

# Hardware Implementations of Evolvable Systems

## A critical analysis of autonomic systems with self-properties on reconfigurable architectures

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November 5, 2013

### Abstract

Reconfigurable hardware is becoming increasingly more important in SoC design as it allows efficient hardware acceleration and virtually unlimited adaptability. With the increase of complex, heterogeneous, multi-core and many-core processors system complexity is skyrocketing. This increase in size and complexity of systems introduces the need for autonomous systems that are capable of self-adapting and self-optimization. Self-aware adaptive computing systems are capable of adapting their behavior in dynamic environments at run-time to accomplish given goals. Combining these capabilities with reconfigurable hardware allows for self-adapting and self-optimization at run-time. The increasing presence of heterogeneous architectures such as FPGAs that utilize these techniques make the hardware domain shift more and more into the software domain.

In this paper we will propose a co-designed hardware implementation of evolvable systems that blends the power of flexible software techniques such as monitoring, decision making and self-adaptation with the speed of hardware. The proposed system is composed of a 2D systolic array of processing elements and utilizes partial dynamic reconfiguration in combination with self-properties techniques.

*Keywords:* self-aware , computing systems, reconfigurable, autonomic, evolvable

## 1 Introduction

In the past few years, the term *evolvable hardware* (EHW) has arisen. A lot of research has been done in this new field of electronics, which utilizes *evolutionary algorithms* (EA) and *self-adaptive techniques* in order to eliminate manual engineering. Reconfigurable hardware, artificial intelligence, fault tolerance and autonomous systems are brought together, enabling the system to change its architecture and behaviour dynamically and autonomously based on its internal state and its environment. By defining a specific goal or task, the system is programmed to evolve in real-time towards an implementation. It continues research on self-aware

systems, machine learning and is often linked to bio-inspired hardware systems.

This paper will introduce several proposed architectures for hardware implementation of evolvable systems in Section 3. Section 4 will then present the techniques that are used in order to accomplish these implementations. Section 5 proposes the system design that is in our opinion the best hardware implementation possible given the current techniques. This design will be critically analyzed using the proposed designs presented in the discussed papers in Section 6. Finally, our literature study will be wrapped up by a conclusion in Section 7.

## 2 Fundamental knowledge

In this section an introduction to the fundamental terms used in this paper is given. These terms concern prior knowledge required when working with autonomic or evolvable systems and their implementations in hardware.

Computing system containing *self-properties* are capable of adapting their behavior and resources thousands of times based on changing environmental conditions and demands [5]. This allows them to automatically accomplish their goals in the best way possible. This behavior is achieved through *self-monitoring* which recognizes changes in its internal state that may require a modification, called *self-adjusting*. *Self-healing* concerns effective recovery under fault condition, *self-optimization* invokes optimizing operation in proactive and reactive manners and *self-configuring* concerns automatically installing, configuring and integrating new components seamlessly into the system to meet stated goals [?].

*Evolvable systems* exploit self-adaptive, self-configuring and self-optimizing techniques and are capable of changing their operations to meet the given performance goals by modifying either the underlying heterogeneous architecture, the operating system and the self-adaptive applications. [4]

*Autonomic systems* are inspired by the human body's nervous system and contains all self-properties: *self-managing*, *self-protecting*, *self-healing* and *self-optimizing* [8].

Autonomic and evolvable systems have the need for heterogeneous underlying architectures, which can be provided by using Field Programmable Gate Arrays (FPGAs). These can be configured to fulfill a desired functionality by using one or more bitstreams. These bitstreams are binary files in which FPGA specific configuration information is stored and these are to be copied along with the proper commands on to the configuration SRAM cells, or the configuration memory [9].

## 3 Discussion of the Different Papers

Considerable research has already been done in order to efficiently accelerate hardware while still maintaining virtually unlimited adaptability. Soft-

ware techniques in autonomic computing systems such as hot-swapping and data clustering are discussed in [1]. [5] proposes a self-aware system able to adapt its behavior of FPGA-based systems. Other approaches start with a FPGA-based architecture with a reconfigurable core [2], added programming schemes and new cell structures [3], [6] or even bio-inspired hardware using the POE-model [7]. More recent papers put effort in a combined approach by either implementing autonomic systems on reconfigurable architectures [9] or creating evolvable systems via self-aware applications [4]. In this section software based designs, hardware based designs are co-designs are discussed.

