
Containing Control Hazards

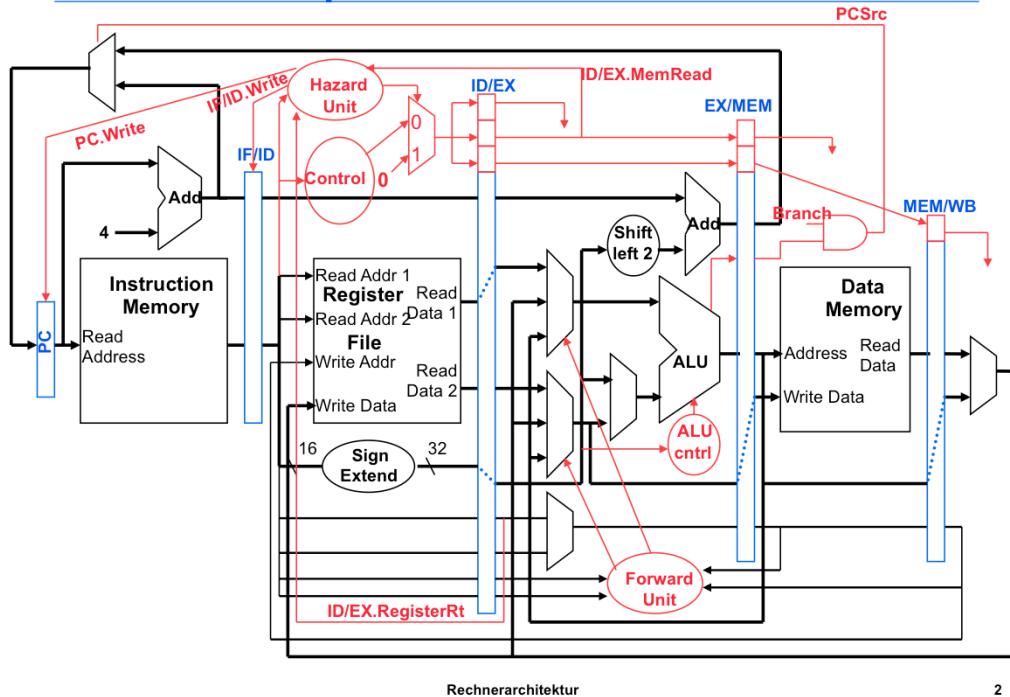
[Adapted from Mary Jane Irwin for
Computer Organization and Design,
Patterson & Hennessy, © 2005, UCB]

Other handouts

To handout next time

Ab 6.6. im Buch

Review: Datapath with Data Hazard Control



Review of last lecture

Data Hazards:

- 1/ result is used before being computed: forward result (from EX/MEM or MEM/WB registers) as soon as it is available
- 2/ result is obtained via load (lw) : stall 1 cycle

The hazard detection unit controls the writing of the PC and the IF/ID registers plus the multiplexor that chooses between the control values and all zeros (STALL - noop).

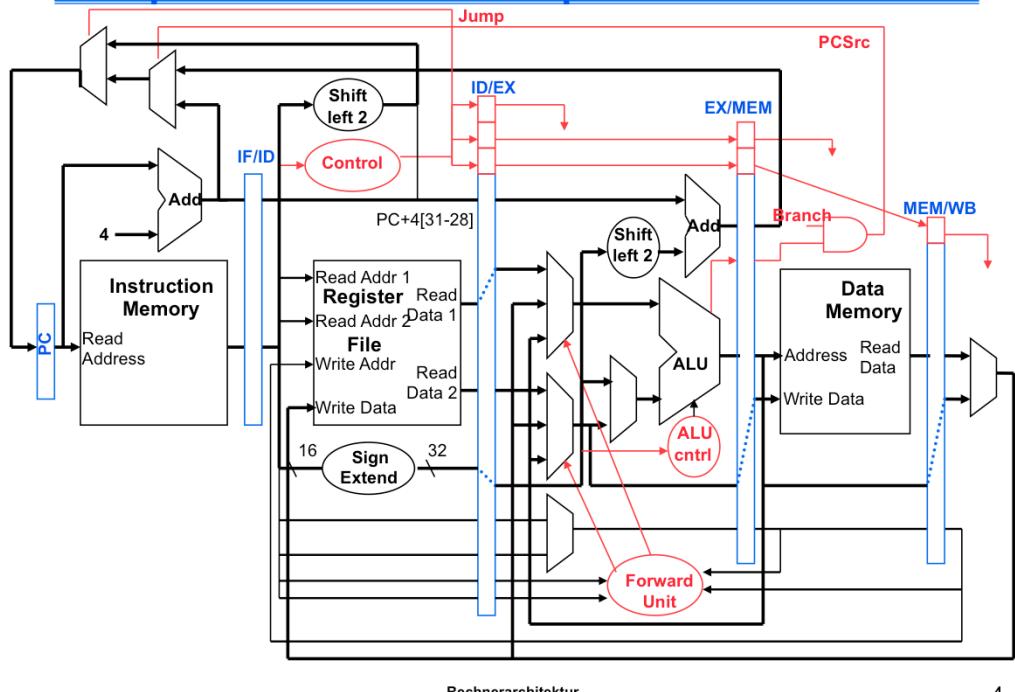
This means that the hazard detection unit stalls and deasserts the control fields if the load-use hazard test is true.

