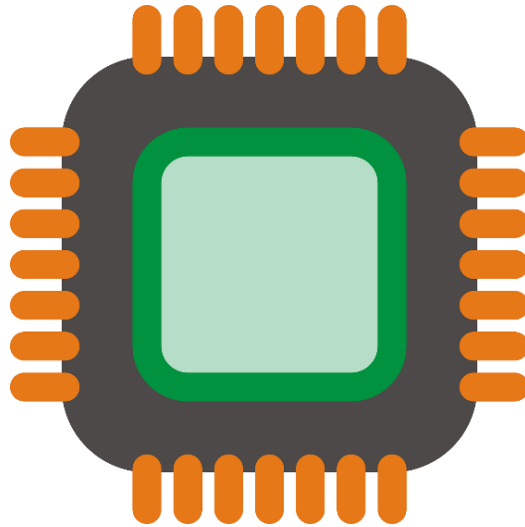


LOW POWER SCHEDULING FOR HIGH LEVEL SYNTHESIS

Hardware Software Co-
Design

MOTIVATION



WHY HIGH LEVEL SYNTHESIS (HLS)?

Power consumption can be reduced by:

Reducing chip and
package capacitance
→ Expensive.

Scaling the supply
voltage → Need
extra circuits.

Better design
techniques → Cost-
effective.

Power management
strategies →
significant power
savings.



Solution: Integrate power scheduler in
High Level Synthesis (HLS) [1].

WHAT IS HLS?

- Translation function from behavioural to structural description [3].
- Three phases [1]:
 - Scheduling: which clock cycle?
 - Allocation: how many resources?
 - Binding: which operation to which resource?

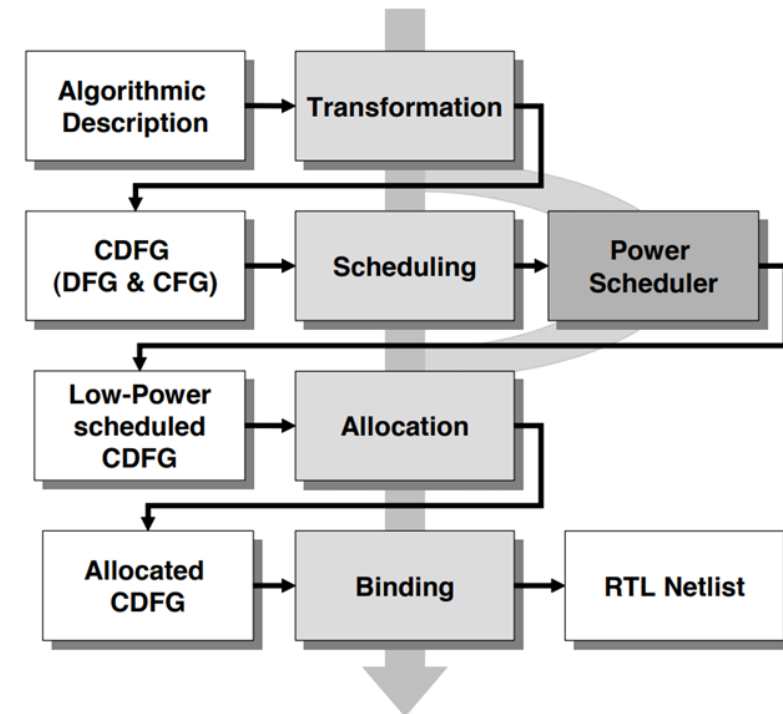


Fig. 1: HLS Design Flow with Power Scheduler integrated [1]

DISSIPATION SOURCE AND REDUCTION METHOD

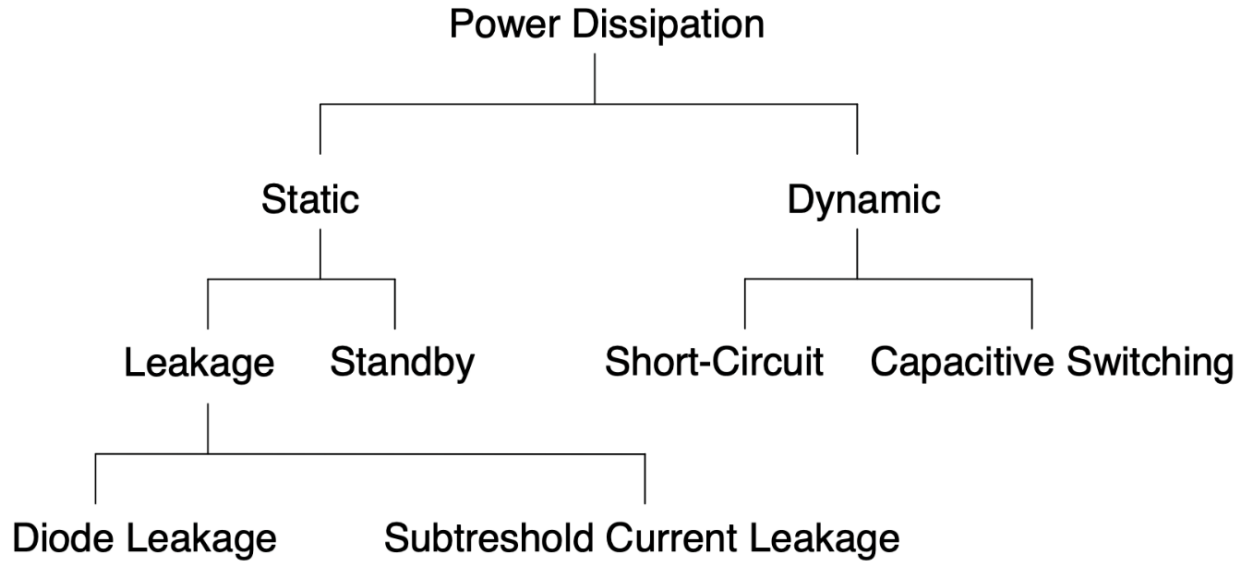


Fig. 2: Sources of power dissipation [1]

