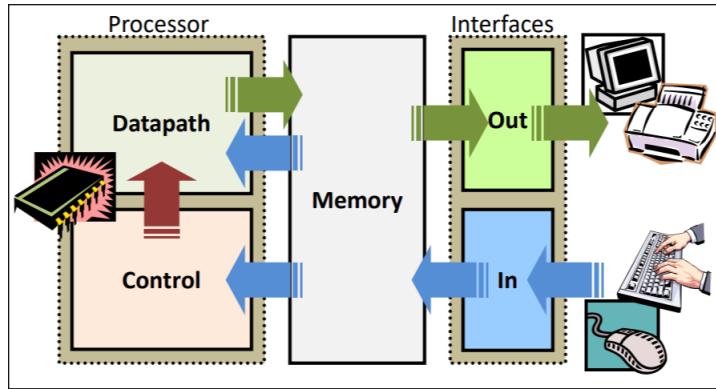


After that the instruction has been fetched, it is processed in the Control logic and then read/write etc... into the register file, and give the information (the opcode) to the ALU for it to know which operation to perform.



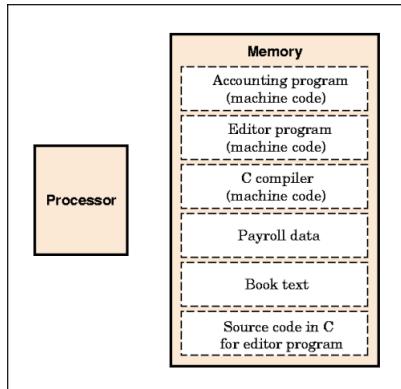
### The five classic components of a computer

For an every day computer you need four other components other than the control components, you need to have a memory to store data (bigger than 32 word registers), you need to take input from the outside worlds (Internet, bluetooth, a keyboard, mouse ...) and also output something to the outside word. On top of that, you need all of that to communicate  $\Rightarrow$  you need a data path.



Okay, we have memory, we have input output and a place to compute everything, but what do we need to compute? Where is the program that is being executed? At the moment we have a place for the data but not for our program so how do we do it?

We store the program in the same memory than the one for the data. This is called a *Unified Architecture* (On the other hand, an architecture that have two separates memory, one for the instruction and one for the data is called a *Harvard Architecture*). This is a **Key concept to computer science**, our instruction (therefore program) are represented as numbers (just like data).



Now a good question to have is: how to decode and encode those instructions and in the mean time, also what makes a good encoding?

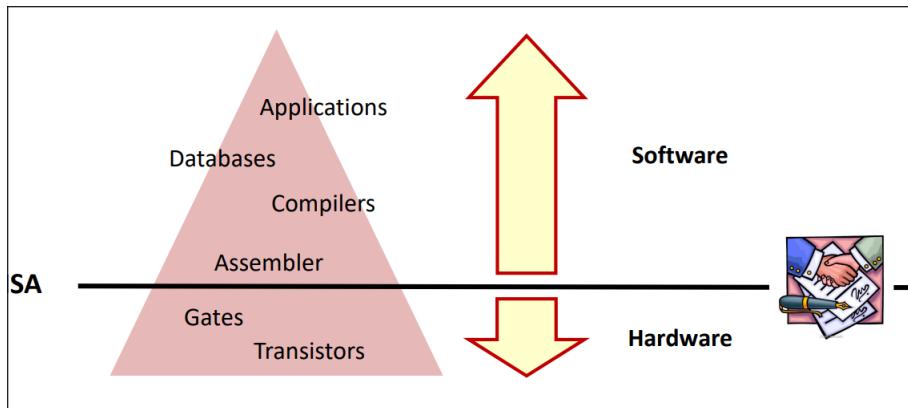
A good encoding would be one that allows us to minimize the resource in hardware and also is the fastest. This is where RISC-V comes in the play!! RISC-V is an instruction set architecture as like many others for instance x86, x64 for the most famous and used one.

The difference between assembly language and high-level language is in the "*translation*", for the assembly language, we use an **assembler**, for a high-level language (a compiled one), we use a **compiler**:

- Assembler can easily translate from code to binary code (this is what the instruction set tells us to do). All we need to do is the look up in the table and translate
- A compiler on the other hand cannot look up in a table, it has to translate the code into Assembly code to be translated, but translating the code into Assembly is a very hard thing to do, you have to find the best way or at least, try to find the best way to say the same thing but in assembly.

## 2.2 Instruction set architecture: Branches, Function and stack

The main goal that ISA does is to put a **Contract** between the hardware and the software: If you are a hardware person, all you care about is to make your processor the fastest on the ISA. If you are a software person, you don't need to worry about the hardware behind anything, you only care about the software that you are building. This ISA gives a level of abstraction which makes it easier to develop better software/hardware.



As we have seen in cs-173, arithmetic and logic operation are quite easy to understand and use in RISC-V. But here are some facts to know about them:

- Immediate constant takes at maximum 12 bits. The reason behind this is that the immediate part of the instruction is directly stored in the instruction, this means that there are 12 bits of the instruction that are reserved for the immediate part. Imagine having for instance a 30 bits immediate, then you would only have 2 bits for: the opcode, result register, input register ...
- A way to go around this is to use the `.equ num` and then to use `lui` directly on `num`. (this is possible because the assembler will directly translate the one line instruction into a three lines instruction).
- Register `x0`, this register is **always** zero (by definition), you can write anything to this register, the value in it will always be zero. This can be useful in a lot of cases, it happens quite often that we need a zero in an instruction and the only way to do so would have been to `li` a register to 0 and then calling the instruction. Therefore, the `x0` register allows us to save instructions

### An if-then-else

To be able to do an if and else cause will need some branches, for instance if we wanted to translate the code:

```
if (x5 == 72) {
    x6 = x6 + 1
} else {
    x6 = x6 - 1
}
...
```

Into RISC-V: it would look like this:

```
.text
    li x7, 72
    beq x5, x7, then_clause
else_clause:
    addi x6, x6, -1
    j end_if
then_clause:
    addi x6, x6, 1
end_if:
...
...
```

As you can see jump and branch are really similar however, there is a universal distinction between them:

- Jumps → **unconditional** control transfer instructions
- Branch → **conditional** control transfer instructions

However this is not the case for every assembly languages, for instance in x86, everything is defined as a jump.

### A Do-while loop

A do while loop in c

```
do {
    x5 = x5 >> 1
    x6 = x6 + 1
} while (x5 != 0);
...
```

A do while loop in risc-v

```
.text
loop:
    srl x5, x5, 1
    addi x6, x6, 1
    bne x5, loop
...
...
```

### 2.2.1 Functions

In our high-level code, we usually use function to organized our code (Scala...) (those function can also be called methods, procedure dependeing of the context).

What we would like is also to have function in assembly so that we don't have to write the same code always. What a function would look like is:

1. Place arguments where the called function can access them
2. jump to the function
3. Acquire storage resources the function needs
4. Perform the desired task of the function
5. Communicate the result value back to the calling program
6. realease any local storage resources
7. Return control to the calling program

That sound pretty hard to do so let's do it step by step. First, the second and seven steps (I know). What we need is to jump to the function and the return. This is fairly easy to do, all we need is to call the jump instruction. For instance, let's call the function two times. This would looks like this

```
sqrt:
...
j back
```

And the main would look like this:

```
main:
...
j sqrt
back:
...
j sqrt
back2:
...
```

However, isn't there an issue? what would happen if we tried to run this code?

The answer is that this would lead to an infinite loop. the `sqrt` function doesn't know about the fact that there are more than one back. The solution to this problem is to:

when you called the function, you store the current PC +4 (to go to the next line) to a register (for instance `x1`). You then, call the function, do the computation there **and then** you rejum to the address store in the register `x1`.

**Jump and link** There is instruction that allows us to do this, those instruction are called jump and link `jal`, and the other one is called jump to the address specified in a register `jr`, however we said before that we only use `x1` for the return address so why don't we make an instruction that directly jump to this address: `ret` (which stands for return I think).

However what we have to be careful with here is that the `x1` register is not preserved accorss the call (this is not something that is known for now but let me explain it shortly). What we will want to do is the call function inside function (have call inside call inside call etc ...) however every time we make a call to a function, the `x1` register will be overwritten: every time you jump and link, you store in the return address register the pc +4. However this is not currently a problem, we will solve it later.

**Acquire storage ressource the function needs** There is a lot of way to do this. The first way to do so is to juste allocate like 10 registers to the current function and the rest to the function that is called. for instance if we have this code:

```

main:
...
jal sqrt
...

...
jal sqrt
...
ret

sqrt:
...
add x5, x7, x8
jal round
sub x6, x6, x5
...
ret

round:
...
addi x10, x11, 3
...
ret

```

You see that the round procedure only use the register `x10` to `x15`. and that sqrt the one from 2 to 9. We can clearly see that this is not scalable, so we need another solution.

### 2.2.2 The stack

The **stack** is the solution!! Fisrt what is the stack:

#### Définition 1

- *The stack is a empty region in the memory*
- *We use the register `x2` (also called `sp`) to store the address of the end of the used region*
- *If we are using all variables and we still want to make a call to a function, we need to store in the stack our variable before calling the function and then restore our variable from the stack.*

The complexity of this is to understand the order of what is needed to be stored or not. For instance if you have a function that is being called from above. We have to be sure that we don't overwrite the values from the function that is above. to do so, we store the value in the stack and restore them afterward. (only the register that we are changing). to do so we have to dynamically allocate more space in the stack.

Here is an example:

```

...
addi sp, sp, -8
sw x8, 0(sp)
sw x9, 4(sp)
...
#we have here free use of x8 and x9
...

```

```

lw x9, 4(sp)
lw x8, 0(sp)
addi sp, sp, 8

```

However, do we need to store all the register? how do we return something, how do we pass arguments to a function. To do so we agree to use some register as argument, return register, other for return address, stack pointer, temporaries, saved... I strongly advise to go read the RV32i Reference Card.

So what do we still need? we are currently able to jump to function, return from the function, acquire storage resources, perform the desired stack of the function, All we need is the argument and return values. To do so is very simple, as I said before we can:

- Use some particular registers, both for the **arguments** and for the return **result**.
- We can do it ad-hoc ...
  - `sqrt` gets the argument in `x5` and returns the result in `x6`
- Or we can have some convention
  - All function pass arguments in register `x10` to `x17` and return the result in `x10`
- Can this be insufficient? **More arguments** than allocated registers? What if we have 10 arguments

**Option 2** If we don't have enough registers, we can just put them in the task right? we know that the stack is unlimited (in theory), all we would need is to do more work (allocate space, storing, loading etc ...)

To do so we can use another register: `fp` or `x8` in risc-v which point to the same location as `sp` on entry.

This make the code more readable because:

- `sp` changes inside the function and so do relative offsets
- offsets with respect to the `fp` are **fixed**

The use of the `fp` register is **optional** and even varies among users and compilers. (I personally didn't use it during lab 1, I only used the registers that are reserved).

Register	Mnemonic	Description	Preserved across Call?
x0	zero	Hard-wired zero	—
x1	ra	Return Address	No
x2	sp	Stack Pointer	Yes
x3	gp	Global Pointer	—
x4	tp	Thread Pointer	—
x5	t0	Temporary/alternate link register	No
x6-x7	t1-t2	Temporaries	No
x8	s0/fp	Saved register/Frame Pointer	Yes
x9	s1	Saved register	Yes
x10-x11	a0-a1	Function Arguments/return values	No
x12-x17	a2-a7	Function Arguments	No
x18-x27	s2-s11	Saved registers	Yes
x28-x31	t3-t6	Temporaries	No
pc		Program counter	—

## 2.3 Memory and Addressing Modes

### 2.3.1 Memory

Memory is an incredibly important component of a computing system:

- We store our **programs** in it
- We store our **data** in it
- It is often through memory that we will **receive data and send out data**

Memory is a reccurent topic in this course, we have already seen it with the stack however the type of the memory is also an important topic:

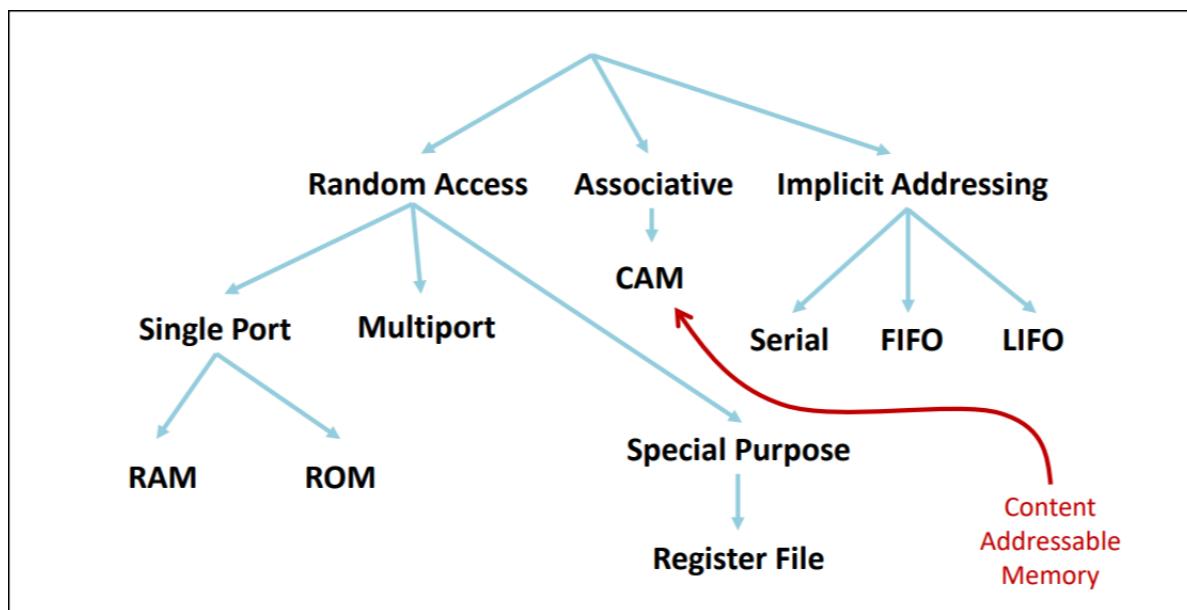
- Memory can be **very slow**  $\Rightarrow$  Caches
- Memory is *finite* (relatively small)  $\Rightarrow$  Virtual memory
- Memory can make an **ISA too complex**  $\Rightarrow$  pipelining

**Types of memory** There is a lot of different technologies for memory:

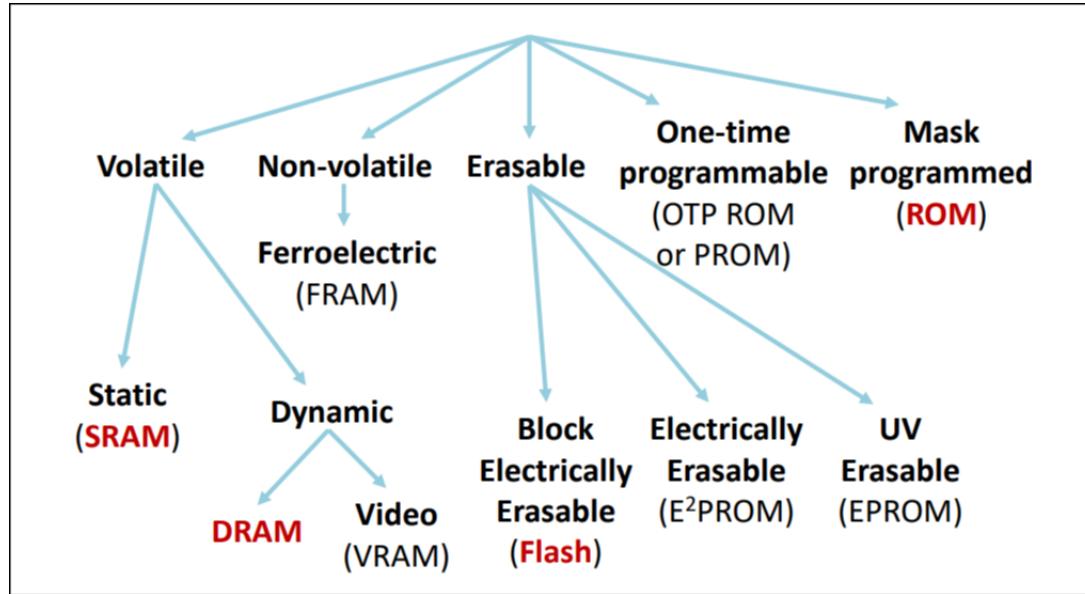
- SRAM, DRAM, EPROM, Flash, etc.

Each of those has a variations in **capabilities** therefore also in how we use them, memory change by:

- Capacity, density
- Speed
- Writable, permanent, reprogrammable

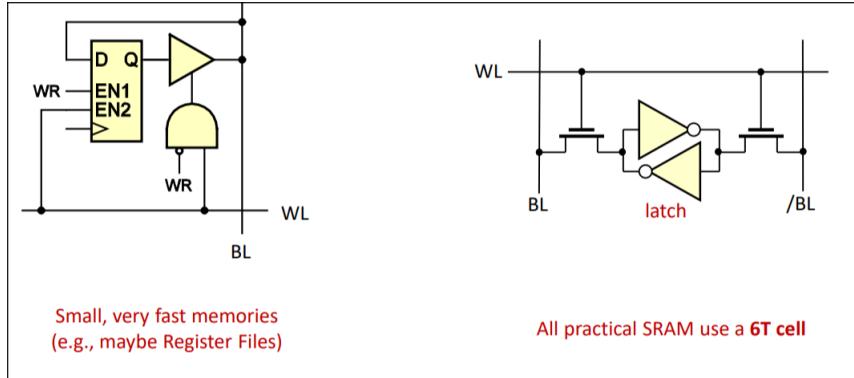


We have here all the type of memory that can be used, What we use when we program are Random access memory, this means that the memory can be accessed with an address. In the tree of random access memory we have:



The basic structure behind those memory are DFF, (D flip flop). which are stacked one on another in a  $n$  times 4 grid. Each flip flop looks like this:

**SRAM** SRAM stands for **static random access memory**. It stores data with flip flops which makes it faster than DRAM (which we will see later) but more expensive. We use it for CPU caches and for the register file



So here we have to make a difference between the boolean system and the electrical components. The circuit on the left is a disaster in terms of electrical components it has approximately 20 transistors which makes it **slower and costlier**. The real way to do SRAM is with the right circuit. However this looks bad, normally it is forbidden to have a closed loop in a circuit! We are forbidden to have a loop in our circuit without a flip flop in it, you cannot have a loop inside a combinational circuit. So this is a big special thing for us however, this "works", it is compatible there is no issue in the circuit. The issue we have is that:

Imagine putting a one on the left or right part of the circuit  $\Rightarrow$  the value cannot be changed, it is stucked there for ever. This looks really good because one **NOT** gate costs us only two transistors so the memory (loop) costs us only 4 transistors. But we still need to write and read from the memory, to do so we had the two transistors (see on the image) which also allows us to let the memory live on its own (when the transistors are open) **or** to be connected to the world.

If I want to see what is on the memory I put one in the word line (WL) and I will get the value on the bit line.

The question now is how to write? As said earlier, now we have a signal that is stored in there but

it is stored for infinity.

The only way to write is to "shout louder than the current signal". Imagine we currently have a 1 as the output of the latch and I want to put a 0. If I shout 0 louder than the 1 while connected, it will have a short circuit... and this is bad. **However** what is going on in fact is the upper not gate will have two inputs, a **loud** 0 and a quiet 1, the not gate will then take the loudest one thus 0.

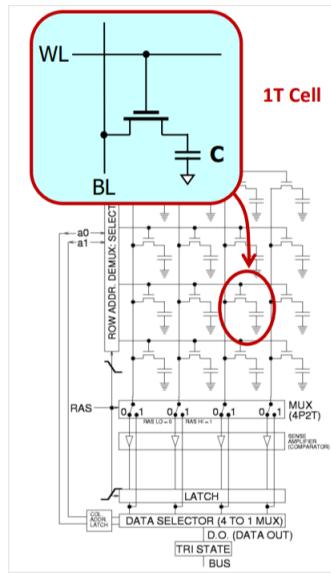
And now it will take a really short time to the latch to adapt itself to the new value, the short circuit here takes the times two the 0 to go through two not gates. and then it agrees.

On the other hand we have DRAM:

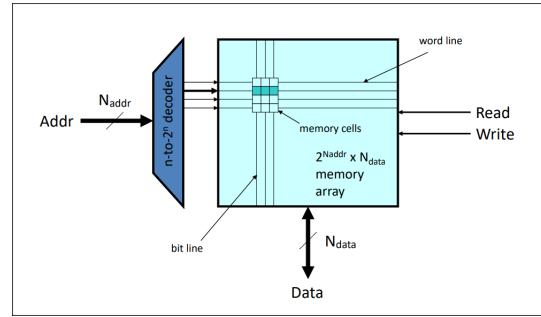
### DRAM

- Dynamic RAMs are the densest (and thus cheapest) form of random access semiconductor memory
- DRAMs store **information as charge in small capacitors** part of the memory cell
- First patented in 1968 by Robert Dennard, scaled amazingly over decades and was somehow an important ingredient of the progress of computing systems.
- charges **leaks off** the capacitors due to parasitic resistance  $\Rightarrow$  every DRAM cell needs a **periodic refresh** (e.g. every 60ms) lest it forgets information.