Control Hazards

- ❑ When the flow of instruction addresses is not sequential (i.e., $PC = PC + 4$); incurred by change of flow instructions
 - Conditional branches (`beq`, `bne`)
 - Unconditional branches (`j`, `jal`, `jr`)
 - Exceptions
- ❑ Possible approaches
 - Stall (impacts CPI)
 - Move decision point as early in the pipeline as possible, thereby reducing the number of stall cycles
 - Delay decision (requires compiler support)
 - Predict and hope for the best !
- ❑ Control hazards occur less frequently than data hazards, but there is *nothing* as effective against control hazards as forwarding is for data hazards

2 schemes to resolve control hazards and
1 optimization to improve on these schemes.

Datapath Branch and Jump Hardware



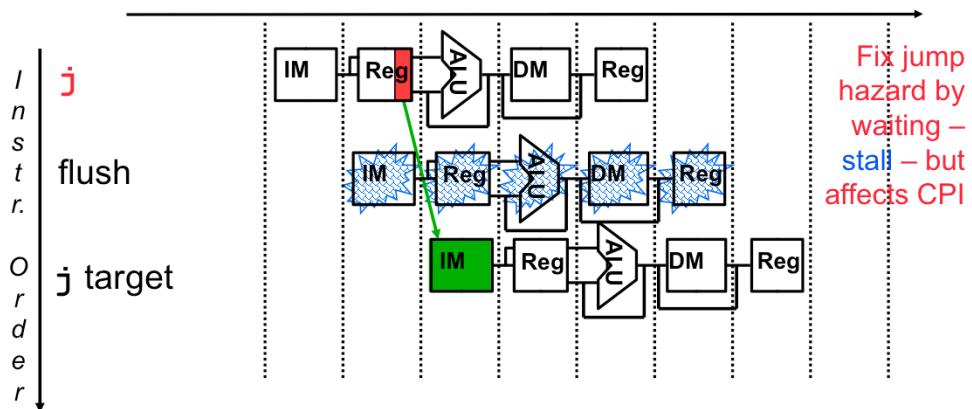
Rechnerarchitektur

4

For lecture

Jumps Incur One Stall

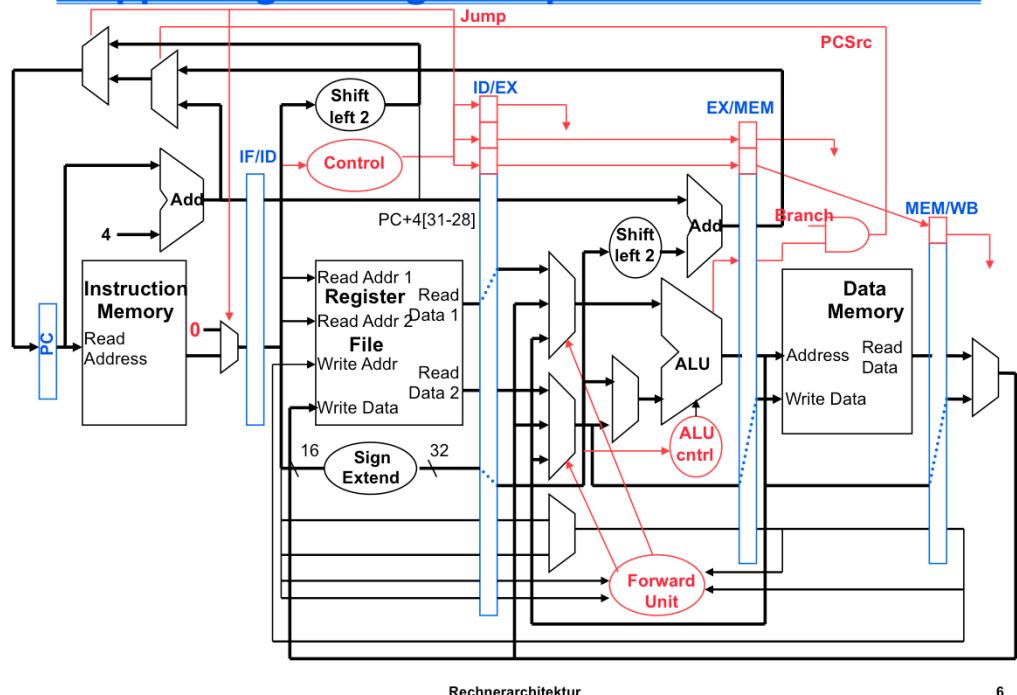
- ❑ Jumps not decoded until ID, so one **flush** is needed



