



CUDA Laboratory 2

Introduction to High-Performance Computing

Introduction

In this second laboratory about GPU programming in CUDA, we are going to continue building your skills in order to develop more advanced GPU-accelerated applications. As a friendly reminder, the laboratory is divided in two different blocks and exercises:

- **Block A (Friday / 18th of August):** The first block provided you with a first notion on how to use CUDA. This includes how to compile a CUDA program, how to launch a CUDA kernel, how to index 1D arrays, and more.
- **Block B (Monday / 21st of August):** The second block presents a use-case for using GPUs with images. The goal is to make you understand how to index 2D matrices, while doing something practical.

We assume that everyone have already finished the exercises of the first block of the laboratory session. If you have not attempted these exercises, it will be relatively difficult to complete the second block of exercises that we are presenting today. The reason is that you should already understand most of the basic concepts of CUDA presented in the first block. For instance, by now, you must know how to compile a CUDA program, how to manage the memory of the GPU, and (more importantly) how to implement and launch a CUDA kernel. If none of these requirements seem familiar, please, try the first block of exercises before proceeding!

Once again, we are going to use Tegner¹ for the set of exercises. This is a cluster at KTH Royal Institute of Technology with 65 heterogeneous nodes. Every node has a one or two GPUs, based on the NVIDIA Quadro K420 or the NVIDIA Tesla K80. For the purposes of this laboratory, we will use the “Thin Nodes” of Tegner. These nodes contain 2×12-core Intel E5-2690v3 CPUs at 2.60GHz, 512GB DRAM and NVIDIA Quadro K420 GPU per node. More information can be found [here](#).

In case you need help or you do not understand some of the topics of CUDA presented in this laboratory session, do not worry, we are here to help you out!

¹ Even though you may have a laptop with a CUDA-supported GPU, we encourage you to use Tegner during the sessions of today and Monday.

Block B

For the second block of exercises, we are going to play with images and perform some basic image processing to create the base for an edge detector, such as [Canny](#). Our goal is to make you understand how to index 2D matrices, while doing something fun and practical. As a matter of fact, the result of the exercises below represent some of the main image processing techniques used in Computer Vision that allow for object and text recognition. If you would like to get a feeling on how the final output would look like, check the cover of this document!

Once again, we encourage you to really understand the concepts explained within the first block of exercises. If you do, then this block will be easy for you to solve, you will see.

Exercise 3 - Experimental Setup

We will use a different CUDA source code file to implement the exercises below. This source code file, named `lab02_ex3_6.cu`, is included inside the [`CUDA_Lab02.tar.gz`](#) file:

```
cd /cfs/klemming/nobackup/your_initial/your_username
wget https://www.pdc.kth.se/education/tutorials/summer-school/cuda/CUDA_Lab02.tar.gz
tar -xzvf CUDA_Lab02.tar.gz
```

We also need a reference image file to process on each step. We will use the file `lab02.bmp`, located inside the `images` folder. This file is stored using the Bitmap (BMP) image format, a popular uncompressed format widely used by the Windows operating system. Each BMP file contains an encoded header that specifies the `{width, height}` of the image, the number of bits per color plane, and more. After the header, a subsequent string of interleaved color values follow (e.g., in BGR). Here is a simplified example of how a 3x3 image looks like inside the file:

Header									
(0,0)	(0,1)	(0,2)	(0,3)	(0,4)	(0,5)	(0,6)	(0,7)	(0,8)	
(1,0)	(1,1)	(1,2)	(1,3)	(1,4)	(1,5)	(1,6)	(1,7)	(1,8)	
(2,0)	(2,1)	(2,2)	(2,3)	(2,4)	(2,5)	(2,6)	(2,7)	(2,8)	

Each BGR, from Blue / Green / Red, represents an 8-bit pixel value in the image that encodes the intensity of each channel. The values span from 0 to 255 in the case of BMP 24bpp², being 0 the absence of representation by this color and 255 the full representation. This means that

² Other Bitmap formats, such as BMP 32bpp, can contain an extra Alpha channel for transparency.

we could create a completely white image by setting all the pixel values to 255, or the opposite, a completely black image setting them to 0. One aspect of BMP files is that it is common to encounter that the pixel values are stored bottom-up (i.e., as if the image pixels were flipped).

