
CS 267

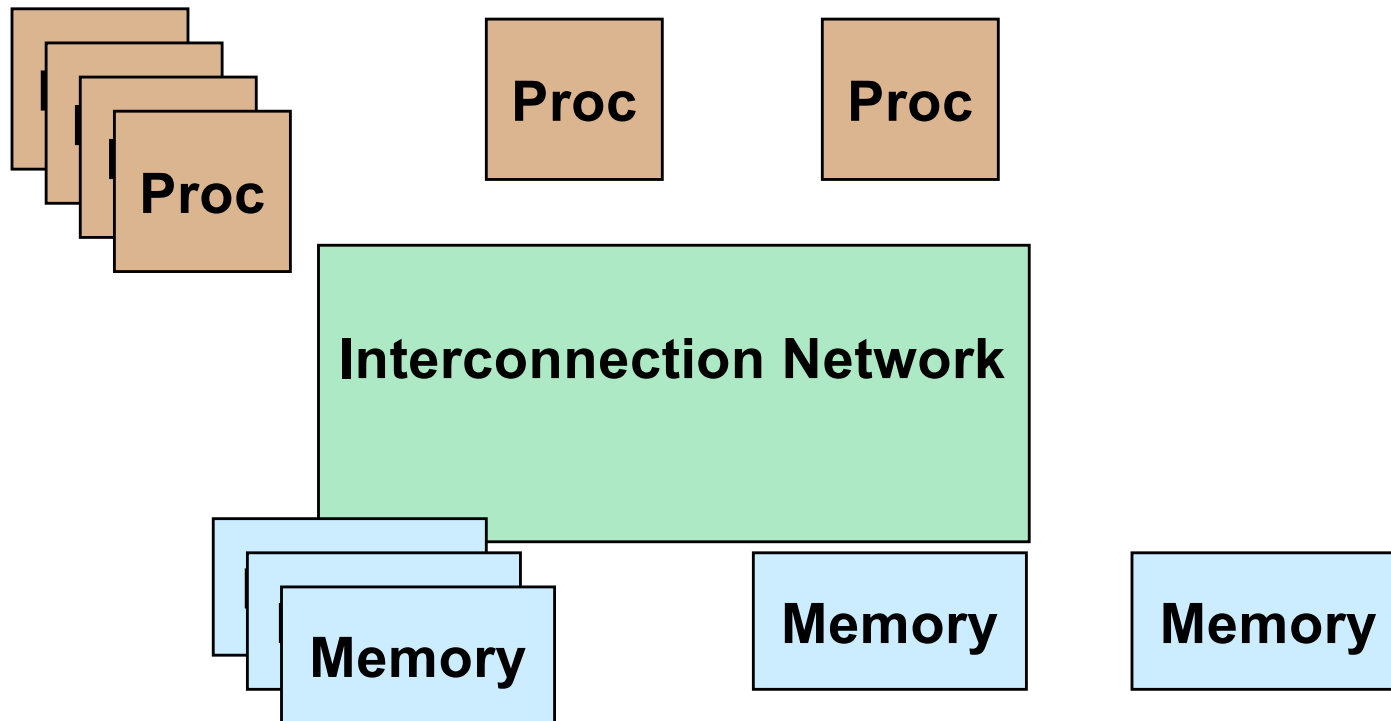
Sources of Parallelism and Locality in Simulation

Lecture 3

James Demmel

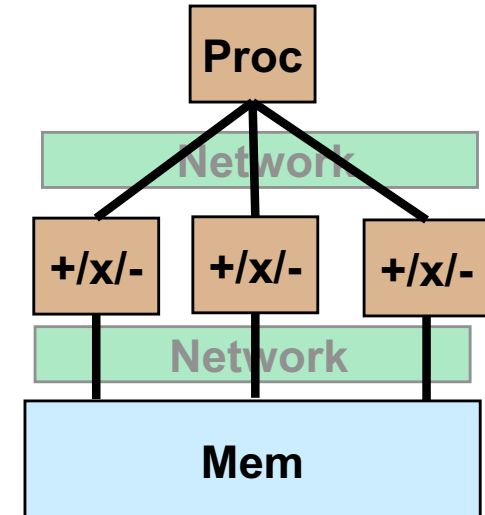
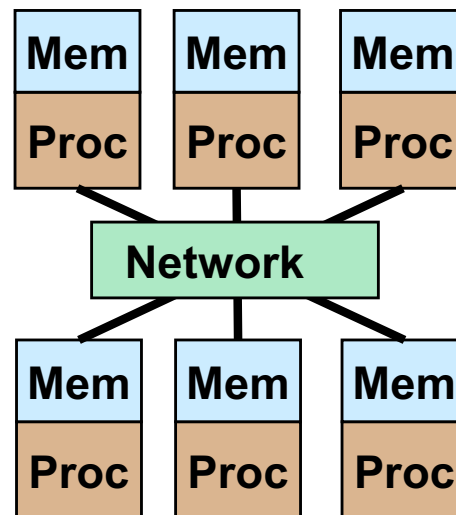
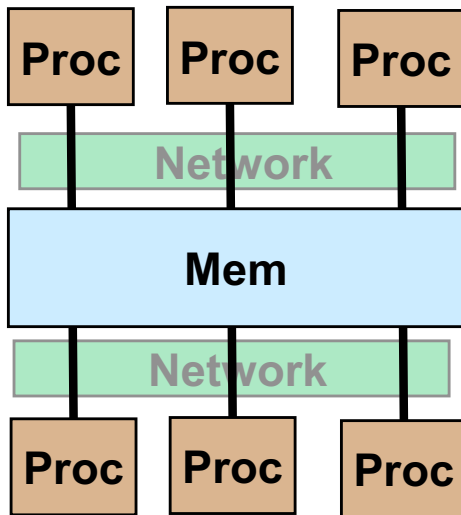
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A generic parallel architecture



- Where is the memory physically located?
- Is it connected directly to processors?
- What is the connectivity of the network?
- How are the processor controlled?

Parallel Machines and Programming



| Shared Memory | Distributed Memory | Single Instruction Multiple Data (SIMD) |
|---|--|---|
| Processors execute own instruction stream | Processors execute own instruction stream | One instruction stream (all run same instruction) |
| Communicate by reading/writing memory | Communicate by sending messages | Communicate through memory |
| Cost of a read/write is constant | Message time depends on size, but not location | Assume unbounded # of arithmetic units |