### 3.1 Software based flexible approaches

The *Heartbeats application* is a monitoring application which makes it possible to assert performance goals as heart-rate windows delimited by a minimum and maximum performance, or *heart-rate* [4]. The Heartbeats API is made of small straightforward functions and allows declaring performance goals. Software components first have to register, specifying parameters such as minimum and maximum heart-rate, size of the windows of observation and history buffers [5]. The application then updates the progress of the execution calling the function that signifies a heartbeat [4].

[9] discusses using adaptive programming in situations where input changes lead to relatively small output changes. They present a hardware/software codesign paradigm that develops a new performance model and associated evaluation metrics to differentiate between various levels of performance across different portions of software modules. Incorporating this into a codesign environment increases the flexibility of the system.

### 3.2 Hardware based fast approaches

FPGAs are a commonly used device for implementing the reconfigurable architecture of evolvable systems, especially Virtex FPGAs produced by Xilinx. Unfortunately, these devices have some drawbacks. The Erlangen Slot Machine from [6] tackles the three major limitations of the Virtex-II FPGA. A pipelined data flow architecture has been used, replacing the finite state machine by a MicroBlaze mi-

crocontroller and employing a data crossbar between plug-ins. Providing a new architecture to avoid the current physical problems of reconfigurable FPGAs, a new inter-module communication concept, as well as an intelligent module reconfiguration management has made the ESM an alternative for the Virtex FPGAs.

In [3] and [2] a Virtex-4 FPGA implementation is introduced for evolvable systems. Other than earlier versions of Virtex (e.g. the Virtex-II Pro), Virtex4 devices enable two-dimensional dynamic reconfiguration, a feature which considerably reduces the reconfiguration time and thus the evolution time ([3]). A big limitation of Virtex FPGAs is an almost unknown and undocumented bitstream data format and a unsafe configurations schema. By using both VRCs (Virtual Reconfigurable Circuits) and direct bitstream manipulation, this architecture eliminates this limitation. This Virtex-4 based device, which takes advantage of 2D reconfiguration capabilities and direct manipulation of the bitstreams is the first one of its kind and will be discussed later.

A second Virtex-4 based architecture introduced in [2] also applies a 2D reconfiguration core. Rather than direct bitstream manipulation, an optimized Dynamically and Partially Reconfiguration (DPR) control engine has been integrated. As a result, the processing elements (PEs) of the reconfigurable core are structured as a 2D systolic array, known for its high performance and restrained use of resources. Also, the reconfiguration engine has been optimized by applying three enhancements that will be discussed in 4.3.3.

### 3.3 Co-design based systems

In [9] the importance of hardware/software co-design during design space exploration is urged on. Right now this co-design emphasizes on identifying intensive kernel tasks and implementing these tasks on the reconfigurable hardware. Existing adaptive systems often fail because of they are largely ad hoc and fail to incorporate true goals. The current performance model of the hardware however, depends on the degree of parallelism while the performance model for software execution is static and does not become affected by external factors. Since the introduction of reconfigurable hardware platforms such as FPGAs, the hardware domain shifted into the software domain: the possibility of implementing a

reconfigurable architecture increased the flexibility of the hardware.

Partial dynamic reconfiguration is a key feature that makes FPGAs unique. This addresses the lack of resources to implement an application and its adaptability needs. Reconfigurable hardware taking advantage of partial dynamic reconfiguration is the perfect trade-off between the speed of HW and the flexibility of SW. Other aspects that motivate the use of online self-adaptable systems are the QoS and the reliability and continuity of the service.