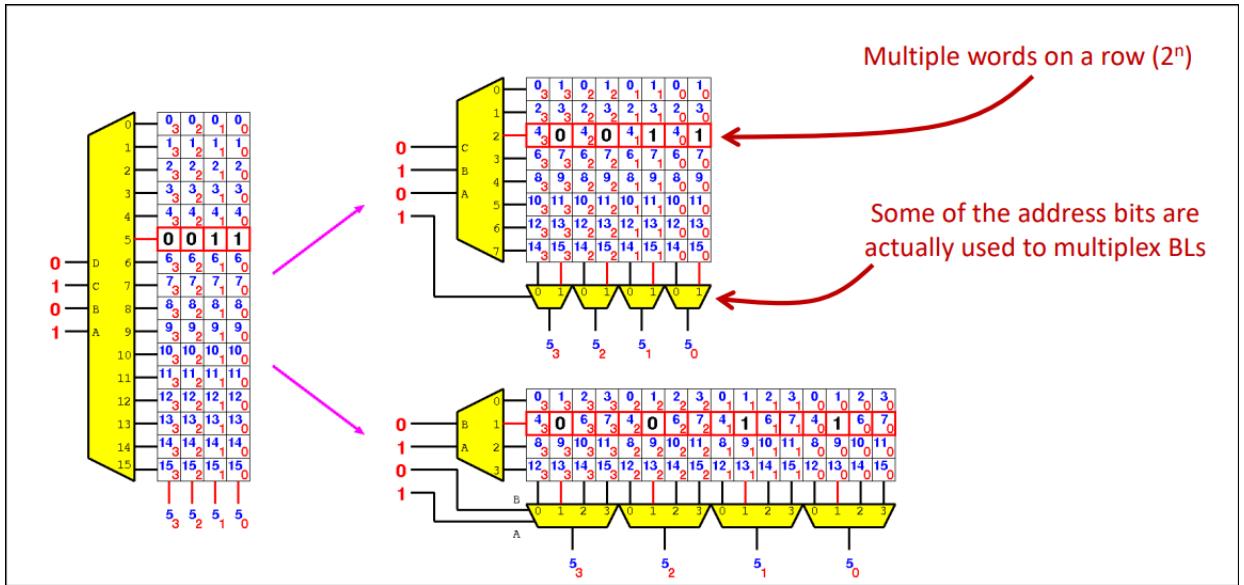
So imagine, if we don't go in each cell every 60ms then we lose the information, but we have other things to do? So how do we do it? - we have someone else refresh them for us. The memory controller is responsible for refreshing the contents of the DRAM instead of the CPU.



The goal after this is to access those memory cells based on the address we input. The *ideal* way to do so, would be to have one **big** decoder that treats the address and directly output the information in the memory cells like this:



However life is not always that easy, and there is a lot of way to get the memory cell based on the address, here are some example:



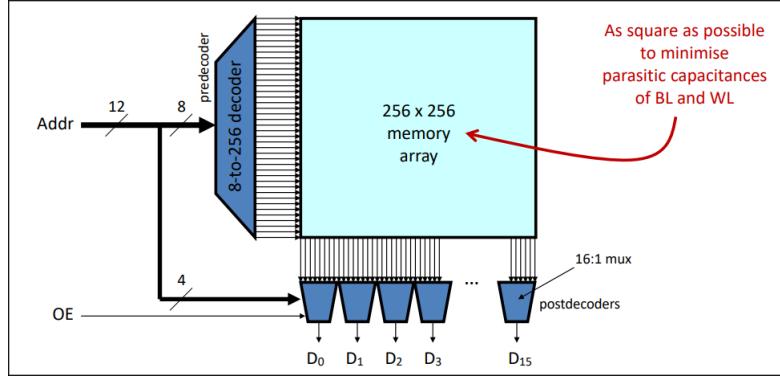
Here we have 3 ways to do so:

- On the left, We have the same way as the *ideal* decoder with one byte per row
- However we can also split up into a grid with more than one **big** multiplexer. This implies that there will be multiple word by row and that the bytes are not necessarily ordered.

The best physical way to create a Random access memory is in a square to minimize parasitic capacitance of BL (bit line) and WL (word line). We want to having it into the most squared possible form because:

- When a word line is activated (row), the bit line carries the data (bit) stored in the selected memory cell to the output circuitry (like a multiplexer or sense amplifier).
- Activating a word line selects all the bits (across bit lines) in that row — this is your selected "word."

Therefore by having the smallest length, we get shorter lines  $\implies$  lower parasitic capacitance  $\implies$  faster access, lower power, and more reliable operation.



Every time we are looking for a memory cell, we need to charge all row and then all column, the goal here is to minimize the number  $x = r + c$  by a fixed area  $A$  (where  $A$  is the number of cell):

We have that

$$A = rc$$

$$\frac{A}{c} = r$$

Which implies that  $x = \frac{A}{c} + c$ , we are minimizing ( $x' = 0$ ) this:

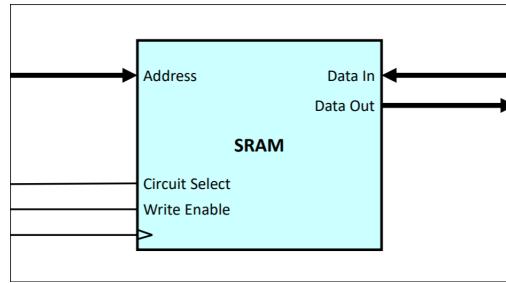
$$x' = -\frac{A}{c^2} + 1$$

$$\frac{A}{c^2} = 1$$

$$c^2 = A \implies c = \sqrt{A}$$

And because we know that  $A = rc \implies r = c = \sqrt{A}$  which is a square.

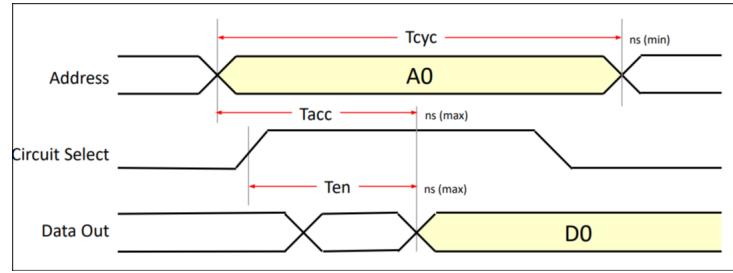
**Static RAM typical interface** This is the typical synchronous SRAM that we have already seen before:



However we don't always have to be synchronous, we can also be asynchronous for a Read cycle which works like this:

#### Asynchronous read cycle

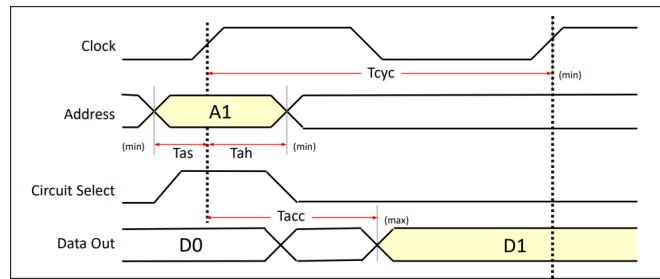
- Enable the memory → assert the address → wait for the data
  - Data out is available after a combinational delay  $T_{acc} = \text{Access Time}$
- Maximum frequency is limited by the minimum  $T_{cyc}$  (time for a cycle, time for us to be able to change the address)



### synchronous SRAM Read cycle

Here this is the other way around, we always wait a rising edge of the clock to do anything. Everything here is working like a flip flop:

- Everything is relative to the clock signal
- Latency is the number of cycles between the address asserted and data available
  - Often one as in this diagram but in some cases (large memories) more

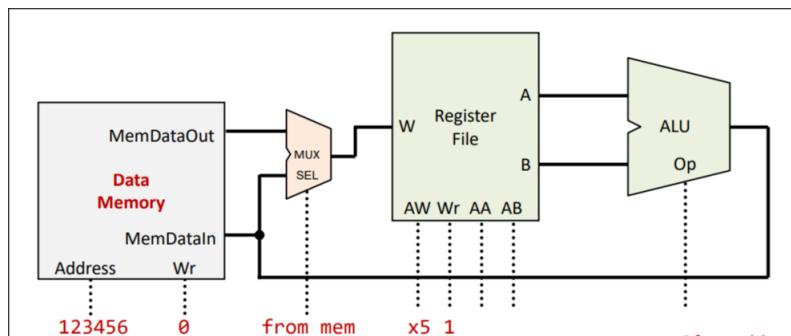


### Load and store instructions

Now that we have seen how it works, we want to see how to implement a load from the memory into the register file. For instance the following instruction:

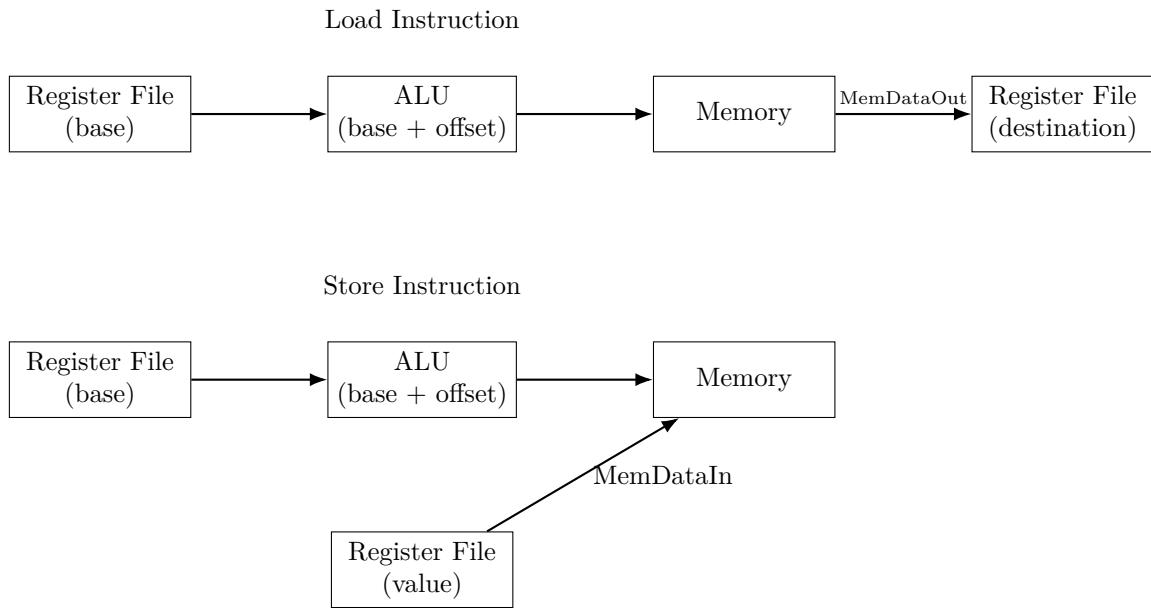
```
lw x5, (123456)
```

This is not a RISC-V instruction but bear with us. (I am not sure that's a saying...)



What we have changed here is the left part now instead of having a loop like ALU → Register file → ALU we break it at the first "→" and add a multiplexer there to be able to interact with the memory.

For the store instruction, instead of using the `MemDataOut` path, we use the `MemDataIn`. The main difference is this:



I had some trouble understand how does the value just pop, but if I understand it right, the register value is stored from the register file into **B** here. We use the **A** port as a address base. This is how it works:

1. IF, Fetch instruction ( `sw x2, 8(x1)` )
2. ID, Read `x1` and `x2` from register file
3. EX, ALU compute `x1 + 8` (address)
4. MEM, Store `x2` to memory at computed address
5. WB, Nothing (no register to write for store)

### Why RISC-V instructions are so simple?

Here are some example of some instruction that would look correct in RISC-V but is not (for addition):

- Based or Indexed

<code>add x0, x1, i5(x2)</code>	<code>#x0 = x1 + mem[x2 + i5]</code>
---------------------------------	--------------------------------------

- Auto-increment or -decrement

<code>add x0, x1, (x2+)</code>	<code>#x0 = x1 + mem[x2]</code>
--------------------------------	---------------------------------

- PC-relative

<code>add x0, x1, 123(pc)</code>	<code>#x0 = x1 + mem[pc + 123]</code>
----------------------------------	---------------------------------------

However those instruciton **does not exist** in RISC-V.

RISC-V is designed to have two world: one for accessing memory, and one for the logic/arithmetic etc. We cannot mix them together.

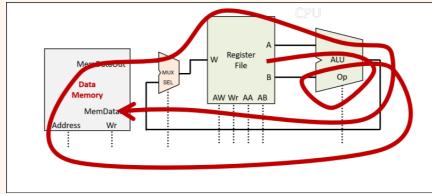
However in x86/x64 we can do this:

<code>ADD DWORD PTR [EBX + ESI*4 + 16], EAX</code>
--

This means:

- The **DWORD** means double word which means that we are working on 64 bits number.
- The **ADD** that has only two operand, the reason why, is that the goal of x86 in 1979 was to be the most compact possible, at that time the memory was limited and to be able to write program you had to be careful of the size of the program that you are writing. So they added the constraints that the output of the instruction is stored in the first operand.  
this means we take something in the memory at  $[EBX + ESI*4 + 16]$ , add it with **EAX** and then store it in  $[EBX + ESI*4 + 16]$ .

this feels pretty slow and pretty confusing, just try to map this into the CPU we created before, this would look like this:



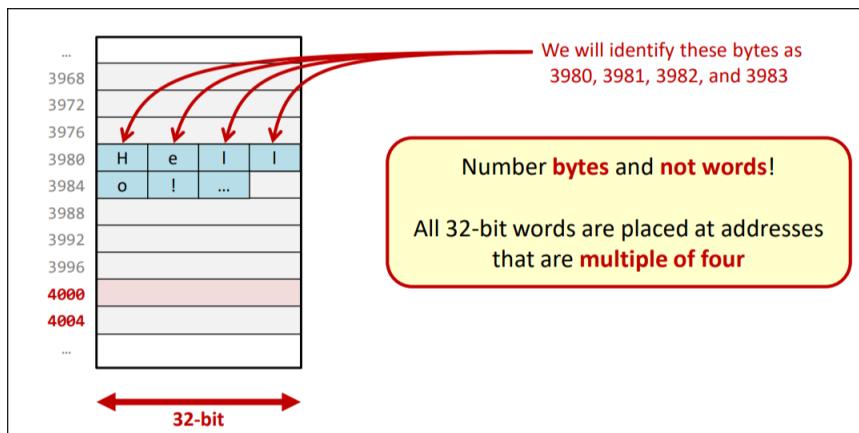
We would need to go like four times to the ALU, the fact is that **this is possible** however it makes it hard to optimize the processor.

The question behind all this is how does intel can still be as famous as they are now with instruction that looks like this and that cannot really be optimized? There is still the majority of the processor to this day that are intel processor (even if amd is better...), we will see this in a couples of weeks.

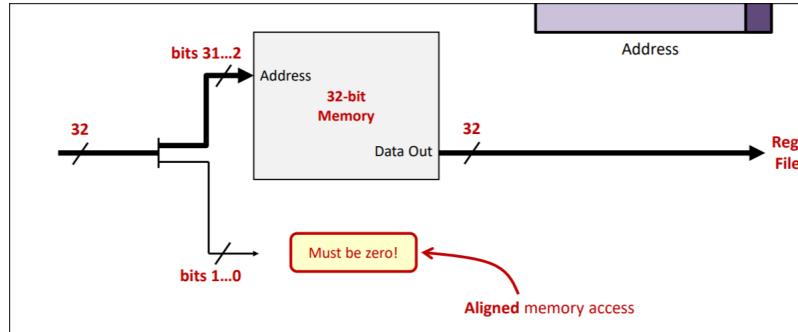
### Byte addressed memory

Almost all ISA today are use byte addressed memory. byte are quite important, disks are organized in bytes, network packets are bytes, **ascii** are byte. A lot of data are represented as byte so using an word addressed memory wouldn't be very efficient here, we would either loose a lot of time looking for the right byte, or loosing a lot of space by putting byte in word address (losing the three other bytes).

The solution is to no change the way memory is placed **but changing the label**.

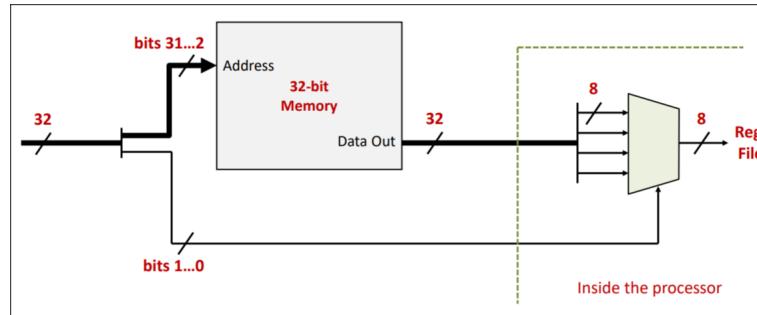


**Loading a word (1w) and Instruction** For instance, if we are interested in word, we cannot look for the word at address 3981, this wouldnt be a word.



As said before when loading a word, it has to be a multiple of 4 so we only care about the 30 most significant bits. The two least significant bits is checked whether there are zero or not and if there are not zero, we would like to **throw an exception** which we will see how in a couple of weeks.

**Loading bytes (1b)** Here what we are doing is the same as what we did before, we are looking for a word (which is the 30 first bits), and then in the word we choose which 8 bits we wants, this would look like this:



Remember when we changed the shape of the memory, how we choose which bit to take; we are doing the **same** here too. The difference is that this part is only in the processor, circuit wise this change nothing.

What is good here is that by just adding a multiplexer we can add a lot of instruction in the ISA.

## 2.4 Arrays and data structures

Data structures is one of the main concept in computer science, even in this course we have already talk about it (the stack).

Arrays in high-level languages

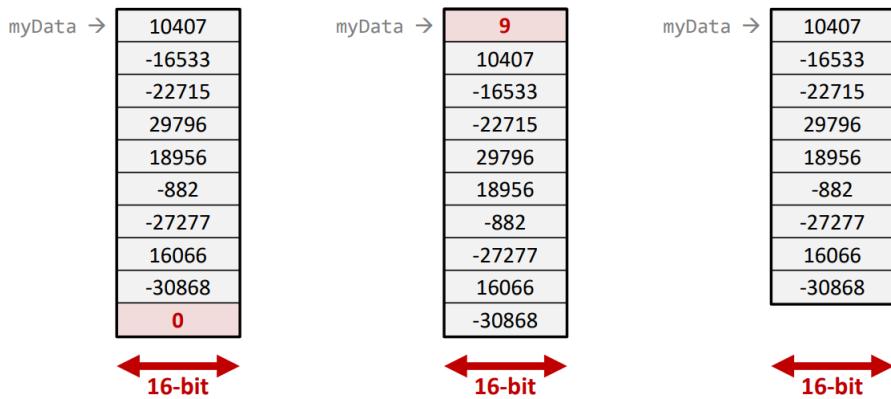
```
val myData: Array[Short] = Array(10407, -16533, -22715,
123133, 12512)
```

Here we have a sequence of number that are indexed, the question however is how do we store them?

We have a lot of ways to do so (three), we can:

have a pointer to the first element, and the having the other element following this one. With this method the issue is when does the array stops? here's three example of how to store arrays:

- One way to do so is to put a *null* element at the end of the array so that we know that this is the end of the array. The definition of string are in fact an array of char with the 0 char at the end.
- A whole other way is to have, at the start of the array the length of the array. You have a pointer at the start of the array which is the length of the array and then you do your computing as usual
- Another way with this is just to do nothing. Having a pointer to the start of the array and then hoping that the programmer knows what he is doing. C Arrays for instance are built like this.



### Adding Positive elements

To add all the positive elements in an array of signed 16-bit integers we would:

- At call time → `a0` points to the array (and, in type 3, `a1` is the length)
- At return time → `a0` contain the result

The result for the type 3 (written in `c`):

```
short add_positive(short myData[], int N) {
    short sum = 0;
    for (int i = 0; i < N; i++) {
        if (myData[i] > 0) {
            sum += myData[i];
        }
    }
    return sum;
}
```

### Adding positive elements (Type 1)

For the first type let us write the code in RISC-V:

```
add_positive:
    li t0, 0 #t0 will hold the sum (initialized to 0)

next_short:
    lh t1, 0(a0) # Load short (half-word) at address a0
    into t1
    beqz t1, end # If t1 is 0 (null short) we are done
    bltz t1, negative # if t1 is negative ignore
    add t0, t0, t1 #Add t1 to the sum (t0)

negative:
    addi a0, a0, 2 # move array pointer (a0) by sizeof(
                    short) to the next element
    j next_short # repeat the loop

end:
```

```

    mv a0, t0 # move the sum (t0) into a0 as the return
    value
    ret # Return the caller

```

### Adding positive element Type 2

```

addi_positive:
    li 01, 0 #t0 will hold the sum (initialized to 0)
    lh t1, 0(a0) # t1 will count the elements to process
    add a0, a0, 2 # Move array pointer (a0) to the first
    real element

next_short:
    beqz t1, end # If t1 is 0 (no more elements), we are
    done
    lh t2, 0(a0) # Load short (half-word) at address a0
    into t2
    bltz t2, negative # If t2 is negative, ignore
    add t0, t0 t2 # Add t2 to the sum (t0)

negative:
    addi a0, a0, 2 # Move array pointer (a0) by sizeof(
    short)
    addi t1, t1, -1 # Decrement the counter of elements to
    process
    j next_short # repeat the loop
end:
    mv a0, t0 # Move the sum (t0) into a0 as the return
    value
    ret # Return to caller

```

### Adding positive element Type 3

```

addi_positive:
    li 01, 0 #t0 will hold the sum (initialized to 0)
    mv t1, a1 # t1 will count the elements to process (a1)

next_short:
    beqz t1, end # If t1 is 0 (no more elements), we are
    done
    lh t2, 0(a0) # Load short (half-word) at address a0
    into t2
    bltz t2, negative # If t2 is negative, ignore
    add t0, t0 t2 # Add t2 to the sum (t0)

negative:
    addi a0, a0, 2 # Move array pointer (a0) by sizeof(
    short)
    addi t1, t1, -1 # Decrement the counter of elements to
    process
    j next_short # repeat the loop
end:
    mv a0, t0 # Move the sum (t0) into a0 as the return
    value
    ret # Return to caller

```

### Adding positive elements (variation on type 3)

Let us add positive elements in an array of signed 16-bits integers:

- At call time → `a0` points to the arrays and `a1` is the length of the array
- At return time → `a0` contains the result

The way od doing it is to incremented the index of the array:

```
int i = 0;
while (i < N) {
    if (myData[i] > 0) {
        ...
    }
    i++
}
```

This is equivalent to:

```
int i;
for (i = 0; i < n; i++) {
    if (myData[i] > 0) {
        ...
    }
}
```

Here we see that we have a variable `i` which is incremented by one, therefore, the way of doing this if we were to be compiled would be by having a variable that is incremented by 1 in every loop **then** be multiplied by the size of the data (2 bytes).

```
addi_positive:
    li t0, 0 #t0 will hold the sum (initialized to 0)
    mv t1, 0 # t1 will hold the array index

next_index:
    beqz t1, end # If index >= number of elements , we
                  are done
    slli t2, t1, 1 # t2 = offset of the element as index
                  (t1) * sizeof(short)
    add t2, a0, t2 # Address of the element = myData (a0)
                  + offset(t2)
    lh t3, 0(t2) # load short (half-word) at address a0
                  into t3
    bltz t3, negative #if t3 is negative, ignore
    add t0, t0, t3 # Add t3, to the sum (t0)

negative:
    addi t1, t1, 1 #Increment the counter of element to
                    process
    j next_index # repeat the loop
end:
    mv a0, t0 # Move the sum (t0) into a0 as the return
               value
    ret # Return to caller
```

*Which one is better?*

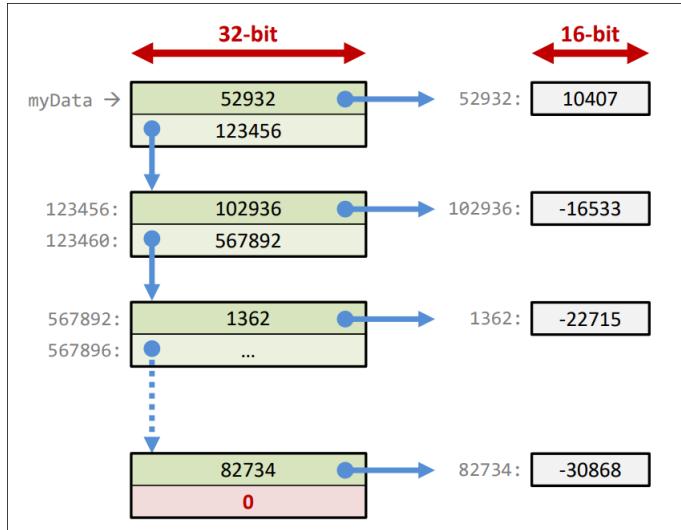
We have now two different way to do the same type (type 3), however which one is faster? this question can be easily answers:

the first one that we have written has less intrustion  $\Rightarrow$  faster. (this is not always that simple)

But this points out an issue, we need **good compiler**, we need a compiler that can translated our code into the **fastest assembly code possible**.