- These are the natural “abstract” machine models

Parallelism and Locality in Simulation

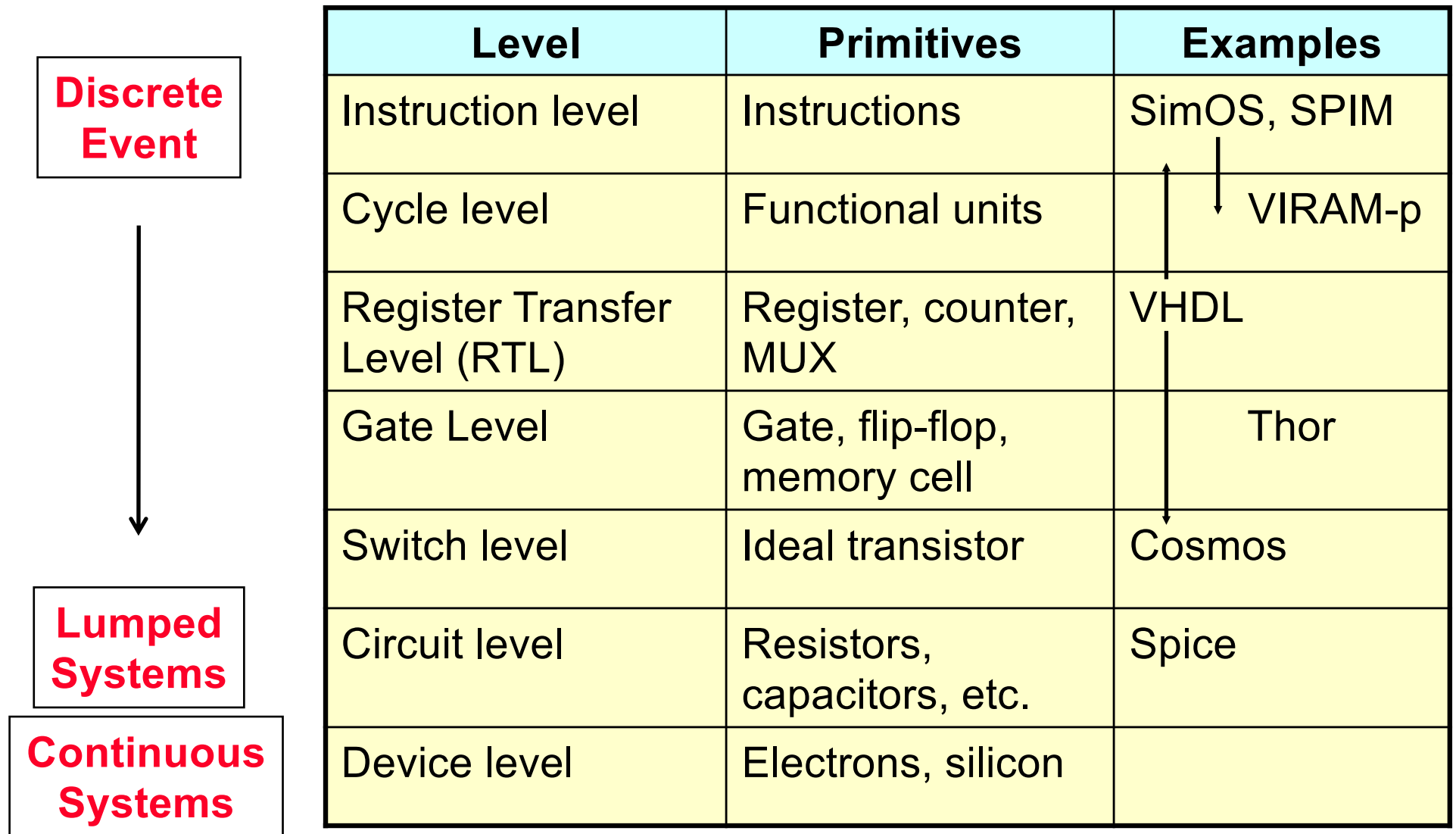
- Parallelism and data locality both critical to performance
 - Recall that moving data is the most expensive operation
- Real world problems have parallelism and locality:
 - Many objects operate independently of others.
 - Objects often depend much more on nearby than distant objects.
 - Dependence on distant objects can often be simplified.
 - Example of all three: particles moving under gravity
- Scientific models may introduce more parallelism:
 - When a continuous problem is discretized, time dependencies are generally limited to adjacent time steps.
 - Helps limit dependence to nearby objects (eg collisions)
 - Far-field effects may be ignored or approximated in many cases.
- Many problems exhibit parallelism at multiple levels

Basic Kinds of Simulation

- Discrete event systems:
 - “Game of Life,” Manufacturing systems, Finance, Circuits, Pacman, ...
- Particle systems:
 - Billiard balls, Galaxies, Atoms, Circuits, Pinball ...
- Lumped variables depending on continuous parameters
 - aka Ordinary Differential Equations (ODEs),
 - Structural mechanics, Chemical kinetics, Circuits, Star Wars: The Force Unleashed
- Continuous variables depending on continuous parameters
 - aka Partial Differential Equations (PDEs)
 - Heat, Elasticity, Electrostatics, Finance, Circuits, Medical Image Analysis, Terminator 3: Rise of the Machines
- A given phenomenon can be modeled at multiple levels.
- Many simulations combine more than one of these techniques.
- For more on simulation in games, see
 - www.cs.berkeley.edu/b-cam/Papers/Parker-2009-RTD

Example: Circuit Simulation

- Circuits are simulated at many different levels



Outline

- Discrete event systems
 - Time and space are discrete
- Particle systems
 - Important special case of lumped systems
- Lumped systems (ODEs)
 - Location/entities are discrete, time is continuous
- Continuous systems (PDEs)
 - Time and space are continuous
 - Next lecture
- Identify common problems and solutions



A Model Problem: Sharks and Fish

- Illustration of parallel programming
 - Original version (discrete event only) proposed by Geoffrey Fox
 - Called WATOR
- Basic idea: sharks and fish living in an ocean
 - rules for movement (discrete and continuous)
 - breeding, eating, and death
 - forces in the ocean
 - forces between sea creatures
- 6 problems (S&F1 - S&F6)
 - Different sets of rules, to illustrate different phenomena
- Available in many languages (see class web page)
 - Matlab, pThreads, MPI, OpenMP, Split-C, Titanium, CMF, CMMD, pSather (not all problems in all languages)
- Some homework based on these

Sharks and Fish

- **S&F 1.** Fish alone move continuously subject to an external current and Newton's laws.
- **S&F 2.** Fish alone move continuously subject to gravitational attraction and Newton's laws.
- **S&F 3.** Fish alone play the "Game of Life" on a square grid.
- **S&F 4.** Fish alone move randomly on a square grid, with at most one fish per grid point.
- **S&F 5.** Sharks and Fish both move randomly on a square grid, with at most one fish or shark per grid point, including rules for fish attracting sharks, eating, breeding and dying.
- **S&F 6.** Like Sharks and Fish 5, but continuous, subject to Newton's laws.

Discrete Event Systems

Discrete Event Systems

- Systems are represented as:
 - finite set of variables.
 - the set of all variable values at a given time is called the **state**.
 - each variable is updated by computing a **transition function** depending on the other variables.
- System may be:
 - **synchronous**: at each discrete timestep evaluate all transition functions; also called a **state machine**.
 - **asynchronous**: transition functions are evaluated only if the inputs change, based on an “**event**” from another part of the system; also called **event driven simulation**.
- Example: The “game of life:”
 - Also known as Sharks and Fish #3:
 - Space divided into cells, rules govern cell contents at each step

Parallelism in Game of Life (S&F 3)

- The simulation is synchronous
 - use two copies of the grid (old and new), “ping-pong” between them
 - the value of each new grid cell depends only on 9 cells (itself plus 8 neighbors) in old grid.
 - simulation proceeds in timesteps-- each cell is updated at every step.
- Easy to parallelize by dividing physical domain: *Domain Decomposition*

| | | |
|----|----|----|
| P1 | P2 | P3 |
| P4 | P5 | P6 |
| P7 | P8 | P9 |

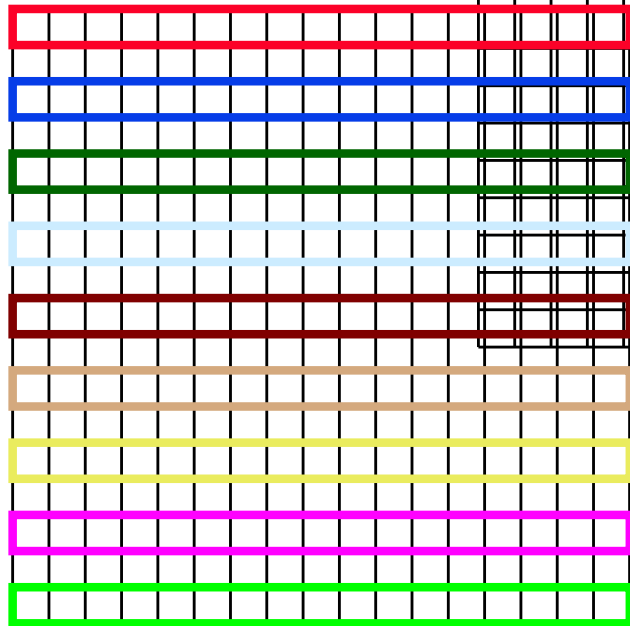
Repeat
compute locally to update local system
barrier()
exchange state info with neighbors
finish updates
until done simulating

- Locality is achieved by using large patches of the ocean
 - Only boundary values from neighboring patches are needed.
- How to pick shapes of domains?

