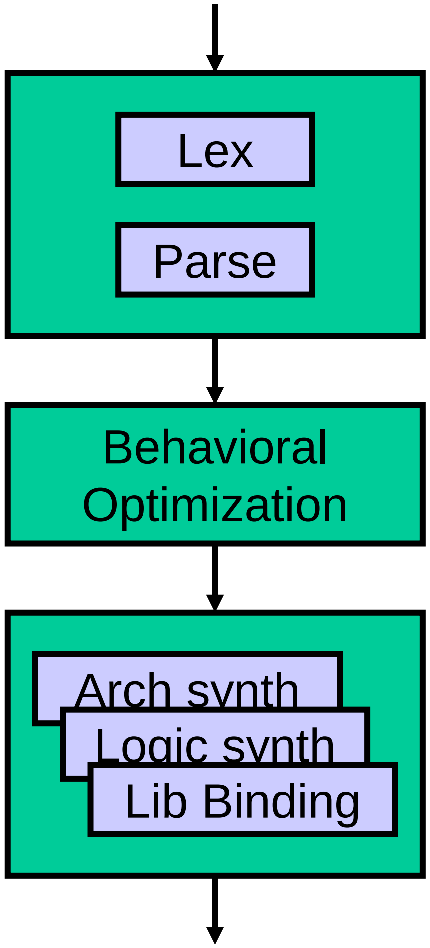
CAD for VLSI

Scheduling

High Level Synthesis (HLS)

- A process of converting high-level description of a design to a netlist
  - Input:
    - High-level languages (ex: C)
    - Behavioral hardware description languages (ex: Verilog, VHDL)
    - Structural HDLs (ex: Verilog, VHDL)
    - State diagrams & logic networks
  - Tools:
    - Parser
    - Library of modules
  - Constraints:
    - Area constraints (ex: # modules of a certain type)
    - Delay constraints (ex: set of operations should finish in λ clock cycles)
  - Output:
    - Operation scheduling (time) and binding (resource)
    - Control generation and detailed interconnections

High-Level Synthesis Compilation Flow

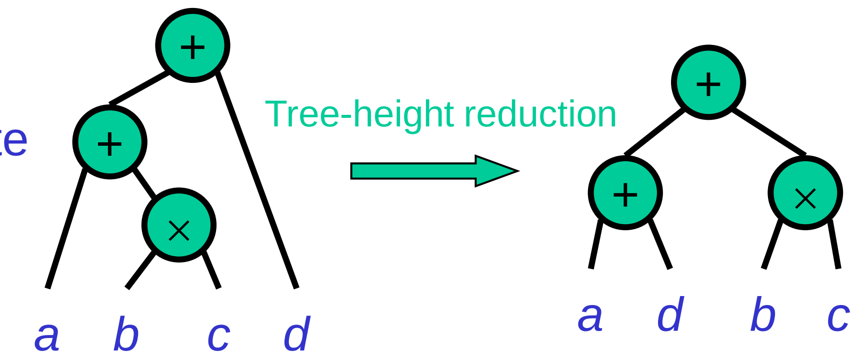


Compilation front-end

Intermediate form

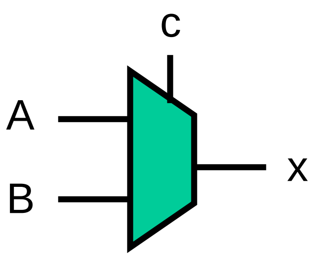
HLS backend

$x = a + b \times c + d$



Behavioral Optimization

- Techniques used in software compilation
  - Expression tree-height reduction
  - Constant and variable propagation
  - Common sub-expression elimination
  - Dead-code elimination
  - Operator strength reduction (ex: *4 → << 2)
- Typical Hardware transformations
  - Conditional expansion
    - If (c) then x=A else x=B
      ➔ compute A and B in parallel, x=(C)?A:B



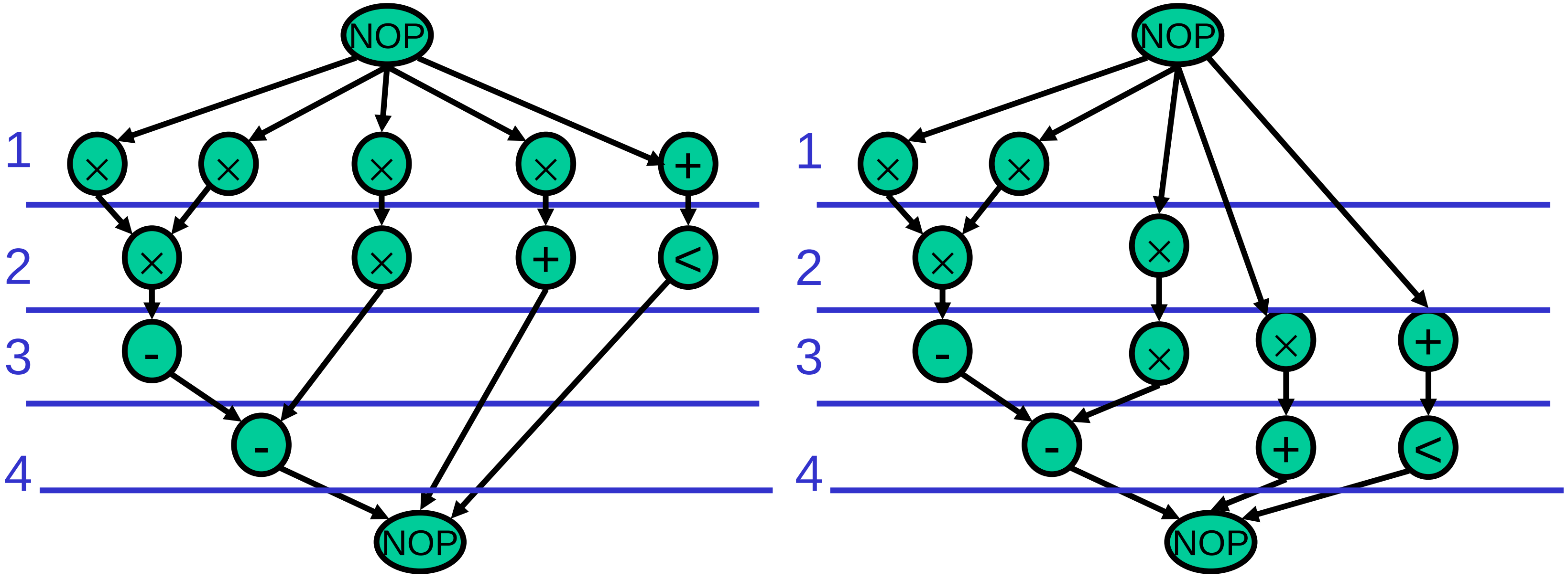
  - Loop expansion
    - Instead of three iterations of a loop, replicate the loop body three times (unrolling)

Architectural Synthesis

- Deals with "computational" behavioral descriptions
  - Behavior as sequencing graph
    (aka dependency graph, or data flow graph DFG)
  - Hardware resources as library elements
    - Pipelined or non-pipelined
    - Resource performance in terms of execution delay
  - Constraints on operation timing
  - Constraints on hardware resource availability
  - Storage as registers, data transfer using wires
- Objective
  - Generate a synchronous, single-phase clock circuit
  - Might have multiple feasible solutions (explore tradeoff)
  - Satisfy constraints, minimize objective:
    - Maximize performance subject to area constraint
    - Minimize area subject to performance constraints

Synthesis in Temporal Domain

- Scheduling and binding can be done in different orders or together
- Scheduling:
  - Mapping of operations to time slots (cycles)
  - A scheduled sequencing graph is a labeled graph

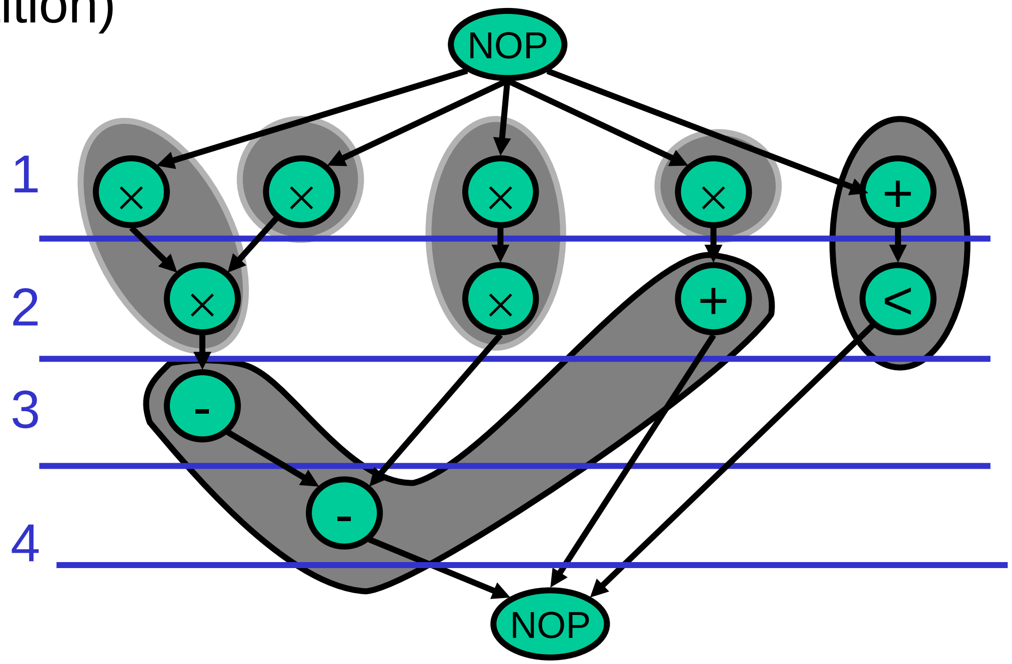


Operation Types

- For each operation, define its type
- For each resource, define a resource type and its delay (in terms of # cycles)
- T is a relation that maps an operation to a resource type that can implement it
  - $T : V \rightarrow \{1, 2, ..., n_{res}\}$.
- More general case:
  - A resource type may implement more than one operation type (ex: ALU)
- Resource binding:
  - Map each operation to a resource with the same type
  - Might have multiple options (ex: DVFS)