**Linked list**

Another way to store data is with a linked list:



As we can see here this is the same principle as what we did before, we store for each element the current address of the value **and** the address of the next value. To iterate through this list all we have to do is to go to the current value get the value via the address and then take the next iteration with the second address.

What is good about this is that:

- Insert element in the array is very easy

However there is a lot of bad thing here:

- For each value we have to use 64 bits of addresses which is a lot
- iterate through the list seems nice however are all the instruction truly equal?

For instance imagine we wanted to recreate the same code as the one we wrote for the other arrays:

```

add_positive:
    li t0, 0 # t0 will hold the sum
next_element:
    beqz a0, end # If address of next element (a0) is zero
                  , we are done
    lw t1, 0(a0) # Load address of actual data into t1
    lh t1, 0(t1) # Load short (half-word) at address t1
                  into t1
    bltz t1, negative # if t1 is negative, ignore
    add t0, t0, t1 # Add t1 to the sum (t0)

negative:
    lw a0, 4(a0) # Load address of next element into a0
    j next_index
end:
    mv a0, t0 # Move the sum (t0) into a0 as the return
               value
    ret # Return to caller
  
```

As we can see here: this is not much more complex. but is it more efficient? **no**. The instruction of loading and storing are way **slower** than the other

instruction, the fact that this way of computing leads to a lot more of load makes it way slower.loading byte

## 2.5 1.e: Instruction Set architecture Arithmetic

### Notation

- Number (represented on a specific no. of digits/bits)

$$A = A^{(n)} = A^{(m)}$$

- Number (in binary or decimal)

$$A = A_{10} = A_2 = A_{2c}$$

- Individual digits (bits)

$$a_{n-1}, a_{n-2}, \dots, a_2, a_1, a_0$$

- Digit string (representation)

$$< a_{n-1}a_{n-2} \cdots a_2a_1a_0 >$$

### Numbers

we usually care for three types of numbers:

- **Integers** (signed and unsigned)
- Fixed point

$$0.12, 3.14, 1013141212512.5124213$$

- Essentially integers with **implicit  $10^k$  or  $2^k$  scaling**
- Extremly important in practice (most signal processing is fixed point)

- **Floating point**

$$3.14E3, -2.4E - 1$$

As we have seen in it fds, we feel like fixed point are just some useless number representation but this is **false**. As said before, in signal processing we use a lot of number that needs to be *pointed* (not integers), but it also need to be **fast** as for us to be able to watch a live twitch or a youtube video... We need to do a lot of computation the fastest way possible. Floating point are pretty bad at this, addition using floating is much more slower than integers addition, we know that fixed point are just integers disguised as rational number. That's the reason why we use fixed point representation.

### Unsigned Integers

$$A = \sum_{i=0}^{n-1} a_i R^i$$

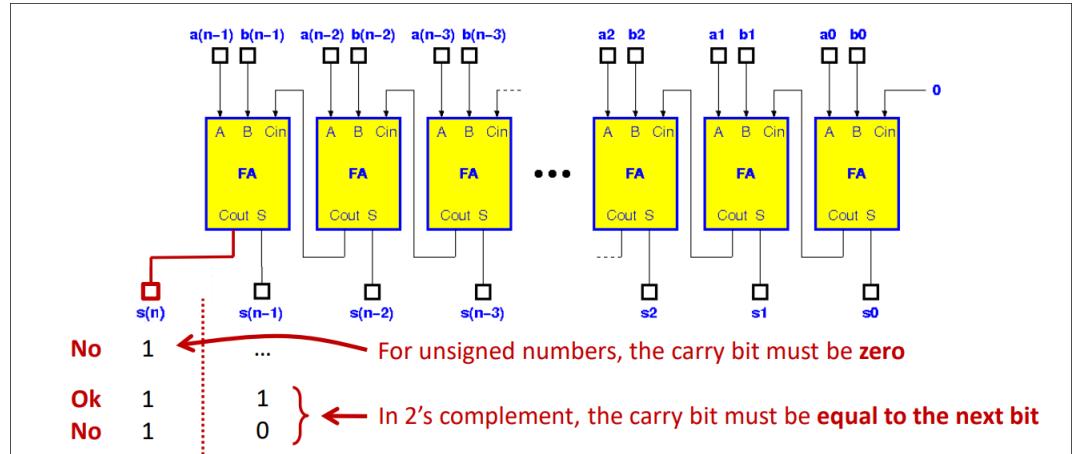
For the next part of this course I am gonna skips this because it is a big review of what we have already seen in fds, I am just going to write what I find intresting **for me** which is not necessarily the most important thing.

### Addition is unchanged from unsigned

As we can see (remember of the table) addition for signed number (in two's complement) and unsigned number is the same, this allows us to have **only** two instructions (`add` and `sub`) without any `addu` like instruction. This is one of the reason why we use 2's complement as the universal representation of signed integers today.

### Overflow in hardware

In hardware, **carry out** is the only missing bit from the **complete** result. We can think of overflows as a **tuncation** problem:



### Overflow in software

Some architecture (e.g., **x86**) gives us the **carry bit** in a special register (a **flag**)

→ overflow detection is the same as in hardware

Other modern architecture gives us **only the result** of the addition (e.g., **RISC-V**). The detection is usually based on the following observations:

- If addition of **opposite sign number** ⇒ magnitude can only reduce →**no overflow possible**
- If addition of **same sign number** ⇒ overflow is possible but the sign of the result will appear wrong.

$$A + \overline{A} = -1$$

As we have seen here

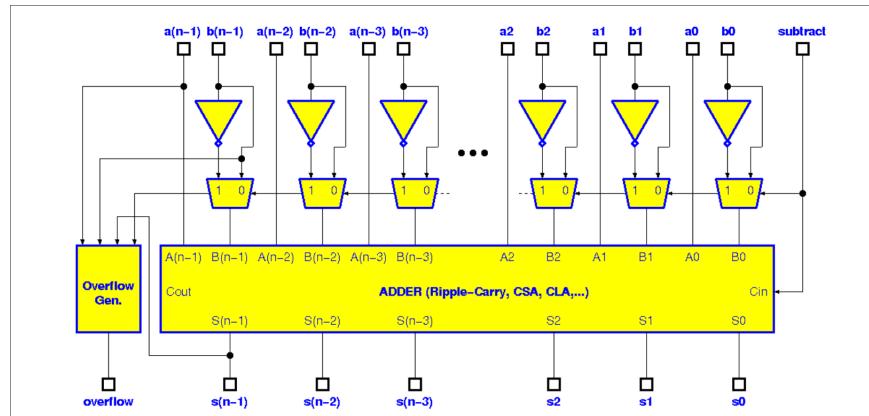
$$-A = \overline{A} + 1$$

To prove it:

$$\begin{aligned} & \left( -a_{n-1}2^{n-1} + \sum_{i=0}^{n-2} a_i 2^i \right) + \left( -\overline{a}_{n-1}2^{n-1} + \sum_{i=0}^{n-2} \overline{a}_i 2^i \right) \\ &= -(a_{n-1} + \overline{a}_{n-1}) \cdot 2^{n-1} + \sum_{i=0}^{n-2} (a_i + \overline{a}_i) \cdot 2^i = -2^{n-1} + \sum_{i=0}^{n-2} 2^i \\ &= -1 \end{aligned}$$

### Two's complement Add/Subtract Units

With this property it becomes very easy to compute subtraction as it is just the use of the addition part but with the inverse + 1. This can be done by having a  $c_{in}$  at the beginning of the adder and to have a multiplexer to choose between the  $b_i$  or  $\neg b_i$



as we can see this allows us to put the subtraction and addition into the same module.

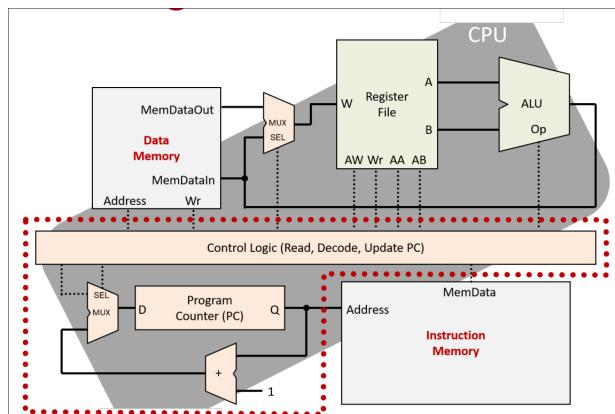
# Chapter 3

## Processors, I/Os, and Exceptions

### 3.1 2a. Multicycle Processor

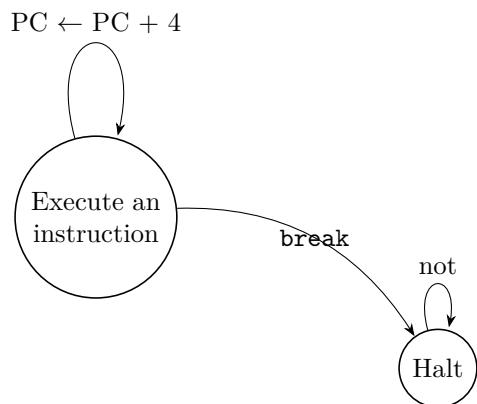
In this section, we will more go into the detail of the **hardware** behind the cpu. Especially multicycle processor.

As seen before, the CPU has more than one part:



However the red part (les pointilles rouges) here is in fact a **big finite-state machine**. This means that we can create a state diagram for it.

**Single cycle processor** For instance the state diagram of a single-cycle processor is very easy:



| *Remark*

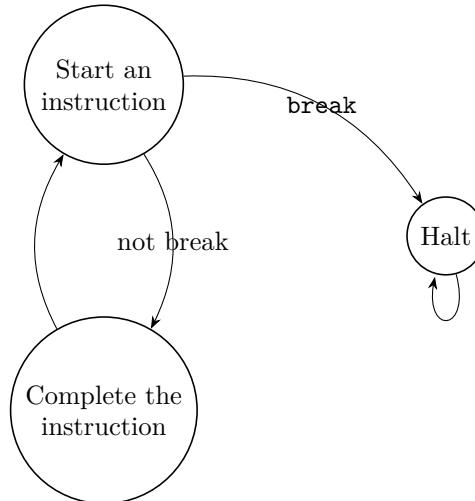
If someone knows how to makes the break here above or below the line I will be curious how.

There is only two state which means that every instruction is done at a separate time (single cycle). This directly implies that the longest **combinational path** determines the operating frequency: **critical path**.

If we wanted to increase frequency then the critical path would be halved into another cycle.

### Two-cycle Processor

let us look at the finite state machine of a two cycle processor:



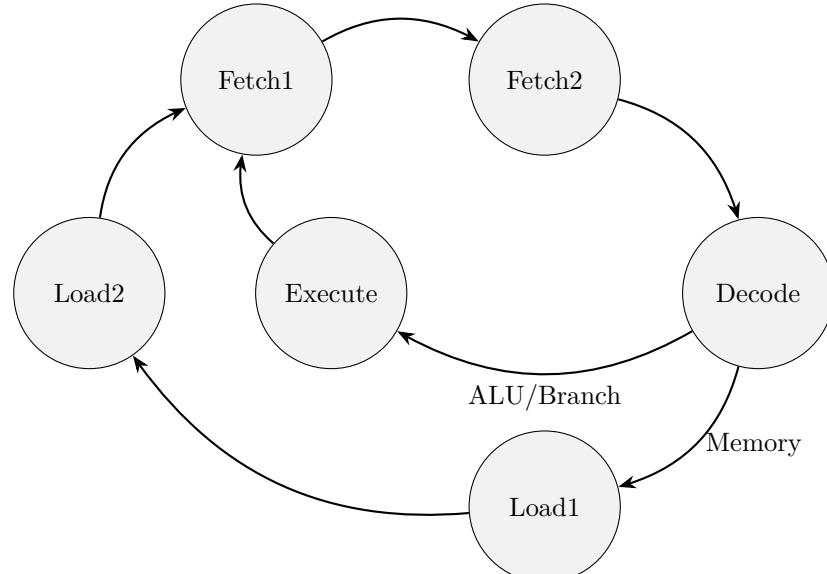
The question we must ask now is: Did we gain anything?

At the moment not really, before we had 1 instruction **per cycle** at frequency  $F$ . Now, we have 1 instruction every **two cycles** at frequency  $2F$ .

### Not all paths are born equal

That's something sad to say but not all path are born equal, some are slower than other, and this is okay (graine de sarrasins). For instance the `andi` instruction is much faster than the `lw` instruction.

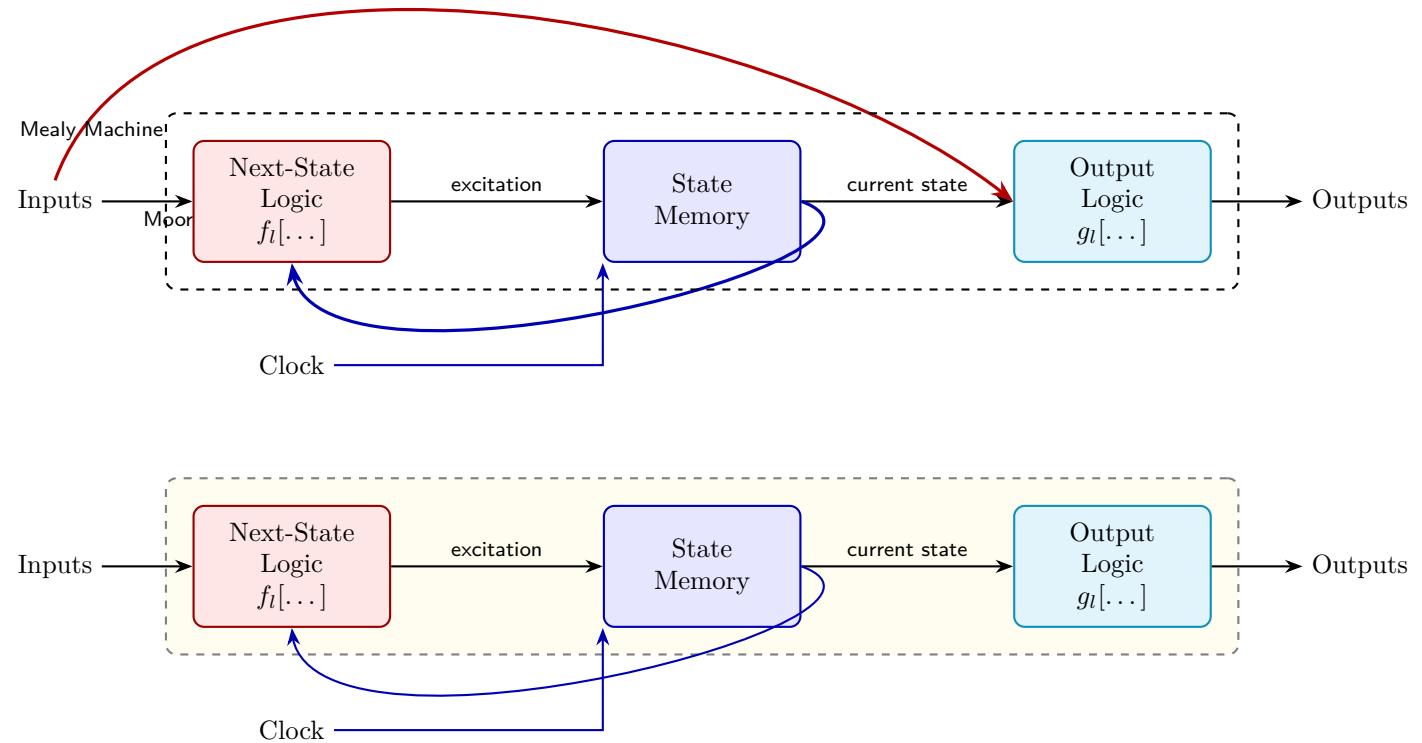
### Multi cycle Processor



The goal here is:

1. **not** to have **too many** stages
2. To have paths as **balanced** as possible

### Mealy or Moore?



I spent an hour on this so please appreciate.

The definition of the mealy fsm is that the output depends on the **input and state**. On the other hand, the definition of the moore fsm is that the output depends on the **state only**.

As a human the moore machine is **way** easier to develop test, etc. We **always** want to implement a fsm as a moore machine. And good news: it is always possible (almost)

All we have to do is to retard the current output to the next cycle and put our output as a *state* of the fsm. This way: the next output (which becomes the current) is just a **part of the state**.

#### 3.1.1 Building the circuit

What we are going to do now is to build the circuit. To do so, we'll do it step by step, adding progressively what we need.

First, we need an instruction register which store the current instruction (so that it doesn't die after one cycle). We will also need a Controller and the `pc`.

##### I-Type instructions Need `RF` and `ALU`

Type I is the instruction with immediate, this means that there is only one value as input (that's why I put value and not values). To be able now to `add`, `sub`, etc. We need three things:

- Value to be computed

- Somewhere to compute
- Value to store the result

The value to be computed and the value to store the result are in the same place: the **register file**. The location where we'll compute the instructions are in the **ALU** (Arithmetic Logic unit)

### R-Type

we'll go over instructions with two values as input. To do so, we'll use the same ALU as the one before and we'll just add a multiplexer to choose from the immediate and the register value.

### U-Type instructions write an immediate

We now need to store immediate instead of the result of the ALU. Therefore, those instructions will need a multiplexer **after** the **ALU** in order to choose to write either the result of the **ALU** or the immediate.

### Load and Store produces a memory address

For those we will need to output the address. At the moment the only *load* that we did is on the program with the **pc**. However now we will also need to load from the memory data. In order to do this, we will need to choose to load either the **pc** or the output of the **ALU** as an address  $\Rightarrow$  we add a multiplexer.

### Loads write the read data into **RF**

So now we can access the memory however after accessing the memory we get a **rdata** which we still need to manage. To do so we will treat it as it is an output from the **ALU** by **adding** a multiplexer. After this output, we will need a signal to know whether we are choosing from memory or from the **ALU** **sel\_mem**.

### Stores send an operand to memory

Now the instruction we want to implement is the **sw t0, 16(t1)** instruction. For this instruction, we will choose the **b** signal as the **t0** and the **a** as the address(as we did before). Therefore we need to connect the **b** into the memory with the new signal **wdata**. The difference between the store and the load is the **we** (write enable) signal that serve the memory to know whether we are reading or writing into it.

### Branches need to write an offset to the **PC**

To implement the instruction **beq t0, t1, 1234**, what we do is to change the **pc** based on a condition, this condition will be compute in the **ALU**, the **alu** will output in his lsb whether or not the **PC** will be updated.

If the branch is successful, we want to replace the current **PC** by the immediate which leads us to add a path from the controller into the **PC**, a new branch of the **imm** signal. The controller has to also informed the **PC** whether or not we have to enable the writing.

Here we have two clauses:

1. **branch\_op**  $\rightarrow$  informs us of if we are in a branch operation
2. **alu\_res** which is the lsb of the **ALU** as said before

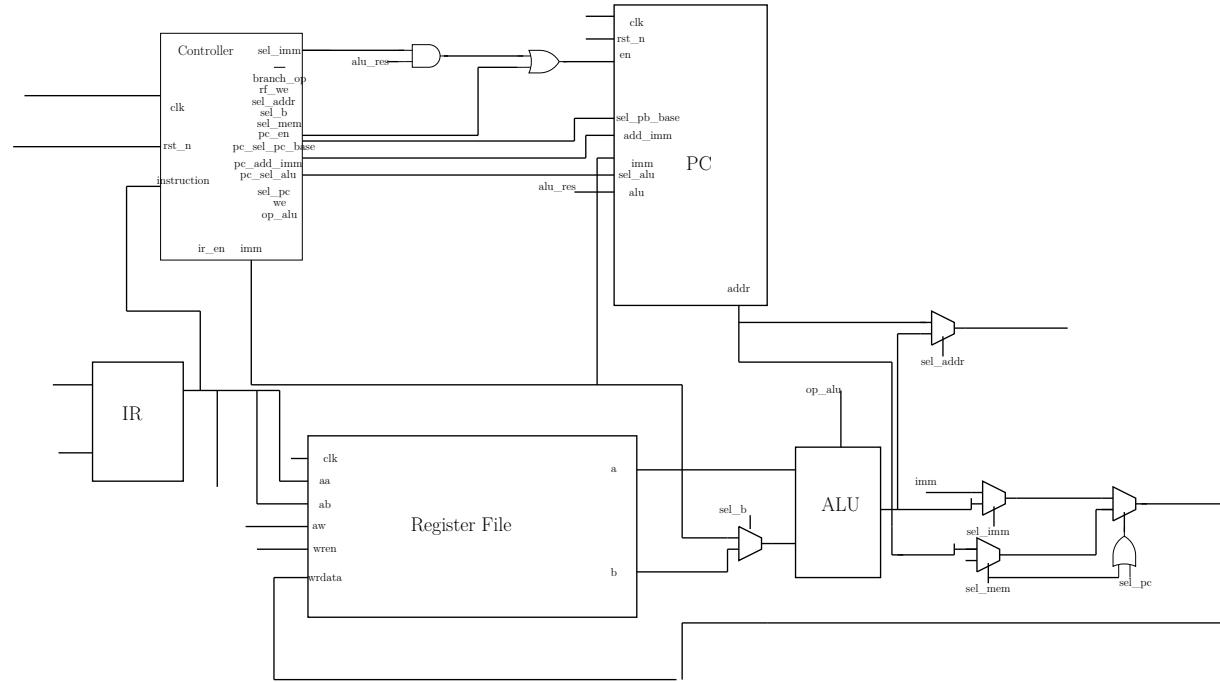
If those two signal are up  $\Rightarrow$  we enable the write of the **PC**.