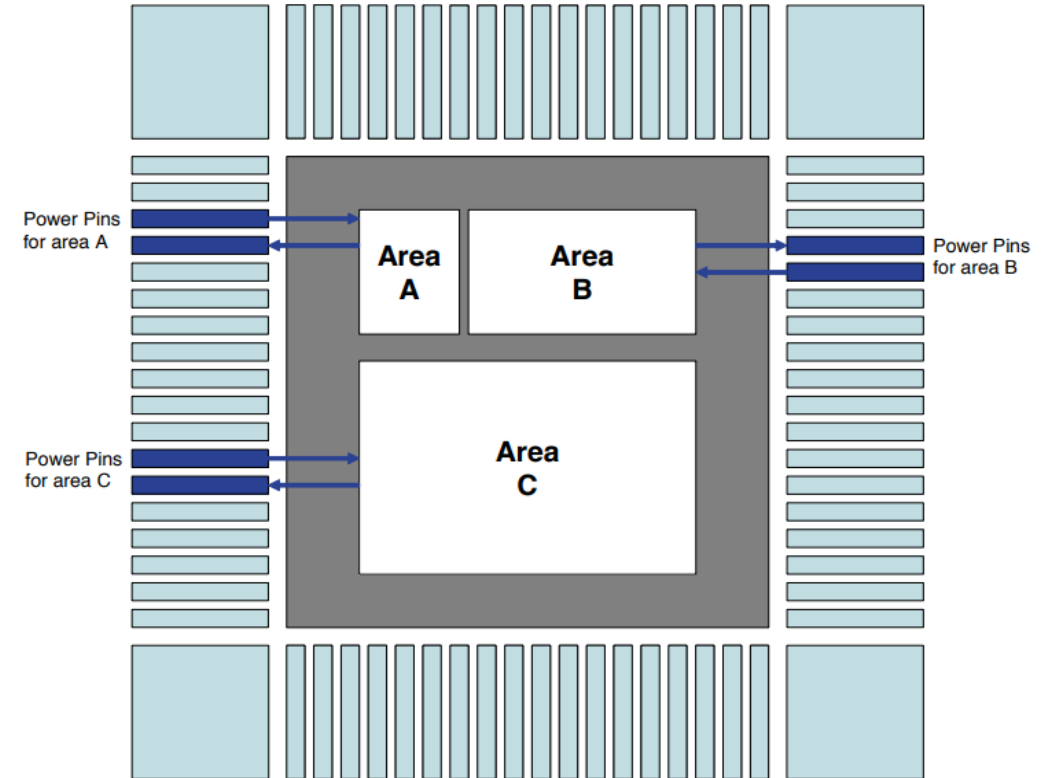


Fig. 3: Power down [1]

STRATEGY

- **Goal 1:** Dedicated turn-on and turn-off mechanisms.
- **Goal 2:** Minimizing control components for those mechanisms.
- **Technique:** Power down.
- **Scheduling method:** Partitioning.