Synthesis in Spatial Domain

- Resource sharing
  - More than one operation is bound to same resource
  - Operations have to be serialized
  - Can be represented using hyperedges (define vertex partition)

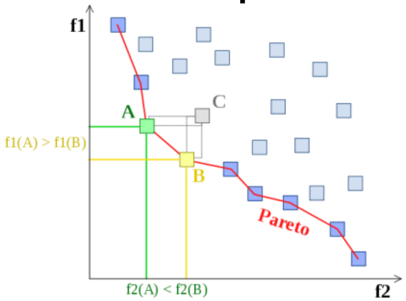


Scheduling and Binding

- Resource constraints:
  - Number of resource instances of each type $\{a_k : k=1, 2, ..., n_{res}\}$
- Scheduling:
  - Labeled vertices $\phi(v_3)=1$
- Binding:
  - Hyperedges (or vertex partitions) $\beta(v_2)=adder_1$
- Cost:
  - Number of resources ≈ area   Resource dominated
  - Registers, steering logic (mux, bus), wiring, control unit
- Delay: Control dominated
  - Start time of the "sink" node
  - Might be affected by steering logic and scheduling (control logic) – resource-dominated vs. control-dominated

Architectural Optimization

- Optimization in view of design space flexibility
- A multi-criteria optimization problem:
  - Determine schedule ϕ and binding β.
  - Under area A, latency λ, and cycle time τ objectives
- Find non-dominated points (Pareto optimality) in solution space
- Solution space tradeoff curves:
  - Non-linear, discontinuous
  - Area, latency, cycle time (more?)
- Evaluate (estimate) cost functions
- Unconstrained optimization problems for resource dominated circuits:
  - Min area: solve for minimum binding
  - Min latency: solve for minimum λ scheduling

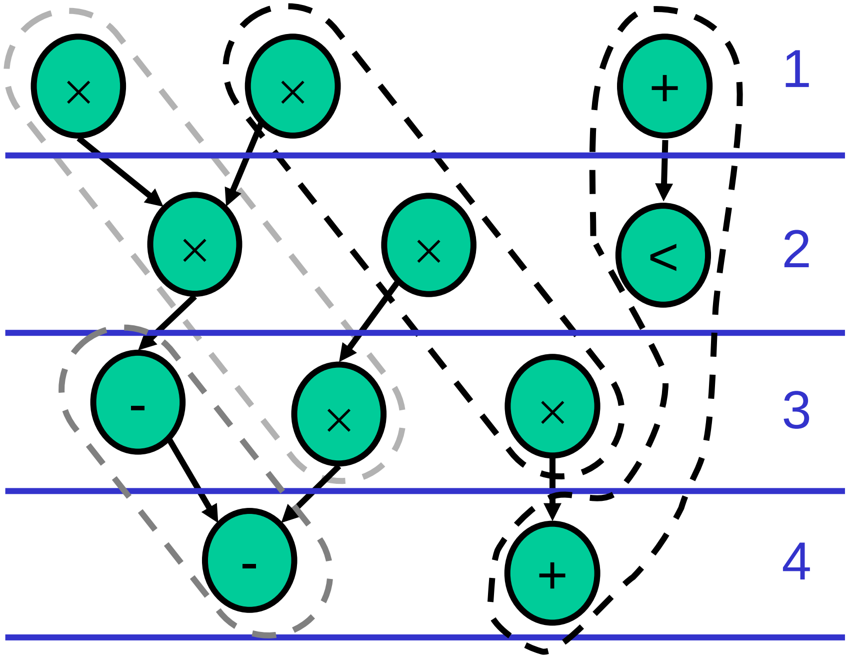


Scheduling and Binding

- Cost λ and A determined by both ϕ and β
  – Also affected by floorplan and detailed routing
- β affected by ϕ:
  – Resources cannot be shared among concurrent operations
- ϕ affected by β:
  – Resources cannot be shared among concurrent operations
  – When register and steering logic delays added to execution delays, might violate cycle time
- Order?
  – Apply either one (scheduling, binding) first

How Is the Datapath Implemented?

- Assuming the following scheduling and binding
  - Wires between modules?
  - Input selection?
  - How do binding and scheduling affect congestion?
  - How do binding and scheduling affect steering logic?



Operation Scheduling

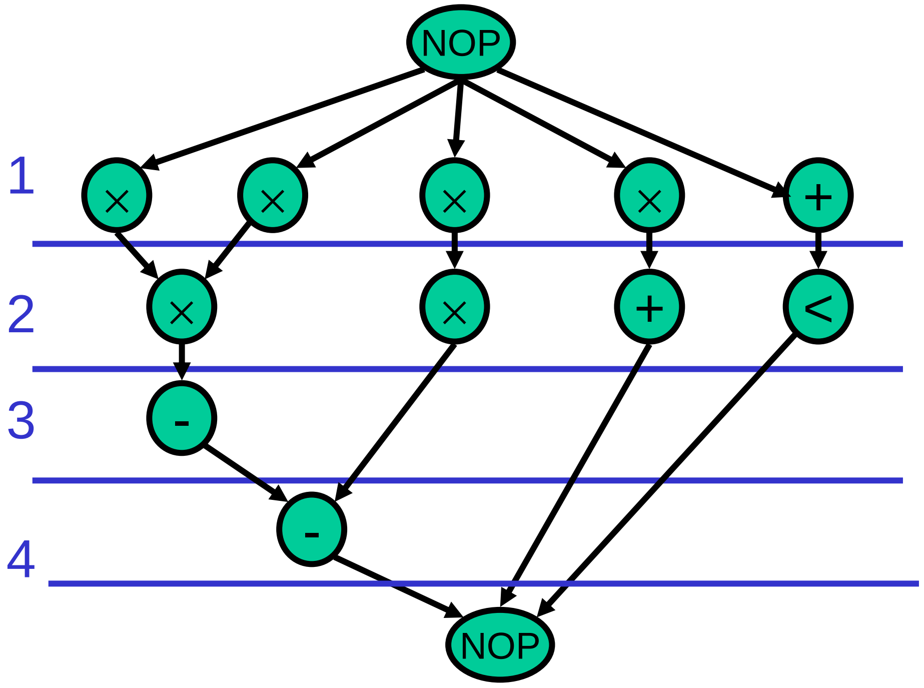
- Input:
  - Sequencing graph G(V, E), with *n* vertices
  - Operation delays $D = \{d_i : i=0..n\}$
  - Cycle time τ
    - Multi-cycle operation when $d_i > \tau$
- Output:
  - Schedule ϕ determines start time t_i of operation v_i
  - Latency $\lambda = t_n - t_0$
- Goal: determine area & latency tradeoff
- Issues:
  - Non-hierarchical and unconstrained
  - Latency constrained
  - Resource constrained
  - Hierarchical

Min Latency Unconstrained Scheduling

- Simplest case: no constraints, find minimum latency
- Given set of vertices *V*, delays *D,* and partial order $\succ$ on operations *E*, find an integer labeling of operations $\phi: V \rightarrow Z^+$, such that:
  - $t_i = \phi(v_i)$
  - $t_i \geq t_j + d_j \qquad \forall (v_j, v_i) \in E$
  - $\lambda = t_n - t_0$ is minimum
- Solvable in polynomial time
- Lower bounds on latency for resource constrained problems
- ASAP algorithm used: topological order

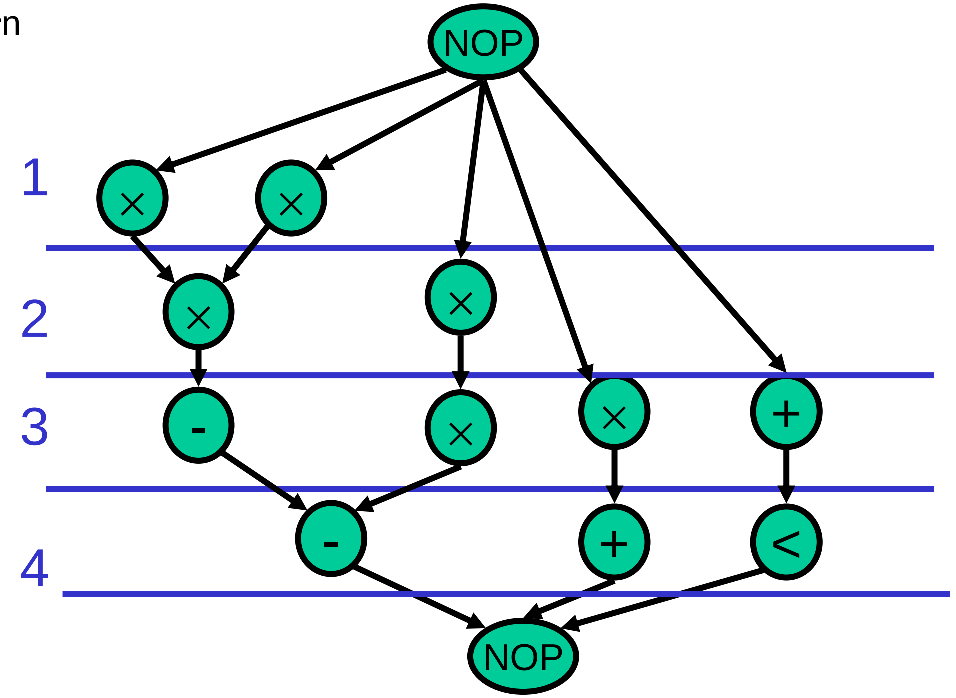
ASAP Scheduling

Schedule v_0 at t_0=0
While (v_n not scheduled)
    Select v_i with all scheduled predecessors
    Schedule v_i at $t_i = \max \{t_j+d_j\}$, v_j being a predecessor of v_i
Return t_n



ALAP Scheduling (Latency Constrained)

Schedule v_n at $t_n = \overline{\lambda} + 1$
While (v_0 not scheduled)
    Select v_i with all scheduled successors
    Schedule v_i at $t_i = \min \{t_j - d_i\}$, v_j being a successor of v_i
Return t_n