We provide you inside `lab02_ex3_6.cu` the functionality to read BMP 24bpp images and retrieve the pixel data in BGR format, as single-precision floating point values (suitable for the GPU). We also provide other set of functionality, such as a function to store BMP 8bpp files for Black & White images. **For this block of exercises, you will not need to handle any of these aspects. We will only ask you to implement the kernels that perform the different image processing steps that will be applied to the reference image.** Everything else, including the set-up of CUDA in the `main()` function, is already defined inside `lab02_ex3_6.cu`.

One important aspect is to connect to Tegner using the `-Y` flag to enable X11 forwarding support. This flag is required because we are going to display the resultant images using the [ImageMagick](#) suite. This is a free and open-source software suite for displaying, converting, and editing raster image and vector image files. The suite contains multiple interfaces (e.g., C API).

In this laboratory session, we will use the terminal interface of ImageMagick to render the images generated by each exercise. Thus, we effectively avoid to copy the images using `scp`. For instance, let us resize the reference `lab02.bmp` image and display its content remotely. First, connect to Tegner with the `-Y` flag and access to the folder that contain the exercises. Then, execute the following command:

```
display -resize 1280x720 images/lab02.bmp
```

If everything worked as expected, you must see a new window after a few seconds (be patient):



You are now ready to begin with the exercises! If you did not get a new window, please, ask any of the laboratory assistants for help.

Exercise 4 - Black & White Image Conversion

One of the frequent initial steps in the development of an edge detector is to discard the color information and work directly in black & white. The idea is to keep only the intensity of the pixels. For instance, if we consider a [YUV](#) color space, which is very common in video streams, one can easily work only on the Y plane and discard the color information. The reason is that the Y plane (luminance) contains the intensity of the pixel values, which represents the main content of the image. The UV planes (chrominance) define the color or tint of the pixels, but they do not necessarily add value to the features that we want to extract from the image.

The BMP image `lab02.bmp` is encoded using a BGR color space, where the combination of the individual intensities of each color value represent the final intensity of the specific pixels. Therefore, the first step for our base edge detector would be to combine these pixels in order to generate a BMP 8bpp image in grayscale. In other words, we want only 8 bits per pixel.

For the conversion to grayscale, we are going to use the [Colorimetric](#) (luminance-preserving) method. This conversion guarantees that both the original and converted image maintains the same absolute luminance. In practice terms, what we are going to do is to take each BGR value of the Bitmap file and apply the following conversion using the weighted sum of the three values:

$$Y_{OUT} = 0.0722 \cdot B_{IN} + 0.7152 \cdot G_{IN} + 0.2126 \cdot R_{IN}$$

Even though we are not going to get into the details of the meaning of each constant, the weighted values constitute how humans perceive color intensities. In particular, humans are more sensitive to green colors than blue colors. Hence, the notable difference in weight.

TO-DO

[4.1]

Open the file `lab02_ex3_6.cu` with your preferred text editor and [briefly](#) examine the overall content of the file. Pay particular attention to the `cpu_greyscale()` function and try to understand how the color conversion is done on the CPU given a BGR 24bpp image plane.

As you might have noticed in the `cpu_greyscale()` implementation, the color conversion is relatively simple. The input image is represented as an encoded 2D image in a 1D array, where each row is consecutively stored in memory. We retrieve the input pixel by considering each one as a BGR value (i.e., $3 \times \text{float}$). In fact, the rows are separated by the width of the image multiplied by the number of colors per pixel. On the other hand, we store the output Y value considering that the image plane now contains only one color value per pixel. Once again, the output is a 2D array encoded as a 1D array. In this case, each row is only separated from the width of the image plane.

From now on, we will use the converted image in grayscale as the input for the subsequent operations. We now ask you to implement the same `cpu_greyscale()` function, but using a GPU kernel in CUDA instead.

☒ TO-DO**[4.2]**

Find the declaration of `gpu_greyscale()` in `lab02_ex3_6.cu` and implement the GPU version of the black & white color conversion filter. The source code is already set-up to call the kernel and generate the output, but you will need to uncomment the code inside `main()`.

Hint #1: The kernel is launched with a 2D grid of 2D blocks. Consider calculating the ID of the thread in the Y direction to select the specific row, and the ID of the thread in the X direction to select the specific column.