As we can see now, the **PC** is no longer just a simple register, it contains some logic to compute new values.

### jump and link need to store **PC + 4** in the **RF**

To do so, we therefore need another output from the **PC** which can be stored into the register file based on a signal **sel\_mem** (which has to be 0, the inverse of what we have used for before) and the

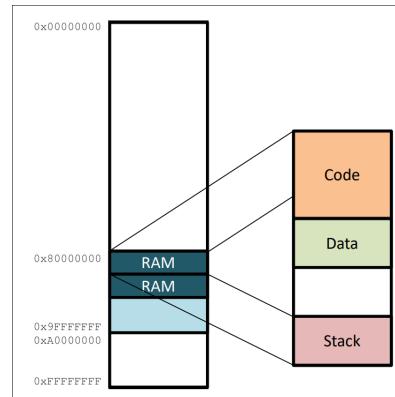
`sel_pc` signal.



I know it is very ugly but this was [loong to do](#). (for those interested I used <https://tikzmaker.com>, to do it)

#### Detail complex combinational modules

As you can guess each part of those module has more into them, for instance the `ALU` has 4 sub modules (which we will implement in the first part of the second lab).



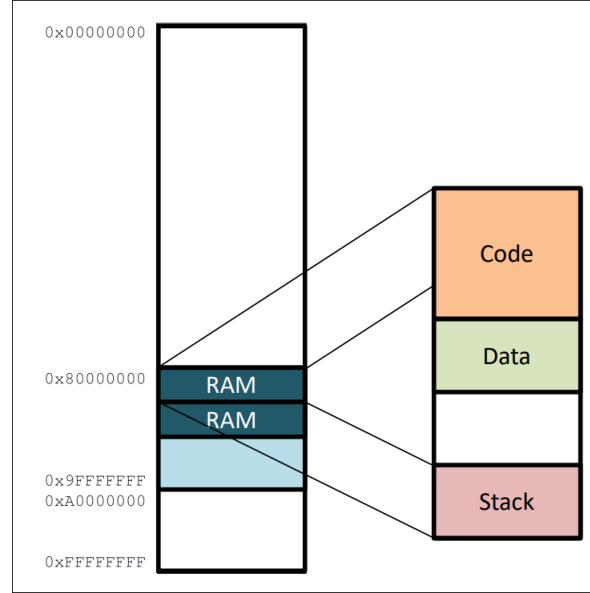
## 3.2 2b. Processor, Inputs and Outputs

### The cpu

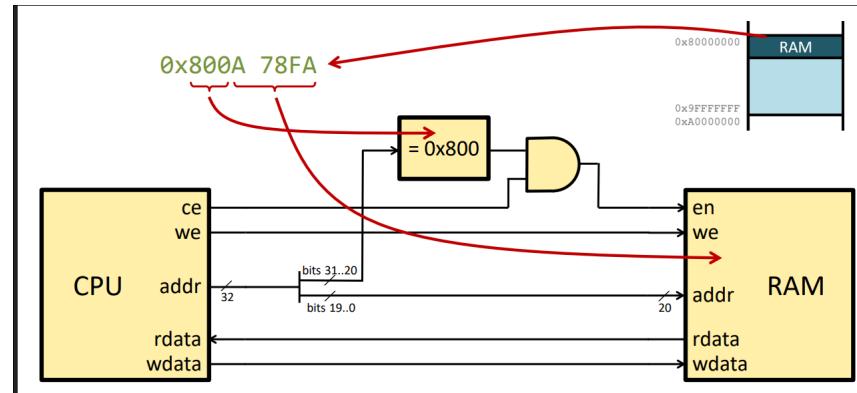
As said before, the cpu is a very **sequential** component (but from now on we may omit the **clock** in diagrams). Therefore, here we only have one data bus for read and write in our processor. The question we have is how can we handle input and output with only one data bus?

### Memory

At the moment we only need to speak about memory, connecting the cpu with the memory is pretty *easy* as seen before



We assume that the ram begins at the address `0x80000000` and then add what is needed to be added:



### Input and Outputs device

As said before we only have 5 classic components of a computer, from where can we get our I/Os then? the way of doing this, is to use memory, we say that the device are just some value in memory with a certain address. However for this we have some issue:

Some devices are way **faster** than others for instance here's a table of some examples:

This is an issue because the CPU doesn't know so sometime it will try to read/write into a **slow device** at the same speed, it will **stall** or waste cycle aiting for the device.

Type	Peripheral	Data Rate
Human Interaction	Keyboard Mouse	~kbps ~kbps
Generic	Serial Port (RS-232) Parallel Port (LPT) USB 4.0	115.2 kbps (max) 150 kbps 20–40 Gbps
Generic (Wireless)	Bluetooth 5.0 PCIe 4.0	2 Mbps 16 Gbps per lane
Storage	SATA III (HDD/SSD) NVMe (PCIe 4.0)	6.0 Gbps 64 Gbps (4-lane)
Networking	Ethernet (10BASE-T) 10 Gigabit Ethernet (10GBASE-T) Wi-Fi 6 (802.11ax)	10 Mbps 10 Gbps Up to 9.6 Gbps
Displays	VGA (analog video) HDMI 2.1	0.6–1.5 Gbps (approx.) 48 Gbps
Optical Discs	CD-ROM DVD-ROM Blu-ray	150 KB/s (1x) – 7.68 MB/s (52x) 1.32 MB/s (1x) – 21.1 MB/s (16x) 4.5 MB/s (1x) – 54 MB/s (12x)

Table 3.1: Approximate data rates for common peripheral interfaces.

#### Accessing I/Os: Port Mapped I/O (PMIO)

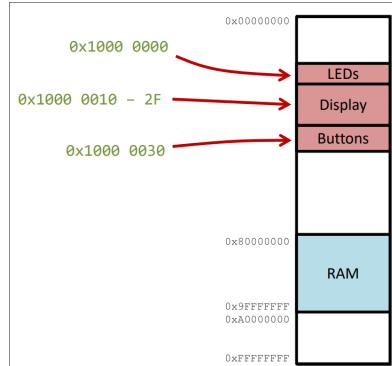
The way for this is to create a **new interface** similar to the memory one. We add the to CPU the port `ctrl-I/O` and `port` Which serves as circuit enable and output enable. (this way, we'll know when accessing memory or I/O).

It implies that we can create new instructions (e.g., `x86` but seldom used):

- `IN register, port`
- `OUT port, register`
- For instance `IN al, Keyboard`

#### Accessing I/Os: Memory Mapped I/O (MMIO)

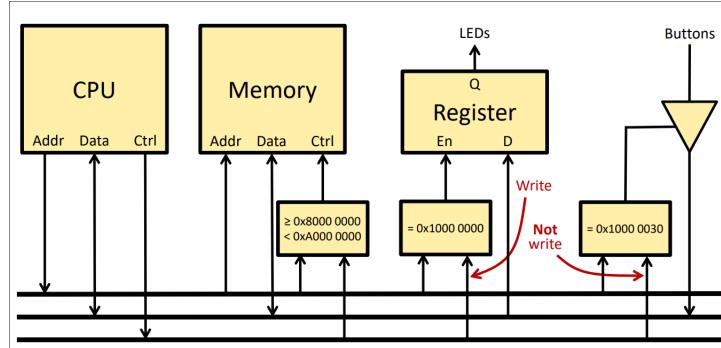
In this way, we don't make any difference between memory and I/Os.



This means that there are no special hardware needed in the cpu  $\Rightarrow$  no special instructions needed. For instance in our example if we wanted to write a new value in the led:

```
lui t0, 0x10000 # pointer to I/Os
sw t1, 0(t0) # write LEDs
```

This means that we have a big data bus and depending on the value **the bus** choose between the Memory and the I/Os:



#### *Memory*

Memory is accessed via unique addresses. RAM begins at a base address (e.g., `0x80000000`) and grows as needed. Connection to the CPU is straightforward.

#### *I/O Devices*

I/O devices are mapped to specific addresses in the system. Devices have widely varying speeds, which can cause the CPU to stall if a slow device is accessed at full speed. Examples include keyboards (kbps) and USB 4.0 (up to 40 Gbps).

#### *Port-Mapped I/O (PMIO)*

PMIO creates a separate I/O address space. The CPU uses control signals and special instructions (`IN` and `OUT`) to access devices. This isolates I/O from memory.

#### *Memory-Mapped I/O (MMIO)*

MMIO maps devices directly into the memory address space. The CPU accesses I/O using standard memory instructions. No special hardware or instructions are needed; the data bus selects memory or I/O based on the address.

### Conclusion

Both PMIO and MMIO allow the CPU to interact with I/O devices using a single data bus.

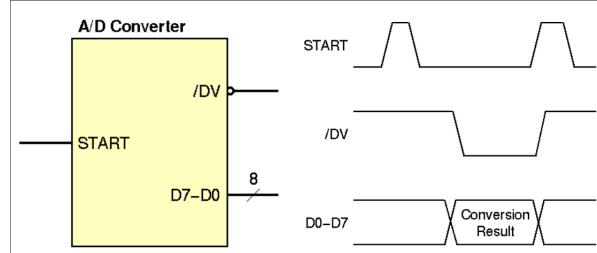
- **PMIO** separates memory and I/O with dedicated instructions and control signals, providing clarity but requiring extra CPU support.
- **MMIO** treats I/O devices as memory, simplifying the CPU design and instruction set at the cost of shared address space.

In modern systems, MMIO is more common because it allows standard memory instructions to handle I/O efficiently, while PMIO is mostly used in legacy systems or for very simple microcontrollers.

### Example: A/D converter

An A/D converter is a device that **converts an analog signal into a digital signal**. What we need is:

1. **Start** (`START`): input; when active → begins a new conversion
2. **Data Valid** (`/DV`): output when active → D7-D0 are valid
3. **Data** (D7-D0): output; last conversion result



### Example: Simple bus interface

*Remark*

Here we are talking about the processor directly this information helps us to do the diagram between the CPU (Here the MC6800) and the A/D converter.

We are also saying a 8 bits processor because the data bus is 8 bits (this doesn't imply anything about the register in the CPU).

Suppose that a 8-bit processor has the following signals:

- **Address** (A23-A0): output; address bus
- **Data** (D7-D0): input data bus
- **Address Strobe** (/AS) output, signals the presence of a valid address on the Address bus during a memory access cycle
- **Read/Write** (R/W): output; signal the direction of the data flow
- **Data Acknowledge** (/DTACK): input; must be activated at the end of a memory access, when the written data have been latched or the read data are ready

This is similar but not identical to the MC68000

ChatGPT on the mc68000:

The MC68000 (also called the Motorola 68000) is a 16/32-bit microprocessor that was very popular in the late 1970s and 1980s. It was used in systems like the original Apple Macintosh, Amiga computers, and early Sun workstations. In your example, it's mentioned as a reference because the bus signals are similar to those on the 68000, but not exactly the same.

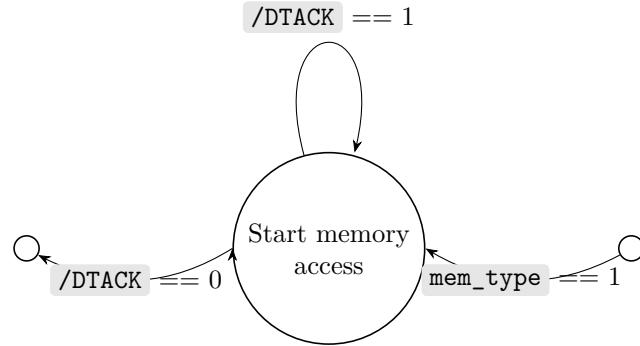
**in short:** the MC68000 is just a classic CPU used as a reference for teaching how these buses work.

The goal now for us is to create a circuit that is able to connect the A/D converter to the processor (the MC68000). For this we will use a **memory mapped interface**.

We want:

- **any access** (R or W) to address **0xFFFF0** starts a **new conversion**
- The **data valid** signal can be read by the processor at address **0xFFFF4** (bit 0)
- The **result of the conversion** can be read by the processor at address **0xFFFF8**

Here's a little diagram of the state



To be able to construct the circuit we have to be careful about the timing diagram here; the fact that the ADDR and the /AS responds only at the clock edge gives us the information that we will need a *register* which stores the DTACK signal and then output the As and ADDR signal after. This big register here is the **processor**.

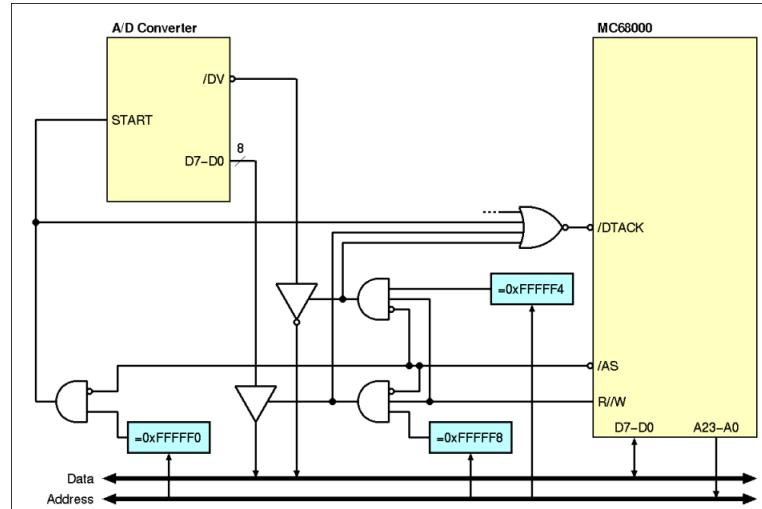
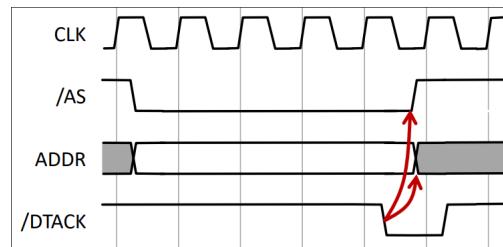


Figure 3.1: A/D converter circuit

Here we can see that we have two tri-state buffer, but why? It is pretty rare for us to see tri-state buffer so why are they useful here?

The answer is that they serve as a multiplexer between the DV and D7-D0, you can look at it and if you think about it, the two tri-state buffers really serve as a *decentralized* multiplexer.

**A/D converter:** Let us now look at it as a software person which is pretty easy because of the MMIO:

```
read_adc:
```

```

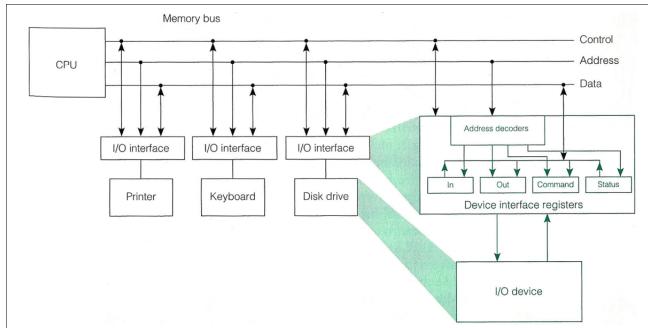
        lui t1, 0xffff
        addi t1, t1, 0xfff0 #t1 = 0xffffffff
        sw zero, 0(t1) # start conversion
poll:
        lw t0, 4(t1) # t0 = DV signal
        beqz t0, poll # wait until done

end:
        lw a0, 8(t1) # a0 = A/D output
        ret

```

### Programmed I/Os

Many peripherals are more developed programmable systems and have a set of registers which the processor reads and writes (a) to **send** and **receive data** and (b) to **issue commands** and **read the status**.



Here we can see an issue that we will solve later, the `poll` part of the function. The code that we wrote here **implies directly** that when we start our conversion we **have to wait until** it is done. But we don't know anything about the time that this is going to take, it can take forever. Imagine having a bug in the A/D converter which makes it not work, we would be polling forever! The only way for us to stop it would be to turn down the computer (not very practical). Therefore we will need to resolve this issue...

#### 3.2.1 A Classic UART

##### Definition

A **UART** means: Universal Asynchronous Receiver-Transmitter

This is one of the **simplest and most common communication** peripherals, it is typically used today to connect terminals to embedded devices. Our UART has a **simple programmed I/O interface** with four registers:

- A **control register** for the processor to configure the UART
  - Bit 7 must be set to 1 for the UART to be enabled
  - Bits 2..0 configure the communication speed (e.g., 0b001 for 9600 baud)
- a **status register** for the processor to check the status of the UART
  - Bit 1 is 1 if there are data available
  - Bit 0 is 1 if the UART is ready to send data
- A **data input** register where the received data are available to the processor
- A **data output** register where the processor places data to send

##### Example: Send a String

For instance we can try to send a String into the UART:

Just to remember, a **String** is an array of char which is terminated by the null character.

The goal here will be to send each char (bytes) to the data bus. To do so we'll

need to check if the UART is ready  $\implies$  is the transmitter is ready. If it is, we can store our bytes into the UART data register which will then do the rest for us.

```

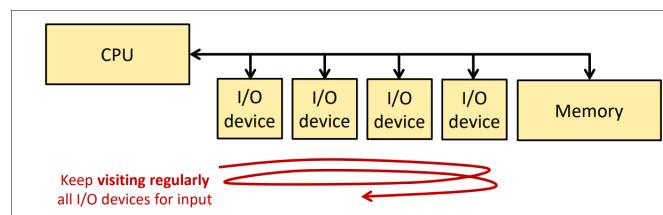
UART_CTRL_ADDR = 0x10000000 # UART status register address
UART_ENABLE_BIT = 0x80 # Enable bit (bit 7)
UART_SPEED_9600 = 0x01 # Speed setting for 9600 baud (4 bits, [3:0])
UART_STATUS_ADDR = 0x10000004 # UART status register address
TX_READY_BIT = 0x01 # Transmitter ready bit (bit 0)
UART_DATAIN_ADDR = 0x10000008 # UART data input (receive) register address
UART_DATAOUT_ADDR = 0x1000000C # UART data output (send) register address
send_string:
    li t0, UART_CTRL_ADDR # Get UART control address
    li t1, UART_STATUS_ADDR # Get UART status address
    li t2, UART_DATAOUT_ADDR # Get UART data address
    li t3, UART_ENABLE_BIT # Get enable bit (0x80)
    li t4, UART_SPEED_9600 # Get speed setting (0x01)
    or t4, t3, t4 # Combine enable and speed bits
    sw t4, 0(t0) # Configure using the UART control register
next_char:
    lb t5, 0(a0) # Load first byte of the string
    beqz t5, finish # If byte is zero (null terminator), finish
check_tx_ready:
    lw t6, 0(t1) # Load UART status register
    andi t6, t6, TX_READY_BIT # Check if TX_READY_BIT is set
    beqz t6, check_tx_ready # If not ready, loop back and check again
    sw t5, 0(t2) # Store the character in UART data register
    addi a0, a0, 1 # Increment string pointer (move to next char)
    j next_char # Jump back to send the next character
finish:
    ret # Return when the string is done

```

### I/O polling

Everything we did here is nice however there is still some issue: **polling**  
The issue with polling is that the cpu is *waiting* until the polling is done which is slowing down the cpu (a lot). Moreover, how do we even know if a peripheral has data for us (key pressed, packet arrived, etc.)? we are not able to poll everything.

For something like a keyboard which would only need to check every ms (approximatively) it would be *okay* however imagine a usb or an ethernet cable this is not managable.



### 3.3 2c: Interrupts

The solution of our previous problem is interrupts! Instead of waiting for each I/O to respond, we can do our stuff and **when a I/O shouts** we do what he want us to do. We have them **asking for attention**

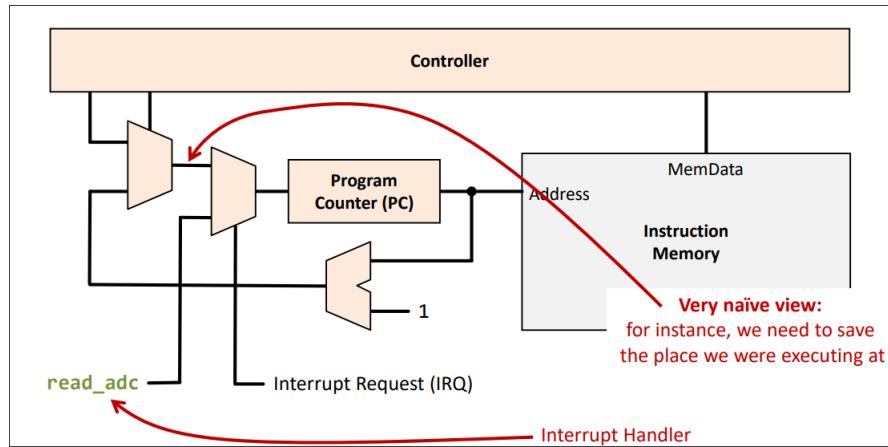
**Seen this already in some languages**

We maybe, have already seen this mechanics in some languages:

- Callbacks, Action, or **Event Listeners** (JavaFX), signals, promises, Futures, Hooks

However does are done by the **compiler/ interpreters**. Here, we are dealing with the cpu directly so how can we do this?

**The basic Idea of I/O interrupts**



We use the `read_adc` address which is where we handle the I/O interrupts. The interrupt request serves to trigger the interruption.

However there are several issues to take care of and behaviours to define:

- We need to know **who needs attention** – we do not have only one peripheral
  - After interrupt, **the software checks all peripherals** in turn (polling), or
  - **I/O peripheral sends identification**
- **Different priorities** need to be expressed – some peripheral can wait long, some cannot
- **Impact on current execution:** Current instruction(s) can complete? One instruction? Five instructions? Twenty instructions? What happens of the program that was being executed?

*How do many peripheral connect to a single IRQ*

In order to do so, we have more than one way, the easiest and most intuitive is a **OR** with  $n$  inputs.

*connect to a single IRQ*

On the other hand, what we also can do is to use tri-state buffers, one for each  $\text{IRQ}_n$ .