FLOW OF POWER SCHEDULER

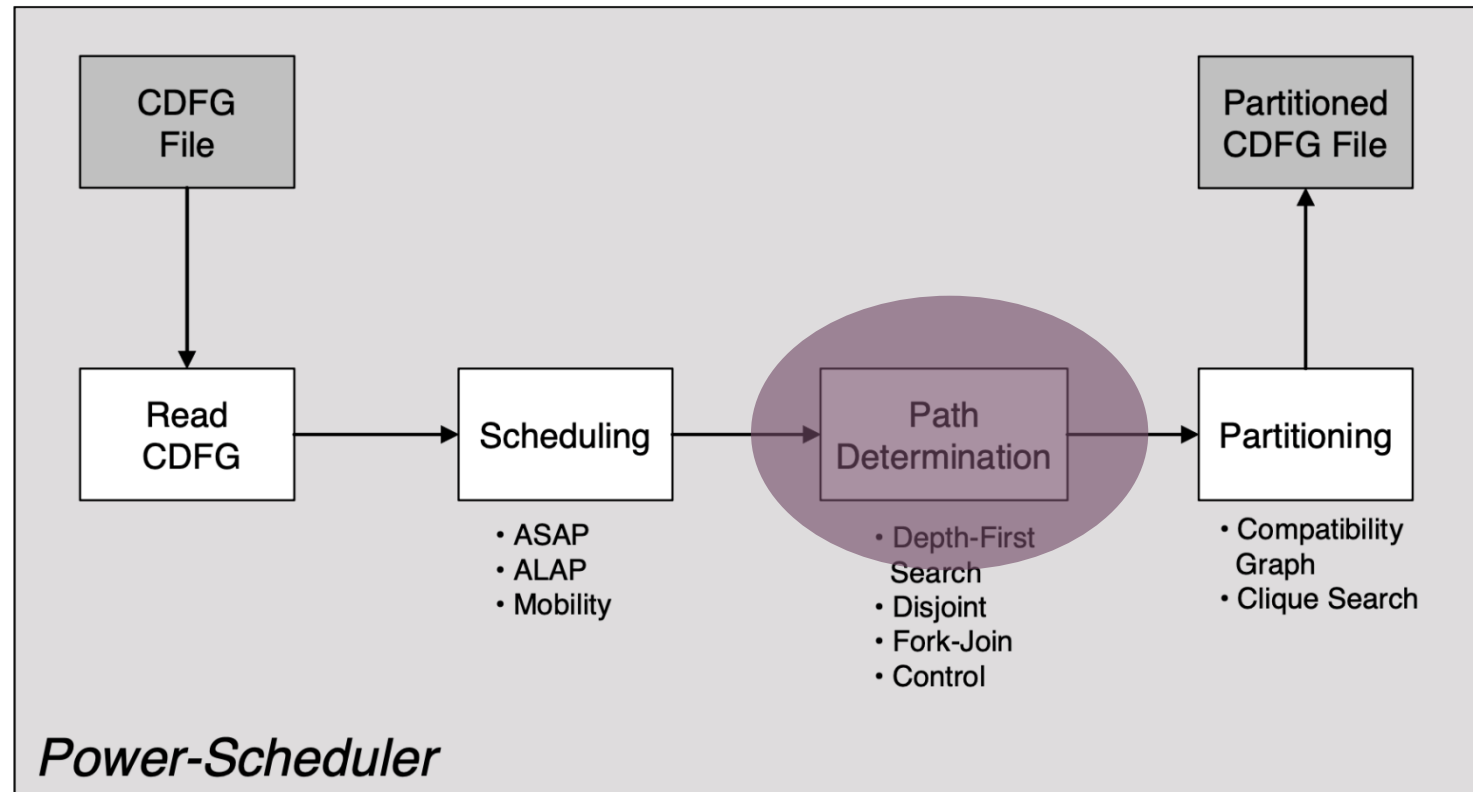


Fig. 4: Steps of Power Scheduler [1].