Hint #2: The boundaries of the image cannot be exceeded. You must include an `if`-statement to prevent any issues, based on the `width` and `height` parameters.

After you have implemented the kernel, you should be able to see the result of the color conversion. Compile the code with `nvcc`, ask for a node in Tegner following the indications of the first laboratory and execute the code with `srun`, providing the path to the input image:

```
srun -n 1 ./lab02_ex3_6.out images/lab02.bmp
```

The code will then store a new image called `lab02_result_0_gpu.bmp` inside the `images` folder. Release the allocation (`exit` command) and visualize the result with ImageMagick:

```
display -resize 1280x720 images/lab02_result_1.bmp
```

You must get a new window that displays the converted image in black & white, such as this:



Exercise 5 - Applying a Convolution Filter

Converting the input image to black & white was a very good first step towards implementing our edge detector. For this exercise, we are going to apply a Gaussian filter to smooth the grayscale image that was generated through the kernel.

In Image Processing, a Gaussian *blur* is the result of blurring an image by the means of a Gaussian function. The visual effect is equivalent to looking at the image through a translucent screen, as if the image suddenly became a thin layer of colored candy. Depending on the intensity of the filter, the Gaussian blur can provide multiple benefits. For instance, it can be used to reduce the image noise. The reason is that the filter effectively reduces the high-frequency components of a given image.

We need this filter as an intermediate step towards increasing the quality of the result of Exercise 6, where we will apply a Sobel filter to define the edges of the image (i.e., the Sobel filter is very sensitive to noise). **For this exercise, we are going to apply a Gaussian filter using a 3×3 convolution matrix on all the pixels of the image.** The term convolution is the result of adding each pixel to its local neighbours, weighted by the matrix values ([source](#)):

$$\left(\begin{bmatrix} a & b & c \\ d & e & f \\ g & h & i \end{bmatrix} * \begin{bmatrix} 1 & 2 & 3 \\ 4 & 5 & 6 \\ 7 & 8 & 9 \end{bmatrix} \right) [2, 2] = (i * 1) + (h * 2) + (g * 3) + (f * 4) + (e * 5) + (d * 6) + (c * 7) + (b * 8) + (a * 9).$$

The $*$ operator represents the convolution, not a matrix multiplication. Here, what you have to consider is to map each pixel as the center of the 3×3 convolution matrix and apply the weights with the surrounding pixels. As we use symmetric filters, the order can be top-bottom as well.

☒ TO-DO

[5.1]

Find the implementation of `cpu_applyFilter()` inside the `lab02_ex3_6.cu` file and try to understand how a given convolution matrix is applied to a certain pixel.

Hint #1: The input block of the image is given by the top-left corner, not the center of the block (the target pixel).

Hint #2: This is not a matrix-matrix multiplication, keep this in mind while reviewing the source code.

We already provide you with an implementation of `cpu_gaussian()` and `gpu_gaussian()`, that contains the CPU and GPU implementation, respectively. Both versions already define a 3×3 convolution filter that constitutes the result of applying a Gaussian function to a particular pixel. Therefore, **we ask you to implement a device function `gpu_applyFilter()` that allows any CUDA kernel to apply a convolution filter given by parameter.** Remember that, in CUDA, device functions can be declared with the `__device__` modifier. The syntax is very similar to a plain C function, with the difference that now the GPU can see this code as well.

TO-DO

[5.2]

Implement the `gpu_applyFilter()` in `lab02_ex3_6.cu` that allows to apply any kind of convolution matrix to a certain pixel. Will the GPU code differ from the CPU code in this case? Examine the implementation of `gpu_gaussian()` to understand the execution flow.

Hint #1: The `gpu_applyFilter()` is called with a single thread from `gpu_gaussian()`. Do not parallelize it!

Hint #2: In some situations, the CPU code and the GPU code can be shared (<https://goo.gl/Wz8iyG>).