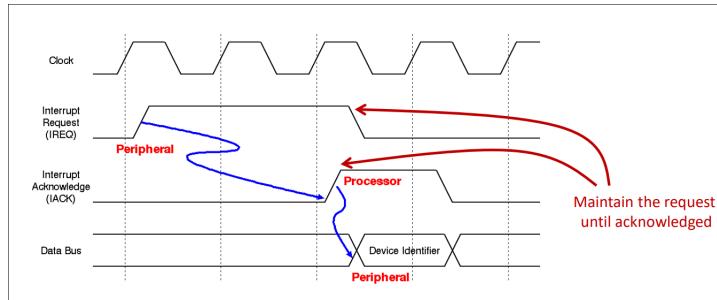
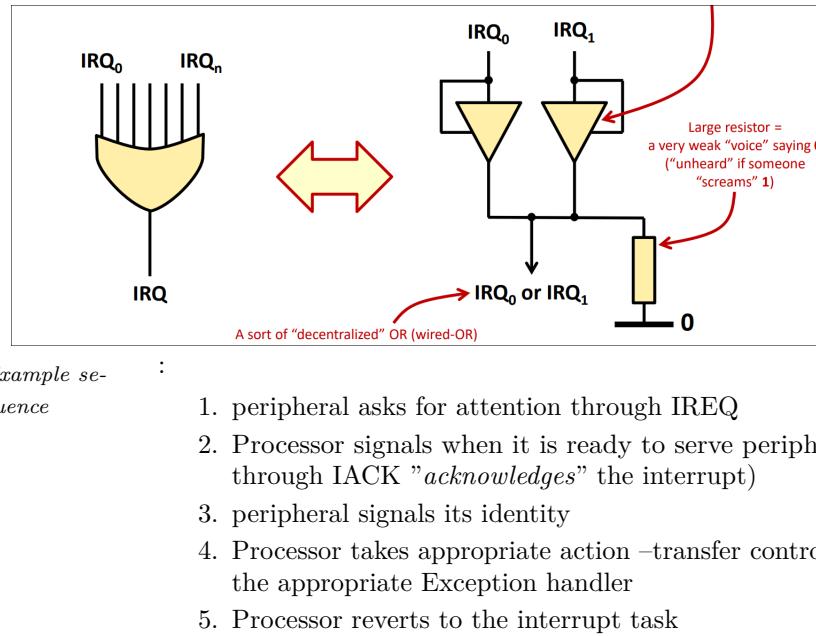


Figure 3.2: timing diagram

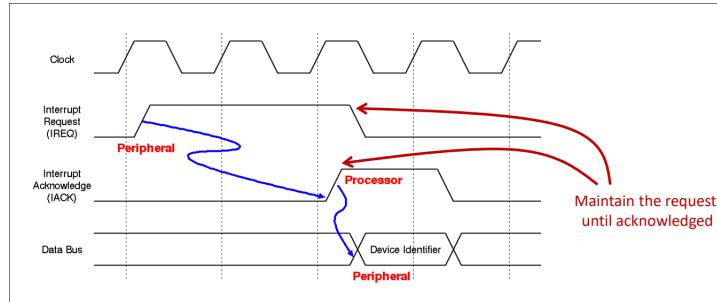
On the software side, it works with the same code we used before for polling. However, the `read_adc` function is now called by the interrupt handler. The interrupt handler stores the address of the program that manages all interrupt requests, and from there, it launches the program that handles the ADC.

It is a very good practice to just look at the timing diagram and "guess" how the circuit would look like.

### I/O Interrupt priorities

**Daisy chain arbitration** is one of the simplest methods:

- Anyone places request (IREQ, Request)
- Acknowledge line (IACK, Grant) passed from one device to the next
- Device which wants access, intercepts the signal and hides it from successive devices
- Simple but (1) slow and (2) hard priorities (meaning hard in like hardcoded something).

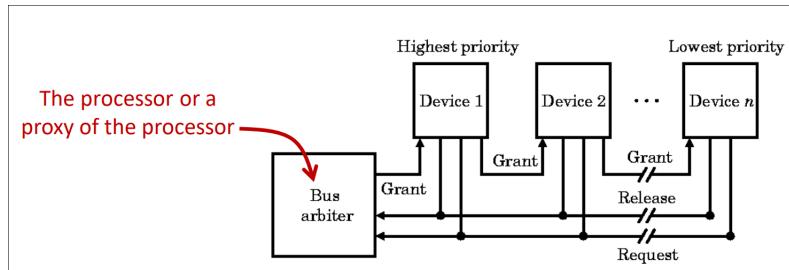


### Interrupt controller

More sophisticated methods involve special hardware:

An **interrupt controller** may be expected to:

- Propagate only one **IREQ** at a time to the processor
  - Select the one with highest fixed priority
  - Select the one with equal priority which has been served last.
- Propagate the returned **IACK** to the appropriate peripheral
- Inhibit certain devices from sending **IREQ**'s
- Allow nesting, that is higher priority **IREQ** to propagate while lower priority interrupts are being served.



### 3.3.1 Direct Memory Access (DMA)

Even when using interrupts, the processor can spend a significant amount of time transferring data to and from input/output devices. This is especially problematic when dealing with high-throughput peripherals such as disks or network interfaces, where large amounts of data need to be moved. To address this inefficiency, the concept of Direct Memory Access (DMA) is introduced. With DMA, a dedicated hardware peripheral takes over the task of transferring data between memory and the I/O devices. This allows the CPU to continue executing other instructions while the data transfer occurs in parallel. By offloading these memory operations to the DMA controller, overall system performance is improved, and the CPU is no longer tied up managing large data transfers.

This idea shortly is:

- Let's have a **special peripheral** perform the needed data transfers from and to memory (R/W) and free the processor to continue computation

#### Without DMA

What we used to do before is:

1. The peripheral launch a interrupt request
2. The Processor load the data from the peripheral
3. The processor store the data into the memory

This processor can be done for like 1,000,00 times.

#### With the DMA

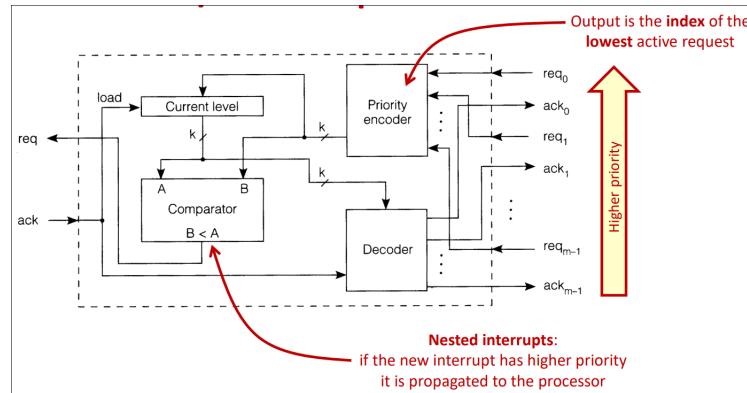
The idea now is to:

1. The peripheral launch a interrupt request
2. The processor launch it back to the DMA (with the needed informations)

### 3. The DMA load

### 4. The DMA store it to the memory

We do the same thing as before except the *boring* part of load store, load, store, load, store ... is done by the DMA.



I put only one screen here but there were like a nice way of introducing it in the slide so I'll just say it there, this is the 2.c. interrupts slide 14 to 24.

## Direct Memory Access

**Définition 2** A minimal DMA is:

- An **increment register** (how many bytes/words to transfer at a time)
- A couple of **address pointers** (source address pointer and destination address pointer), incremented by the above constant at every transfer
- A **counter** (total number of bytes/words to transfer).

*Example*

Here an example of a sequence:

1. The processor tells the DMA controller (a) which device to access, (b) where to read or write the memory, and (c) the number of bytes to transfer.
2. The DMA controller becomes bus master and performs the required accesses controlling directly the address and control busses.
3. The DMA controller sends an interrupt to the processor to signal successful completion or errors

## Timer and Periodic DMA Operations

In some cases, we want DMA transfers to happen at regular intervals without the CPU constantly supervising them. This is where a **timer** comes in. A timer is a hardware peripheral that counts up (or down) automatically and can generate an **interrupt** when it reaches a programmable maximum value. By configuring a timer, the CPU can schedule periodic DMA operations, such as reading data from a sensor every millisecond or streaming data from a peripheral continuously. This mechanism allows the DMA to start transfers on its own, triggered by the timer interrupt, freeing the CPU from constantly checking or initiating these operations.

## Bus Control and Processor Cooperation

During a DMA transfer, the DMA controller must temporarily take control of the memory bus, becoming the **bus master**. The processor must **relinquish control of the bus** during this period, but it can continue executing instruc-

tions that do not require bus access, such as computations using registers. Once the DMA completes the transfer, it sends an interrupt to the processor to signal successful completion or report any errors. This cooperation ensures that both CPU and DMA operate efficiently without conflicts on the memory bus.

### Advantages of DMA

Using DMA brings several benefits to a system:

- It offloads repetitive memory transfer tasks from the CPU, reducing workload.
- It increases system throughput, especially for large data blocks from high-speed peripherals.
- It allows the CPU to focus on computation or other tasks while data transfers happen in parallel.
- It reduces the time the CPU spends in **busy-waiting** loops checking for I/O readiness.

### Example Sequence with Timer and DMA

An example sequence of operations with a timer and DMA could be:

1. The timer reaches its programmed max value and generates an interrupt.
2. The processor acknowledges the timer interrupt and instructs the DMA controller to start a transfer from a peripheral to memory.
3. The DMA controller becomes the bus master and performs the required memory accesses, reading from the peripheral and storing into memory.
4. Once the transfer is complete, the DMA sends an interrupt to the processor to indicate completion.
5. The CPU resumes normal execution, potentially until the next timer-triggered DMA transfer.

This sequence illustrates how CPU, DMA, timer, and peripherals interact to efficiently handle high-throughput data transfers.

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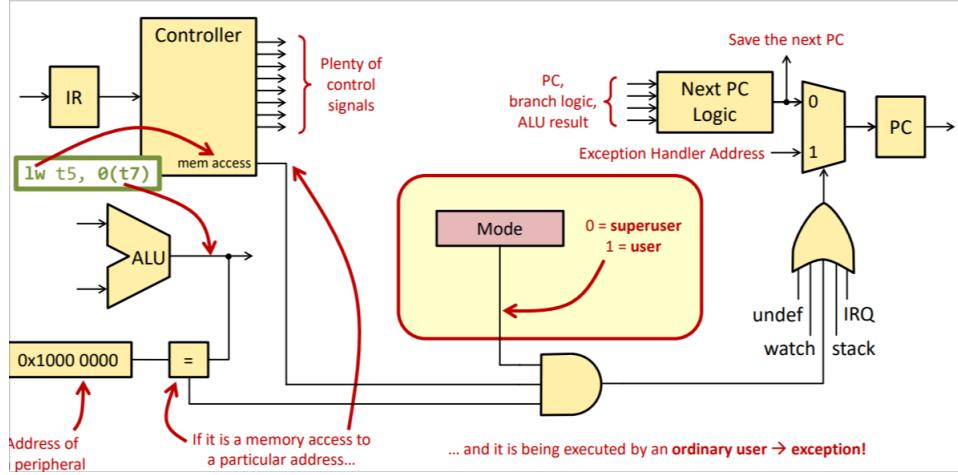
lectureDate — **Cours 10 : Processor and converter**

## 3.4 Exceptions

We still need to do one thing which is more in the hardware side: how can we handle running multiple programs at the same time? The goal is to *fool* the user into believing that the programs are running at the same time.

The idea on how to do that is to execute each program in small delta time, we run a program for 10ms then we stored all the value of the register somewhere, run the other program for 10 ms, store the registers value, restore the first registers values etc.

Another issue is also privacy on computer with multiple users, a user should not be able to go the packet that was coming because maybe this packet was for another user. What we need here is a *superuser* (which will be the os) that can check at who the packet is and whether or not gives it. We need to forbid some users to do a I/Os access



We check if the value is a memory access and it is at the place that I care  $\Rightarrow$  I launch an exception. The **Mode** register is the information which allows us to know if we are the superuser or not, the implementation is **trivial**: adding an input at the and gate. We **need** two Mode otherwise we are cooked, Some questions that I found interesting during the lecture was: "isn't just hardcode in the hardware? Why do we have only one Mode not like three or four?".

But here we need an instruction to change from a mode to another, we need to be able to go

$$\text{user} \leftrightarrow \text{superuser}$$

However this is dangerous, imagine being a user being able to go to superuser and using the code of the user, when changing of user mode, we will also have to change the code that we are currently running.

But here using an exception is just a *cosmetic* way of doing it, this is not an exception as the the pure sens of it.

#### Levels of Privilege = Processors modes

- Distinguish **at least** two Processor **mode** :
  - **user mode** for the user's programs
  - **Kernel, Supervisor, Executive**, etc for the os (kernel)
  - RISC-V has up to three: Machine, Supervisor, User
- Have a part of the **processor state readable by all**, but only **writable with highest levels or privilege**; at least a ;
  - Current **mode register**
  - Other configuration register (we will see some when discussing the memory hierarchy)
- Method to **switch mode** back and forth
  - A **dedicated instruction** to trigger a **software exception** and an instruction to **reset**
  - RISC-V has ecall (system call) and mret sret (return from exception).

### Processor tasks on Exceptions

What the processor should or could do when an exception is raised (depending on processors and type of exceptions):

- Mask further interrupts
- Save EPC
- Save information on the reason for the exception
- Modify privilege level (exception handler run in some privileged mode)
- Free up some registers (e.g., copying them to shadow registers, where supported)
- Jump to the handler

Most or all these tasks are **reverted implicitly** with special instructions on exit

- `mret` in RISC-V reverts the privilege level and the interrupt enable

Some have to be **reverted explicitly by the handler**

- Programmers may want to unmask further interrupts **as soon as it is safe**

#### Priorities

We have seen that hardware **interrupt controllers** can help managing priorities (which interrupts is more urgent to serve?). Yet, this only affects the order IRQs are presented to the processor. But we may also want to **serve a high-priority interrupt while serving a lower priority one**

Alas, there is only one `mepc` and `mcause` register, and this is why, as soon as the processor takes an interrupt, it **must disable further interrupts...**  
What can we do?

- Save critical information about the interrupt (`mepc`, `mcause`, `mstatus`) on some **same stack**, so that CSRs can be overwritten by further interrupts.
- Manually **reenable interrupts** (`mstatus`) without returning from the handler

The idea behind this is the same as the one when calling function and memory, we first thought of having a **static** memory like here. However this won't work with recursive function for instance. What we do instead is to dynamically allocate memory space in the stack. This is the same principle here.

#### Writing the handlers is very very tricky

Writing exception handler is a **difficult task!**

- Maybe the **stack cannot be used** (e.g., the exception results from a stack overflow)
- Maybe the **exception handler cannot be interrupted** (e.g., the handler uses static locations to save data including `mscratch`) and is therefore a nonreentrant procedure)
- Maybe the **system cannot withstand not serving interrupts** for a long time (e.g., I/O buffers fill up)

Buggy **device drivers** from vendors of peripherals (invoked by the interrupt handler of the operating system and running in some privileged mode) are often responsible for operating system instability.

This is why Microsoft **formally verifies** and **certifies** device drivers.

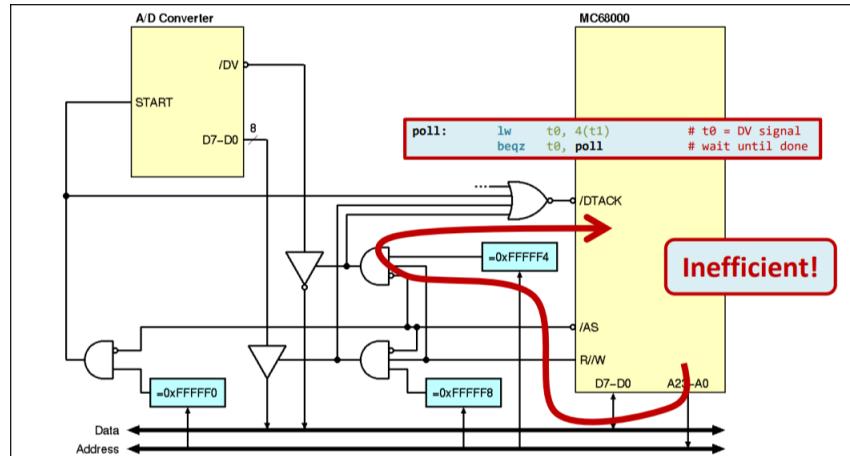
### Processor design Issue with Exceptions

Handling exceptions is **one of the biggest challenges** of high-performance processor design

Great difficulties in determining the exact state of execution and supporting a **precise restart mechanism**

Older processors did not support at all precise exceptions – **Every exception was a terminations one**, and thus things were easy. We will see this more in detail later in CS-200 and in elective courses.

Now let us go back from what we have seen last week. We debated if we could do something better, at the moment, to have access to the data, we were deciding when to read the data with the signal (DTACK)



However this is pretty inefficient, the processor has to always check whether the signal is active or not instead of doing real work.

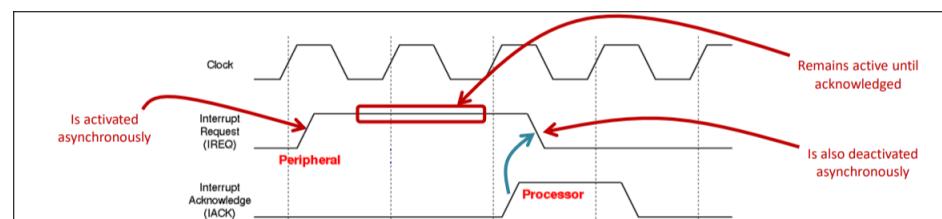
The goal here is to improve the interface to the A/D converter so that:

- Any access (R or W) to address `0xFFFFF0` starts a new conversation
- Upon completion, the A/D converter raises an interrupt through the appropriate interrupt request signal of the processor.
- The result of the conversion can be ready by the processor at address `0xFFFFF8`

Suppose that our 8-bit processor has an internal interrupt controller with various `IREQ` / `IACK` signal pairs for I/O interrupt requests

We have been assigned for our ADC these:

- `IREQ3` : input, dedicated to our peripheral to request attention
- `IACK3` output; used by the processor to signal to our peripheral that the request is acknowledged and is being served

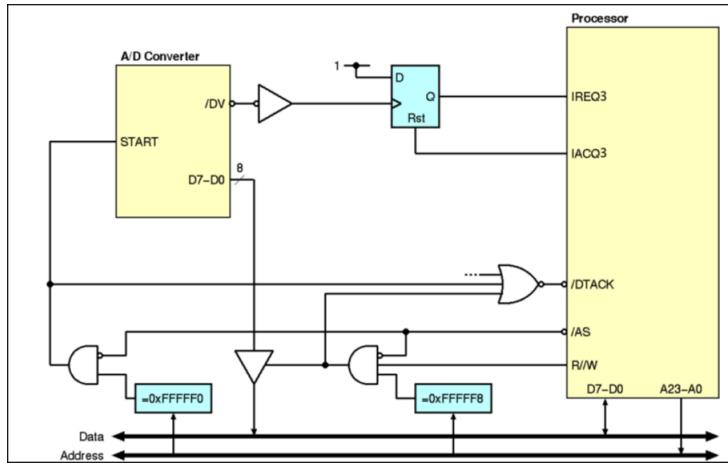


There are two main things here to acknowledge:

First, what we can see is that between the `IREQ` and the processor responds, we don't have a clock edge, this means that the acknowledged is only combination

logic here.

On the other hand, we also see here that the IREQ here stays up until it is acknowledged, this means that we need to store the "up state" for more than one clock cycle. What does this mean?  $\Rightarrow$  **flip flop**, we will ne a flip flop that store this information for us. What is weird about this flip flop is that the input that is store in it is 1, not the input value. The one deciding when it goes up or not is the A/D converter. This is looking very ugly...



But why is this an error in any other context forbidden?

$\Rightarrow$  any flip flop **must** be connected to the clock of the system.

**A/D converter:**  
startADC

```
startADC:      lui t0, 0xffff
                addi t0, t0, 0xff0 # t0 = 0x
                fffff0
                sw zero, 0(t0)

                ret
```

**Handler**

On the other hand the handler part is a bit harder.  
For instance the handler:

```
startADC:      addi sp, sp, --
                ..
                ..
                csrr t0, mcause

                ..
                jal readADC
                jal buffer #we need to store the
                information somewhere for other to
                have access to it
                ..

                mret
```

The **mcause** is the register which stores the machine external interrupt

So the real part for this is:

```

handler:      addi sp, sp, -120 # save all registers but
              zero and sp
              sw x1, 0(sp)
              sw x3, 4(sp)
              .. etc ..
              sw x31, 116(sp)

              csrr s0, mcause # Read exception cause
              bgez s0, handleException #branche if
              not an interrupt (MSB = 0, looks
              like zero or a positive number..)
              slli s0, s0, 1 # Get rid of the MSB of
              s0, so that what is left is the
              cause
              srli s0, s0, 1
              li s1, 11
              bne s1, s2, handleOtherInts # Branch
              if not an external interrupt

              jal readADC # return a0 = ADC result
              jal insertIntoBuffer # Gets a0 =
              value to add to a circular buffer

restore:     lw x1, 0(sp)
              lw x3, 4(sp)
              .. etc ..
              lw x31, 116(sp)

              addi sp, sp, 120
              mret

```

**A/D converter:  
insertIntoBuffer**

```

.section .data
    .equ bufferSize, 1024 #define buffer size
    .equ bufferBytes, bufferSize * 4 # compute the
    total size in bytes for the buffer

    bufferPointer: .word 0 # Initializse the pointer index to 02
                    d
    buffer:          .space bufferBytes # Allocate space
                    for bufferSize * wordsize bytes

.section .text
insertIntoBuffer:
    la t0, la t0 bufferPointer # Load address of
    budderPointer into t0
    lw t1, 0(t0) # Load current buffer pointer into t1
    la t2, buffer # Load base address of the buffer into
    t2
    slli t3, t1, 2 # Multiply
    add t4, t2, t3
    sw a0, 0(t4)
    addi t1, t1, 1
    li t5, bufferSize - 1
    and t1, t1, t5
    sw t1, 0(t0)

    ret

```

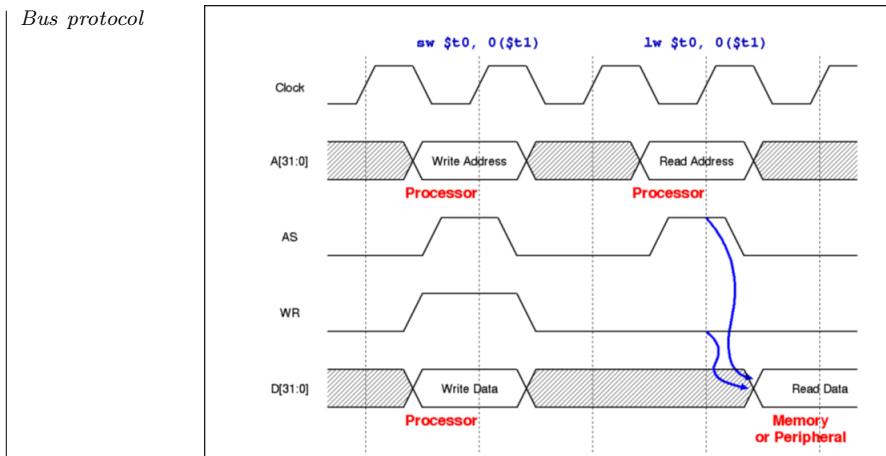
lectureDate2025-10-17 — lectureDate — Cours 12 : Example of I/O/s and Exceptions

Today's lecture is an example of what we did the previous weeks.