DISJOIN PATH CALCULATION

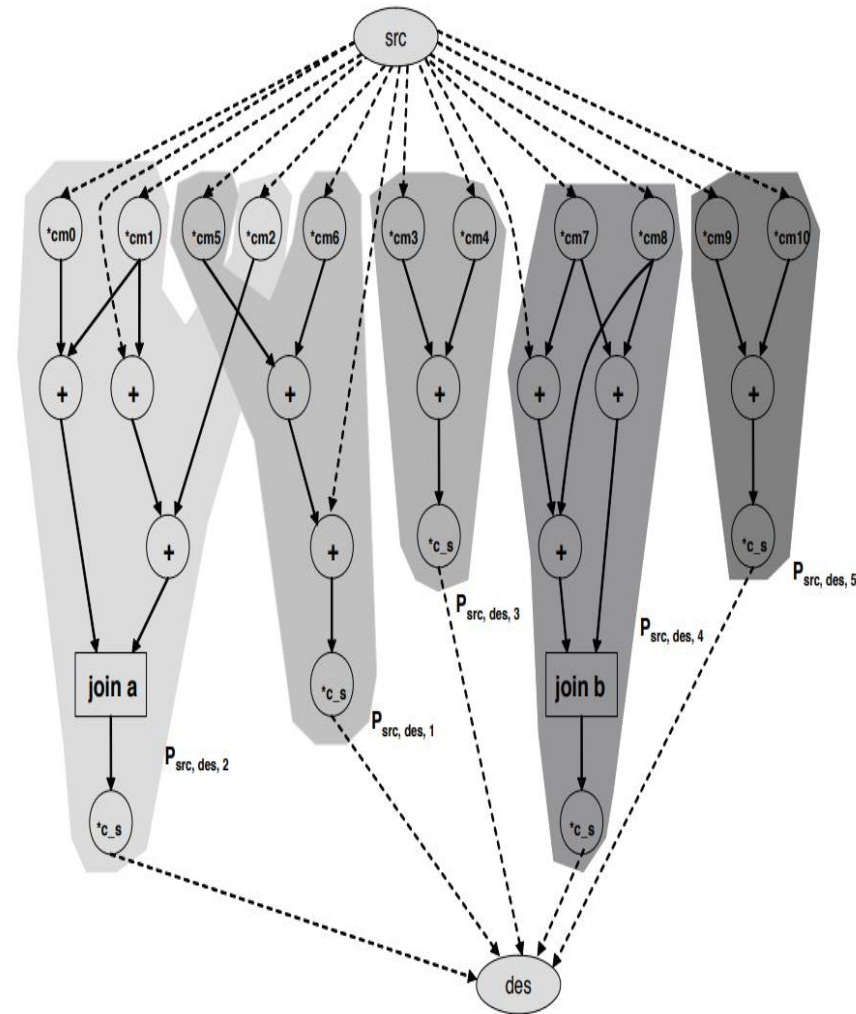
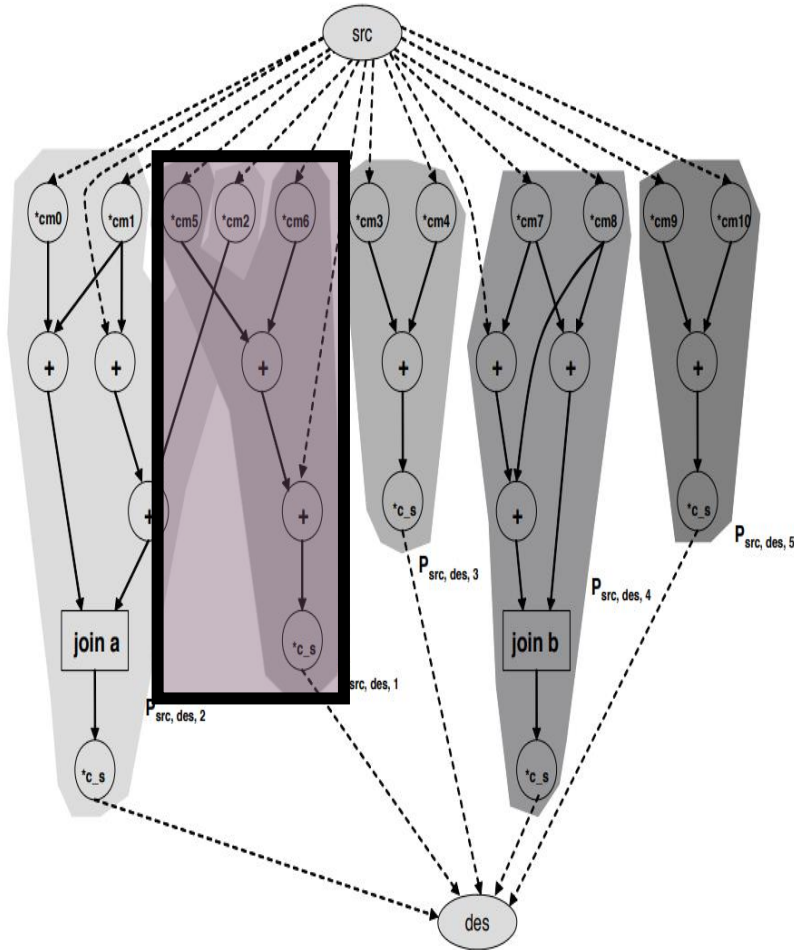