However, an important problem often neglected is the time overhead the reconfiguration process introduces and the two-dimensional partitioning strategy reconfigurable devices need: spatial and temporal. [9] presents the urge to carefully evaluate the overhead created as a negative impact of reconfiguration latency which is not always discussed in present papers. In [4] an evolvable system running self-adaptive application on top of a heterogeneous systems is proposed. The operating system running on top is responsible for providing the self-\* properties and runs this on a general purpose processor and a reconfigurable device

In [4], the underlying hardware architecture is made up of static area and a dynamic area. The reconfigurable device can be configured to implement different functionality through dynamic reconfiguration support provided by the operating system. This is provided through standard libraries and the OS implements parts of the loop. The OS is therefore capable of choosing at run-time the best implementation for the required functionality among the available. The switchable units in the hot-swap method in [4] are identified as the libraries that export an implementation of a certain functionality. The self-adaptive library or Dynamic-link library (DLL) and the software implementation library target the reconfigurable FPGA and multicore respectively.

## 4 Analysis of techniques

This section provides an overview of techniques that are used in current research to create evolvable hardware implementations of evolvable systems. To create such a system, the system has to be self-aware, able to make decisions, self-adapting and the hardware has to support a certain amount of recon-

figuration. In section 5 the overall best combination will be presented, utilizing the flexibility of software and the speed of hardware.

## 4.1 Monitoring techniques

A system is self-aware when it is constantly aware of its internal state. This is the first step towards an autonomic system. Autonomic systems are build up of autonomic elements that include sensors in order to monitor its behavior. A system is self-monitoring when it has knowledge of its available resources, its components, the desired performance characteristics, the current status and the status of the inter-connections with other systems [8]. The knowledge obtained from monitoring is utilized in *closed-control loops* such as the *observe-decide-act (ODA) loop*. Given certain performance goals these loops *observe* the current state, decide upon an action and perform these actions as will be discussed in section 4.2 and 4.3.

The heartbeats application as discussed in section [?] is a technique used for monitoring. A framework like this is particularly convenient because it allows to automatically update all information about the global heart-rate which is then made available to external observers, such as decision making applications. However it introduces an average overhead of 3,52% due to system calls in order to initialize its data structures and updating the global heart rate [5].

## 4.2 Decision making techniques

For a self-adaptive system the intelligence in using the monitoring data is equally important to collecting the data. Results from the monitoring framework are fed to a decision making application. Decision making all depends on the input and constraints given to the system and the expected *Quality-of-Service (QoS)*, which can also concern a sufficiently good performance decision making policy that respects the user's performance goals [4]. Closed-control loops are implemented by the operating system reciding on the reconfigurable hardware. By using dynamic self-adaptive libraries, the operating system can choose at runtime which is the best suiting implementation for the required functionality among the available [4].

A desicioning framework can be divided into 2 categories: analytical models and empirical models [4]. The analytical models are good when working in the same environment as they are manually generated and are very precise because of this prior knowledge. However when considering evolvable systems in dynamic environments, empirical models are favourable as they exploit information collected at run-time, but are in turn less accurate. Current trends in supporting decision making are using heuristic policies, machine learning, control theory and competitive algorithms. Heuristics is the application of experience-derived knowledge to a problem. Heuristic software can be easily developed, applied and reused when working within a known environment including static condition. However within the context of a dynamic live application with changing environments, it is very easy to miss unforeseen problems using software that looks for known problems.

## 4.3 Self-adapting techniques

A self-aware adaptive computing system is an active system where the hardware, the applications and the operating system have to be seen as an unique entity that can autonomously adapt itself to achieve the best performance. [5] presents a general overview of the hardware and software architecture components of a self-aware computing system as can be seen in figure 1. Cognitive hardware mechanisms available in the underlying hardware *observe* and *affect* the execution. A limited amount of scenarios can be pre-configured, but the learning and decision engines are needed to determine the appropriate actions based on the observations.

A fundamental part of a self-aware adaptive computing system is the ability to switch between implementations of the same functionality while the system is running. A control system has to be developed as an actuator in the observe-decide-act loop. The *hot-swap mechanism* is a popular tool to implement self-configuration and self-optimization. It provides the ability of switching among different implementations of the same functionality in a transparent fashion. However state quiescence and state translation are two big issues when using this mechanism and need a framework solution to be reliable. [?] presents a three phase hot-swap