With the functionality for applying the convolution filter on the GPU ready, we can now generate the second output result. **Make sure you uncomment the execution of the kernel inside `main()`,** otherwise you will not see the GPU version enabled. Now, allocate a node on Tegner, execute with `srun` and then introduce these commands:

```
montage -tile 2x1 -crop 320x180+512+512 -geometry 640x360 \
    images/lab02_result_1.bmp images/lab02_result_2.bmp \
    images/lab02_result_2_comp.jpg
display images/lab02_result_2_comp.jpg
```

The new window will display a cropped area of the original black & white image (left), and a cropped area of the new blurred image (right). The differences are very subtle, but you should be able to notice some differences:



If you did not manage to get any differences, please, make sure that you have correctly enabled the new version of the `xxx_applyFilter()` inside the `gpu_gaussian()` kernel. Ask for help to the laboratory assistants if you cannot make any progress.

Exercise 6 - Detecting Edges in the Image

The very last step of our base edge detector is to apply the Sobel filter. With this filter, we are going to compute an approximation of the gradient of the image intensity function. This allows

us to create a new image where the edges are emphasized, which constitutes the base for full edge detection algorithms such as [Canny](#).

The filter uses two 3×3 kernels which are convolved with the original image to calculate approximations of the derivatives on the horizontal and vertical directions. In other words, if we define \mathbf{A} as the source image, and \mathbf{G}_x and \mathbf{G}_y as two convolution matrices that generate the horizontal and vertical derivative approximations, the computations are as follow ([source](#)):

$$\mathbf{G}_x = \begin{bmatrix} +1 & 0 & -1 \\ +2 & 0 & -2 \\ +1 & 0 & -1 \end{bmatrix} * \mathbf{A} \quad \text{and} \quad \mathbf{G}_y = \begin{bmatrix} +1 & +2 & +1 \\ 0 & 0 & 0 \\ -1 & -2 & -1 \end{bmatrix} * \mathbf{A}$$

The resultant gradient magnitude of the pixel is obtained by calculating the square root of these:

$$\mathbf{G} = \sqrt{\mathbf{G}_x^2 + \mathbf{G}_y^2}$$

For the last exercise, we want you to implement the GPU version of `cpu_sobel()`, which is already declared in `lab02_ex3_6.cu` under the name `gpu_sobel()`. The implementation of this function is very similar to `gpu_gaussian()`, except for the fact that we apply two different convolution filters to the same pixel and combine the result.

☒ TO-DO

[6.1]

Implement `gpu_sobel()` in `lab02_ex3_6.cu` to enable the execution of the Sobel filter on the GPU. Pay special attention to the indices used on the CPU implementation `cpu_sobel()` to avoid any issues with the final result.

Hint #1: You can use the `sqrtf()` function to calculate the square root, as in the CPU code.

Hint #2: It might be interesting for you to examine first how `gpu_gaussian()` has been implemented.

With the implementation of `gpu_sobel()` in place, we are almost done with the laboratory session of today. Make sure you uncomment the execution of the kernel inside `main()`, execute the application with `srun`, and open the result with the following two commands:

```
montage -border 0 -geometry 640x360 -tile 3x1 \
    images/lab02.bmp images/lab02_result_2.bmp \
    images/lab02_result_3.bmp images/lab02_result_3_comp.jpg
display images/lab02_result_3_comp.jpg
```

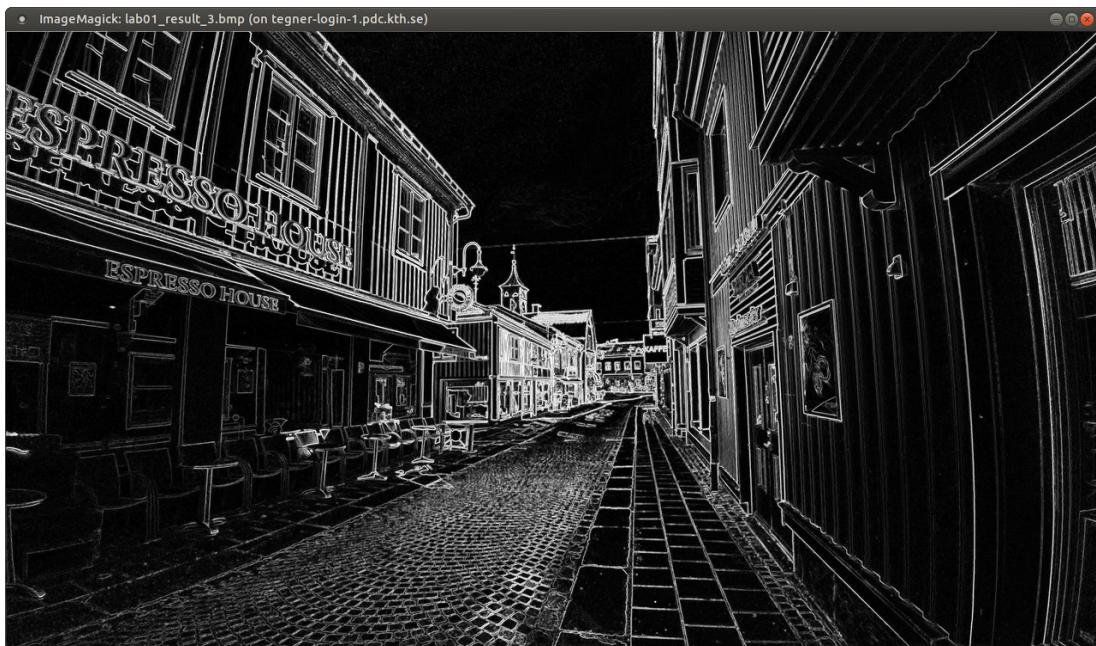
A new window will open that displays the original image (left), the black & white image (center), and finally the result of applying the Gaussian and Sobel filters (right):