Fig. 5: Fork-join path analysis [1].

DISJOIN PATH CALCULATION



- * : 2 timesteps
- + : 1 timestep.

Name	Path	Time
$P_{src,des,1}$	{*cm5,*cm6, + , +,*c_s}	4
$P_{src,des,2}$	{*cm0,*cm1 , *cm2, + +, +, join a, *c_s}	5
$P_{src,des,3}$	{*cm3,*cm4 , +,*c_s}	3
$P_{src,des,4}$	{*cm7, *cm8, + , +, +, join b, *c_s}	5
$P_{src,des,5}$	{*cm9,*cm10 , +,*c_s}	3

Table 1: Determined path from disjoint paths [1].

Fig. 5: Fork-join path analysis [1].

FORK-JOIN PATH CALCULATION

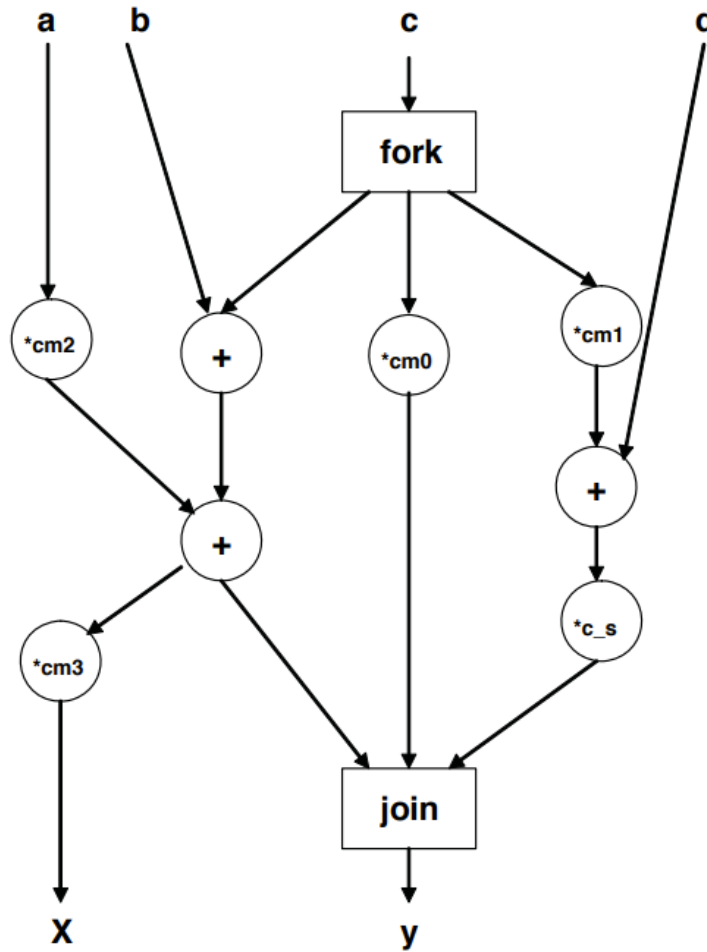
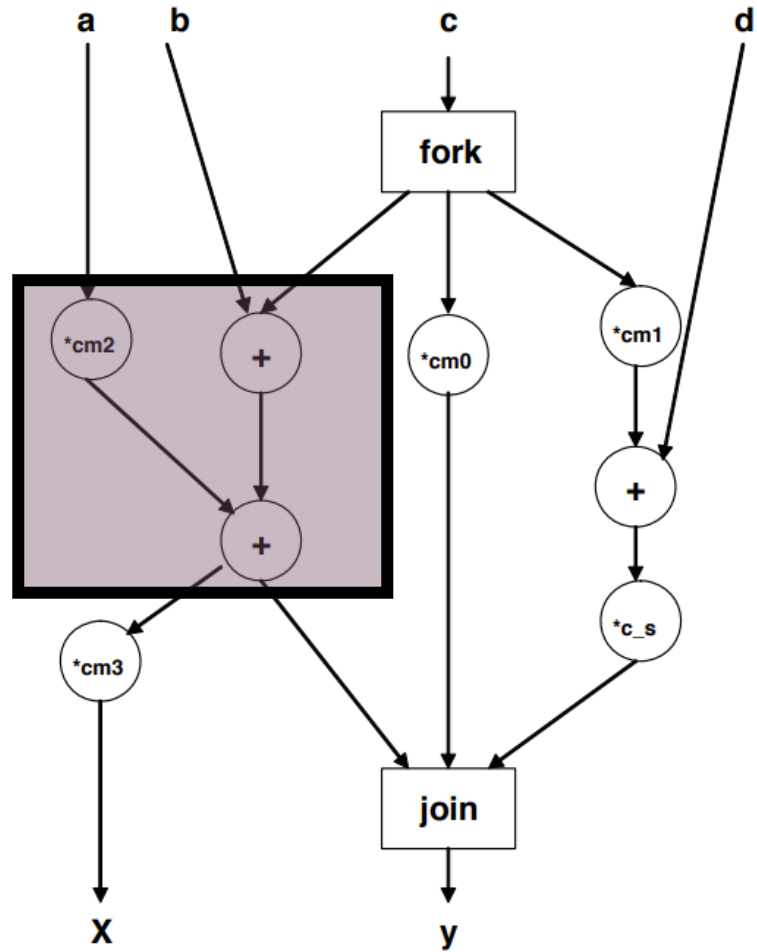


Fig. 6: Fork-join path analysis [2].

FORK-JOIN PATH CALCULATION



- * : 2 timesteps
- + : 1 timestep.

Name	Path	Time
$P_{\text{fork,join},1}$	{*cm2, + , +}	4
$P_{\text{fork,join},2}$	{*cm0}	2
$P_{\text{fork,join},3}$	{*cm1,+,*cs}	5

Table 2: Determined path from fork-join paths [1].

Fig. 6: Fork-join path analysis [2].