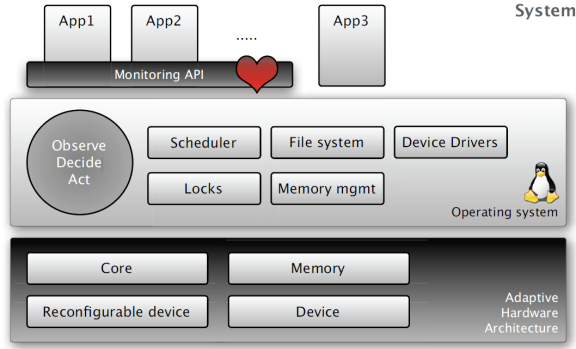


Figure 1: Overview of the proposed self-aware adaptive FPGA-based computing system presented in [5]

that includes a transfer phase in which new requests are blocked to reach a quiescent state to solve this. This approach is solely based on data structures to decouple the data from the implementations.

Other works present *Partial Dynamic Reconfiguration (PDR)* [9] to reduce the amount of overhead introduced by reconfiguration. Hardware portions can adapt over time to cope with new requirements creating an adaptive system. If the application can be partitioned into different phases, PDR can configure the modules one after another to keep area requirements lower than having all functionalities loaded at the same time. PDR can be seen as a trade-off between the speed of hardware and the flexibility of software.

#### 4.3.1 Virtex FPGA with a Two-Dimensional Reconfiguration Core

On Virtex-4 FPGAs, two-dimensional dynamic reconfiguration like figure 2 is supported. With 2D reconfiguration it becomes possible to reconfigure device portions whose height is not constrained to be the device height. This architecture of the reconfiguration core (or RC) speeds up the reconfiguration time and thus the evolution time. The RC can also deploy more candidate solutions as discussed in [3], which are arrays of bidimensional cell (see figure 4.3.2). An alternative for candidate solutions is a mesh-type systolic array of parallel processing elements (PEs) from [2], also following a 2D architecture for the RC. A major feature is the possibility to change the functionality of the PEs by means of

Dynamic and Partial Reconfiguration (DPR). This gives the system the capability to adapt. The outputs of the PEs (east and south side) are connected to the close neighbour's input (west and north side), such that only the lowest and right-most PE has to be read for data output. This systolic approach of communication reduces the reconfiguration time and makes the architecture easy to extend.

A drawback of using Virtex FPGAs are the feed-through signals, mentioned in [6]. Each module must be implemented with all possible feed-through channels needed by other modules. Because we only know at run-time which module needs to feed through a signal, many channels reserved for a possible feed-through become redundant. Also, modules accessing external pins are no longer relocatable, because they are compiled for fixed locations where a direct signal line to these pins is established.

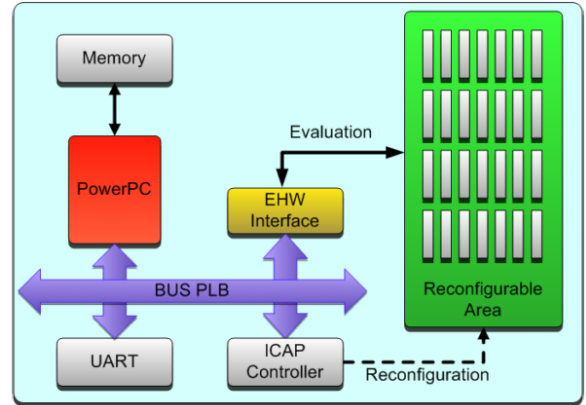


Figure 2: High-level structure of a Two-Dimensional Architecture depicted in [3]

#### 4.3.2 Candidate Solutions and Direct Bitstream Manipulation

With a 2D architecture for the RC, [3] uses safe manipulation of the bitstream to overcome the unknown and undocumented bitstream mentioned in 3.2. Candidate solutions are used to fill the RC with cells, which have an internal flip-flops allowing the evolution of synchronous circuits. This is a common structure for evolvable hardware (EHW) systems making use of direct bitstream manipulation [3]. For the cell structure of the candidate

solutions the use of LUTs and a MUX is proposed, in order to provide direct bitstream manipulation. Combined with the 2D-reconfiguration mechanism, the new architecture causes a speed up of 16x factor. For this system, only Virtex-4 or Virtex-5 FPGAs can be used since Virtex-II does not support 2D reconfiguration ([3].