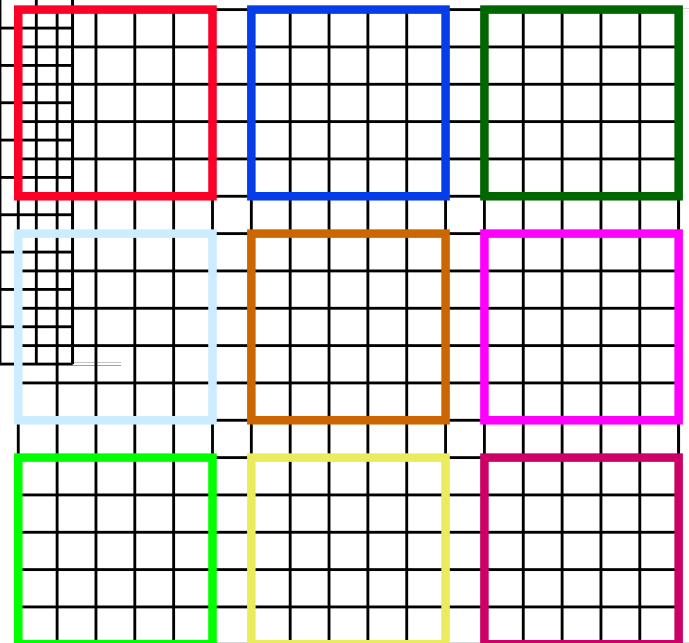
Regular Meshes (e.g. Game of Life)

- Suppose graph is $n \times n$ mesh with connection NSEW neighbors
- Which partition has less communication? ($n=18$, $p=9$)
- Minimizing communication on mesh \equiv minimizing “surface to volume ratio” of partition

$n \cdot (p-1)$
edge crossings

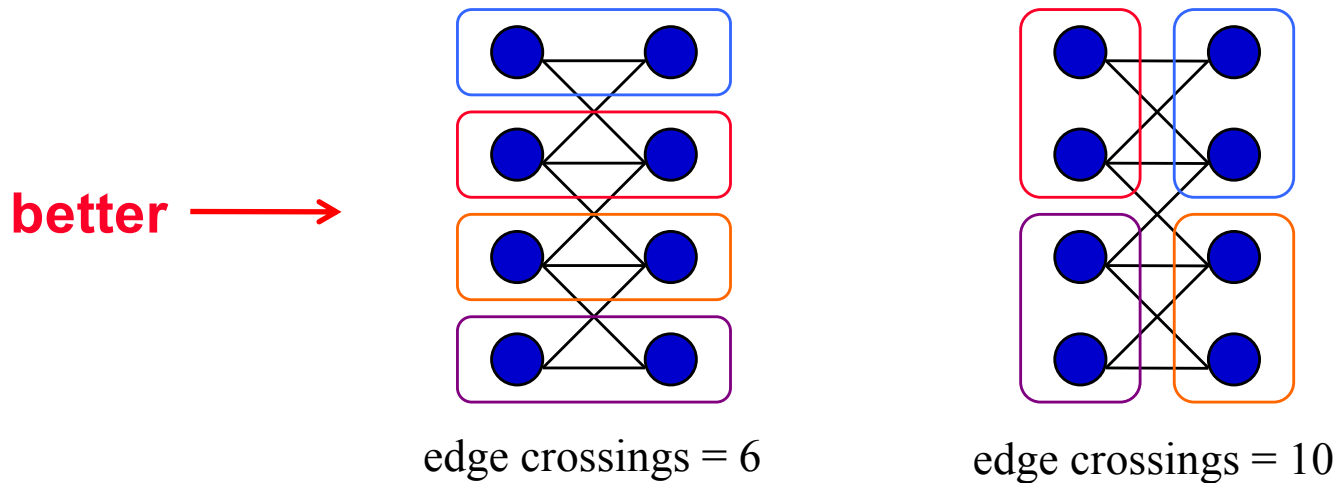


$2 \cdot n \cdot (p^{1/2} - 1)$
edge crossings

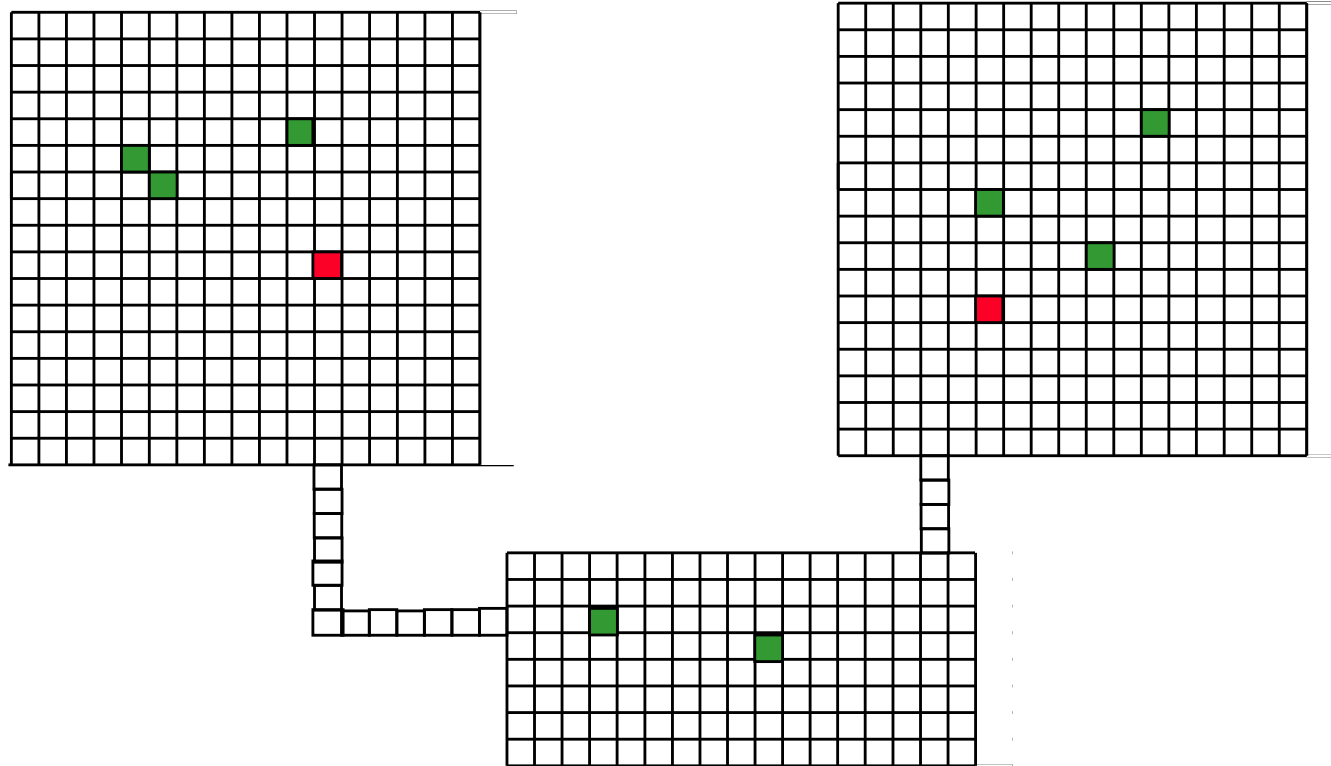


Synchronous Circuit Simulation

- Circuit is a **graph** made up of subcircuits connected by wires
 - Component simulations need to interact if they share a wire.
 - Data structure is (irregular) graph of subcircuits.
 - Parallel algorithm is timing-driven or **synchronous**:
 - Evaluate all components at every timestep (determined by known circuit delay)
- **Graph partitioning** assigns subgraphs to processors
 - Determines parallelism and locality.
 - Goal 1 is to evenly distribute subgraphs to nodes (load balance).
 - Goal 2 is to minimize edge crossings (minimize communication).
 - Easy for meshes, NP-hard in general, so we will approximate (future lecture)



Sharks & Fish in Loosely Connected Ponds



- Parallelization: each processor gets a set of ponds with roughly equal total area
 - work is proportional to area, not number of creatures
- One pond can affect another (through streams) but infrequently

Asynchronous Simulation

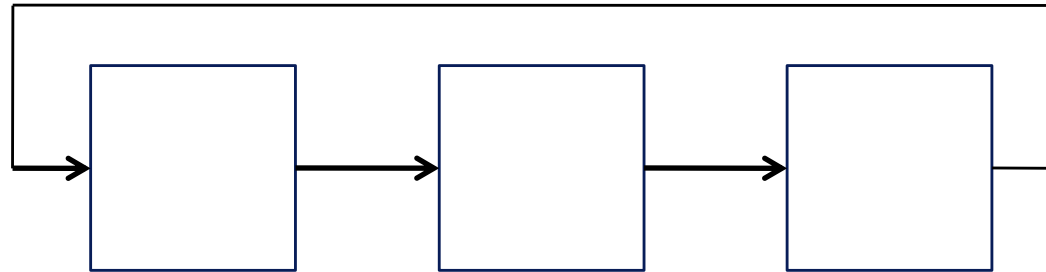
- Synchronous simulations may waste time:
 - Simulates even when the inputs do not change
- Asynchronous (event-driven) simulations update only when an **event** arrives from another component:
 - No global time steps, but individual events contain time stamp.
 - Example: Game of life in loosely connected ponds (don't simulate empty ponds).
 - Example: Circuit simulation with delays (events are gates changing).
 - Example: Traffic simulation (events are cars changing lanes, etc.).
- Asynchronous is more efficient, but harder to parallelize
 - On distributed memory, events are naturally implemented as messages between processors (eg using MPI), but how do you know when to execute a “receive”?