CONTROL PATH CALCULATION

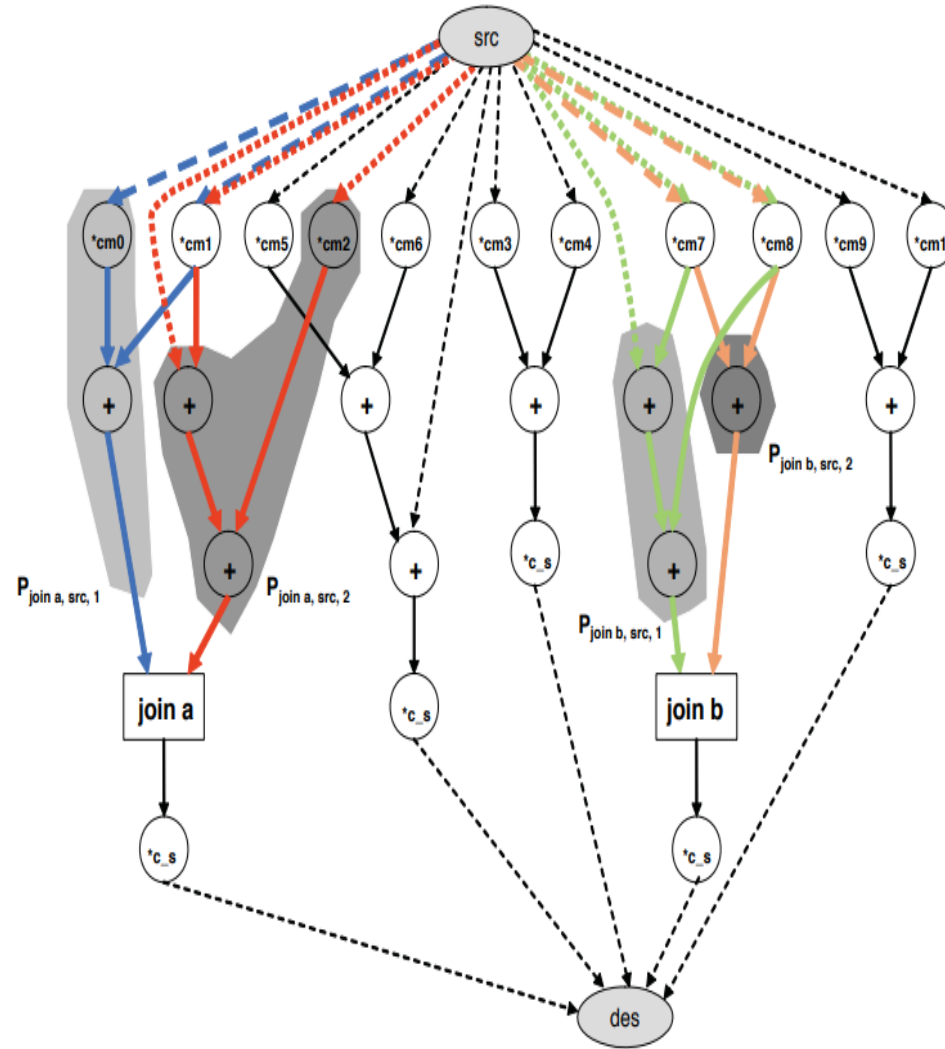
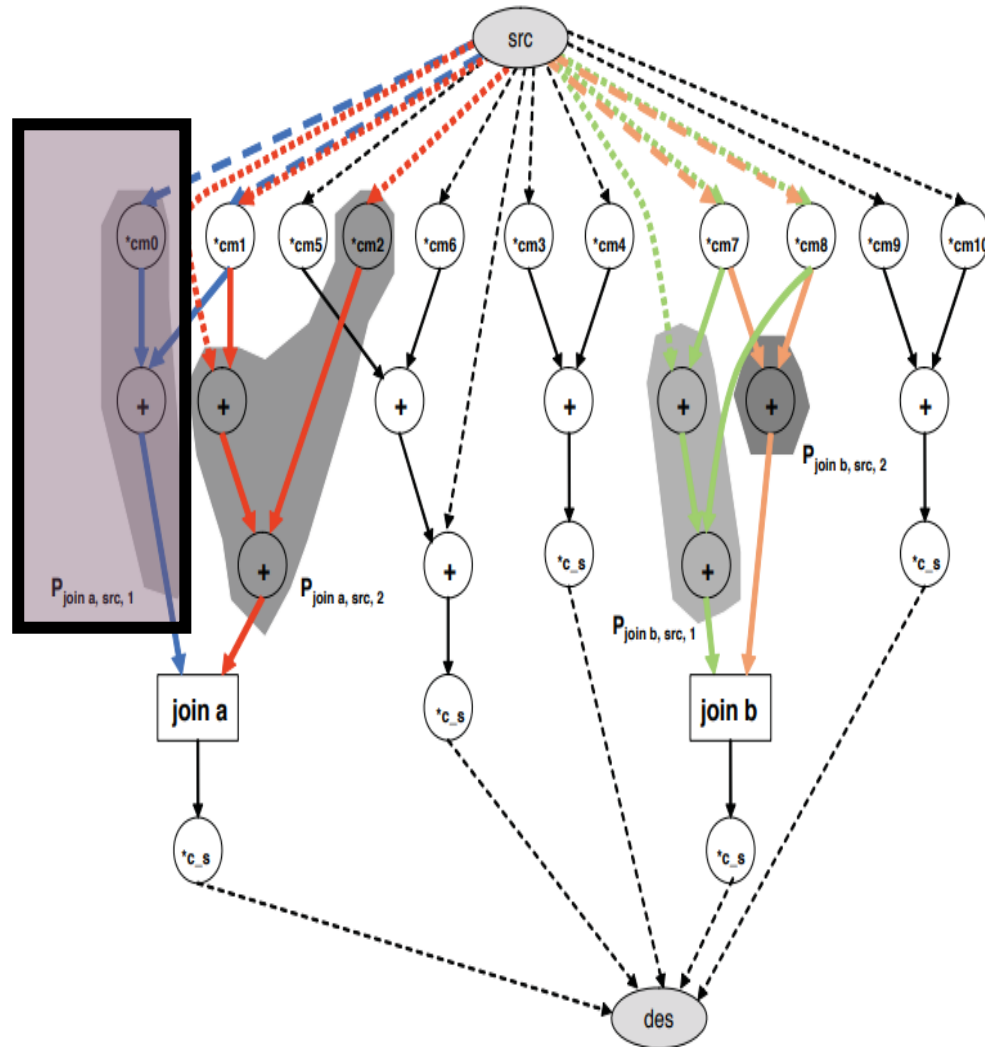


Fig. 7: Control path analysis [1].

CONTROL PATH CALCULATION

- * : 2 timesteps
- + : 1 timestep.



Name	Path	Time
$P_{\text{join a,src,,1}}$	{*cm0, +}	2
$P_{\text{join a,src,,1}}$	{*cm2, +, +}	2
$P_{\text{join b,src,,1}}$	{+, +}	2
$P_{\text{join b,src,,1}}$	{+}	1

Table 3: Determined path from control paths [1].

Fig. 7: Control path analysis [1].