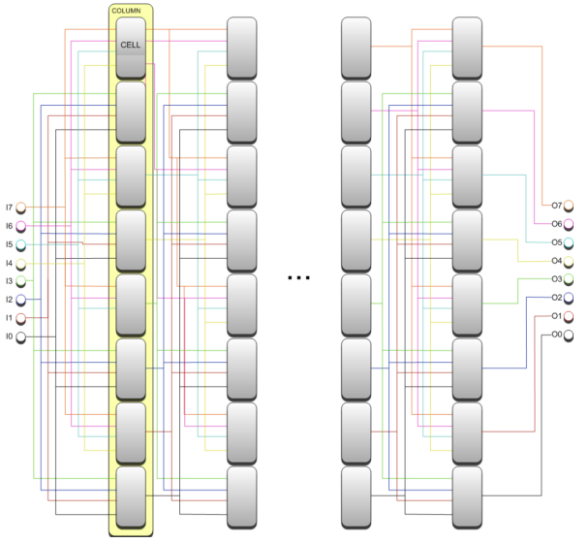


Figure 3: Internal structure of a Candidate Solution proposed in [3]

#### 4.3.3 Systolic array of PEs and Optimized DPR

Other than [3], [2] uses a systolic array of PEs. In this approach, each PE is a basic computation unit able to perform a single operation on the data take from their close neighbors. The architecture can be easily extended to any other processing purposes, since new PEs can be added to the library. In addition, PEs included in this library can be reused among applications. As can be seen in fig. 4, the size of the implemented structure is 4x4, but it can be completely and easily scaled. This DPR with elements relocation is carried out using a special HW block, the reconfiguration engine (RE).

[2] describes an implementation of this RE. By storing only the body of the bitstream (cutting of the header and the tail), overclocking the FPGA by 2,5x and including internal memory (to avoid

pasting the same configuration module in different positions of the architecture) the DPR is optimized. Due to this the reconfiguration time is greatly reduced. Adding the header and the tail of the bitstream at runtime has two additional advantages: it is allowed having a unique bitstream for each PE that can be configured in any position of the array. Also, bitstream reduction reduces the data transference time from the external memory.

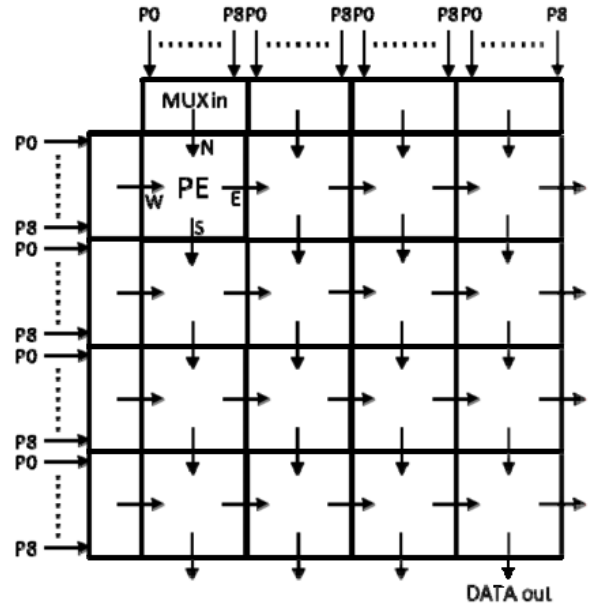


Figure 4: Systolic array of PEs introduced by [2]

#### 4.3.4 Erlangen Slot Machine

The architecture of [6] the Erlangen Slot Machine (ESM) deals with the three drawbacks of FPGAs mentioned in 4.3.1, being fixed pins which are spread around the device (I/O dilemma0, the inter-module dilemma and the local memory dilemma.

First, the I/O dilemma caused by fixed pins spread around the device is solved by connecting all bottom pins from the FPGA to an interface controller realizing a crossbar, as can be seen in figure 5. It connects FPGA pins to peripherals automatically based on the slot position of a placed module. This I/O rerouting principle is done without reconfiguration of the crossbar FPGA.