Scheduling Asynchronous Circuit Simulation

- **Conservative:**
 - Only simulate up to (and including) the minimum time stamp of inputs.
 - Need deadlock detection if there are cycles in graph
 - Example on next slide
 - Example: Pthor circuit simulator in Splash1 from Stanford.
- **Speculative (or Optimistic):**
 - Assume no new inputs will arrive and keep simulating.
 - May need to backup if assumption wrong, using timestamps
 - Example: Timewarp [D. Jefferson], Parswec [Wen, Yelick].
- Optimizing load balance and locality is difficult:
 - Locality means putting tightly coupled subcircuit on one processor.
 - Since “active” part of circuit likely to be in a tightly coupled subcircuit, this may be bad for load balance.

Deadlock in Conservative Asynchronous Circuit Simulation

- Example: Sharks & Fish 3, with 3 processors simulating 3 ponds connected by streams along which fish can move



- Suppose all ponds simulated up to time t_0 , but no fish move, so no messages sent from one proc to another
 - So no processor can simulate past time t_0
- Fix: After waiting for an incoming message for a while, send out an “Are you stuck too?” message
 - If you ever receive such a message, pass it on
 - If you receive such a message that you sent, you have a deadlock cycle, so just take a step with latest input
- Can be a serial bottleneck

Summary of Discrete Event Simulations

- Model of the world is discrete
 - Both time and space
- Approaches
 - Decompose domain, i.e., set of objects
 - Run each component ahead using
 - **Synchronous**: communicate at end of each timestep
 - **Asynchronous**: communicate on-demand
 - **Conservative scheduling** – wait for inputs
 - need deadlock detection
 - **Speculative scheduling** – assume no inputs
 - roll back if necessary

Particle Systems

Particle Systems

- A particle system has
 - a finite number of particles
 - moving in space according to Newton's Laws (i.e. $F = ma$)
 - Time and positions are continuous
- Examples
 - stars in space with laws of gravity
 - electron beam in semiconductor manufacturing
 - atoms in a molecule with electrostatic forces
 - neutrons in a fission reactor
 - cars on a freeway with Newton's laws plus model of driver and engine
 - balls in a pinball game
- Reminder: many simulations combine techniques such as particle simulations with some discrete events (Ex Sharks and Fish)

Forces in Particle Systems

- Force on each particle can be subdivided

$$\text{force} = \text{external_force} + \text{nearby_force} + \text{far_field_force}$$

- External force
 - ocean current in sharks and fish world (S&F 1)
 - externally imposed electric field in electron beam
- Nearby force
 - sharks attracted to eat nearby fish (S&F 5)
 - balls on a billiard table bounce off of each other
 - Van der Waals forces in fluid ($1/r^6$) ... how Gecko feet work?
- Far-field force
 - fish attract other fish by gravity-like ($1/r^2$) force (S&F 2)
 - gravity, electrostatics, radiosity in graphics
 - forces governed by elliptic PDE

Example S&F 1: Fish in an External Current

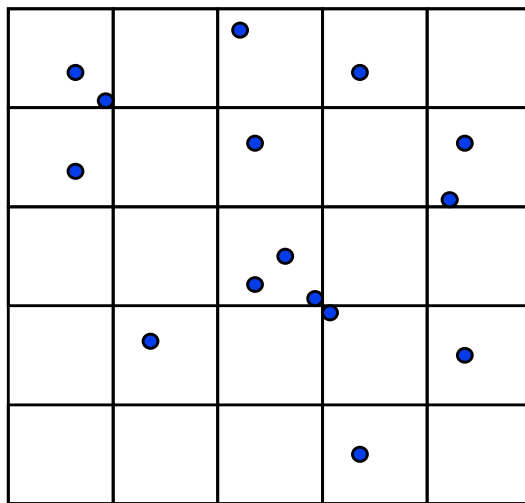
```
% fishp = array of initial fish positions (stored as complex numbers)
% fishv = array of initial fish velocities (stored as complex numbers)
% fishm = array of masses of fish
% tfinal = final time for simulation (0 = initial time)
% Algorithm: integrate using Euler's method with varying step size
% Initialize time step, iteration count, and array of times
dt = .01; t = 0;
% loop over time steps
while t < tfinal,
    t = t + dt;
    fishp = fishp + dt*fishv;
    accel = current(fishp)./fishm;    % current depends on position
    fishv = fishv + dt*accel;
% update time step (small enough to be accurate, but not too small)
dt = min(.1*max(abs(fishv))/max(abs(accel)),1);
end
```

Parallelism in External Forces

- These are the simplest
- The force on each particle is independent
- Called “embarrassingly parallel”
 - Sometimes called “map reduce” by analogy
- Evenly distribute particles on processors
 - Any distribution works
 - Locality is not an issue
- For each particle on processor, apply the external force
 - Also called “map”
 - May need to “reduce” (eg compute maximum) to compute time step, other data

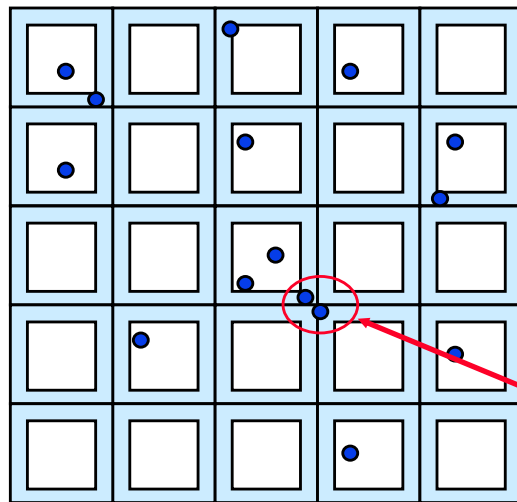
Parallelism in Nearby Forces

- Nearby forces require interaction and therefore communication.
- Force may depend on other nearby particles:
 - Example: collisions.
 - simplest algorithm is $O(n^2)$: look at all pairs to see if they collide.
- Usual parallel model is **domain decomposition** of physical region in which particles are located
 - $O(n/p)$ particles per processor if evenly distributed.



Parallelism in Nearby Forces

- Challenge 1: interactions of particles near processor boundary:
 - need to communicate particles near boundary to neighboring processors.
 - Region near boundary called “ghost zone” or “halo”
 - Low surface to volume ratio means low communication.
 - Use squares, not slabs, to minimize ghost zone sizes

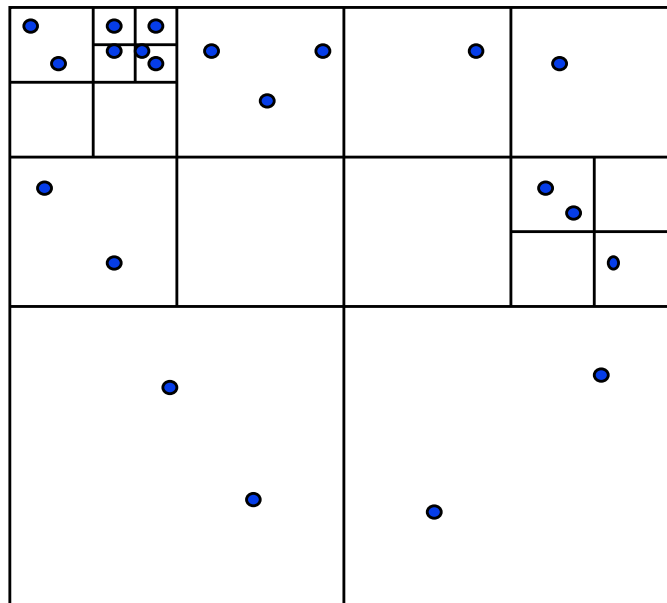


Communicate particles in boundary region to neighbors

Need to check for collisions between regions

Parallelism in Nearby Forces

- Challenge 2: load imbalance, if particles cluster:
 - galaxies, electrons hitting a device wall.
- To reduce load imbalance, divide space unevenly.
 - Each region contains roughly equal number of particles.
 - Quad-tree in 2D, oct-tree in 3D.