COMPATIBILITY GRAPH

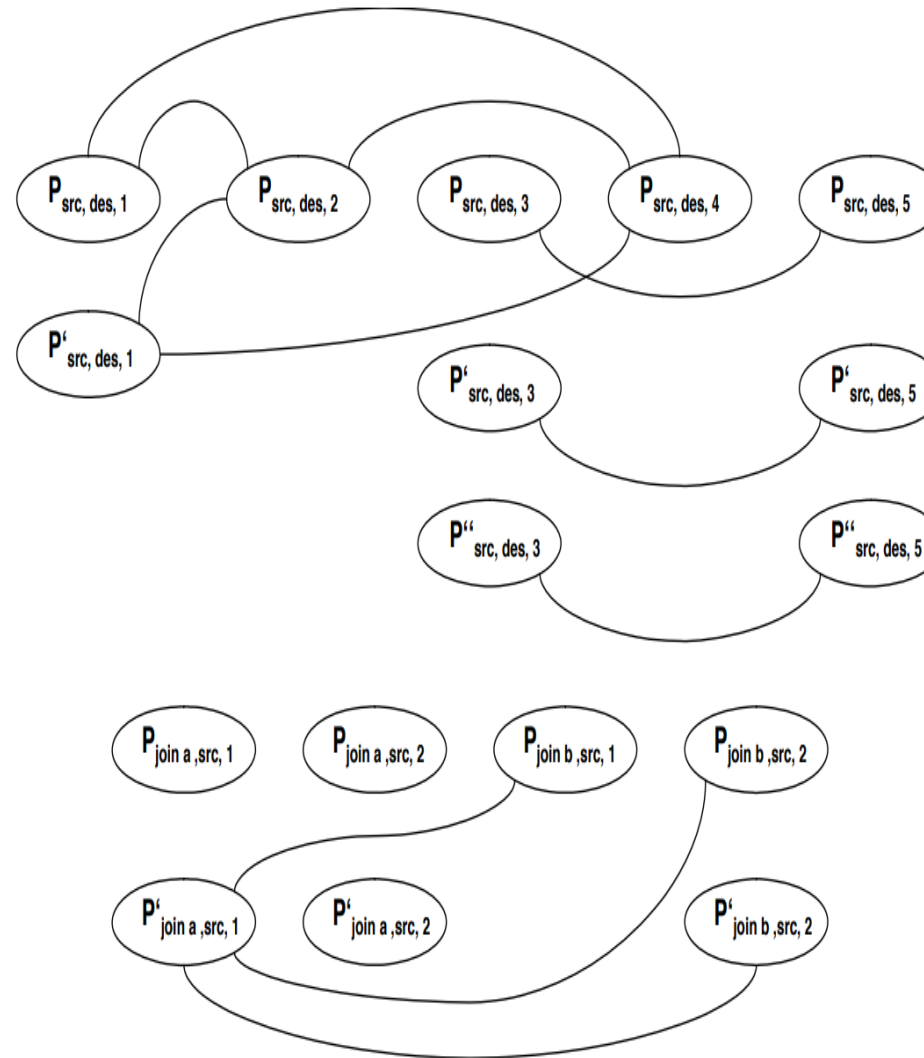


Fig. 8: Formation of compatibility graph [1].