- ❑ Fortunately, jumps are very infrequent – only 3% of the SPECint instruction mix

Fortunately, jumps are very infrequent – less than 2% of the SPECint instructions and x% of the SPECfp ones.

Supporting ID Stage Jumps



Rechnerarchitektur

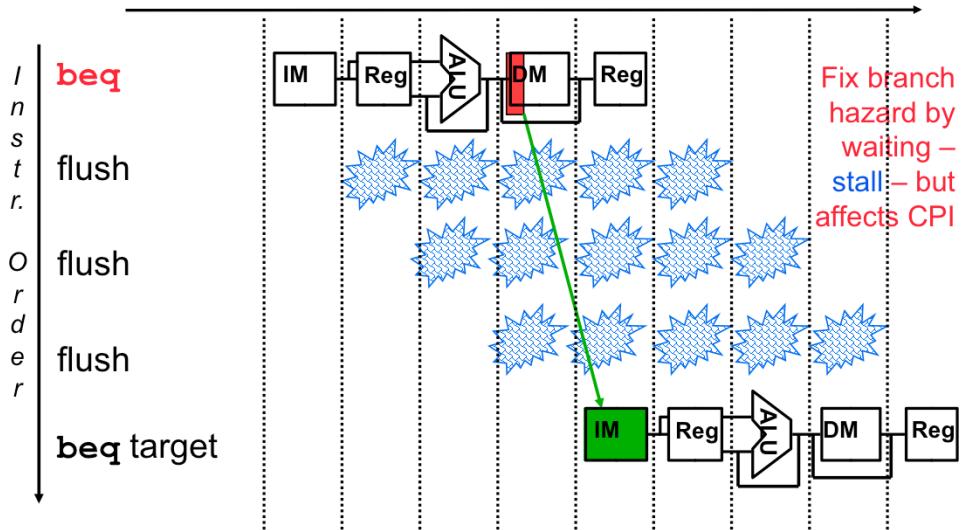
6

We set control signals to 0 as we did for the load (lw) instruction

Two “Types” of Stalls

- ❑ Noop instruction (or bubble) **inserted** between two instructions in the pipeline (as done for load-use situations)
 - Keep the instructions *earlier* in the pipeline (later in the code) from progressing down the pipeline for a cycle (“bounce” them in place with write control signals)
 - Insert `noop` by zeroing control bits in the pipeline register at the appropriate stage
 - Let the instructions later in the pipeline (earlier in the code) progress normally down the pipeline
- ❑ Flushes (or instruction squashing), where an instruction in the pipeline is **replaced** with a `noop` instruction (as done for instructions located sequentially after j instructions)
 - Zero the control bits for the instruction to be flushed

Review: Branches Incur Three Stalls



Another “solution” is to put in enough extra hardware so that we can test registers, calculate the branch address, and update the PC during the second stage of the pipeline. That would reduce the number of stalls to only one.

A third approach is to make a prediction to handle branches, e.g., always predict that branches will be untaken. When right, the pipeline proceeds at full speed. When wrong, have to stall (and make sure nothing completes – changes machine state – that shouldn’t have). Will talk about these options in more detail in next lecture.

Moving Branch Decisions Earlier in the Pipe

- ❑ Move the branch decision hardware back to the EX stage
 - Reduces the number of stall (flush) cycles to two
 - Adds an `and` gate and a 2×1 mux to the EX timing path
- ❑ Add hardware to compute the branch target address `and` evaluate the branch decision in the ID stage
 - Reduces the number of stall (flush) cycles to one (like with jumps)
 - But now need to add **forwarding hardware** in ID stage
 - Computing branch target address can be done in parallel with RegFile read (done for all instructions – only used when needed)
 - Comparing the registers cannot be done until after RegFile read, so comparing and updating the PC adds a mux, a comparator, and an `and` gate to the ID timing path
- ❑ For deeper pipelines, branch decision points can be even *later* in the pipeline, incurring more stalls

9

Want a small branch penalty.