### Part 1a: Connecting an Input Peripheral

Consider an hypothetical processor with the following buses and control signals

- A[31:1] → Address bus
- D[31:1] → Data bus
- AS → Address Strobe (active when a valide address is present on A[31:0])
- WR → Write (active with an ASS when performing a write cycle)



Here this is something that is very useful for us to read

What do we want?

- Connect to the processor **10 buttons numbered from 0 to 9**
- Each button outputs a logic '1' if pressed '0' otherwise
- The processor must read the **state of the buttons** with a read from memory location **0xFFFF'FFF0**: '0' indicates no button pressed '1' indicates a button pressed
- The processor must read the **number of the button pressed** with a read from memory location **0xFFFF'FFF4**.

The question now is: what do we need to do?

### Circuit

The first thing we need to do is to OR all the button together (so that if at least one of the button is pressed, the result would be one). Then we need to know which button is pressed. To do so, we need to decode the buttons outputs into a 4 bits number  $\Rightarrow$  we add a  $2^n$  decoder.

For the rest of the course I think the video is better than this because I cannot really explain it well while "drawing".



# Chapter 4

## Memory Hierarchy

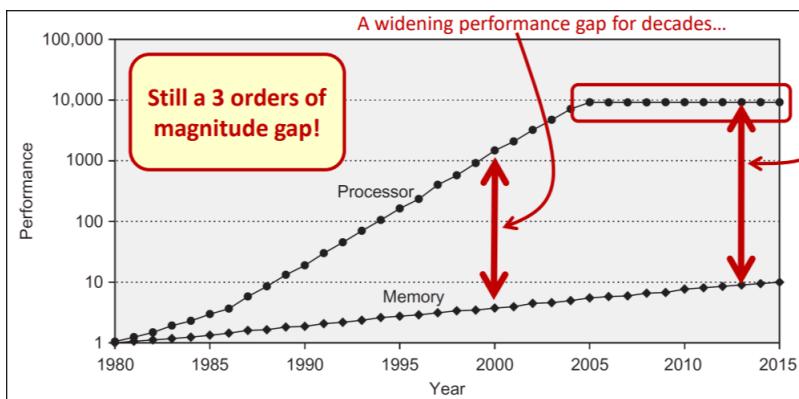
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lectureDate — Cours 12 : cache

What we want now is to go back to memory and spent quite a lot of time on this topic. What we will change here is that we will care about the **performance** of the memory we are building. So far we were only concerned about how does it works, now we have a concern about the quality of memory.

### 4.1 Caches

The question we have is what is the problem with memory:



Here we are talking about the *performance* of our processor, this is not really performance but more the frequency of the processor which has stabilized in the current last year.

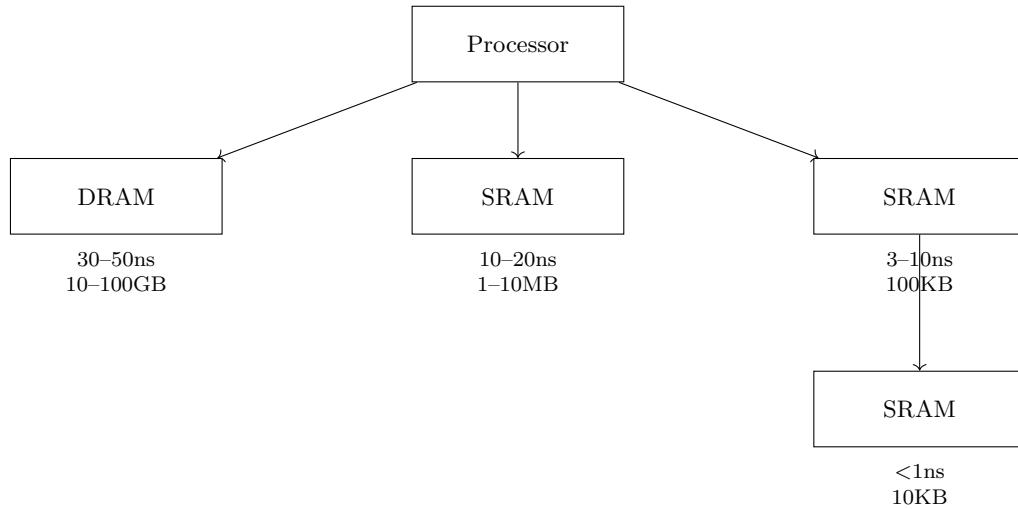
Processor has been improved a **lot** in comparison of memory. When we say *memory*, we mean **DRAM**.

The issue is that we want a **big** memory and a **fast** processor which cannot really work well together, we need to **do something** ourselves.

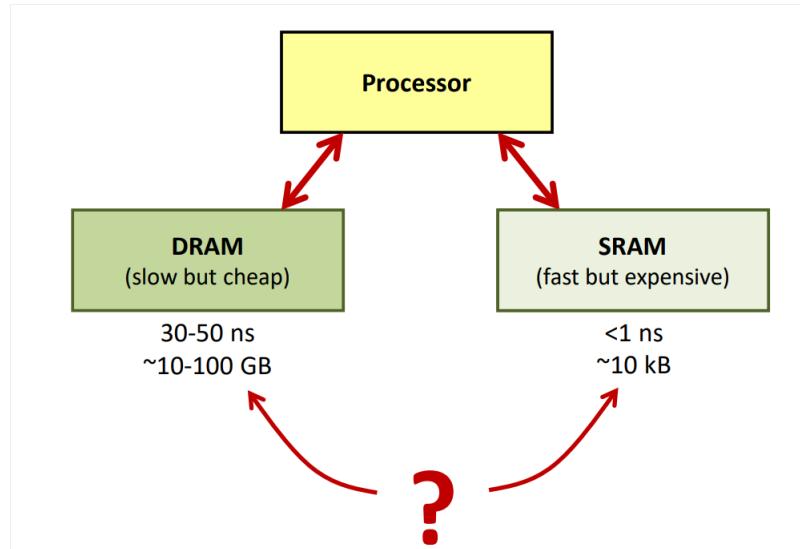
What we can do is to use other type of memory which is **faster but costlier**

**Out goal today**

What we can do here is to instead of having one memory for everything, we can have **two memory**: one that is fast but expensive and one that is slow but cheap.



So the fact is: this is not only a technology issue even though we are not able to make `DRAM` faster. The issue is more in `SRAM` side, `SRAM` is a very *maleable* component, it is a part of the logic of our processor, the problem is when we are trying to get big with our `SRAM`, in term of mega byte (which is still affordable in terms of cost), the speed is not longer the same: it begins to be one or two order of magnitude away (in terms of clock cycle) of the processor.



Putting two type of memory in the processor is kind of a trivial thing to do, we only have to have two decoder one for the `DRAM` and one for the `SRAM`. We check the size of the data and decide based on this where we put our data.

**What memory to use?** When we execute code, there is some thing that we do over and over and on the other side, some code are only executed once. Is there a way that we can *use* this *phenomenon* to make memory faster?

The question is where do we put our data, in which memory? For instance let us took a look at this code:

```
i = 0;
sum = 0;
while (i < 1024) {
```

```

    sum = sum + a[i];
    i = i + 1;
}

```

- Instruction corresponds to line 3-5 that are **read over and over**, they should be in fast memory
- if variable **i** and **sum** are stored in memory, they are also **used often** and should also be stored in fast memory
- One would like to anticipate the future and load the **following** instructions and vector elements.

**Spatial and Temporal locality** There are two important criteria for the choice of the placement:

- **Temporal locality**

- Data that have been **used recently**, have likelihood of being used again (Code: loop, function, ...) (Data: local variables and data structures)

- **Spatial locality**

- Data which **follow in the memory other data** that are currently used are likelyhood to be used in the future (Code are usually sequential, Data: array)

However, this is not perfect, this is only a probabilistic model. We are only making guess and hoping there were right so that we can win some time.

**Our placement policy must be:**

The fact that we do not give the choice for the programmer is not something that is impartial and always true. For instance in a lot of embedded system the programmer can the choice on where to put his data. The fact that this is true for embedded system is that, when developing those system, there is only one person/team that is developing the program. When the program is done, we ship the product and we never heard about it again (hopefully). It is totally legitimate to think that this is the solution. However here this is not the case, for us, we don't want to bother the programmer about this.

*Invisible to the programmer*

- One could analyse data structures and program semantics to detect easily used variables/arrays and thus decide placement → OK in some context (embedded) but we want to have the programmers not to go through this hassle
- To do so, we will add **hardware** to help

*Extremely simple and fast*

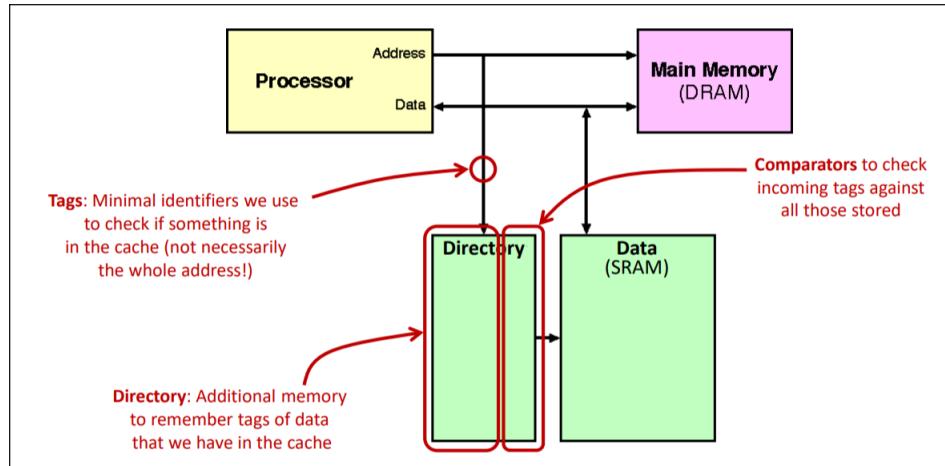
The decision are made in the hardware, they need to be simple. The goal is to access memory very fast, in the order of a ns or less: **not much time** to make a complex decision...

### Cache: The idea

The main difference between this and the tree make before is that now as a **programmer** I don't know which memory I am using, I am at a level of abstraction above which makes it easier for me to develop software.

The idea behind the cache is the following:

The processor makes a request for an address, we first check if the address is in the directory if it is → we cut off the main memory and answer ourselves (as **SRAM**).



The cache here is the directory + the **SRAM**.

**Definition of a Cache**

**Définition 3** A **cache** is any form of storage which takes automatically advantage of locality of accesses.

- The idea works so well that now they are **not only in processors**
- Web browsers have caches, network routers have routing information and even data caches, DNSs cache frequent names, databases cache queries, even in cs108 we used a cache.

When we find the data required in the cache, we call it a **hit**; otherwise it is a **miss**.

**Définition 4 hit (or miss) rate** is the numbers of hits (or misses) over the total number of accesses

**The question now is how does it works?**

**CAM**

What a cam is here is only the **directory** part here, the difference between **CAM** and **RAM** is:

- **RAM**

address → content

- **CAM**

content → address

And as we can see we have the **Tag** which are the content and the address which is the output of the encoder.

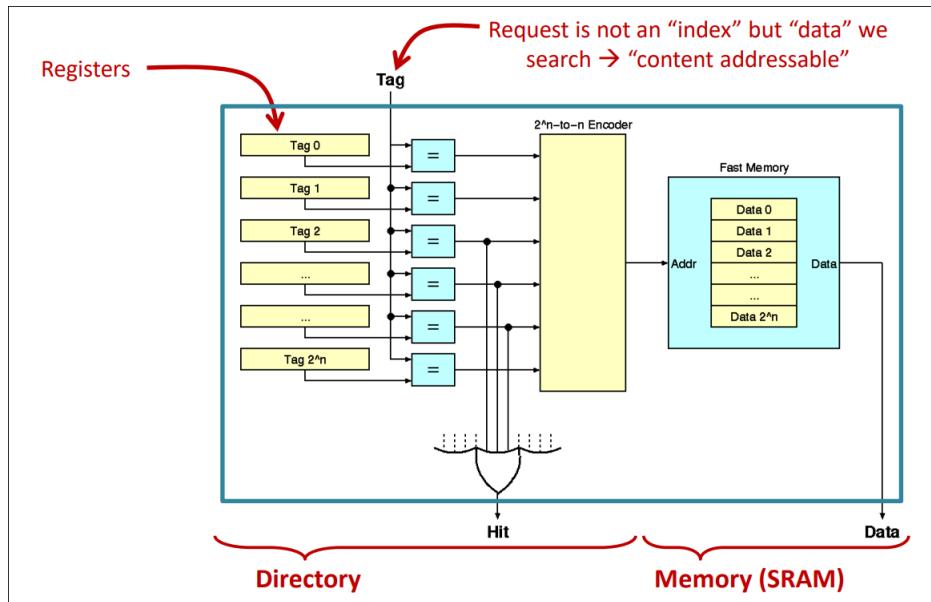
How do we identify if we have an element, to do so we store a **tag** for each elements that is stored, which is stored in a **register**. When we are looking for an element, we check all register and if one of them matched, we have a **hit** and we then also know which one it is (because each line is different). Then we can just deconde the tag to access the content in the **SRAM**.

From the beginning of this course we works with memory access based **only from the address** in the memory however here this is different:

We have a tag which is **not** an index but data, we search based on the content instead of the address  $\Rightarrow$  **CAM** (Content addressable memory).

We use a memory that is addressable based on the **content of the tag**.

### Fully-Associative cache



A **Fully-Associative cache** is a cache organization in which any block of memory can be stored in any cache line.

There are three different types of cache organization types:

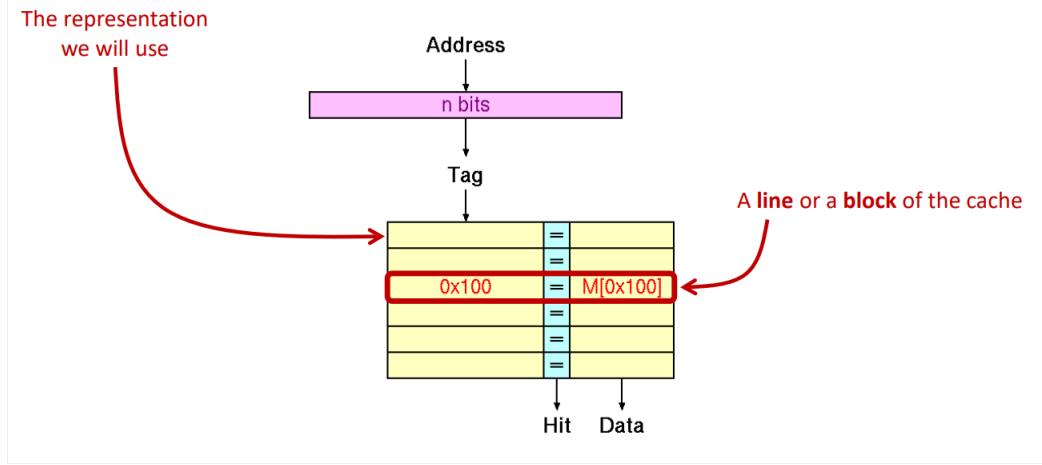
- **Direct-mapped cache**  $\rightarrow$  each memory block maps to **exactly one** cache line.
- **Set-associative cache**  $\rightarrow$  each memory block maps to a **set of cache lines**, and can go into **any line** of them
- **Fully-Associative cache**  $\rightarrow$  a memory block can go **anywhere** in the cache.

For our fully associative cache:

- The cache has no **fixed mapping** between memory addresses and cache line
- When a memory request arrives, the cache **compares** the address tag with all entries in parallel (using a **content addressable memory CAM**)
- If a match is found  $\rightarrow$  **hit**
- If not  $\rightarrow$  **miss**, and the block is loaded into any free line (or one chosen by a replacement policy (which we'll see later)).

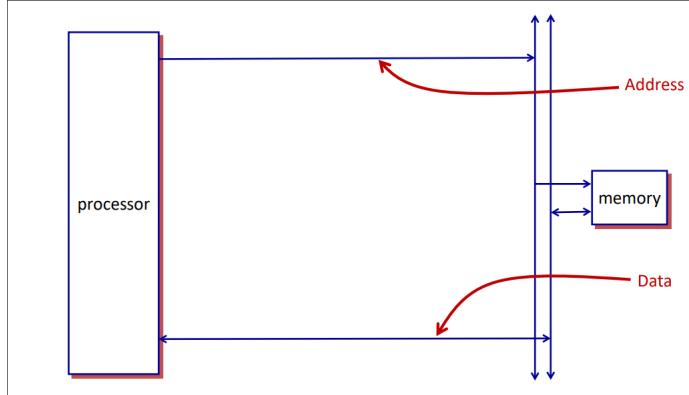
The issue here also is that **all those comparators** are pretty expensive, for each tag we have a to have a comparator which is pretty costly.

### The representation

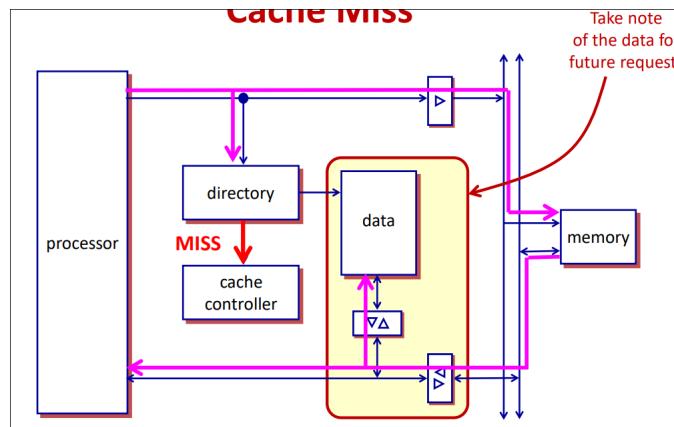


So this diagram is **the same** as the one above we just simplified to make it easier to *understand*.

### Cache and Cache controller



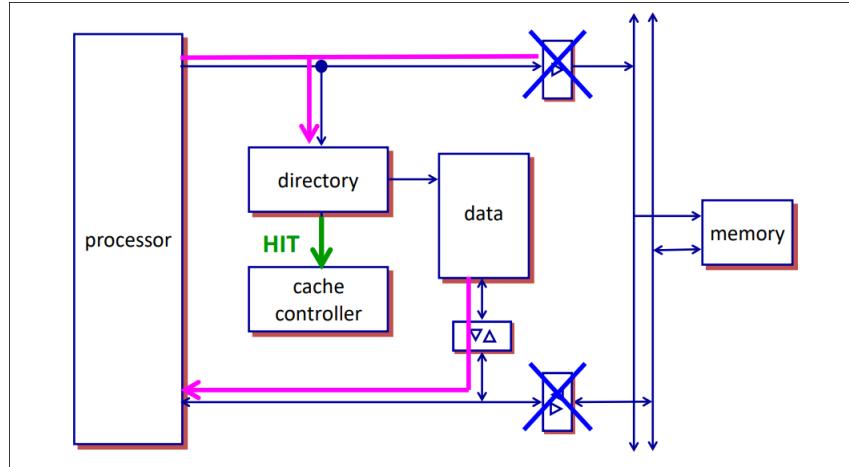
The difference from before is now that the processor **talks to the cache** and if the cache doesn't find the content it send the address into the memory:



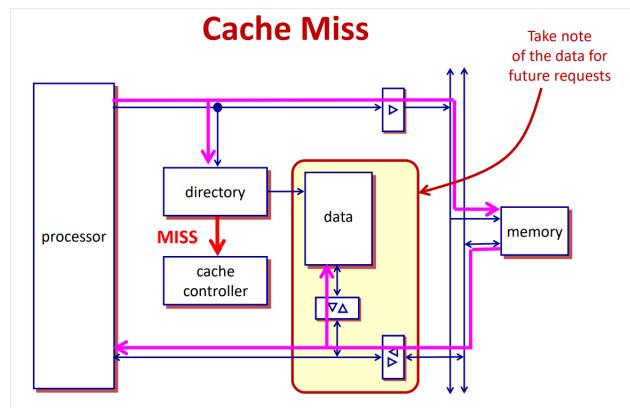
The main character here is the **cache controller**. It is the one that blocks or not the arrows that let us cut or not the memory of the data bus. The cache controller here is a finite state machine. In

this course we will not do it but as the professor said if we had a lab d we would then implement it in verilog. But the important thing here is that this is something that is reacting to some signal and do something based on input etc. We exported in some sense a part of the processor. (we took the part which used to talk to memory here) and do the **cache jobs**.

For instance if the directory output a **HIT** then the cache controller would block the address of the processor for the memory:



So When the processor asks for something, the directory says **HIT** or **MISS**, if it is a **HIT** the cache controller cuts the address to the memory and activate the result from **data**. What is important here is that when searching we used to **always do it sequentially**. However here this is **not** the case, we has as many comparators as tag, to figure in a fraction of nano second wether I have the information or not. I want a million of element in the cache, then I need a million of comparators. If we have a miss then the controller let the memory works, then takes in the data register the new element. The reason for this is **Temporal locality**, if we seen something passing by, there is a high chance that we will see it again.



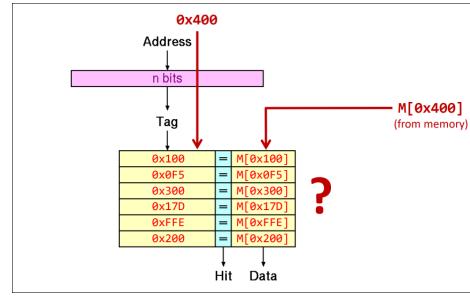
**The cache is a hardware device**

The important thing here is that the cache is **only on hardware** this means that it is completely invisible from a software perspective.