COMPATIBILITY GRAPH

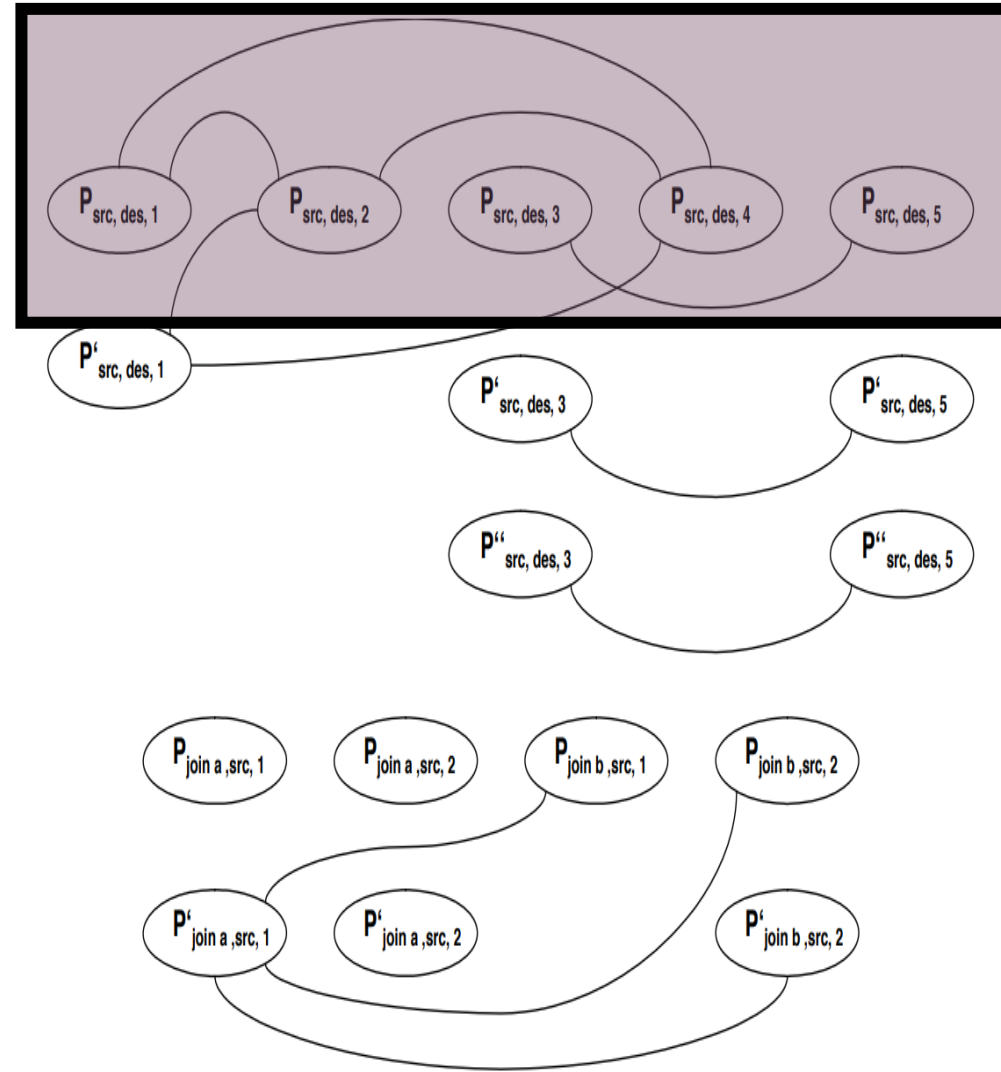
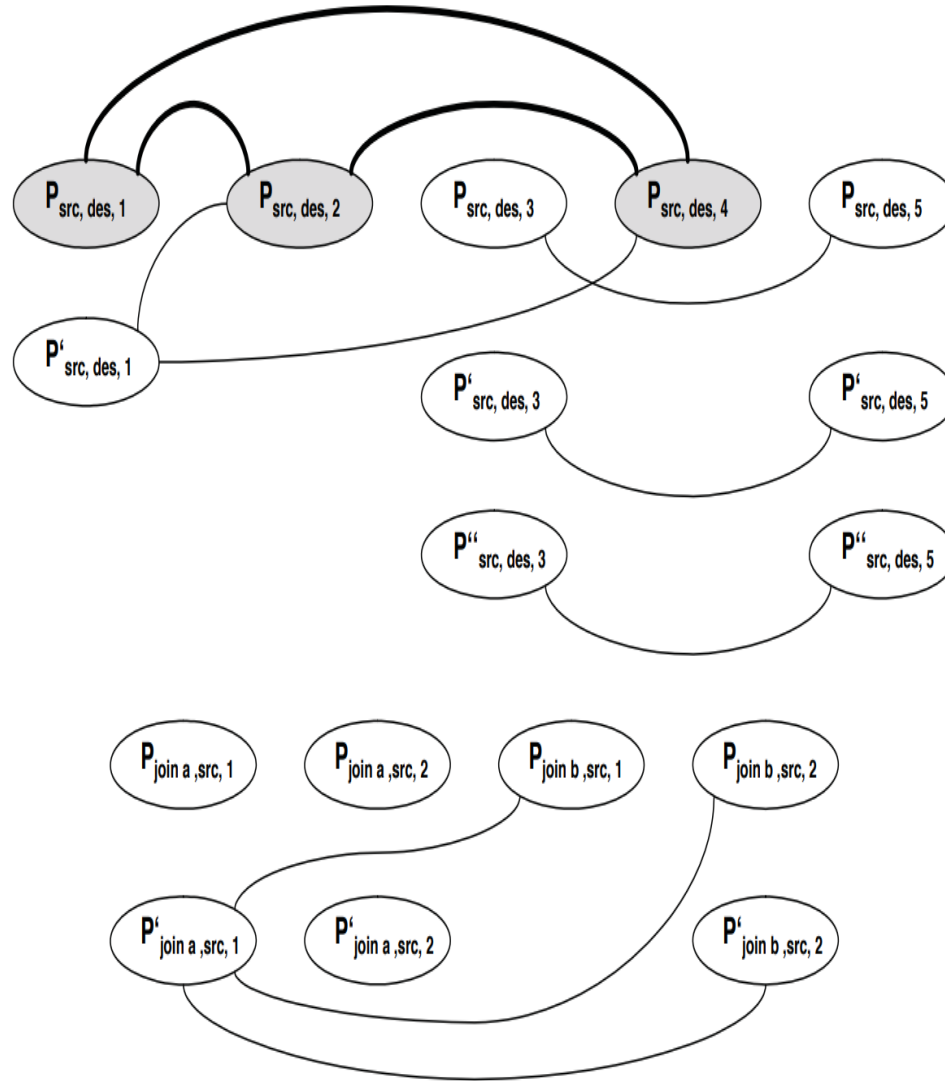


Fig. 8: Formation of compatibility graph [1].

CLIQUE SEARCH



Name	Partition
A1	$P_{src,des,1} , P_{src,des,2} , P_{src,des,4}$
A2	$P_{src,des,3} , P_{src,des,5}$
A3	$P_{join b,src,1} , P'_{join a,src,1}$
A4	$P_{join a,src,2}$
A5	$P_{join b,src,2}$

Table 4: Partitions determined from clique search [1].

Fig. 11: Clique search from compatibility graph[1].

OVERVIEW AND CONCLUSION

	Partitioned	Unpartitioned
Power consumption	1008000 μ J	1180000 μ J

Table 5: Difference in energy consumption between partitioned and unpartitioned approach [1].

- Low power driven synthesis is discussed.
- A developed power scheduler is the focus.
- Scheduler produces partitioned CDFG.
- Partition allows for dedicated turn-on and turn-off mechanism.
- Part of MPEG-2 algorithm is used as an example.
- Energy saving of 15% achieved [4].

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