

Technische Universität München

## Assignment 3: MPI Point-to-Point and One-Sided Communication

Programming of Super Computers

Friedrich Menhorn, Benjamin R  th, Erik Wannerberg  
Team 12

December 12, 2015



# Contents

## 1. Provided Implementation and Baseline

- 1.1 Cannon's algorithm
- 1.2 Baseline
- 1.3 Scalability

## 2. MPI Point-to-Point Communication

- 2.1 MPI Non-Blocking Operations
- 2.2 Optimizations
- 2.3 Scaling

## 3. MPI One-Sided Communication

- 3.1 MPI One-Sided Operations
- 3.2 Optimizations
- 3.3 Scaling

## 1. Provided Implementation and Baseline

- 1.1 Cannon's algorithm
- 1.2 Baseline
- 1.3 Scalability

## 2. MPI Point-to-Point Communication

- 2.1 MPI Non-Blocking Operations
- 2.2 Optimizations
- 2.3 Scaling

## 3. MPI One-Sided Communication

- 3.1 MPI One-Sided Operations
- 3.2 Optimizations
- 3.3 Scaling

# Cannon's algorithm

- explain algorithm
- provided implementation

# Baseline

Challenges in getting an accurate baseline and changes to the Load-Leveler batch script.

# Scalability

- Compute time scalability with fixed 64 processes and varying size of input files.
- MPI time scalability with fixed 64 processes and varying size of input files.
- Differences in scalability between the Sandy Bridge and Haswell architectures.

### 1. Provided Implementation and Baseline

- 1.1 Cannon's algorithm
- 1.2 Baseline
- 1.3 Scalability

### 2. MPI Point-to-Point Communication

- 2.1 MPI Non-Blocking Operations
- 2.2 Optimizations
- 2.3 Scaling

### 3. MPI One-Sided Communication

- 3.1 MPI One-Sided Operations
- 3.2 Optimizations
- 3.3 Scaling

# MPI Non-Blocking Operations

- Send/Receive
  - **MPI\_Isend**
  - **MPI\_Irecv**
- Synchronization
  - **MPI\_Wait**
  - **MPI\_Probe**



## Optimizations

- **What is overlap?**

We do not wait for either task to be completed, but try to do communication and computation at the same time. We are hiding communication time by doing computation in the meantime.

- **What is the theoretical maximum overlap that can be achieved?**

Bounds for pure communication time:

$$\max \left( 0, T_{\text{MPI}}^{\text{blocking}} - T_{\text{computation}} \right) \leq T_{\text{MPI}}^{\text{non-blocking}} \leq T_{\text{MPI}}^{\text{blocking}}$$

Overheads:

- Copying into and from buffers
- Initialization

Maximum overlap depends on amount of  $T_{\text{computation}}$ . As soon as  $T_{\text{computation}} > T_{\text{MPI}}^{\text{blocking}}$ , we can theoretically achieve 100% overlap.

## Optimizations (cond.)

- **Was communication and computation overlap achieved?**

# Scaling

- Was a speedup observed versus the baseline?
- Were there any differences between Sandy Bridge and Haswell nodes?

## 1. Provided Implementation and Baseline

- 1.1 Cannon's algorithm
- 1.2 Baseline
- 1.3 Scalability

## 2. MPI Point-to-Point Communication

- 2.1 MPI Non-Blocking Operations
- 2.2 Optimizations
- 2.3 Scaling

## 3. MPI One-Sided Communication

- 3.1 MPI One-Sided Operations
- 3.2 Optimizations
- 3.3 Scaling

# MPI One-Sided Operations

- Initialization
  - **MPI.Win.create**
  - **MPI.Win.free**
- Remote Memory Access
  - **MPI.Put**
  - MPI.Get
  - MPI.Accumulate
- Synchronization
  - **MPI.Win.fence**
  - MPI.Win.post / MPI.Win.start / MPI.Win.complete / MPI.Win.wait
  - MPI.Win.lock / MPI.Win.unlock

# Optimizations

- Was communication and computation overlap achieved?

## Scaling

- Was a speedup observed versus the baseline?
- Was a speedup observed versus the non-blocking version?
- Were there any differences between Sandy Bridge and Haswell nodes?