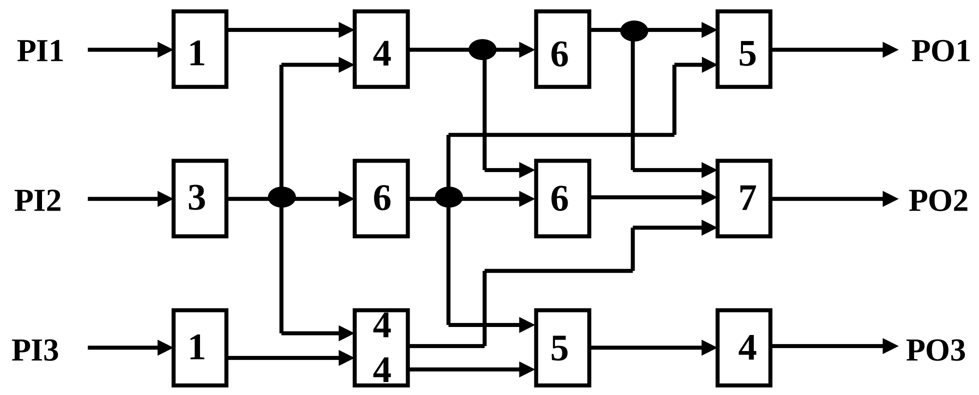


Related Terminologies

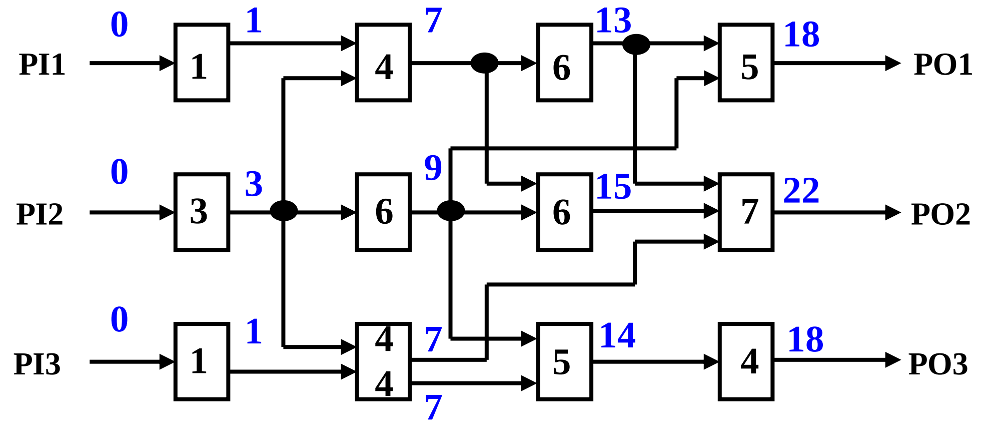
- ASAP, ALAP
  - Slack, mobility
  - Critical node, critical path
  - Criticality
- Static timing analysis
  - Arrival time
  - Required time
- Statistical static timing analysis
  - Advanced process technology: 45nm, 32nm, …

Timing Analysis

Netlist with gate delay

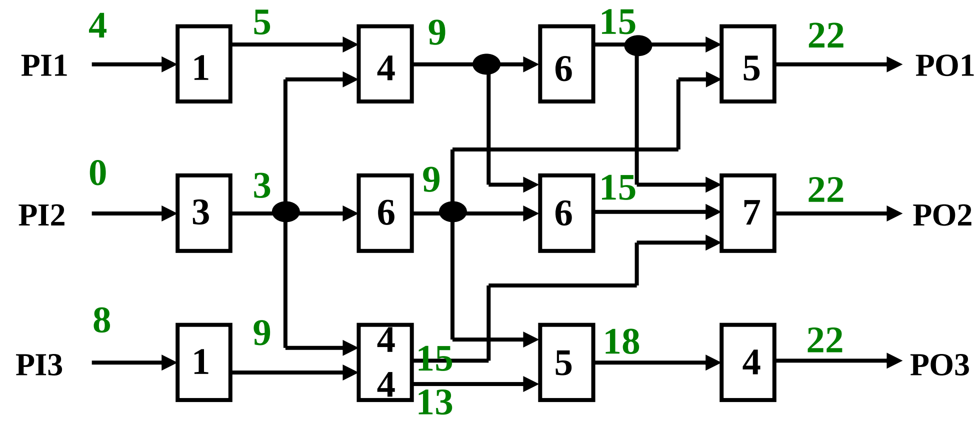


Arrival time (ASAP)

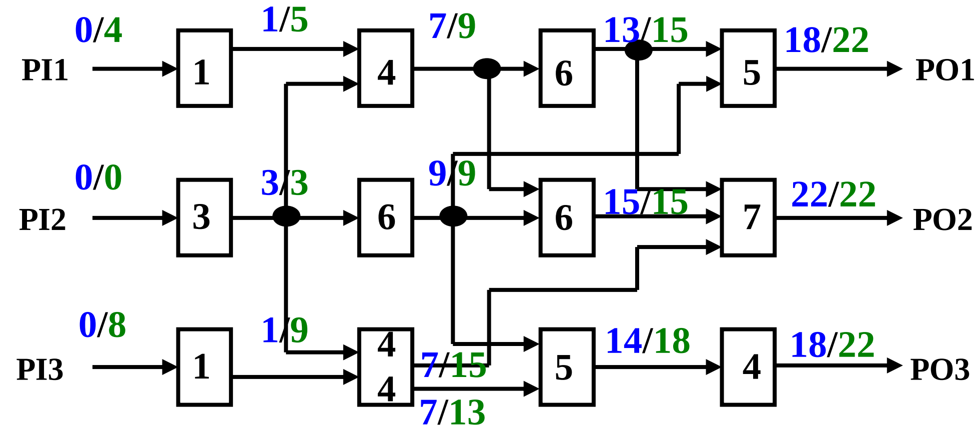


Timing Analysis

Required time (ALAP)