You can also observe how the result image looks like in larger resolution. Use the `display` command in combination with the `resize` flag:

```
display -resize 1280x720 images/lab02_result_3.bmp
```

Alternatively, you can remove the “`-resize 1280x720`” option to visualize a full resolution of the image. This might take some time to load, but it might be worth it to consider all the small details. Whether you resize the image or not, you should observe something like the following:



If you reached this point, you can consider yourself a CUDA master! We hope that you enjoyed the laboratory session.

Bonus Exercises

In this section, we provide you with additional exercises with the purpose of getting deeper into CUDA optimizations. These exercises are optional, but we consider that advanced users might be interested in understanding how they could improve the performance of their applications.

Exercise 7 - Optimizing Memory Accesses

During the lectures, we have seen that the memory hierarchy of the GPU is rich and complex. We can encounter different layers that vary the speed and capacity. For instance, the texture memory is a very limited and special memory that allows you for efficient access to random locations inside a texture, which is tremendously useful in video games.

This hierarchy is also visible from a CUDA program perspective, and effectively selecting where to place our data can make a difference in some situations. Up until now, we have been using the Global Memory space, which is provided by default if nothing is specified. This Global Memory offers very high-capacity and represents the first layer we access when copying data from the CPU to the GPU. Unfortunately, this memory features high-latency to access the data.

In this exercise, we are going to try to optimize the GPU versions of the Gaussian and Sobel filter by using the Shared Memory instead. The idea is to bring the content of the image from Global Memory to Shared Memory in blocks of size `BLOCK_SIZE_SH`. This constant is also the dimension of each block inside the grid, plus some additional values in X and Y.

We ask you first to declare the `BLOCK_SIZE_SH` constant on top of the file, that defines the dimension of the Shared Memory block. Use the following³:cells

```
#define BLOCK_SIZE_SH 18
```

We will use this constant for the declaration of the memory space inside `gpu_gaussian()` and `gpu_sobel()`. The declaration is defined in the first or one of the first lines of each kernel:

```
__shared__ float sh_block[BLOCK_SIZE_SH * BLOCK_SIZE_SH];
```

This will declare a 2D shared block in Shared Memory, using the 1D array representation that we have already discussed in the previous exercises. The `__shared__` attribute is given in the declaration to suggest the compiler that we want this variable to be located in Shared Memory and not in Local or Global Memory.

³ We will provide more details of why we use 18 here and not 16, as in the number of threads per block.