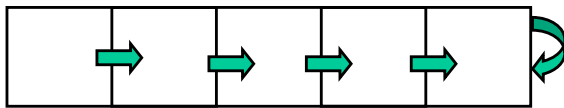


Example: each square
contains at most 3
particles

- May need to rebalance as particles move, hopefully seldom

Parallelism in Far-Field Forces

- Far-field forces involve all-to-all interaction and therefore communication.
- Force depends on all other particles:
 - Examples: gravity, protein folding
 - Simplest algorithm is $O(n^2)$ as in S&F 2, 4, 5.
 - Just decomposing space does not help since every particle needs to “visit” every other particle.



Implement by rotating particle sets.

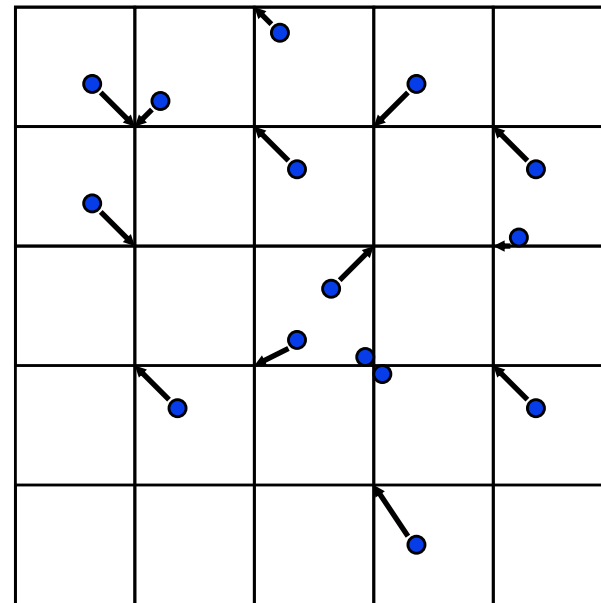
- Keeps processors busy
- All processors eventually see all particles

- Use more clever algorithms to reduce communication
- Use more clever algorithms to beat $O(n^2)$.

Far-field Forces: Particle-Mesh Methods

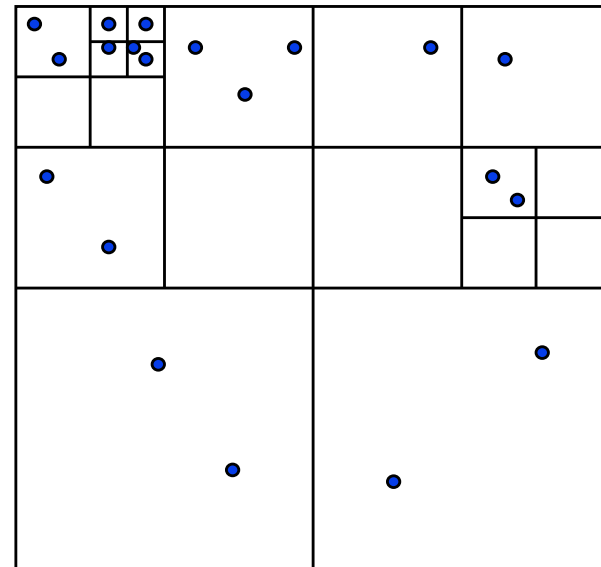
- Based on approximation:
 - Superimpose a regular mesh.
 - “Move” particles to nearest grid point.
- Exploit fact that the far-field force satisfies a PDE that is easy to solve on a regular mesh:
 - FFT, multigrid (described in future lectures)
 - Cost drops to $O(n \log n)$ or $O(n)$ instead of $O(n^2)$
- Accuracy depends on the fineness of the grid is and the uniformity of the particle distribution.

- 1) Particles are moved to nearby mesh points (scatter)
- 2) Solve mesh problem
- 3) Forces are interpolated at particles from mesh points (gather)



Far-field forces: Tree Decomposition

- Based on approximation.
 - Forces from group of far-away particles “simplified” -- resembles a single large particle.
 - Use tree; each node contains an approximation of descendants.
- Also $O(n \log n)$ or $O(n)$ instead of $O(n^2)$.
- Several Algorithms
 - Barnes-Hut.
 - Fast multipole method (FMM) of Greengard/Rohklin.
 - Anderson’s method.
- Discussed in later lecture.



Summary of Particle Methods

- Model contains discrete entities, namely, particles
- Time is continuous – must be discretized to solve
- Simulation follows particles through timesteps
 - Force = external_force + nearby_force + far_field_force
 - All-pairs algorithm is simple, but inefficient, $O(n^2)$
 - Particle-mesh methods approximates by moving particles to a regular mesh, where it is easier to compute forces
 - Tree-based algorithms approximate by treating set of particles as a group, when far away
- May think of this as a special case of a “lumped” system

Lumped Systems: ODEs

System of Lumped Variables

- Many systems are approximated by
 - System of “lumped” variables.
 - Each depends on continuous parameter (usually time).
- Example -- circuit:
 - approximate as graph.
 - wires are edges.
 - nodes are connections between 2 or more wires.
 - each edge has resistor, capacitor, inductor or voltage source.
 - system is “lumped” because we are not computing the voltage/current at every point in space along a wire, just endpoints.
 - Variables related by Ohm’s Law, Kirchoff’s Laws, etc.
- Forms a system of ordinary differential equations (ODEs).
 - Differentiated with respect to time
 - Variant: ODEs with some constraints
 - Also called DAEs, Differential Algebraic Equations

Circuit Example

- State of the system is represented by

$$\left. \begin{array}{l} \bullet v_n(t) \text{ node voltages} \\ \bullet i_b(t) \text{ branch currents} \\ \bullet v_b(t) \text{ branch voltages} \end{array} \right\} \text{ all at times } t$$

- Equations include

$$\begin{array}{l} \bullet \text{Kirchoff's current} \\ \bullet \text{Kirchoff's voltage} \\ \bullet \text{Ohm's law} \\ \bullet \text{Capacitance} \\ \bullet \text{Inductance} \end{array} \begin{pmatrix} 0 & A & 0 \\ A' & 0 & -I \\ 0 & R & -I \\ 0 & -I & C*d/dt \\ 0 & L*d/dt & I \end{pmatrix} * \begin{pmatrix} v_n \\ i_b \\ v_b \end{pmatrix} = \begin{pmatrix} 0 \\ S \\ 0 \\ 0 \\ 0 \end{pmatrix}$$

- A is sparse matrix, representing connections in circuit
 - One column per branch (edge), one row per node (vertex) with +1 and -1 in each column at rows indicating end points
- Write as single large system of ODEs or DAEs

Structural Analysis Example

- Another example is structural analysis in civil engineering:
 - Variables are displacement of points in a building.
 - Newton's and Hook's (spring) laws apply.
 - Static modeling: exert force and determine displacement.
 - Dynamic modeling: apply continuous force (earthquake).
 - Eigenvalue problem: do the resonant modes of the building match an earthquake?



OpenSees project in CE at Berkeley looks at this section of 880, among others

Gaming Example

Star Wars – The Force Unleashed ...