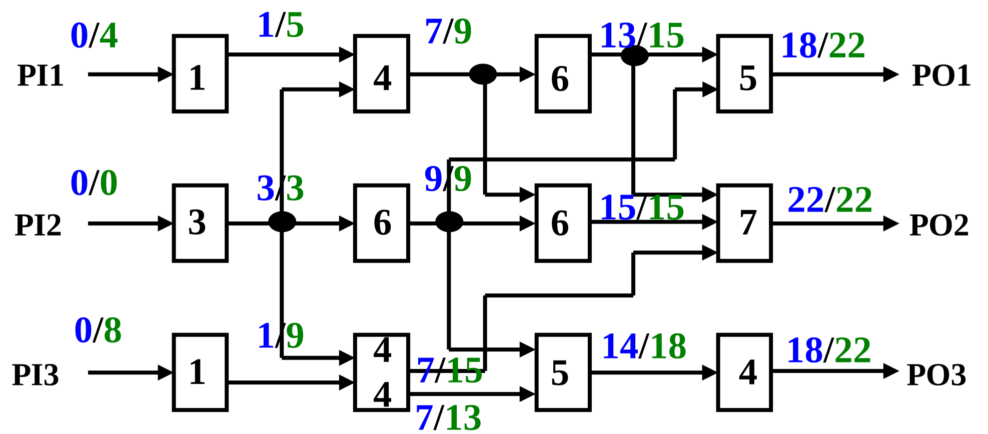


Arrival time/Required time

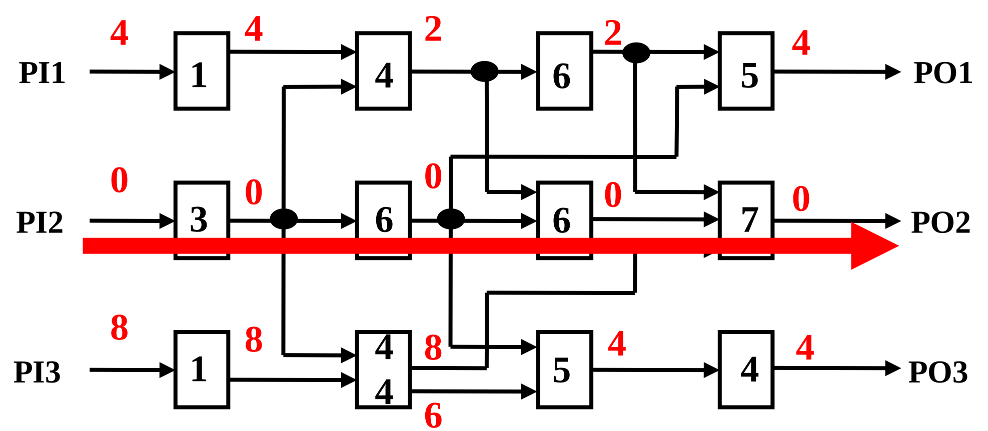


Timing Analysis

Arrival time/Required time



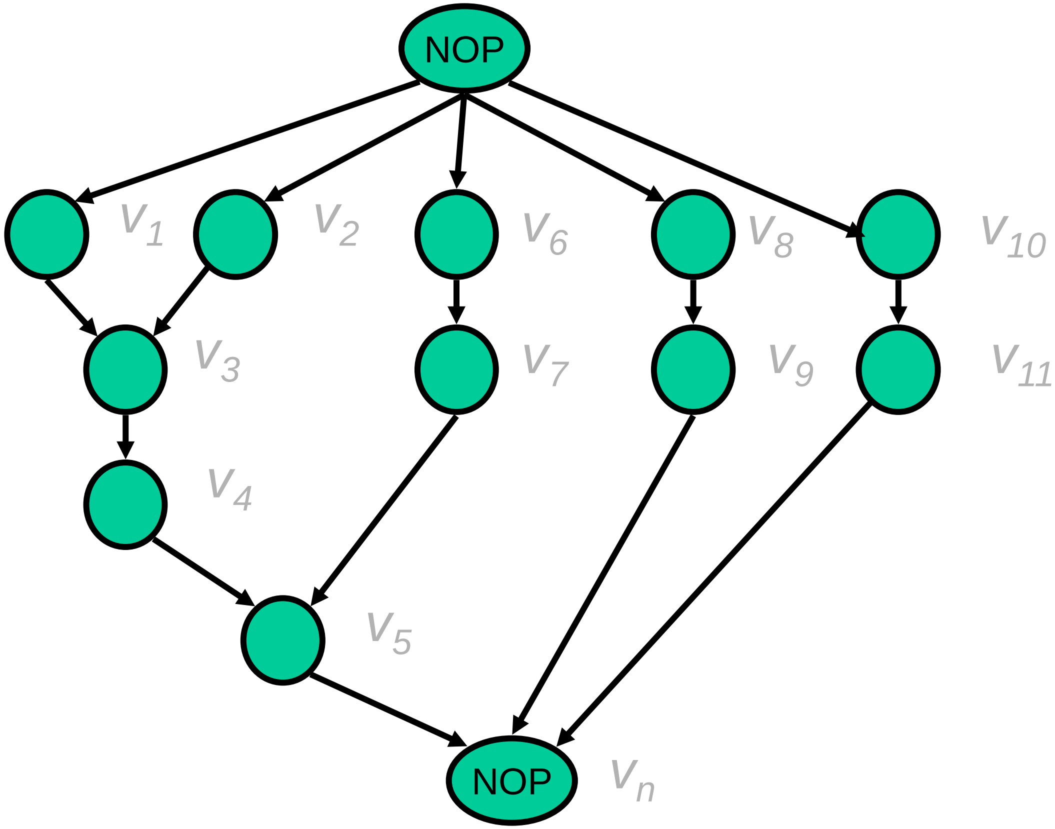
Slack (餘裕) =
Required time – Arrival time



Constrained Scheduling

- Constrained scheduling
  - General case NP-complete
  - Minimize latency given constraints on area or the resources (ML-RCS)
  - Minimize resources subject to bound on latency (MR-LCS)
- Exact solution methods
  - ILP: Integer Linear Programming
  - Hu's heuristic algorithm for identical processors (operations)
- Heuristics
  - List scheduling
  - Force-directed scheduling

Precedence-constrained Multiprocessor Scheduling



Hu's Algorithm

- Simple case of the scheduling problem
  - Operations (and resources) of the same type
  - Operations of unit delay
- Hu's algorithm
  - Greedy
  - Polynomial & optimal
  - Compute lower bound on number of resources for a given latency (MR-LCS)
    -OR-
    Compute lower bound on latency subject to resource constraints (ML-RCS)
- Basic idea:
  - Label operations based on their distances from the sink
  - Try to schedule nodes with higher labels first
    (i.e., most "critical" operations have highest priority)

Hu's Algorithm

HU (G(V,E), a) {

    Label the vertices   // label = length of longest path passing through the vertex

    $l = 1$

    repeat {

        U = unscheduled vertices in V whose predecessors have been scheduled (or have no predecessors) → "ready state"

        Select S $\subseteq$ U such that |S| $\leq$ a and labels in S are maximal

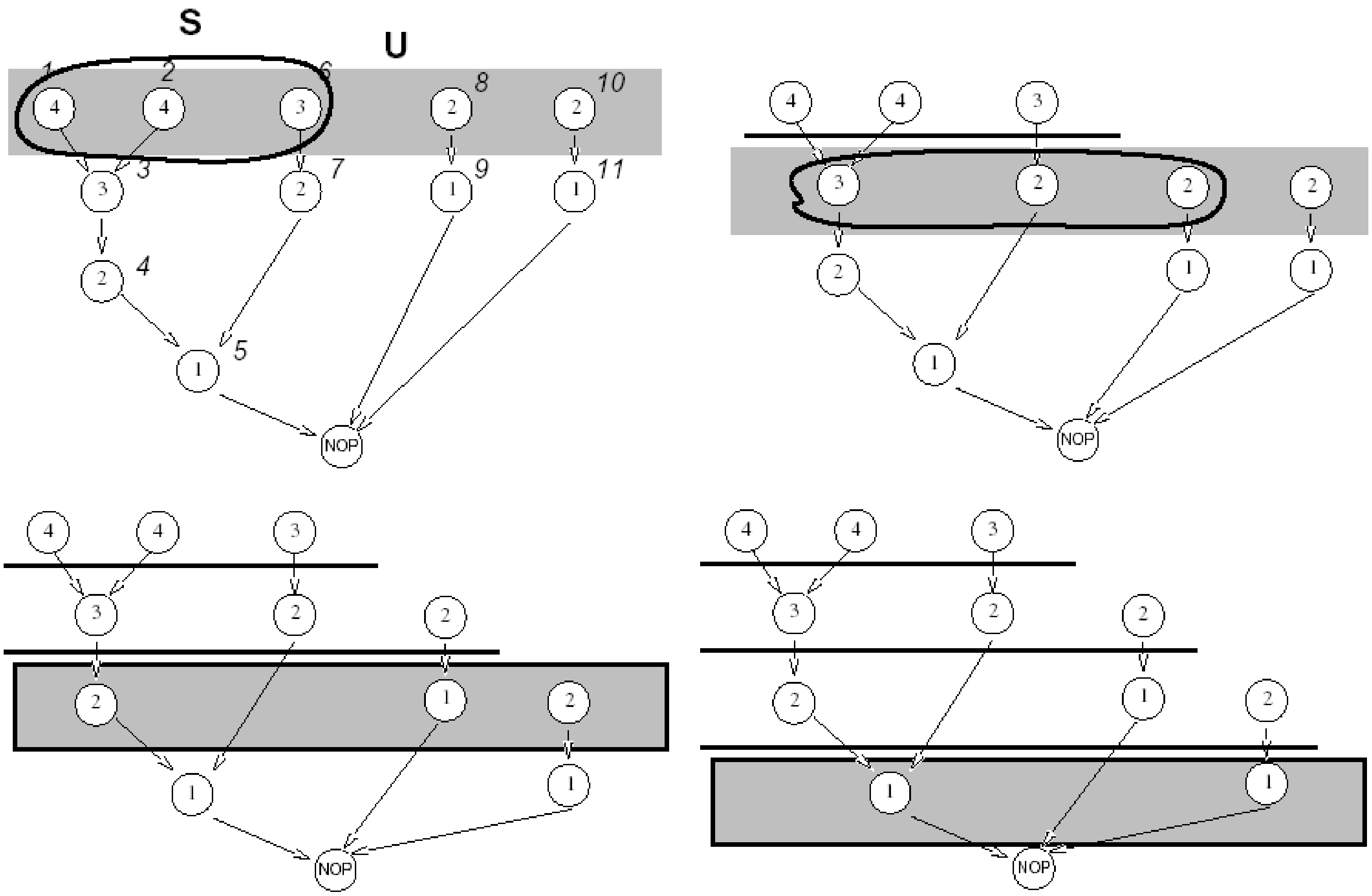
        Schedule the S operations at step l by setting $t_i = l,\ i: v_i \in$ S

        $l = l + 1$

    } until v_n is scheduled

}

Hu's Algorithm: Example



List Scheduling

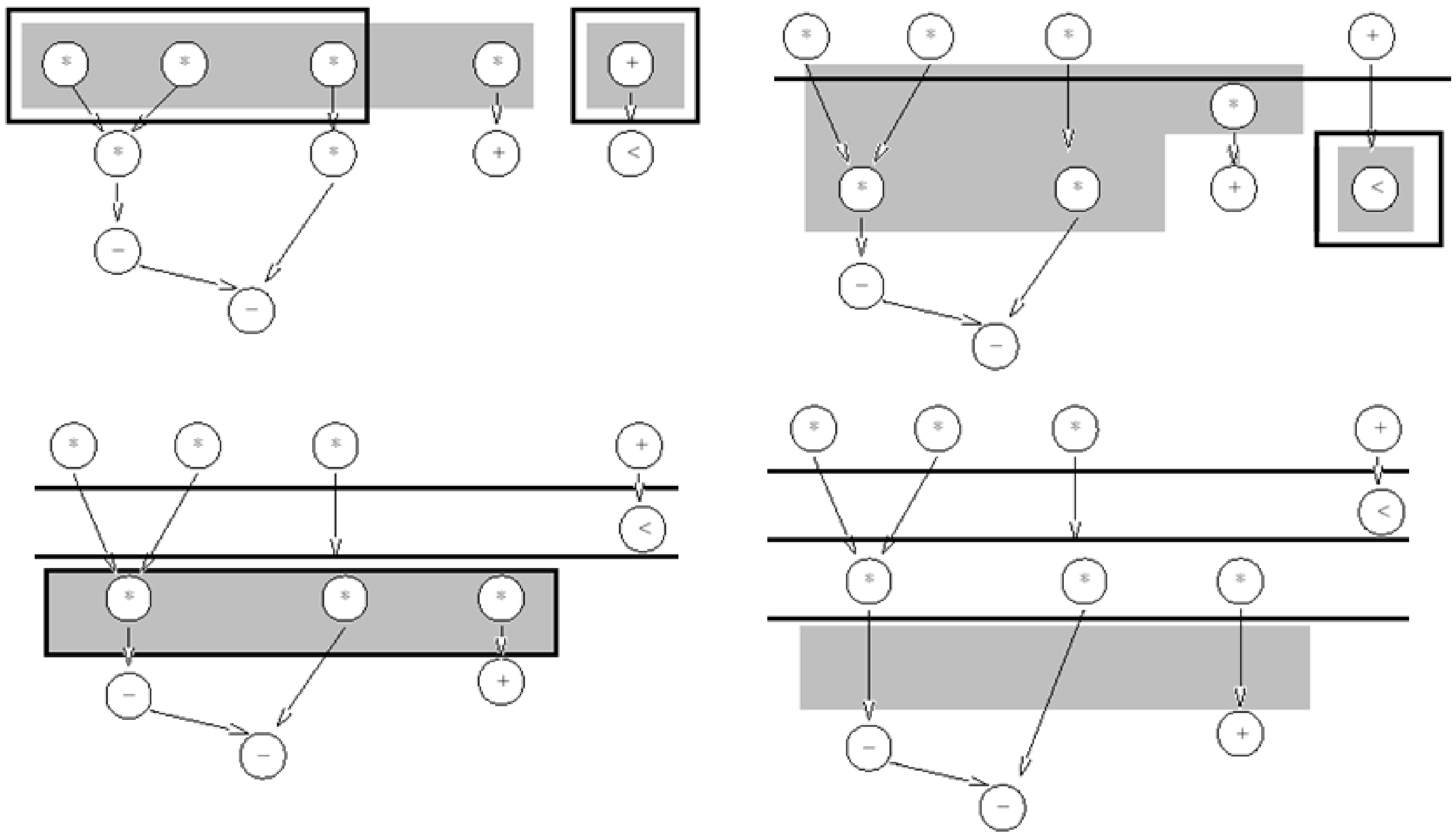
- Greedy algorithm for ML-RCS and MR-LCS
  - Does NOT guarantee optimum solution
- Similar to Hu's algorithm
  - Operation selection decided by criticality
  - O(n) time complexity
- More general input
  - Resource constraints on different resource types