As the processor we cannot see if when taking a value it will take 1 cycle or 100 cycles.

**What if the cache is full**

The question here is what happens when the cache is already full, do we overwrite?



Maybe we want to overwrite the one that we used the latest? or the one that was put here the oldest one?

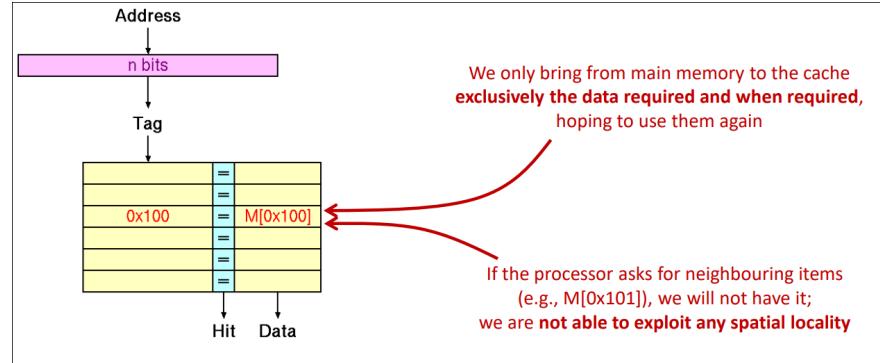
*Eviction policy* When there is no appropriate space for a new piece of data, we must overwrite one of the existing lines (**eviction** or **replacement**)

Several policies to decide what to evict:

- **Least recently used** (LRU)
  - Replace the data that have been unused for the longest period of time
- **First in First out** (FIFO)
  - Replace the data that came in earliest
- **Random** → pick one at random and throw it away

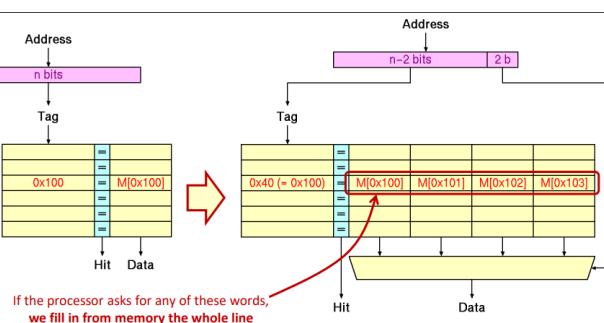
The biggest constraint here is how to implement those policies and be as fast as a fraction of nano second?

Only exploiting Temporal locality

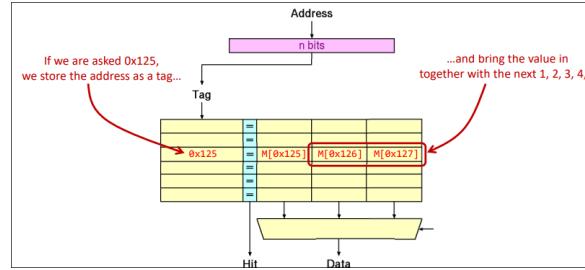


At the current moment we are only exploiting the temporal locality (the upper arrows that goes into data when we are fetching from memory).

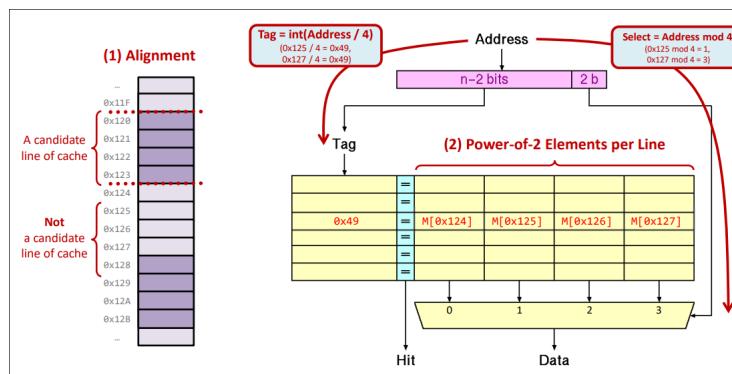
A solution here is that when we are fetching the element at address `0x100` I also store the element at address `0x100`, `0x101`, `0x102`, `0x103`.



Why don't we store the address of the first one as a tag? We where storing here for instance `0x40` but wht don't we store `0x100` directly. This works:



However here there is a big issue: if the address we are asking is for instance `0x127` we don't know just from a comparator if the data contains it. What we will have to do is to actually take the range from `0x125` to `0x127`. Which we don't have, it would be too slow. How can we recover from this? What we can do is to store as a tag only the  $n - 2$  bits as a tag:



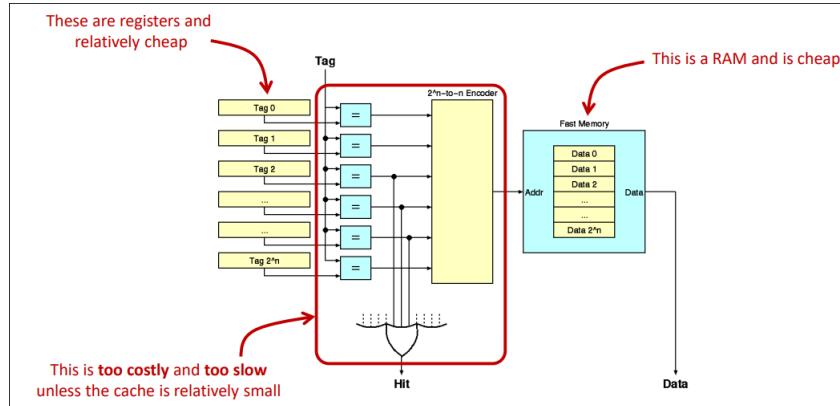
Here all our problems are gone! We only have to do a comparison and the data is easily access **and** it is **hardware friendly**. This means that this can be *easily* implementable.

We have a constraint here is that the family of cache has to be adjacent, so that we don't miss any element. Here we will choose all the number divided by a power of 2.

So that by a division by two we can find the family of each element.

### Fully-Associative Cache

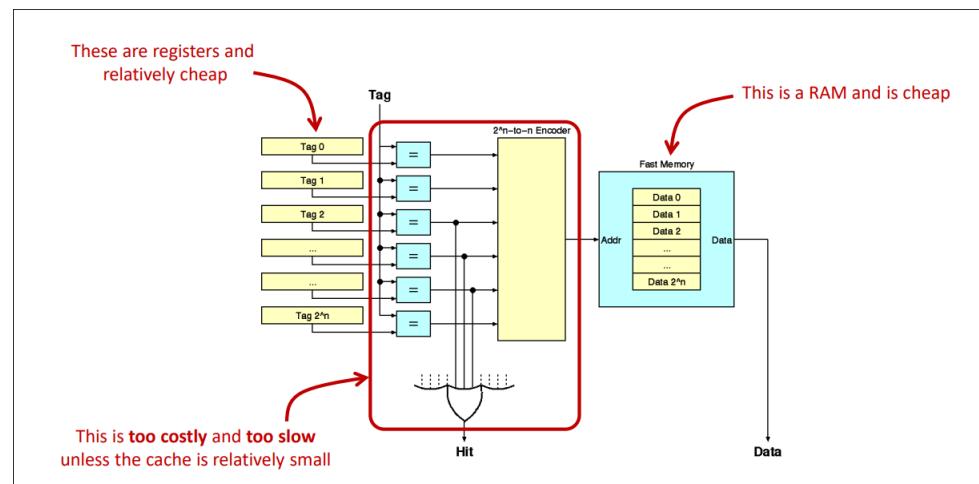
Okay all of this is pretty nice however, there is an issue that has still never been mention, how can we tell to the cache controller when there is a **hit** or a **miss**? The easiest way to do so is to put a big **OR** gate from all the tag. However this is slow to do imagine having an **OR** gate with a million of input. this time growth of this would be a logarithmic one which is not good for us, furthermore, it would be too costly.



When we say here cheap here, cheap is compared to the rest of this circuit which are not cheap at all ( SRAM is still expensive compared to DRAM ).

THE issue here is that this doesn't work on mega byte of information so we **need** to change something:

### How can we make it simpler



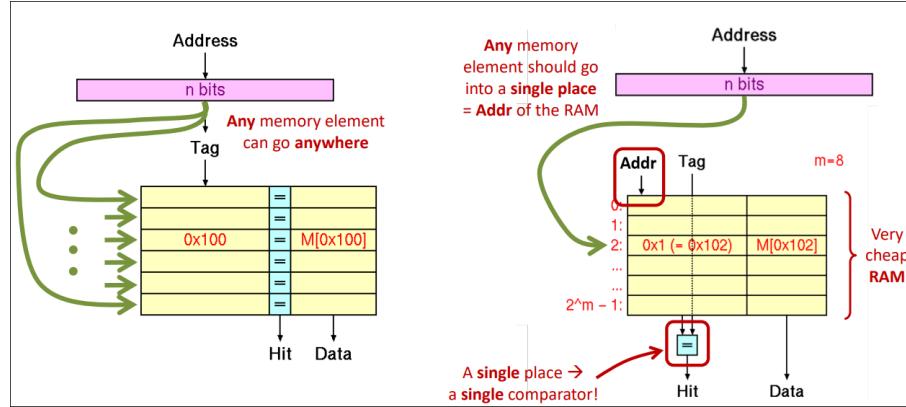
Instead of doing what is done one the left, we can do a simpler comparison. On the right we can do a cheap RAM (compared to CAM) as the direct output of the Tag which is now an address. For this to works, every element should go into a **single place** of the RAM. I take the address from the processor, I figured the index in the cache, we'll get out **one** candidate word, we have the Tag here, we'll read and compare the tag and the content, if it is a HIT then we won else we MISS.

Tag

What I found hard to understand here is that how can we know when accessing the memory that we hit? we have an address that in a memory give the output the tag and the content and with the tag we can know if we have a HIT or MISS ?

### How to generate Addr and Tag

Now we are looking at the purple box above:

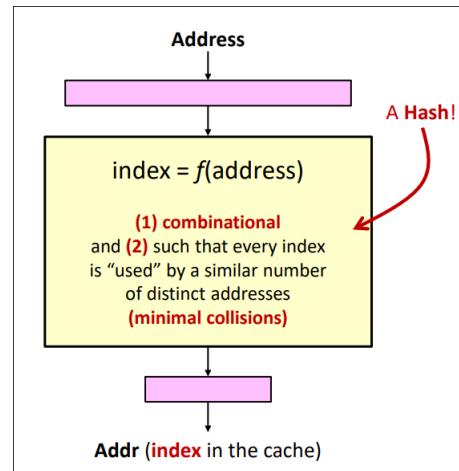


What we want to do is to go from the address in memory which is a 32 bits memory for instance, into a 10 bits memory which is the cache size. How can we do so? We are **Hashing** here we are taking less bits but produce the most different combination possible.

*The simplest hashes*

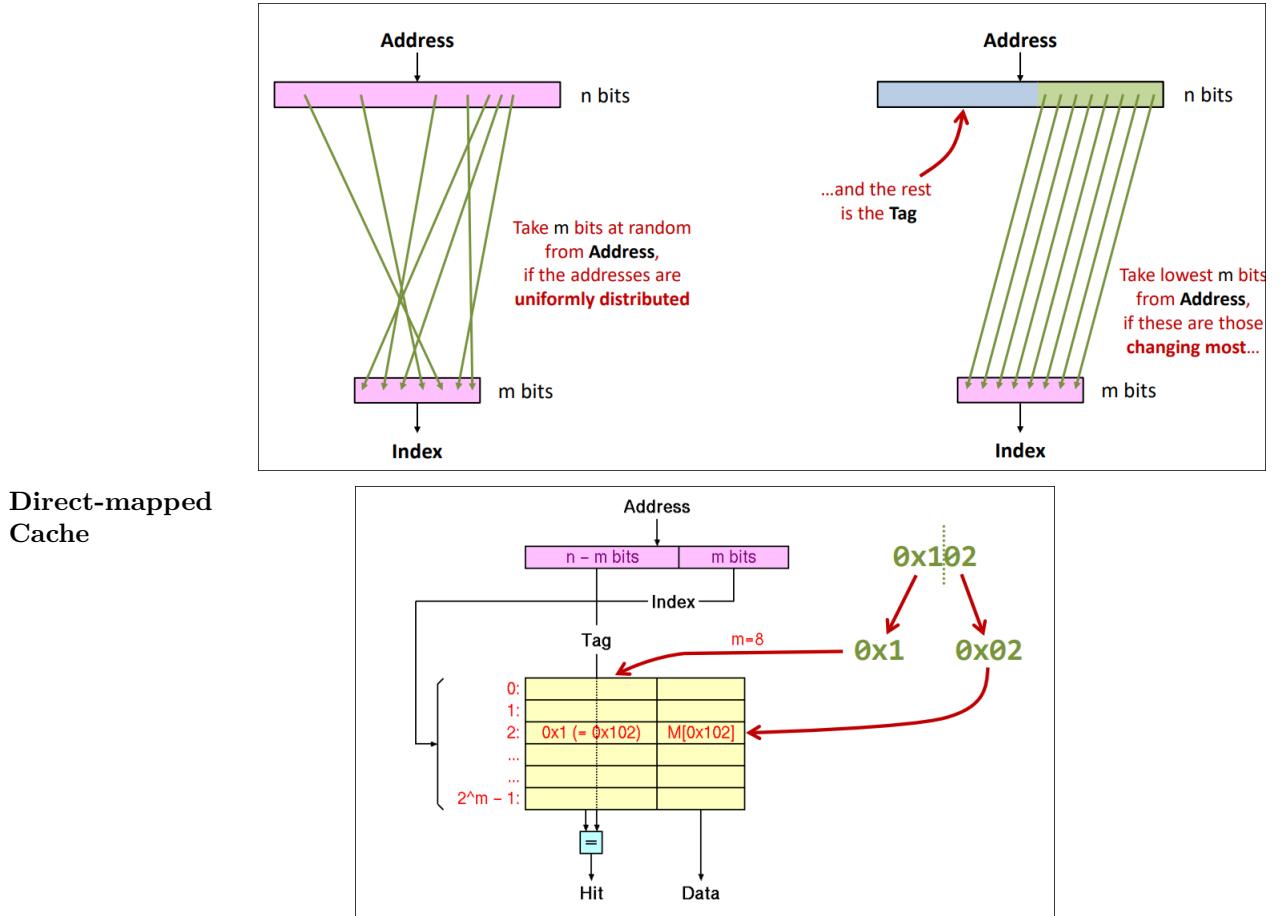
What we want as a hash here is a hash that is the simplest and **fastest**.

We can just take some of the bits and we put them in a random (or not) order:



Is this a reasonable hash? It is, **only** if there are uniformly distributed. But when we are writing code or writing data, is the data uniformly distributed?

No: we are always starting at the bottom of the data, we almost never write something at the address 300 millions something (at the end of the memory). We need to take in our decisions the fact that the most significant bits are very rarely used. This is the reason why taking the **least significant bits** is (as we think) the best way of doing it.



So here: the index of our address is the lsb bits, then as a tag we can put the most significant bit. If we are taking the  $m$  bits for the index, then we can take the  $n - m$  most significant bits as a **Tag** for our element, then when we are accessing something we can check if the tag at the index is the same as the  $n - m$  msb of our address.

*What about it?* This is a **very** simple cache here **and** it is **fast**. For each access, we only need to do **one** comparison which is very fast.

But is it better than the previous cache:

**NO:** we have a **lot of constraint** here if we have to important element to store in the cache but are in the same hashing index then we are screwed...

### Which one is the Best Cache

The question we will try to answer is:

Which one is the best cache:

- Fully-Associative Cache
- Direct-Mapped Cache

### Example

Consider a **fully-associative** and **direct-mapped** cache, both with **64 lines** with **four words per lines**  $\rightarrow$  256 words per cache.

The question is how good are they, the criteria for this will be the number of hits.

For this example I found it pretty hard to explain it without drawing so this is the video CS-200-3a. memory hierarchy (30 october 2024 at 46 min).

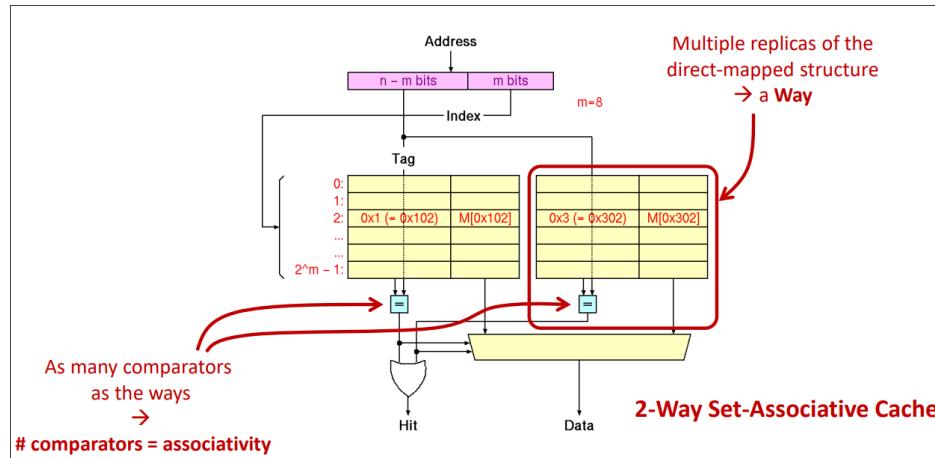
But what we can see here is that sometimes the direct mapped cache can be very very inefficient. Is there a way to find the best out of the two worlds: The speed of the direct mapped and the hit rate of the fully-associative one?

### Intermediate?

Is there an **intermediate** between:

- **Fully-Associative**: every word can go in every line of the cache (hence the 'full') → associativity is the number of lines in the cache
- **Direct-Mapped**: every word is 'mapped' to a single line of the cache → associativity is 1

### Set-Associative Cache

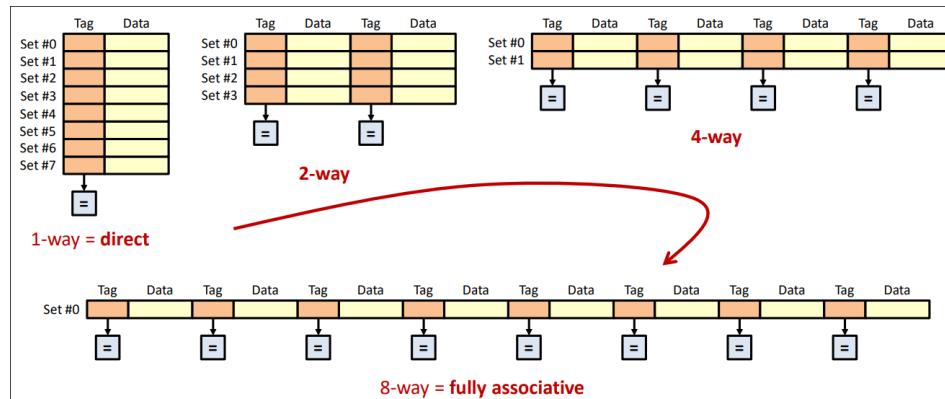


So the idea is to add a second cache map with the exact same direct-mapped structure. By doing this we allow a **second** element for the same index

*Critical path*      Here the critical path is in the **multiplexer**, furthermore every comparison that is made.

### Continuum of Possibilities

What we can see here is that we have a **lot** of choice for a given number of storage. For instance if we have 8 storage units we have the following ways of creating a cache:



*Power of two*    Do we have to have a power of two as the number of way?  
 Do we have to have a power of two as the number of set?

So here there is something very interesting to see is:

For the first way which is the classical direct-mapped, we only have one comparator, however imagine having to put all the sram next to each other in one set; then we get a cache with 8 comparator  $\Rightarrow$  We get a fully-associative cache.

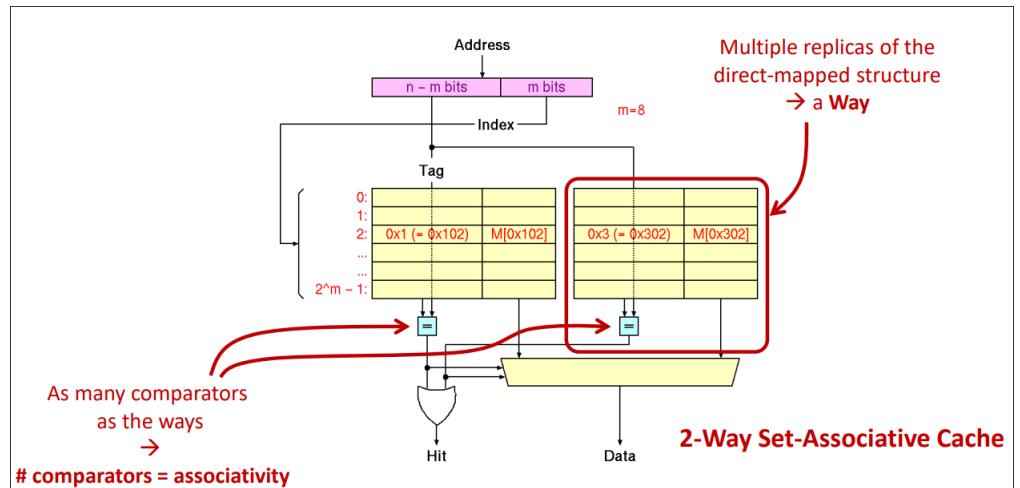
We can see it as the direct-mapped is the *transpose* of the fully-associative and vis versa.

## Validity

All of this is pretty perfect however we have some issue with the implementation, we always said *If there is nothing there then we put something, if there is something then we get and check*, however: how can we know?

In the memory the initial content is **garbage** we don't know if the value that is in the memory is a good one or not.

To fix this issue, all caches need a special bit (**valid bit**) in each cache line to indicate whether something meaningful is in the specific cache line ('0' at reset).



## Addressing by Byte

If addressing is **by byte** and **word size is  $2^n$  bytes**, the **n least significant bits** of the address represent the byte offset and are thus **irrelevant**. The last two bits of the address are **internal** to the processor and do not even get to the memory system. As we have seen in Section 2.3.1 the actual way of loading a byte is just a multiplexer between the 4 bytes of a word based on the last two bits of the address. So the **allocation of bits** begin **only** after the second bits. (we do not care about the last 2 bits here).