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Solving ODEs

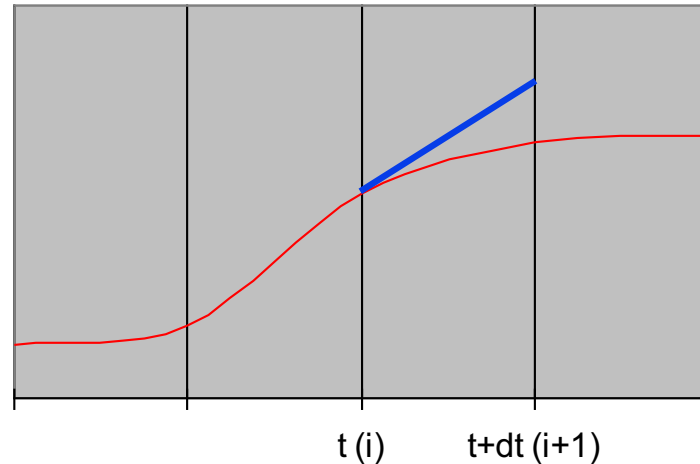
- In these examples, and most others, the matrices are sparse:
 - i.e., most array elements are 0.
 - neither store nor compute on these 0's.
 - Sparse because each component only depends on a few others
- Given a set of ODEs, two kinds of questions are:
 - Compute the values of the variables at some time t
 - Explicit methods
 - Implicit methods
 - Compute modes of vibration
 - Eigenvalue problems

Solving ODEs: Explicit Methods

- Assume ODE is $x'(t) = f(x) = A*x(t)$, where A is a sparse matrix
 - Compute $x(i*dt) = x[i]$
at $i=0,1,2,\dots$

- ODE gives $x'(i*dt) = \text{slope}$
 $x[i+1] = x[i] + dt * \text{slope}$

Use slope at $x[i]$



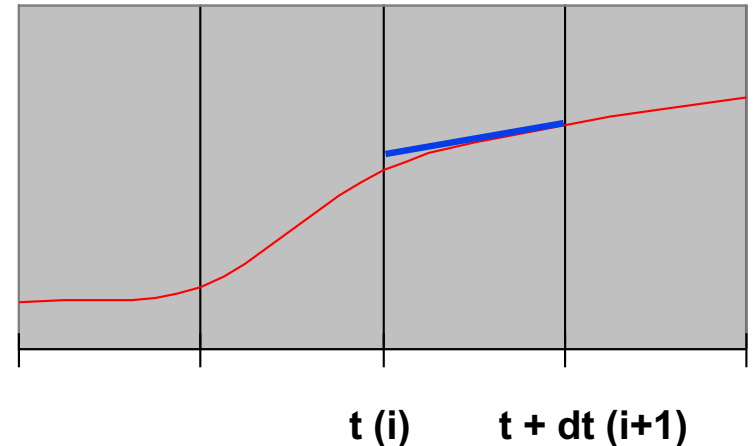
- Explicit methods, e.g., (Forward) Euler's method.
 - Approximate $x'(t) = A*x(t)$ by $(x[i+1] - x[i]) / dt = A*x[i]$.
 - $x[i+1] = x[i] + dt * A*x[i]$, i.e. sparse matrix-vector multiplication.
- Tradeoffs:
 - Simple algorithm: sparse matrix vector multiply.
 - Stability problems: May need to take very small time steps, especially if system is **stiff** (i.e. A has some large entries, so x can change rapidly).

Solving ODEs: Implicit Methods

- Assume ODE is $x'(t) = f(x) = A*x(t)$, where A is a sparse matrix

- Compute $x(i*dt) = x[i]$
at $i=0,1,2,\dots$
- ODE gives $x'((i+1)*dt) = \text{slope}$
 $x[i+1] = x[i] + dt*\text{slope}$

Use slope at $x[i+1]$



- Implicit method, e.g., Backward Euler solve:
 - Approximate $x'(t) = A*x(t)$ by $(x[i+1] - x[i])/dt = A*x[i+1]$.
 - $(I - dt*A)*x[i+1] = x[i]$, i.e. we need to solve a sparse linear system of equations.
- Trade-offs:
 - Larger timestep possible: especially for **stiff** problems
 - More difficult algorithm: need to solve a sparse linear system of equations at each step

Solving ODEs: Eigensolvers

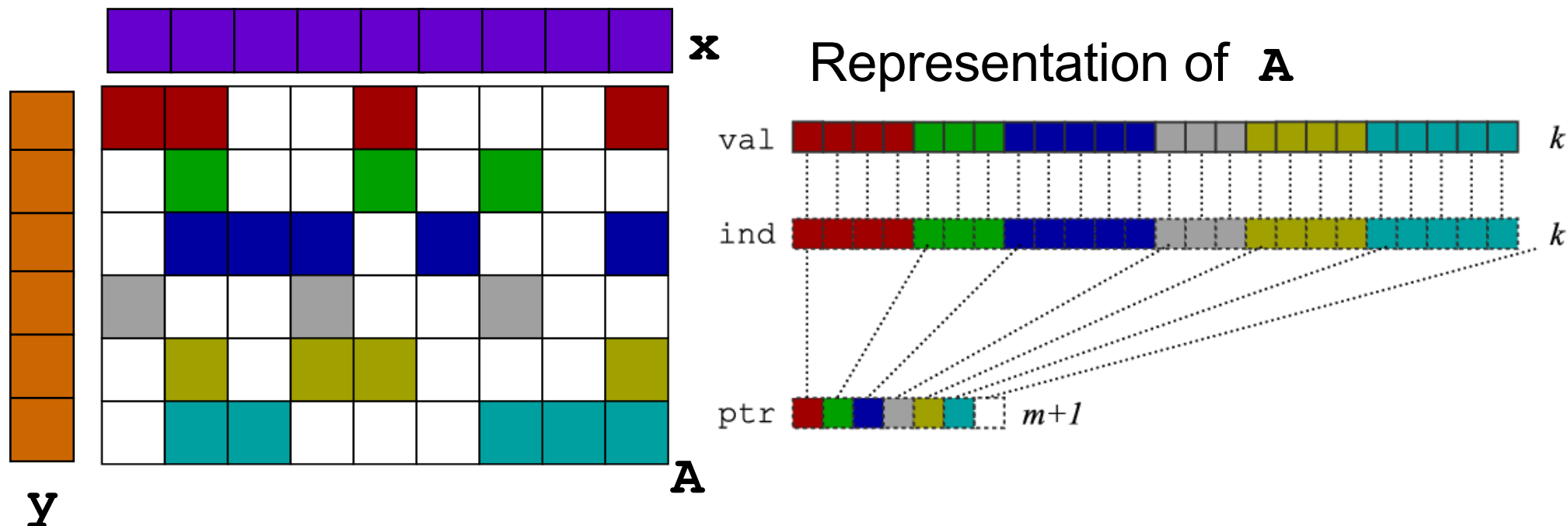
- Computing modes of vibration: finding eigenvalues and eigenvectors.
 - Seek solution of $d^2x(t)/dt^2 = A*x(t)$ of form $x(t) = \sin(\omega*t) * x_0$, where x_0 is a constant vector
 - ω called the frequency of vibration
 - x_0 sometimes called a “mode shape”
 - Plug in to get $-\omega^2 * x_0 = A*x_0$, so that $-\omega^2$ is an eigenvalue and x_0 is an eigenvector of A .
 - Solution schemes reduce either to sparse-matrix multiplications, or solving sparse linear systems.

Summary of ODE Methods

- Explicit methods for ODEs need sparse-matrix-vector mult.
- Implicit methods for ODEs need to solve linear systems
- Direct methods (Gaussian elimination)
 - Called LU Decomposition, because we factor $A = L*U$.
 - Future lectures will consider both dense and sparse cases.
 - More complicated than sparse-matrix vector multiplication.
- Iterative solvers
 - Will discuss several of these in future.
 - Jacobi, Successive over-relaxation (SOR) , Conjugate Gradient (CG), Multigrid,...
 - Most have sparse-matrix-vector multiplication in kernel.
- Eigenproblems
 - Future lectures will discuss dense and sparse cases.
 - Also depend on sparse-matrix-vector multiplication, direct methods.

SpMV in Compressed Sparse Row (CSR) Format

SpMV: $y = y + A \times x$, only store, do arithmetic, on nonzero entries
 CSR format is simplest one of many possible data structures for A



Matrix-vector multiply kernel: $y(i) \leftarrow y(i) + A(i,j) \times x(j)$

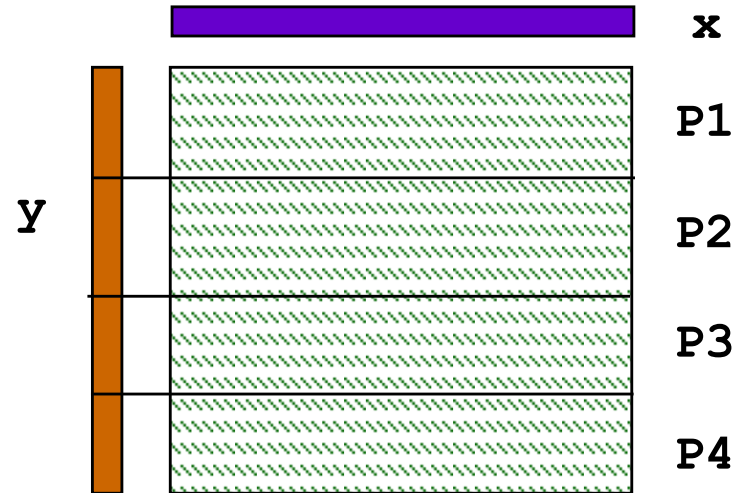
for each row i

for $k=ptr[i]$ to $ptr[i+1]-1$ do

$y[i] = y[i] + val[k] * x[ind[k]]$

Parallel Sparse Matrix-vector multiplication

- $y = A * x$, where A is a sparse $n \times n$ matrix



- Questions

- which processors store
 - $y[i]$, $x[i]$, and $A[i,j]$
- which processors compute