List Scheduling Algorithm: ML-RCS

```
LIST_L (G(V,E), a) {
    l = 1
    repeat {
        for each resource type k {
            U_l,k = available vertices in V → "ready state"
            T_l,k = operations in progress → "ongoing state"
            Select S_k ⊆ U_l,k such that |S_k| + |T_l,k| ≤ a_k
            Schedule the S_k operations at step l
        }
        l = l + 1
    } until v_n is scheduled
}
```

List Scheduling Example

- OP *: delay = 2, number: 3 OP +: delay = 1, number 1



List Scheduling Algorithm: MR-LCS

```
LIST_R (G(V,E), λ') {
    a = 1,    l = 1
    Compute the ALAP times t^L
    if t_0^L < 0
        return (not feasible)
    repeat {
        for each resource type k {
            U_{l,k} = available vertices in V → "ready state"
            Compute the slacks { s_i = t_i^L - l,  ∀ v_i ∈ U_{l,k} }
            Schedule operations with zero slack, update a
            Schedule additional S_k ⊆ U_{l,k} under a constraints
        }
        l = l + 1
    } until v_n is scheduled
}
```

Force-Directed Scheduling

- Similar to list scheduling
  - Can handle ML-RCS and MR-LCS
  - For ML-RCS, schedules step-by-step
  - BUT, selection of the operations tries to find the *globally* best set of operations
- Idea – time frame:
  - Find the mobility $\mu_i = t_i^L - t_i^S$ of operations
  - Look at the operation type probability distributions
  - Try to flatten the operation type distributions
- Definition: operation probability density
  - $p_i(l) = \Pr\{v_i \text{ starts at step } l\}$
  - Assume uniform distribution:

$$p_i(l) = \frac{1}{\mu_i + 1} \quad for\ l \in [t_i^S, t_i^L]$$

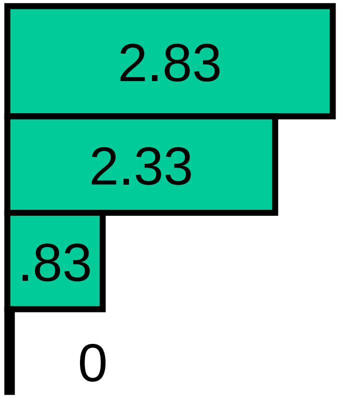
Force-Directed Scheduling: Definitions

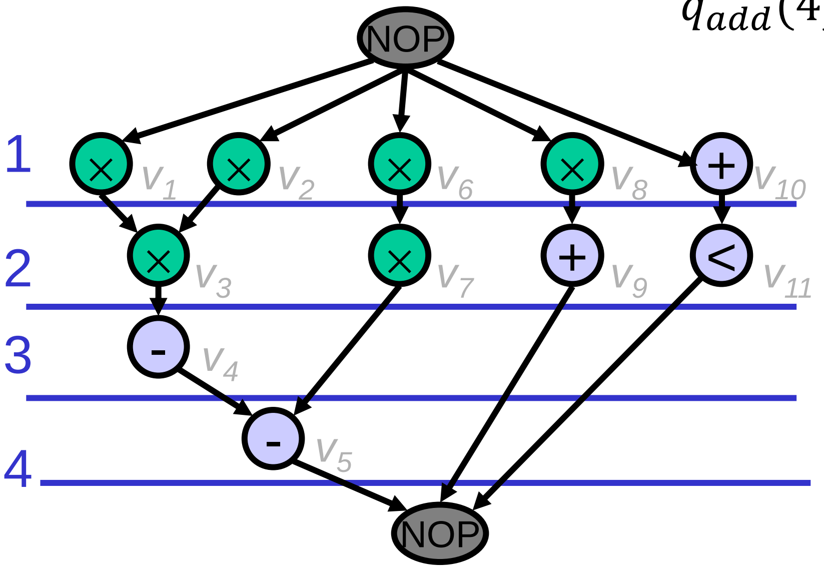
- Operation-type distribution (NOT normalized to 1)
  - $q_k(l) = \sum_{i\,:\,T(v_i)=k} p_i(l)$
- Operation probabilities over control steps:
  - $p_i = \{p_i(0), p_i(1), \ldots, p_i(n)\}$
- Distribution graph of type *k* over all steps:
  - $\{q_k(0), q_k(1), \ldots, q_k(n)\}$
  - $q_k(\,l\,)$ can be thought of as *expected* operator cost for implementing operations of type *k* at step *l*.

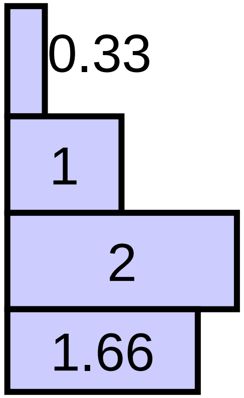
Example

$$q_{mult}(1) = 1 + 1 + \frac{1}{2} + \frac{1}{3} = 2.83$$
$$q_{mult}(2) = 1 + \frac{1}{2} + \frac{1}{2} + \frac{1}{3} = 2.33$$
$$q_{mult}(3) = \frac{1}{2} + \frac{1}{3} = 0.83$$
$$q_{mult}(4) = 0$$

$$q_{add}(1) = \frac{1}{3} = 0.33$$
$$q_{add}(2) = \frac{1}{3} + \frac{1}{3} + \frac{1}{3} = 1$$
$$q_{add}(3) = 1 + \frac{1}{3} + \frac{1}{3} + \frac{1}{3} = 2$$
$$q_{add}(4) = 1 + \frac{1}{3} + \frac{1}{3} = 1.66$$







Force

- Used as *priority* function
- Force is related to concurrency:
  - Sort operations for least force
- Mechanical analogy:
- Force = constant $\times$ displacement
  - Constant = operation-type distribution, $q_k(l)$
  - Displacement = change in probability

Self Force

- Sum of forces to feasible schedule steps
- Self-force for operation v_i in step l

$$\text{self}-\text{force}(i,l) = \sum_{m=t_i^S}^{t_i^L} q_k(m)(\delta_{lm} - p_i(m))$$

$$= q_k(l) - \frac{1}{\mu_i + 1} \sum_{m=t_i^S}^{t_i^L} q_k(m)$$

$$\delta_{lm} = \begin{cases} 1, & \textbf{if } l = m \\ 0, & \textbf{if } l \neq m \end{cases}$$

$$p_i(m) = \frac{1}{\mu_i + 1}$$

Predecessor/successor Force

- Related to the predecessors/successors
  - Fixing an operation timeframe restricts timeframe of predecessors/successors
  - Ex: Delaying an operation implies delaying its successors

$$\mathrm{ps-force}(i,l) = \frac{1}{\tilde{\mu}_i + 1} \sum_{m=\tilde{t}_i^S}^{\tilde{t}_i^L} q_k(m) - \frac{1}{\mu_i + 1} \sum_{m=t_i^S}^{t_i^L} q_k(m)$$