Second, the memory dilemma has been solved. In

normal Virtex-II FPGAs, a module can only occupy the memory inside its physical slot boundary. Storing data in off-chip memories is therefore the only solution. In the ESM, six SRAM banks are connected to the FPGA. Since these banks are placed at the opposite side as the crossbar, a module will connect to peripherals from one side, while the other side will be used for temporally storing computational data. In order to use a SRAM bank (called a slot), the module must have at least a width of three micro-slots, in which the total device is divided (see 5). This organization simplifies relocation, enabling a partially reconfigurable computing system. Also, equal resources will be available for each module.

Finally, the inter-module communication dilemma is dealt with. Dynamically routing signal lines on the hardware is a very difficult task. The ESM uses a combination of bus-macros, shared memory, RMB (Reconfigurable Multiple Bus) and a crossbar to take away the limiting factor for the wide use of partial dynamic reconfiguration ([6]).

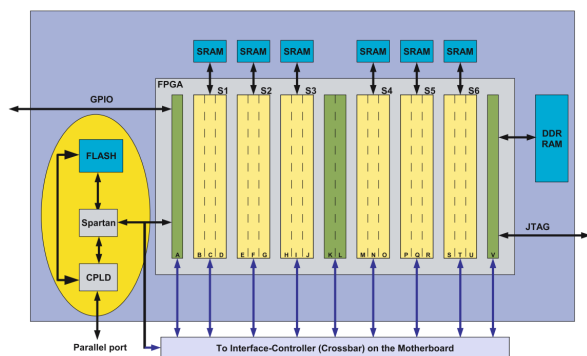


Figure 5: Architecture of the ESM board. Three consecutive micro-slots define a macro-slot, which can access one full external SRAM bank.

## 5 Proposed adaptive system design

\* set up of a proposed system \*

## 6 Related works

In [3], [2] and [6], the software used by the system to evolve certain application is called the Evolution-

ary Algorithm (EA): a generic population-based metaheuristic optimization algorithm. Candidate solutions play the role of individuals in the population. At every iteration, a new generation of candidate solution is created. For each generation, the genetic algorithm uses the current population to create the children that make up the next generation. The algorithm selects a group of individuals in the current population, called parents, who contribute their genes (the entries of their vectors) to their children. The algorithm usually selects individuals that have better fitness values as parents.

For performance experiments, [3] uses a standard testbench to prove the EHW systems effectiveness. The system is being requested to evolve a parity generator in order to report the results of the EA. A parity generator checks data to be transmitted for logic '1's. If the number is even, the parity bit is set to '1'. If the number is odd, parity bit is '0'. For executing this task, the average duration of the EA runs is 7,9 seconds for a 5-bit input number (and 76,8 seconds for an 8-bit number). A second experiment concerning the evolution of communication channels causes trouble, since the fine-grained evolution by evolving candidate solutions at low level (using direct bitstream manipulation) is not able to succeed most of the times. A third experiment involves the evolution of a counter. For a 3-bit counter, using low level evolution and six columns of cells, the average evolution time of 2,7 seconds is needed. For a 4-bit counter, however, the system failed almost every time. [add a qualitative value to the numbers of generation]

Although the ESM introduced in [6] sounds promising, the machine is a customized design that has been manufactured only in very small amounts at the University of Erlangen-Nuremberg. In order for this system to become wide-spread, all parts have to become easy to assemble for mass production. Their case study about video and audio streaming started with a data block-oriented reconfiguration manager. Unfortunately, the maximum upload speed of a bitstream to the FPGA was slowed down by factor two, due to the bottleneck of scratch pad-oriented data flow combined with the sequential execution of the instructions. When applying a pipelined data flow architecture as mentioned in 3.2, however, additional plug-ins can be added such that the bitstream can be uploaded into the FPGA at the speed of the flash interface. The article concludes

with a proposal to add another decompression plugin in order to further increase the data rate of the bitstreams from 10 MB/s to 50 MB/s, but has no further numbers to quantitatively beat the existing FPGA-based platforms. Maybe this system will have break through in a couple of years.

As for [2], evolution of image noise filters is selected as the proof of concept application. The average evolution time needed to achieve a correct result is 128 seconds, which at first seems hard to compare to the 2,7 seconds of the 3-bit counter mentioned in [3]. However, given the fact that the input image is a 256 x 256 image (with each pixel existing of 8 bits), this result is quite impressive.

## 7 Conclusion

\*Conclusion\*

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