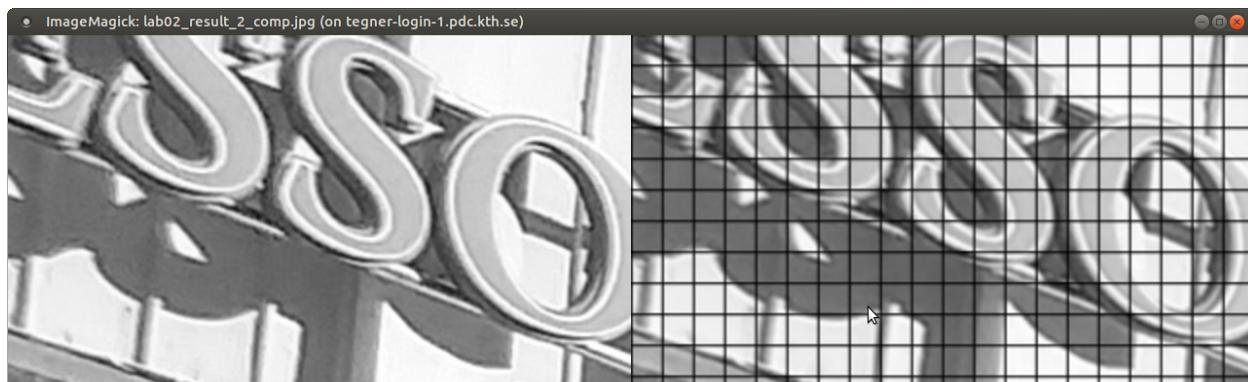
Hence, the first exercise would be to declare the shared block inside `gpu_gaussian()` and `gpu_sobel()`. Then, we ask you to make each thread copy a pixel from the input image into the shared memory block. You have to call `__syncthreads()` to guarantee that each thread has finished retrieving its part of the block before using the data. Thereafter, change the input of the `applyFilter()` function to use the shared block instead.

☒ TO-DO [B2.1]

In `lab02_ex3_6.cu`, declare a Shared Memory block within `gpu_gaussian()` and another one within `gpu_sobel()`. Thereafter, introduce the necessary changes to make each thread bring one pixel value to the shared block. Change the input parameter of `applyFilter()` to use the shared block (i.e., instead of a reference to the input image directly).

Hint #1: Use `__syncthreads()` to guarantee that all the threads have copied their pixels to the Shared Memory.

If you have implemented it “correctly”, you will observe that the output result is not exactly what you expected it to be. You should see by now something like this, in the case of the Gaussian filter and the side-by-side comparison with the original image:



The reason is that the exercise is a little bit more complex than initially one might expect. With the change that you just introduced, we are not considering the fact that we also have to bring extra columns and rows on one of the sides of the block. Without this change, some of the threads are accessing uninitialized data.

This is the main reason why we declared the constant `BLOCK_SIZE_SH` with two additional elements per dimension. This will make sure that all the threads within the block access data that is available inside the Shared Memory space. As such, **the final exercise for you would be to consider the boundaries of each thread block**. We already gave you a hint in the declaration of the constant `BLOCK_SIZE_SH` (i.e., two extra columns and rows are needed).

☒ TO-DO**[B2.2]**

Extend the Shared Memory version of `gpu_gaussian()` and `gpu_sobel()` to transfer part of the surrounding pixels of the thread block to Shared Memory. Make sure that you do not exceed the boundaries of the image.

Hint #1: Once again, use `__syncthreads()` to guarantee that all the threads have copied their pixels to the Shared Memory. You will need more than one call to this function.

After your implementation is completed, you will see that the execution time has been reduced around 5-10ms, compared to the original implementation. The output should state something as:

```
Step #1 Completed - Result stored in "images/lab02_result_1.bmp".  
Elapsed CPU: 52ms / Elapsed GPU: 16ms  
Step #2 Completed - Result stored in "images/lab02_result_2.bmp".  
Elapsed CPU: 270ms / Elapsed GPU: 19ms  
Step #3 Completed - Result stored in "images/lab02_result_3.bmp".  
Elapsed CPU: 570ms / Elapsed GPU: 20ms
```

Despite this might not seem as a major achievement, this change represents between 15% to 30% performance improvement. In fact, in real-time rendering such as in games, saving 5ms could make a huge difference in performance. Here, the limit per frame is usually around 16ms for 60FPS or 33ms for 30FPS. Hence, game developers usually fight for any slight optimization of the code that could make them achieve these rates.

Nonetheless, **we must note that this was a very naive implementation**. We just wanted you to try how you could define a Shared Memory space in the GPU, as a fine grain performance optimization. However, we did not account for other issues, such as memory bank conflicts, that could boost the performance considerably. In fact, we could have combined the Gaussian and Sobel filters to exploit data locality. Advanced users might be interested in reading the following article from NVIDIA: <https://goo.gl/1WuZGy>.