Self Force Example

$$q_{mult}(1) = 1 + 1 + \frac{1}{2} + \frac{1}{3} = 2.83$$

$$q_{mult}(2) = 1 + \frac{1}{2} + \frac{1}{2} + \frac{1}{3} = 2.33$$

$$q_{mult}(3) = \frac{1}{2} + \frac{1}{3} = 0.83$$

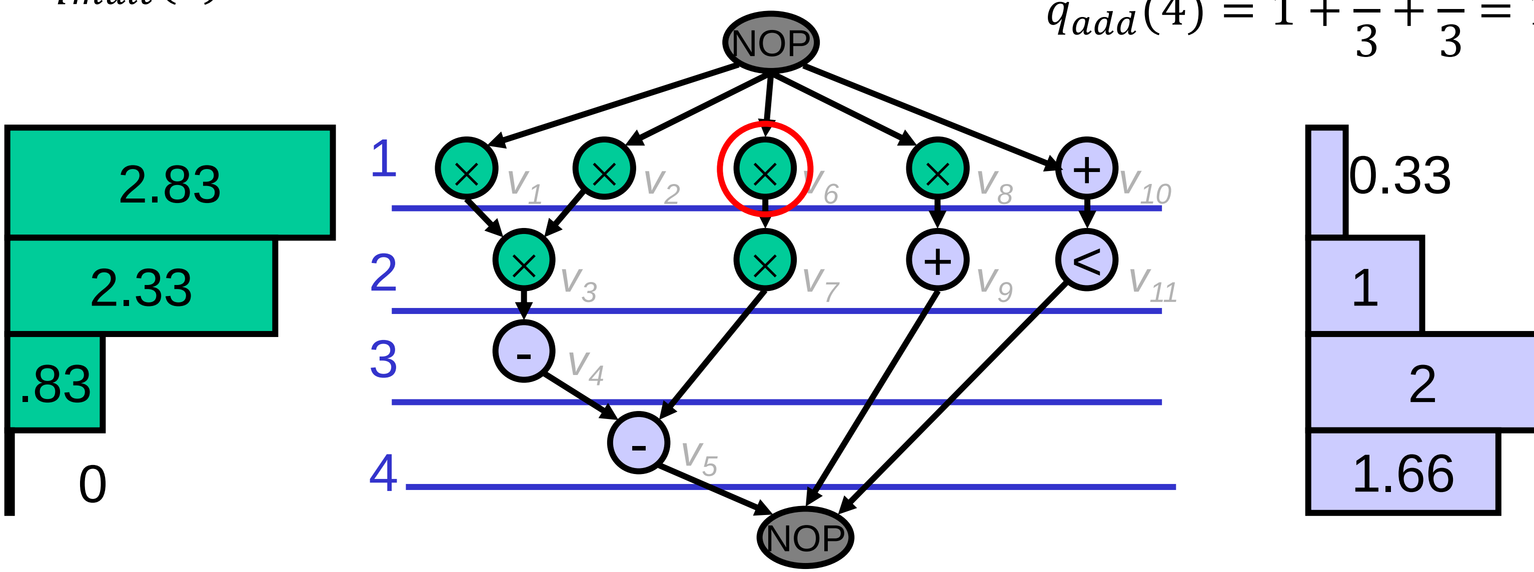
$$q_{mult}(4) = 0$$

$$q_{add}(1) = \frac{1}{3} = 0.33$$

$$q_{add}(2) = \frac{1}{3} + \frac{1}{3} + \frac{1}{3} = 1$$

$$q_{add}(3) = 1 + \frac{1}{3} + \frac{1}{3} + \frac{1}{3} = 2$$

$$q_{add}(4) = 1 + \frac{1}{3} + \frac{1}{3} = 1.66$$



Self Force Example: v_6

- Op v_6 can be scheduled in the first two steps
  - p(1) = 0.5; p(2) = 0.5; p(3) = 0; p(4) = 0
  - Distribution: q (1) = 2.8; q (2) = 2.3
- Assign v_6 to step 1:
  - variation in probability 1 – 0.5 = 0.5 for step 1
  - variation in probability 0 – 0.5 = -0.5 for step 2
  - Self-force: 2.8 * 0.5 – 2.3 * 0.5 = + 0.25
  - No successor force
- Assign v_6 to step 2:
  - variation in probability 0 – 0.5 = -0.5 for step 1
  - variation in probability 1 – 0.5 = 0.5 for step 2
  - Self-force: -2.8 * 0.5 + 2.3 * 0.5 = -0.25
  - Successor-force:
  - Successor (v_7) force is 2.3 * (0 – 0.5) + 0.8 * (1 – 0.5) = -0.75
  - Total force = -1

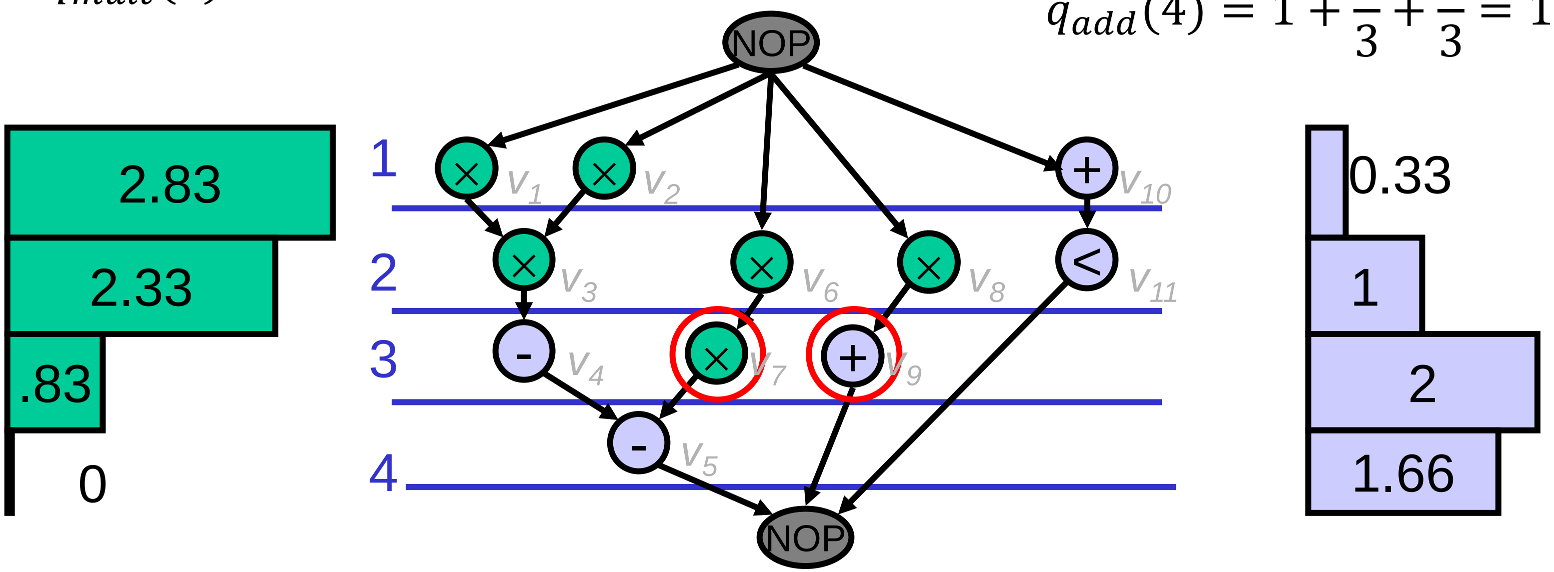
1 * 0.8 – 0.5 * (2.3 + 0.8) = -0.75

- Hence, assign v_6 to step 2

P/S Force Example

$$q_{mult}(1) = 1 + 1 + \frac{1}{2} + \frac{1}{3} = 2.83$$
$$q_{mult}(2) = 1 + \frac{1}{2} + \frac{1}{2} + \frac{1}{3} = 2.33$$
$$q_{mult}(3) = \frac{1}{2} + \frac{1}{3} = 0.83$$
$$q_{mult}(4) = 0$$

$$q_{add}(1) = \frac{1}{3} = 0.33$$
$$q_{add}(2) = \frac{1}{3} + \frac{1}{3} + \frac{1}{3} = 1$$
$$q_{add}(3) = 1 + \frac{1}{3} + \frac{1}{3} + \frac{1}{3} = 2$$
$$q_{add}(4) = 1 + \frac{1}{3} + \frac{1}{3} = 1.66$$



P/S Force Example: v_7 & v_9

- Type 1 (v_7) distribution:
  - $q(1) = 2.8$; $q(2) = 2.3$; $q(3) = 0.8$; $q(4) = 0$
- Assign v_6 to step 2:
  - Time frame of v_7 is reduced
  - $1 * (0.8) - 0.5 * (2.3 + 0.8) = -0.75$

- Type 2 (v_9) distribution:
  - $q(1) = 0.3$; $q(2) = 1$; $q(3) = 2$; $q(4) = 1.6$
- Assign v_8 to step 2:
  - Time frame of v_9 is reduced
  - $0.5 * (2 + 1.6) - 0.3 * (1 + 2 + 1.6) = 0.3$

Force-Directed Scheduling: Algorithm

```
FDS (G(V, E), λ̄) {
    repeat {
        Compute/update the time-frames
        Compute the operation and type probabilities
        Compute the self-force, ps-force and total force
        Schedule the op. with least force
    }
    until (all operations are scheduled)
    return (t)
}
```

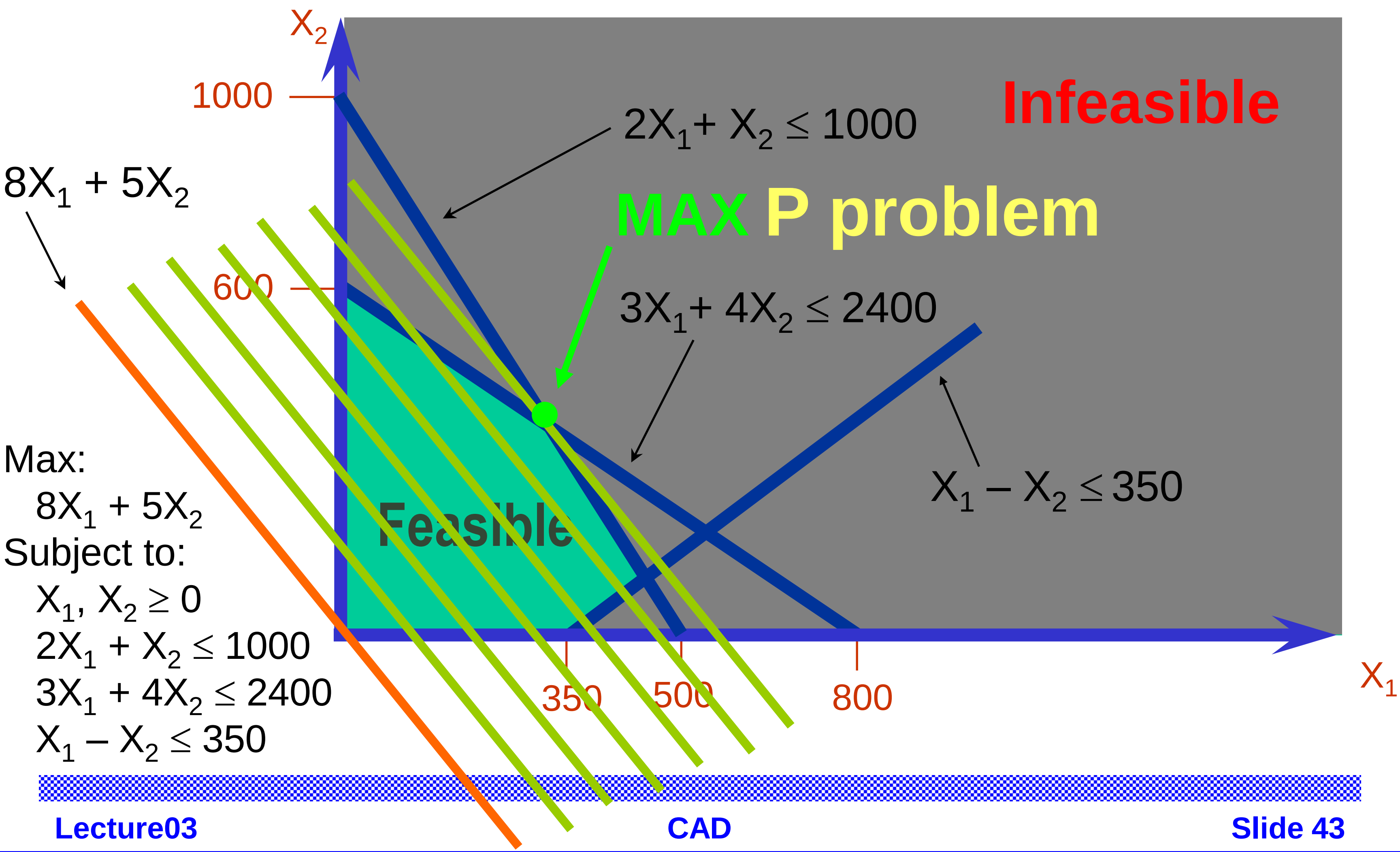
Force-Directed Scheduling: Algorithm

- Very similar to LIST_L(G(V,E), **a**)
  - Compute mobility of operations using ASAP and ALAP
  - Select and schedule operations
  - Go to next control step
- Difference with list scheduling in selecting operations
  - Compute operation probabilities and type distributions
  - Select operations with least force
  - Update operation probabilities and type distributions
  - Consider the effect on the type distribution
  - Consider the effect on p/s nodes and their type distributions
  - Complexity: $O(n^3)$