### 4.1.1 Write and Cache

#### Write Hit

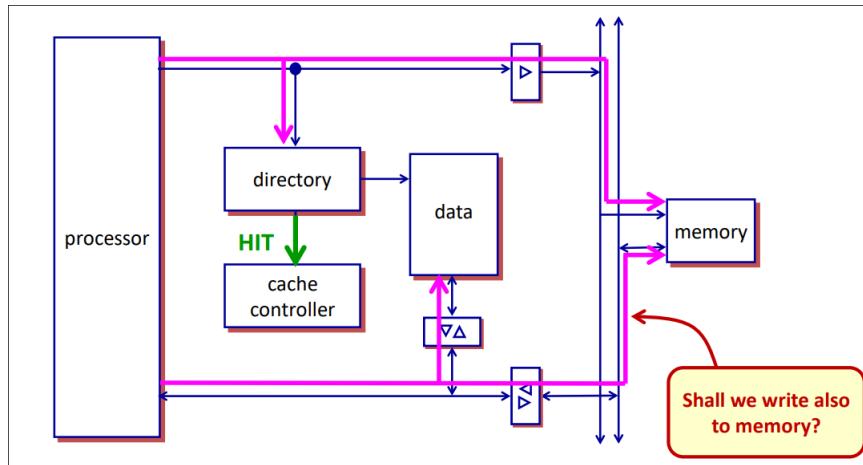
The question now is if we want to write something in the memory and we have a hit (in the cache controller). The first thing we should do is update the cache so that the next time we are getting something from this address we access the correct value.

The question we have now is Shall we write also to memory?

This is a legitimate question, by not writing we gain a lot of time. Also if we can avoid to write to memory we let the bus data and address **free**.

However there is a big issue, as we have said before, the cache has only **copies** of what is in memory

so overwriting something was not a big deal because the content was still in the memory. Now this is different, we now wrote in the cache **but not** in the memory, this means that the next time we are overwriting the cache our data is gone!



### Write policies

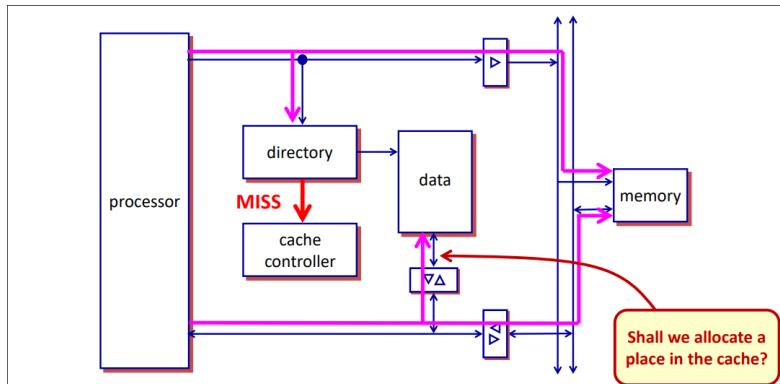
There is a couple of way to fix this issue:

- **Write-through:** On a write, data are always immediately written into main memory
  - Simpler policy
  - May keep the memory/buses busy for nothing
- **Write back or Copy back:** on a write, data are only updated in the cache (hence, main memory data will become wrong/obsolete)
  - Needs a **dirty Bit** to remember that cache **data are incoherent with memory**
  - When a dirty line is **evicted**, first it must be **copied back** to main memory

What we are doing here is like putting a *flag* that says content has changed and will we don't overwrite we don't change the content in memory. This is same principle as lazy evaluation in scala (kind of), we don't change anything until we have to.

### Write miss

The question now is when the cache doesn't have the value yet, shall we put the value in the cache or not. This question has less *issues* that comes with it, however this is still a legitimate questions:



### Allocation Policies

- **Write-allocate:** on a write miss, data are also placed in the cache
  - Simple and straightforward
  - Need to **fetch the block of data** from memory **first**
  - If the processor writes a lot of data that it will never read back, it may **unnecessarily pollute the cache**
- **Write around or Write no allocate:** on a write miss, data are only written to memory
  - If the processor will load from the same address, it will be a **read miss**

### The '3Cs' of caches

There are three types of **cache miss**

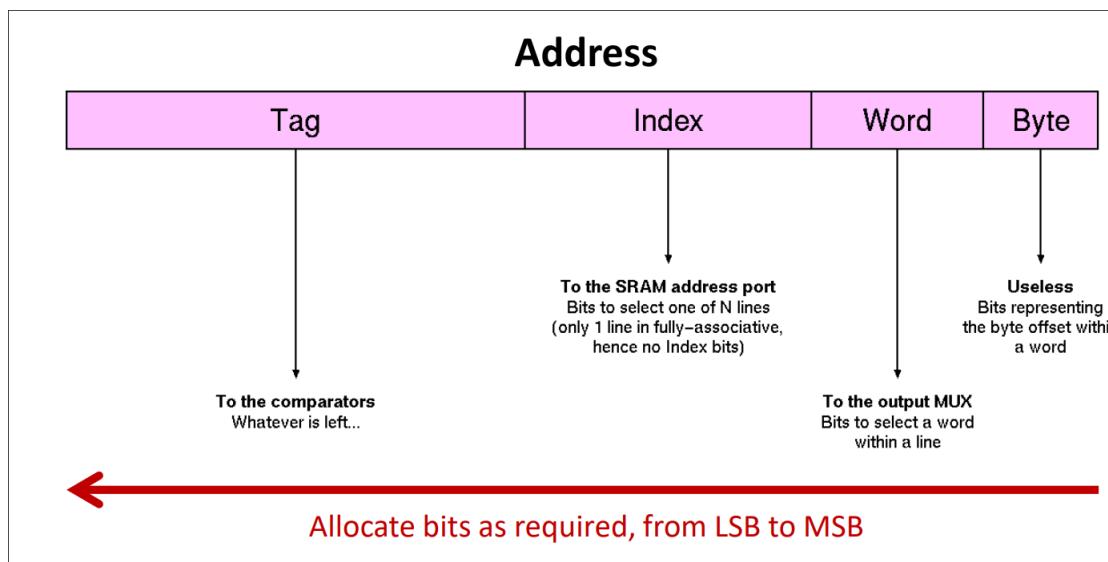
1. **Compulsory** → Missed that would happen in an infinitely large fully associative cache with the same block (also called **cold-start** misses or **first-reference** misses)
2. **Capacity** → Additional misses that occur because the corresponding block has been evicted due to the **limited capacity of the real cache**
3. **Conflict** → Further misses that occur because the corresponding block has been evicted due to the **limited associativity of the cache**

Those types of cache miss are useful to understand the **source of the limited performance.**

### Summary of cache Features

Here's the features of a cache and what's make a cache:

- **Cache size:** total data storage (usually excluding tags, valid bits, dirty bits, etc.)
- **Addressing** by byte or word
- **Line or block size:** bytes or words per line
- **Associativity:** fully-associative, k-way set-associative, direct-mapped
- **Replacement policy** (except for direct mapped): LRU, FIFO, random, etc.
- **Write policy:** write-through or write back
- **Allocation policy:** write-allocate or write-around



## 4.2 3b: Simple Cache Examples

**Compulsory Misses of a Direct Mapped Cache**

- Given an initially empty **direct-mapped cache** with **4 lines** and **2 words per line**, find the total number of compulsory misses for the following memory access sequence (in decimal)

12, 15, 11, 1, 17, 3, 17, 11, 17

**Hits in a 2-Way Set-Associative**

- The memory is word addressed
- The least recently used (LRU) replacement policy used
- Given an initially empty **2-Way set associative cache** with **2 sets** and **4 words per block**, find the total number of hits for the following memory access sequence (in decimal):

11, 15, 4, 16, 3, 10, 12, 24, 19, 25

**Miss Rate in a 2-Way Set-Associative**

- The memory is word-addressed
- The least recently used (LRU) replacement policy is used
- Given an initially empty **2-way set associative cache** with **2 sets**, find the miss rate for the following **block address** access sequence (in decimal):

6, 0, 0, 5, 5, 6, 1, 2, 2, 0

**Direct-Mapped cache**

Consider now a **direct-mapped cache** with a **capacity of 128KiB** and **2 words per line**

- The memory is word-addressed (one word = 4 bytes)
- The memory address has 32 bits
- Show how the address bits are used in the cache

**Tag of a 2-Way Set-Associative**

Finally, consider a **2 way set-associative cache** with a capacity of 128 KiB and **6<math><math>**

Those are examples

## 4.3 3c Virtual memory

### Segmentation Fault? Bus Error?

```
#include <stdlib.h>
#include <stdio.h>
int main() {
    int *p = (int *) 1234; /*li t0, 12345*/
    printf("\%i", p);      /*la a0, format*/
    /*lw a1, 0(t0)*/
    /*jal printf*/
}
```

What this program do is try to read at the address 1234? Here is the output:

```
Segmentation fault (core dumped)
```

Here the system sends us a message that this instruction cannot be done, we cannot *steal* an element from memory.

But know at the moment we cannot do this, for us if we gave an address, the processor gives us the element that is stored at the address.

### Overview

There is **three problems**:

- How to **protect memory** so that each program (processes). Running *simultaneously* in the system can only access its own data? How can we isolate processes?
- What happens if the main **memory** (DRAM) is **not sufficient** for the execution of program? Can we use our disk? How?
- How do we run several programs (processes)?!p snip.rv = match.group(1)  
‘simultaneously’?  
How do we load **multiple programs in memory**? Where?

This is where we need multiprogrammed system

### Needs of Multiprogrammed System

- Relocation
  - All programs must be written without knowledge of where they will be in memory
- Protection
  - Programs can access only their own data
- Space
  - If several program run at the same time, memory shortage will be even more a problem

What this means is that for instance gcc compiles a c file, it put it into the address `0x0` (by convention). However how can we compile more than just one language here? The simple solution is to relocate our load into memory each time

### Simples solution: Relocation at Load Time

```
0x0000: add v0, zero, zero # v0 = 0
          add t0, zero, zero # t0 = 0
0x0008: sltu t2, t0, a1 # t2 = (t0 < a1)
          beq t2, zero, 0x003C # if (!t2) goto fin
          lw t3, 0(a0) # t3 = mem[a0]
          addi t4, zero, 32 # t4 = 32
0x0014: beq t4, zero, 0x0030 # if (!t4) goto next
          andi t1, t3, 1 # t1 = t3 & 1
          add v0, v0, t1 # v0 = v0 + t1
          srl t3, t3, 1 # t3 = t3 >> 1
          subi t4, t4, 1 # t4 = t4 - 1
          j 0x0014 # goto inner
0x0030: addi t0, t0, 1 # t0 = t0 + 1
          addi a0, a0, 4 # a0 = a0 + 4
          j 0x0008 # goto outer
0x003c: ret # return to caller
```

So if we want to add a new program at this address we can just relocate this one (the code above) at address for instance 0x1234, which will gives us

```

0x1234: add v0, zero, zero # v0 = 0
          add t0, zero, zero # t0 = 0
0x123c: sltu t2, t0, a1 # t2 = (t0 < a1)
          beq t2, zero, 0x1270 # if (!t2) goto fin
          lw t3, 0(a0) # t3 = mem[a0]
          addi t4, zero, 32 # t4 = 32
0x1248: beq t4, zero, 0x1264 # if (!t4) goto next
          andi t1, t3, 1 # t1 = t3 & 1
          add v0, v0, t1 # v0 = v0 + t1
          srl t3, t3, 1 # t3 = t3 >> 1
          subi t4, t4, 1 # t4 = t4 - 1
          j 0x1248 # goto inner
0x1264: addi t0, t0, 1 # t0 = t0 + 1
          addi a0, a0, 4 # a0 = a0 + 4
          j 0x123c # goto outer
0x1270: ret # return to caller

```

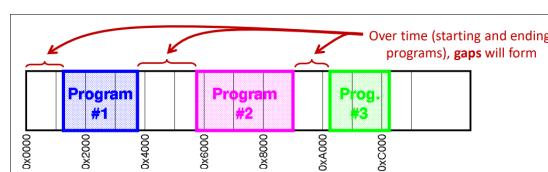
The relocation **must** take place at a **binary** level, not **assembly code**. We need **relocation tables** to know **where** are the addresses to change

<u>0x0000:</u>	<u>0x1234:</u>
00 00 10 20	00 00 10 20
00 00 40 20	00 00 40 20
01 05 50 2B	01 05 50 2B
10 0A 00 0B	10 0A 00 0B
8C 88 00 00	8C 88 00 00
20 0C 00 20	20 0C 00 20
10 0C 00 05	10 0C 00 05
31 69 00 01	31 69 00 01
00 49 10 20	00 49 10 20
00 0B 58 42	00 0B 58 42
21 8C FF FF	21 8C FF FF
08 00 00 06	08 00 04 8F
21 08 00 01	21 08 00 01
20 84 00 04	20 84 00 04
08 00 00 02	08 00 04 92
03 E0 00 08	03 E0 00 08

This idea has been used for many many years, and it is still used, this is a simple but very useful solution. However this is still a not the best for us but why?

### Limitations

So when we are running for instance programm 1, 2 and 3 at the same time we get this at memory



However as we can see there is **gaps** here.

So here we have a lot of **garbage** that we need to collect to have again some space. For instance if we wanted to add a fourth program and it is bigger than the individual gaps, how can we do it? The solution is the one that we said before, we need a **garbage collector**.

The limitations of this is that

- Large amount of work to do at load time

- **inflexible** → cannot be changed later

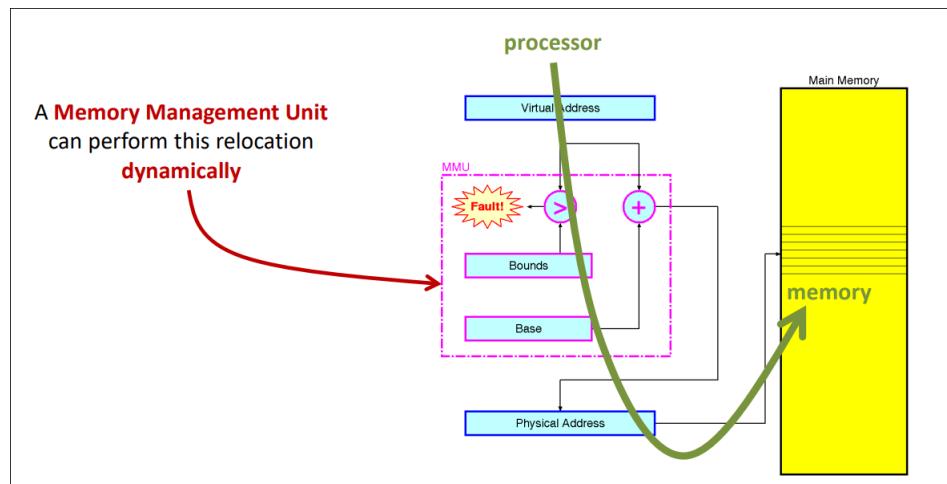
However we cannot move any program here. We would think that moving a program is just moving it into a new address and renew the pc to the current line that is being executed. **BUT** What if we are in a function that has a return address that is stored **in the stack** how would we know? From a hardware perspective the memory is **only storing some bytes here and there**. It doesn't know if it is a program, data, or anything else. Therefore it is impossible to put a program somewhere else **during its execution**. (Try this with a program that calls a function into another function (If we changed everything line by a certain offset then the return that was in the stack is not changed which make the program break.))

What is important (from what I see) is the fact that this is not an issue of something too hard or too slow. This is just **impossible** to do. we cannot shift a program

The issue is **static**, the fact that we choose the address of the program **staticly** makes it impossible to move before, this is the same issue as in Section 2.2.1

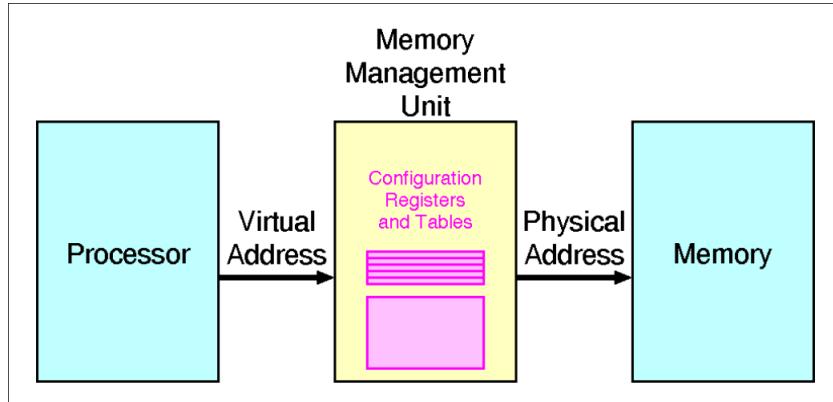
### Relocation in hardware: Base and Bounds MMU

Now Instead of doing it **before** it run, we can do it **while it runs**. What we want is that from a software perspective we use a virtual address (which thinks that the program start at **0x0**) which is **right** from a software point of view. Where the Program is in fact at address **0x1234**.



### Memory, Management Unit

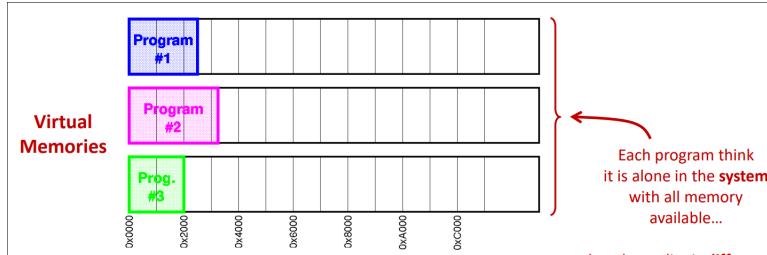
Here what we have to is just to put some gates between the processor and the memory That lie to us. We transform **at runtime** the real memory into virtual memory.



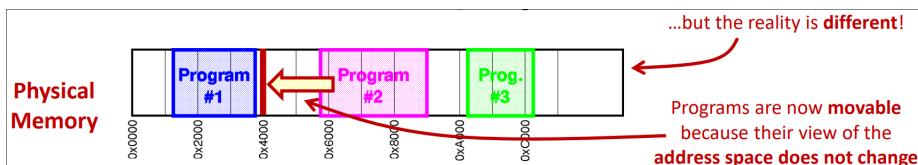
<i>Virtual Memory</i>	This is a memory that the OS allows a program to believe it has.
<i>Virtual address</i>	Conventional address used by a program → the MMU must translate it into physical address at the time of an access
<i>Physical Memory</i>	Memory actually available in the computer
<i>Physical Address</i>	Real location in physical memory; identifies actual storage.

### Virtual and Physical Memory

So here Hows it work is now very clean.



But this is only from a software perspective. But in reality (physical memory) this is the exact same thing as in section 4.3. If we are able to do the change on the fly then program **become movable**. If we return to `0x100`, in respective of where I am in the program, I will always return to `0x100`. Now the view of the address space does not change.

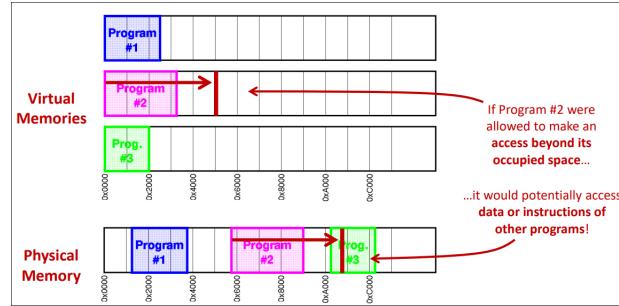


If we take the example of the stack of before, the issue was that when we were accessing returning but the memory was shift then the program was lost. However now, even when we are changing anything in the physical memory, the stack from a software perspective stays the exact same. The MMU handles the translation to wherever the physical stack actually lives at any given moment.

There are two very nice things here. We have the first offset that is being computed here. **AND** an not very costly part which checks whether or not the address that we are asking is too big or not. The part with the Bounds and Fault is checking if the program is asking for an address that is too big.

### Why we check

The reason of this check is very important. For instance if we are the second program and we want to fetch something from another program then we can just access something that is further from our scope.



The **Base** and **Bounds** value are different for each program. On a **context switch** (changing the program running), the OS must **reload these registers**.

### Needs of multi-programmed

Now:

- All programs must be written without knowledge of where they will be in memory
  - Space allocation may need **garbage collection**, **moving programs** and **data**, etc.
- Programs can access only their own data
  - Protection is a bit crude: **one chunk of memory**

*Was is still not good* If several programs run at the same time, memory shortage will be even more a problem

### Segmentation and Paging

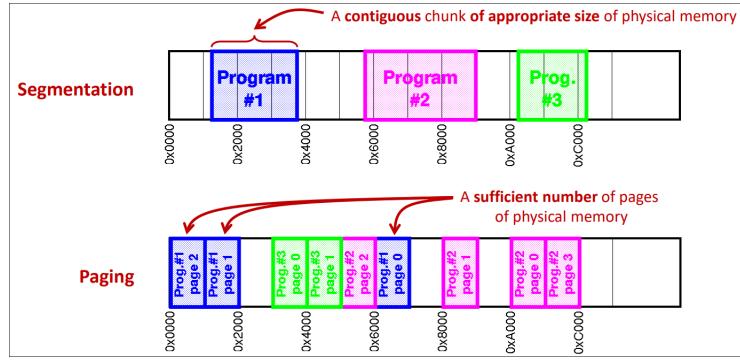
#### Segmentation

An **Segmentation** (an extension of **Base & Bounds**) splits the physical memory exactly as needed by each program

- Arbitrary start of a block
- Arbitrary length
- Multiple block per application

#### Paging

**Paging** splits the memory in equal small block (e.g., 4-64KiB) and assigns as many as needed to each program.



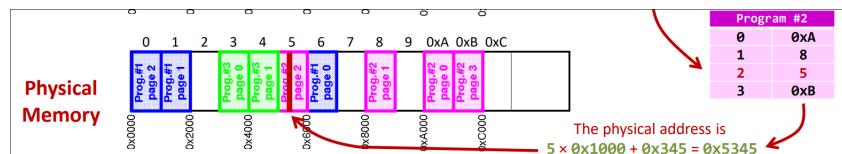
From there, there is a lot of questions on in which page are we now? Where in the current page are we now?

In other word

### How do we translate

For instance let us take the previous example and assume that we are in the virtual address `0x2345` and that pages are `0x1000` in size.

To know in which page we currently are we can just do a integer division:  $0x2345 / 0x1000 = \text{page } 2$  and to know the position in the page we only have to take the modulo:  $0x2345 \bmod 0x1000 = 0x345$ . Then we need a **table** that tells us the physical memory of each page.



### What if the page is a power of 2

If the length of the page is a power of 2 then this has became totally trivial all we have to do is to take the first  $n$  bits for the offset and the  $32 - n$  last bits as the input for the page table.