- $y[i] = \text{sum (from 1 to n) } A[i,j] * x[j]$
 $= (\text{row } i \text{ of } A) * x \quad \dots \text{ a sparse dot product}$

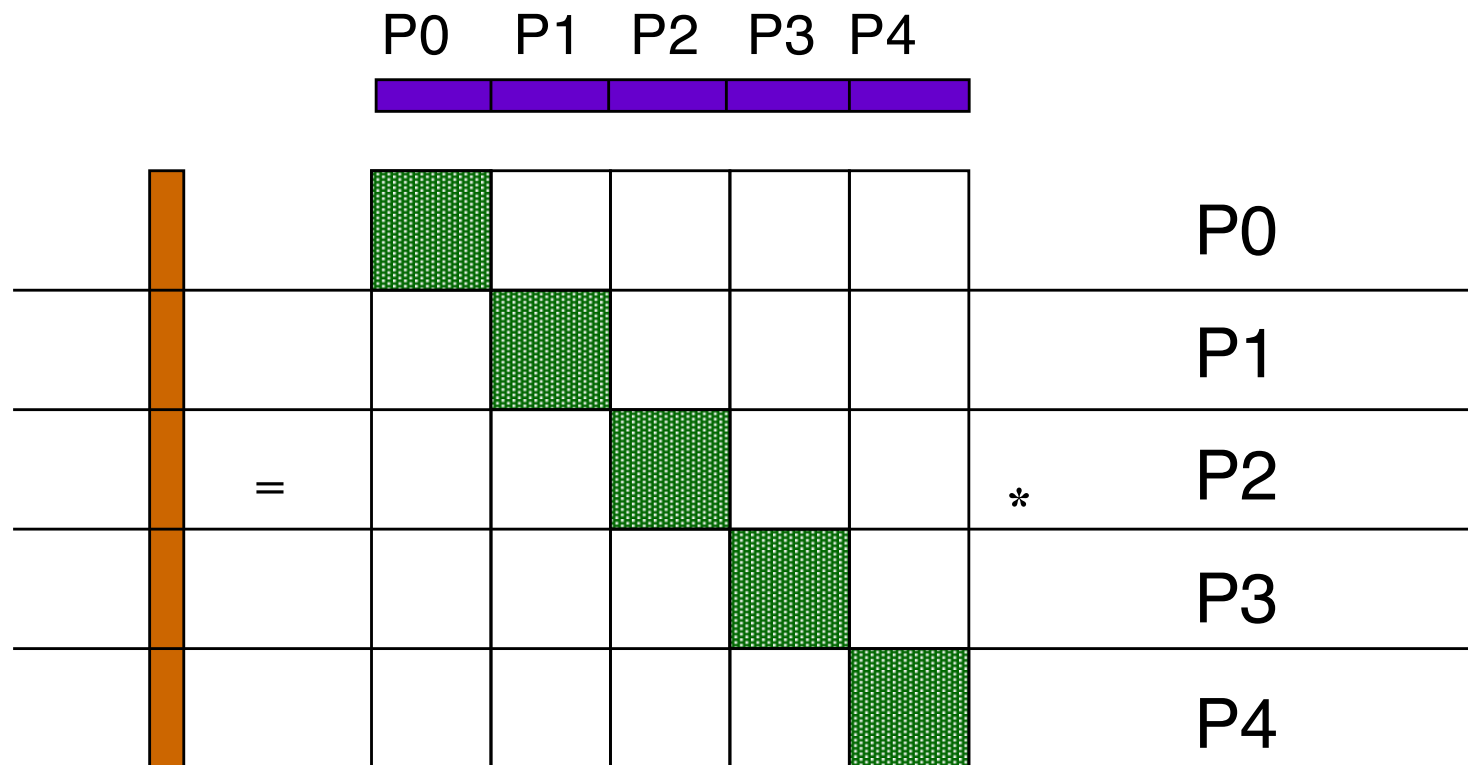
- Partitioning

- Partition index set $\{1, \dots, n\} = N1 \cup N2 \cup \dots \cup Np$.
- For all i in Nk , Processor k stores $y[i]$, $x[i]$, and row i of A
- For all i in Nk , Processor k computes $y[i] = (\text{row } i \text{ of } A) * x$
 - “owner computes” rule: Processor k computes the $y[i]$ s it owns.

May require communication

Matrix Reordering via Graph Partitioning

- “Ideal” matrix structure for parallelism: block diagonal
 - p (number of processors) blocks, can all be computed locally.
 - If no non-zeros outside these blocks, no communication needed
- Can we reorder the rows/columns to get close to this?
 - Most nonzeros in diagonal blocks, few outside



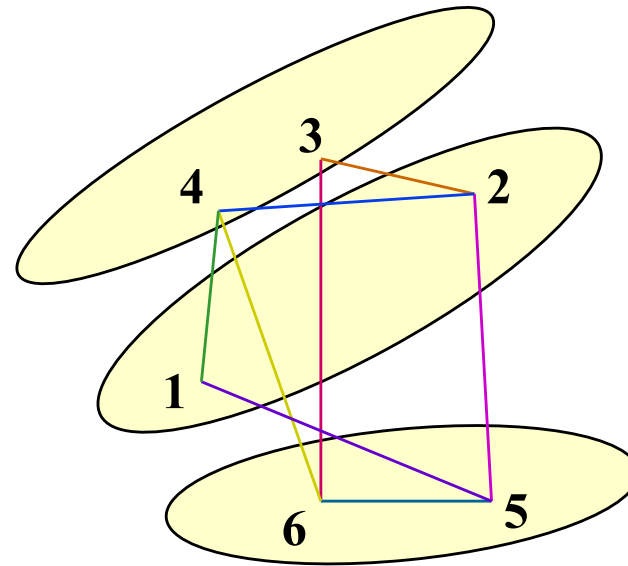
Goals of Reordering

- Performance goals
 - balance load (how is load measured?).
 - Approx equal number of nonzeros (not necessarily rows)
 - balance storage (how much does each processor store?).
 - Approx equal number of nonzeros
 - minimize communication (how much is communicated?).
 - Minimize nonzeros outside diagonal blocks
 - Related optimization criterion is to move nonzeros near diagonal
 - improve register and cache re-use
 - Group nonzeros in small vertical blocks so source (x) elements loaded into cache or registers may be reused (temporal locality)
 - Group nonzeros in small horizontal blocks so nearby source (x) elements in the cache may be used (spatial locality)
- Other algorithms reorder rows/columns for other reasons
 - Reduce # nonzeros in matrix after Gaussian elimination
 - Improve numerical stability

Graph Partitioning and Sparse Matrices

- Relationship between matrix and graph

| | 1 | 2 | 3 | 4 | 5 | 6 |
|---|---|---|---|---|---|---|
| 1 | 1 | | | 1 | 1 | |
| 2 | | 1 | 1 | 1 | 1 | |
| 3 | | | 1 | | | 1 |
| 4 | 1 | 1 | | 1 | | 1 |
| 5 | 1 | 1 | | | 1 | 1 |
| 6 | | | 1 | 1 | 1 | 1 |