Resource Constraint Scheduling

- Constrained scheduling
  - General case NP-complete
  - Minimize latency given constraints on area or the resources (ML-RCS)
  - Minimize resources subject to bound on latency (MR-LCS)
- Exact solution methods
  - ILP: Integer Linear Programming
  - Hu's heuristic algorithm for identical processors (operations)
- Heuristics
  - List scheduling
  - Force-directed scheduling

Linear Programming Example



Max:

$8X_1 + 5X_2$

Subject to:

$X_1, X_2 \ge 0$

$2X_1 + X_2 \le 1000$

$3X_1 + 4X_2 \le 2400$

$X_1 - X_2 \le 350$

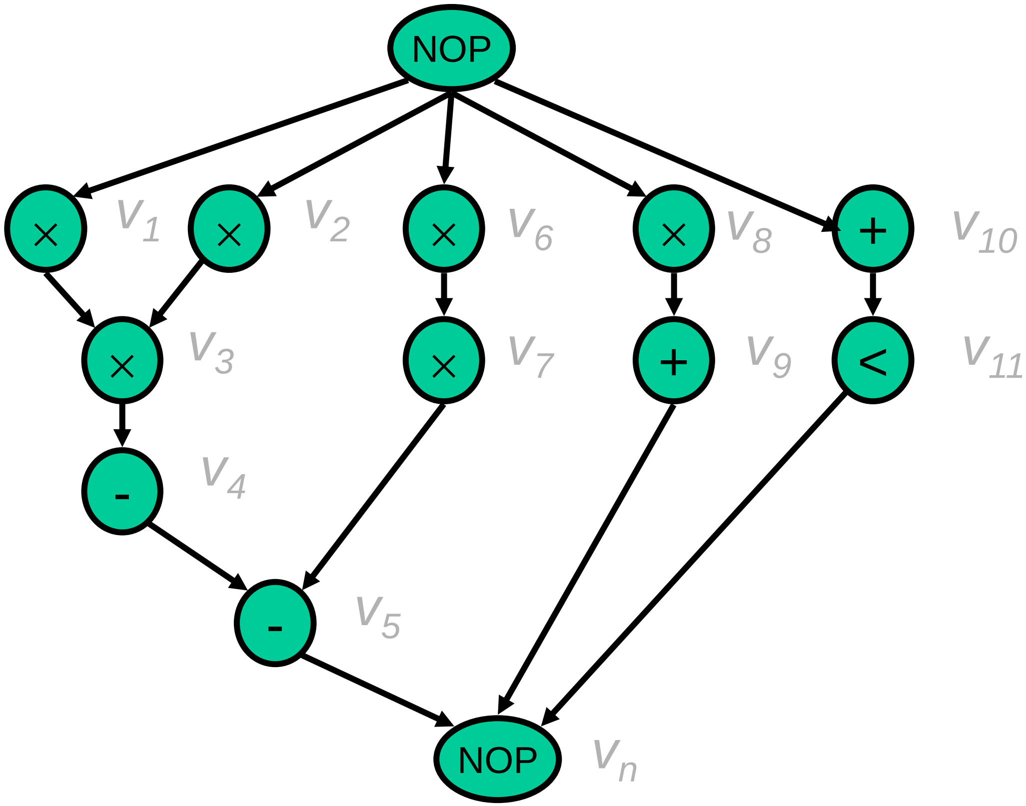
Mixed Integer Linear Programming

- A mathematical programming such that:
  - The objective is a linear function
  - All constraints are linear functions
  - Some variables are real numbers and some are integers, i.e., "mixed integer"
- It is almost like a linear programming, except that some variables are integers

NP-C problem

ILP Scheduling

- How to construct a mathematical model?



ILP Formulation of ML-RCS

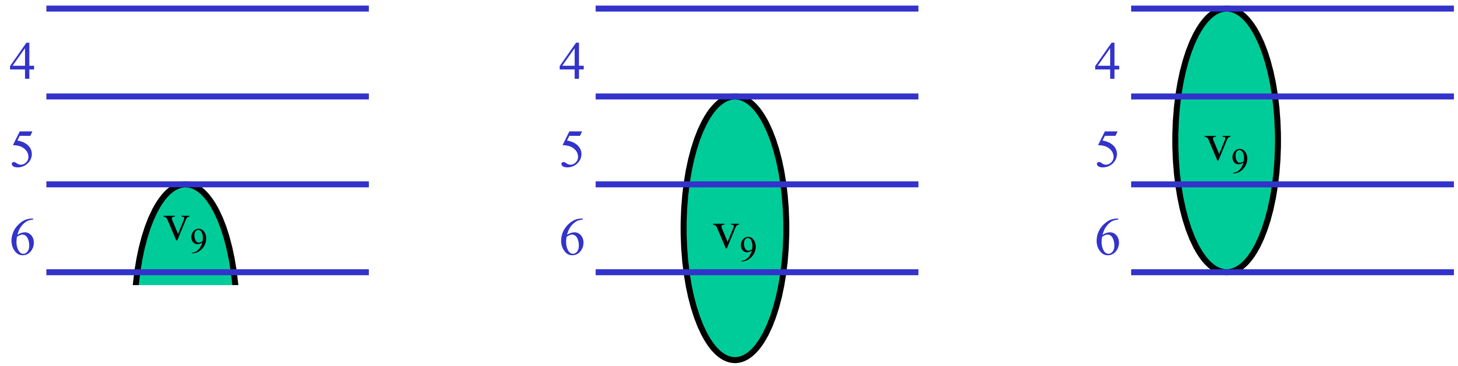
- Use binary decision variables
  - $i = 0, 1, \ldots, n$
  - $l = 1, 2, \ldots, \lambda'+1$ λ': given upper-bound on latency
  - $x_{i,l} = 1$ if operation i starts at step l, 0 otherwise.
- Set of linear inequalities (constraints), and an objective function (min latency)
- Observations
  - $x_{i,l} = 0 \quad for \quad l < t_i^S \quad and \quad l > t_i^L$ start time feasibility
    $(t_i^S = ASAP(v_i),\ t_i^L = ALAP(v_i))$
  - $t_i = \sum_l l \cdot x_{i,l}$ t_i = start time of op i
  - $\sum_{m=l-d_i+1}^{l} x_{i,m} = 1$ If op v_i takes d_i steps,
    is op v_i (still) executing at step l?

Start Time vs. Execution Time

- For each operation v_i , only one start time
- If $d_i=1$, then the following questions are the same:
  - Does operation v_i **start** at step l?
  - Is operation v_i **running** at step l?
- But if $d_i>1$, then the two questions should be formulated as:
  - Does operation v_i **start** at step l?
    - Does $x_{i,l} = 1$ hold?
  - Is operation v_i **running** at step l?
    - Does $\sum_{m=l-d_i+1}^{l} x_{i,m} = 1$ hold?

Operation v_i Still Running at Step l?

- Assume that v_9 takes 3 steps, is v_9 running at step 6?
  - Is $x_{9,6} + x_{9,5} + x_{9,4} = 1$?

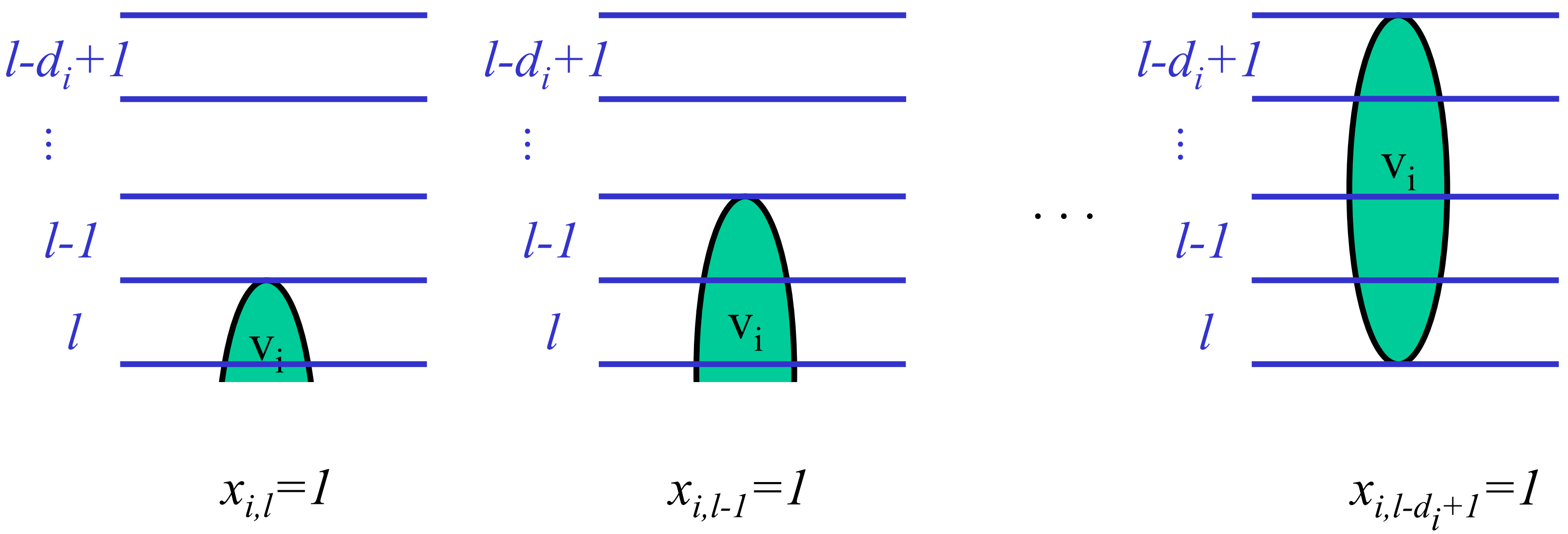


$x_{9,6}=1$ $x_{9,5}=1$ $x_{9,4}=1$

- Note:
  - Only one (if any) of the above three cases can happen
  - To meet resource constraints, we have to ask the same question for ALL steps, and ALL operations of that type

Operation v_i Still Running at Step l ?

- Is v_i running at step l ?
  - Is $x_{i,l} + x_{i,l-1} + \ldots + x_{i,l-d_i+1} = 1$?



ILP Formulation of ML-RCS (Cont.)

- Constraints:
  - Unique start times: $\sum_{l} x_{i,l} = 1, \quad i = 0,1,\ldots,n$
  - Sequencing (dependency) relations must be satisfied

$$t_i \geq t_j + d_j \ \forall (v_j, v_i) \in E \ \Rightarrow \ \sum_{l} l \cdot x_{i,l} \geq \sum_{l} l \cdot x_{j,l} + d_j$$

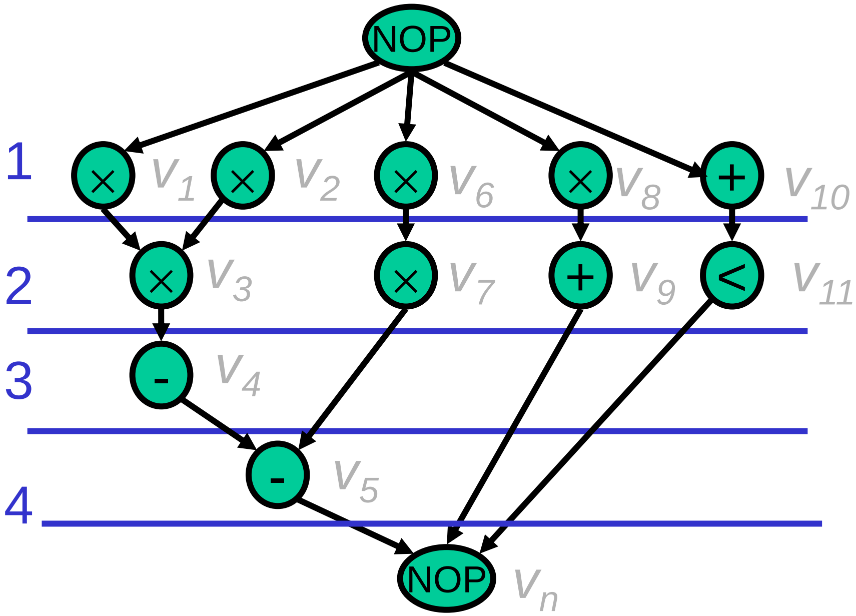
  - Resource constraints

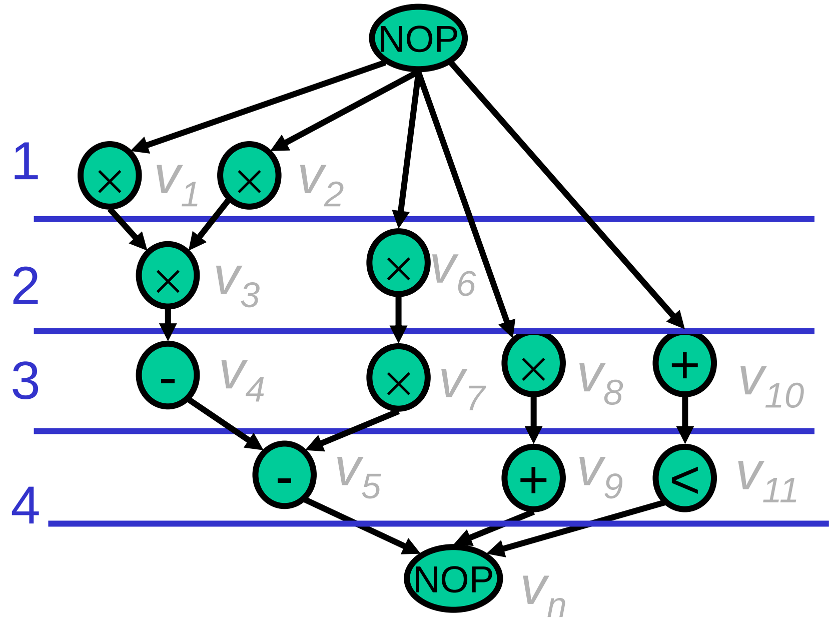
$$\sum_{i\,:\,T(v_i)=k} \ \sum_{m=l-d_i+1}^{l} x_{i,m} \leq a_k, \quad k = 1,\ldots,n_{res}, \quad l = 1,\ldots,\bar{\lambda}+1$$

- Objective: min $\boldsymbol{c}^T\boldsymbol{t}$.
  - $\boldsymbol{t}$ =start times vector, $\boldsymbol{c}$ =cost weight (ex: [0 0 ... 1])
  - When $\boldsymbol{c}$ =[0 0 ... 1], $\boldsymbol{c}^T\boldsymbol{t} = \sum_{l} l \cdot x_{n,l}$

ILP Example

- Assume $\bar{\lambda} = 4$
- First, perform ASAP and ALAP
  - (we can write the ILP without ASAP and ALAP, but using ASAP and ALAP will simplify the inequalities)





ILP Example: Unique Start Times Constraint

- Without using ASAP and ALAP values:

$$x_{1,1} + x_{1,2} + x_{1,3} + x_{1,4} = 1$$
$$x_{2,1} + x_{2,2} + x_{2,3} + x_{2,4} = 1$$
$$\cdots$$
$$\cdots$$
$$\cdots$$
$$x_{11,1} + x_{11,2} + x_{11,3} + x_{11,4} = 1$$

- Using ASAP and ALAP:

$$x_{1,1} = 1$$
$$x_{2,1} = 1$$
$$x_{3,2} = 1$$
$$x_{4,3} = 1$$
$$x_{5,4} = 1$$
$$x_{6,1} + x_{6,2} = 1$$
$$x_{7,2} + x_{7,3} = 1$$
$$x_{8,1} + x_{8,2} + x_{8,3} = 1$$
$$x_{9,2} + x_{9,3} + x_{9,4} = 1$$
$$\cdots$$

ILP Example: Dependency Constraints

- Using ASAP and ALAP, the non-trivial inequalities are: (assuming unit delay for + and *)

$$2 \cdot x_{7,2} + 3 \cdot x_{7,3} - 1 \cdot x_{6,1} - 2 \cdot x_{6,2} - 1 \geq 0$$

$$2 \cdot x_{9,2} + 3 \cdot x_{9,3} + 4 \cdot x_{9,4} - 1 \cdot x_{8,1} - 2 \cdot x_{8,2} - 3 \cdot x_{8,3} - 1 \geq 0$$

$$2 \cdot x_{11,2} + 3 \cdot x_{11,3} + 4 \cdot x_{11,4} - 1 \cdot x_{10,1} - 2 \cdot x_{10,2} - 3 \cdot x_{10,3} - 1 \geq 0$$

$$4 \cdot x_{5,4} - 2 \cdot x_{7,2} - 3 \cdot x_{7,3} - 1 \geq 0$$

$$5 \cdot x_{n,5} - 2 \cdot x_{9,2} - 3 \cdot x_{9,3} - 4 \cdot x_{9,4} - 1 \geq 0$$

$$5 \cdot x_{n,5} - 2 \cdot x_{11,2} - 3 \cdot x_{11,3} - 4 \cdot x_{11,4} - 1 \geq 0$$

ILP Example: Resource Constraints

- Resource constraints (assuming 2 adders and 2 multipliers)

$$x_{1,1} + x_{2,1} + x_{6,1} + x_{8,1} \leq 2$$
$$x_{3,2} + x_{6,2} + x_{7,2} + x_{8,2} \leq 2$$
$$x_{7,3} + x_{8,3} \leq 2$$
$$x_{10,1} \leq 2$$
$$x_{9,2} + x_{10,2} + x_{11,2} \leq 2$$
$$x_{4,3} + x_{9,3} + x_{10,3} + x_{11,3} \leq 2$$
$$x_{5,4} + x_{9,4} + x_{11,4} \leq 2$$

- Objective:
  – Since λ=4 and sink has no mobility, any feasible solution is optimum, but we can use the following anyway: $Min \quad 1 \cdot x_{n,1} + 2 \cdot x_{n,2} + 3 \cdot x_{n,3} + 4 \cdot x_{n,4} + 5 \cdot x_{n,5}$

ILP Formulation of MR-LCS

- Dual problem to ML-RCS
- Objective:
  - Goal is to optimize total resource usage, $\mathbf{a}$.
  - Objective function is $\boldsymbol{c}^T\boldsymbol{a}$, where entries in $\boldsymbol{c}$ are respective area costs of resources
- Constraints:
  - Same as ML-RCS constraints, plus:
  - Latency constraint added:

$$\sum_{l} l \cdot x_{n,l} \leq \bar{\lambda} + 1$$

  - Note: unknown a_k appears in constraints.

Further Study

- Linear programming
  - http://www.cs.sunysb.edu/~algorith/files/linear-programming.shtml
- Linear programming tools
  - https://en.wikipedia.org/wiki/List_of_optimization_software


WWW.MJJQ.COM TRAVEL PHOTOGRAPHY WALLPAPERS @2006.02