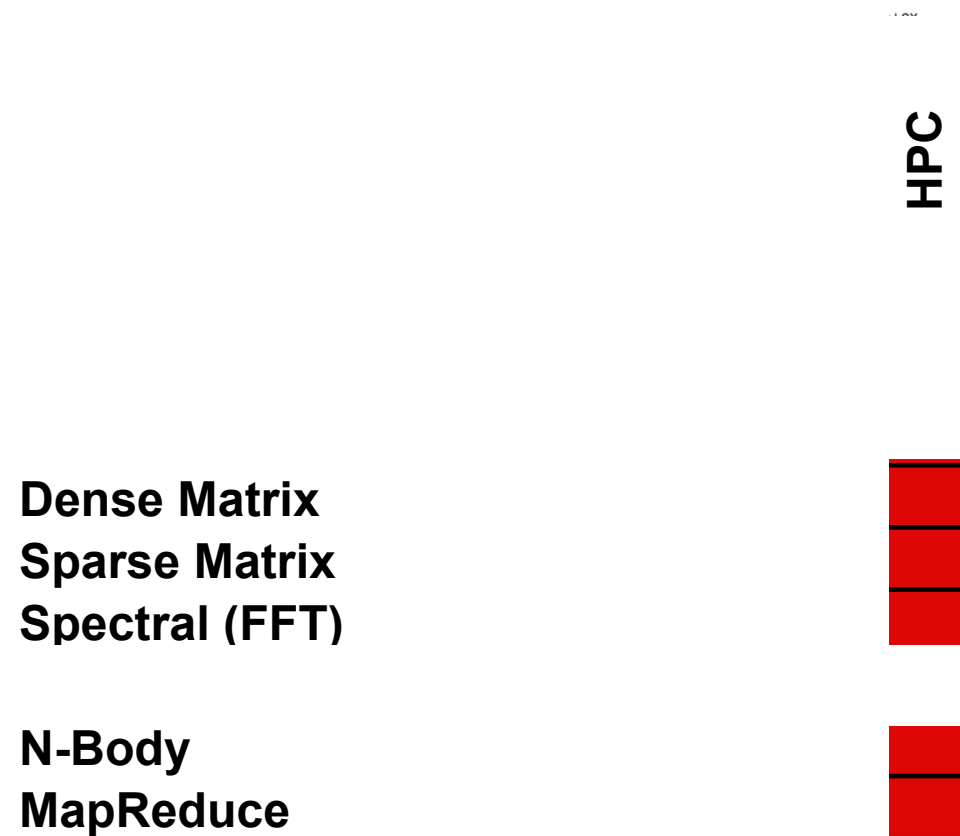
- Edges in the graph are nonzero in the matrix: here the matrix is symmetric (edges are unordered) and weights are equal (1)
- If divided over 3 procs, there are 14 nonzeros outside the diagonal blocks, which represent the 7 (bidirectional) edges

Summary: Common Problems

- Load Balancing
 - Statically - Graph partitioning
 - Discrete event simulation
 - Sparse matrix vector multiplication
 - Dynamically – if load changes significantly during job
- Linear algebra
 - Solving linear systems (sparse and dense)
 - Eigenvalue problems will use similar techniques
- Fast Particle Methods
 - $O(n \log n)$ instead of $O(n^2)$

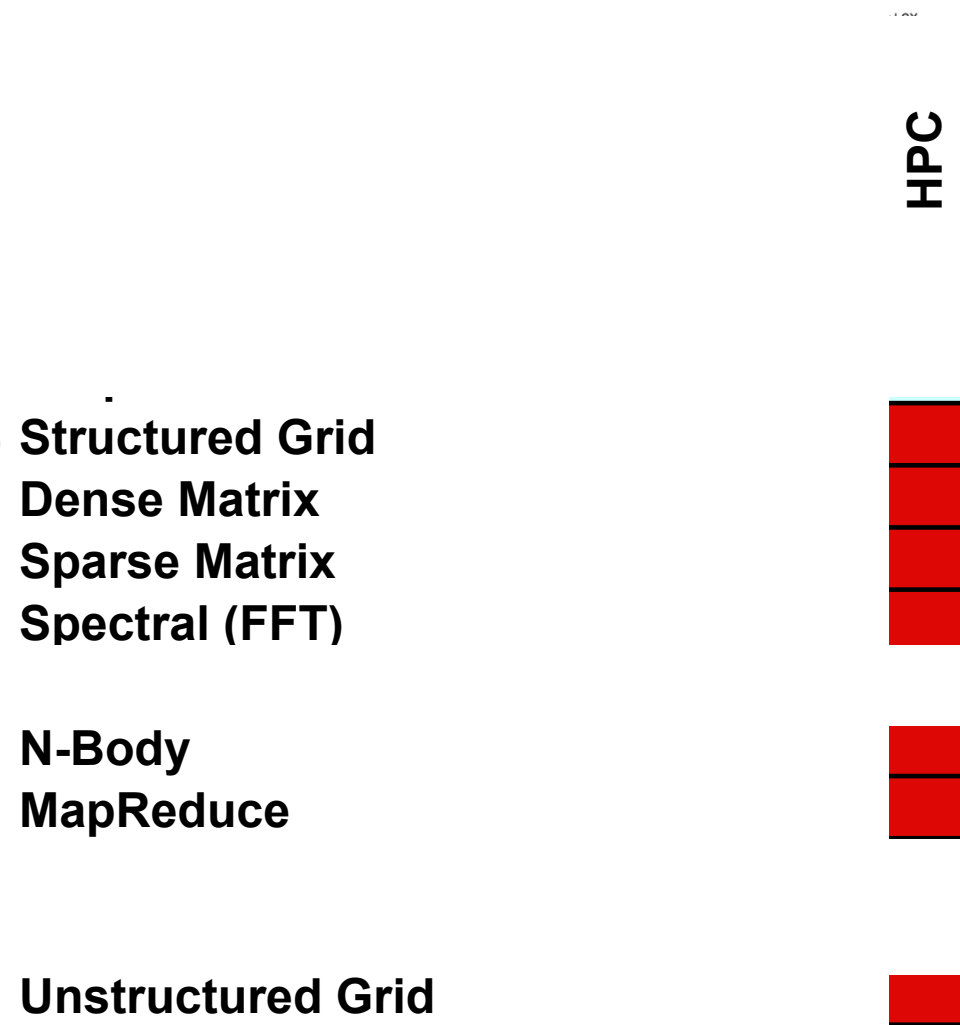
What do commercial and CSE applications have in common?

Motif/Dwarf: Common Computational Methods



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What do commercial and CSE applications have in common?

Motif/Dwarf: Common Computational Methods

| | Embed | SPEC | DB | Games | ML | HPC |
|-------------------|-------|------|----|-------|----|-----|
| Structured Grid | | | | | | |
| Dense Matrix | | | | | | |
| Sparse Matrix | | | | | | |
| Spectral (FFT) | | | | | | |
| N-Body | | | | | | |
| MapReduce | | | | | | |
| Unstructured Grid | | | | | | |

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Motif/Dwarf: Common Computational Methods

| | Embed | SPEC | DB | Games | ML | HPC |
|----------------------|-------|------|----|-------|----|-----|
| 1 Finite State Mach. | | | | | | |
| 2 Combinational | | | | | | |
| 3 Graph Traversal | | | | | | |
| 4 Structured Grid | | | | | | |
| 5 Dense Matrix | | | | | | |
| 6 Sparse Matrix | | | | | | |
| 7 Spectral (FFT) | | | | | | |
| 8 Dynamic Prog | | | | | | |
| 9 N-Body | | | | | | |
| 10 MapReduce | | | | | | |
| 11 Backtrack/ B&B | | | | | | |
| 12 Graphical Models | | | | | | |
| 13 Unstructured Grid | | | | | | |

What do commercial and CSE applications have in common?

Motif/Dwarf: Common Computational Methods

(Red Hot → Blue Cool)

| | Embed | SPEC | DB | Games | ML | HPC |
|----------------------|------------|------------|------------|------------|------------|------------|
| 1 Finite State Mach. | Red | Red | Red | Yellow | Yellow | Light Blue |
| 2 Combinational | Red | Light Blue | Green | Light Blue | Green | Light Blue |
| 3 Graph Traversal | Red | Yellow | Yellow | Yellow | Red | Light Blue |
| 4 Structured Grid | Red | Red | Light Blue | Yellow | Light Blue | Red |
| 5 Dense Matrix | Red | Red | Yellow | Red | Red | Red |
| 6 Sparse Matrix | Yellow | Yellow | Light Blue | Red | Red | Red |
| 7 Spectral (FFT) | Yellow | Light Blue | Light Blue | Yellow | Yellow | Red |
| 8 Dynamic Prog | Yellow | Light Blue | Red | Light Blue | Red | Light Blue |
| 9 N-Body | Light Blue | Yellow | Light Blue | Yellow | Light Blue | Red |
| 10 MapReduce | Light Blue | Green | Red | Light Blue | Red | Red |
| 11 Backtrack/ B&B | Light Blue | Light Blue | Yellow | Light Blue | Red | Light Blue |
| 12 Graphical Models | Light Blue | Light Blue | Yellow | Light Blue | Red | Light Blue |
| 13 Unstructured Grid | Light Blue | Light Blue | Light Blue | Yellow | Yellow | Red |