Need more forwarding and hazard detection hardware for second option (one stall implementation) since a branch depended on a result still in the pipeline (that is one of the source operands for the comparison logic) must be forwarded from the EX/MEM or MEM/WB pipeline latches.

The calculation of the branch address is relatively easy to do:

We have PC and the IMMEDIATE field in the IF/ID register; then move branch adder from the EX stage to the ID stage (address will be always computed)

The branching decision is more complicated:

Need forwarding and hazard detection hardware (decision can depend on values still in the pipeline)

ID Branch Forwarding Issues

- ❑ MEM/WB “forwarding” is taken care of by the normal RegFile write before read operation

WB	add3	\$1,
MEM	add2	\$3,
EX	add1	\$4,
ID	beq	\$1, \$2, Loop
IF	next_seq_instr	

- ❑ Need to forward from the EX/MEM pipeline stage to the ID comparison hardware for cases like

WB	add3	\$3,
MEM	add2	\$1,
EX	add1	\$4,
ID	beq	\$1, \$2, Loop
IF	next_seq_instr	

```
if (IDcontrol.Branch  
and (EX/MEM.RegisterRd != 0)  
and (EX/MEM.RegisterRd == IF/ID.RegisterRs))  
    ForwardC = 1  
if (IDcontrol.Branch  
and (EX/MEM.RegisterRd != 0)  
and (EX/MEM.RegisterRd == IF/ID.RegisterRt))  
    ForwardD = 1
```

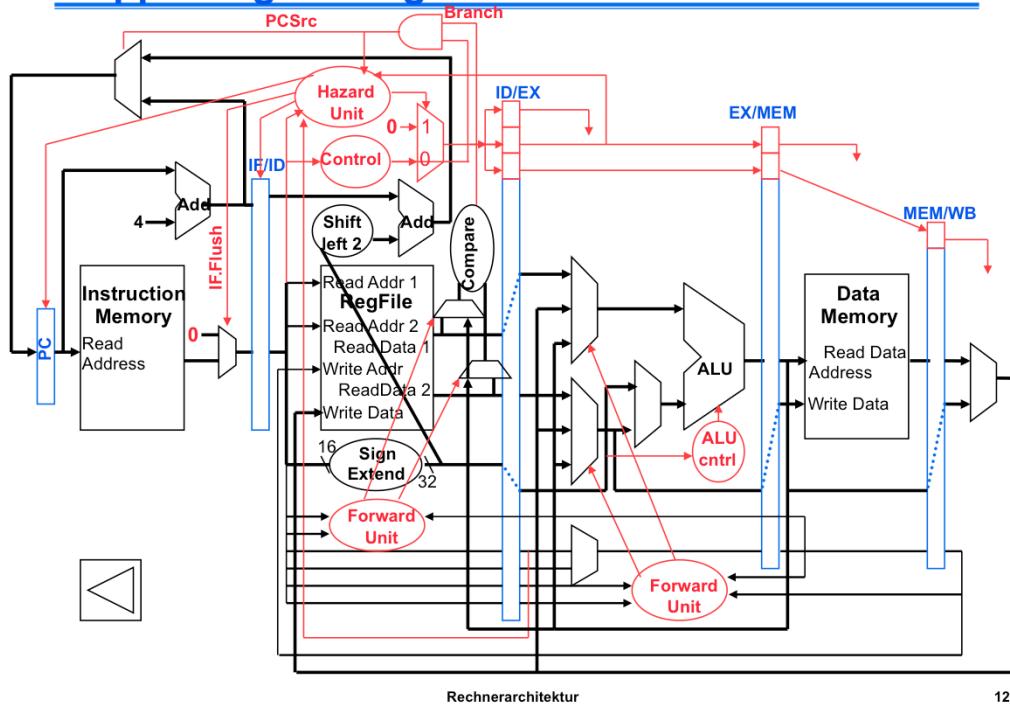
Forwards the result from the second previous instr. to either input of the compare

ID Branch Forwarding Issues, con't

- ❑ If the instruction immediately before the branch produces one of the branch source operands, then a **stall** needs to be inserted (between the `beq` and `add1`) since the EX stage ALU operation is occurring at the *same time* as the ID stage branch compare operation
 - “Bounce” the `beq` (in ID) and `next_seq_instr` (in IF) in place (ID Hazard Unit deasserts PC.Write and IF/ID.Write)
 - Insert a stall between the `add` in the EX stage and the `beq` in the ID stage by zeroing the control bits going into the ID/EX pipeline register (done by the ID Hazard Unit)
- ❑ If the branch is found to be taken, then flush the instruction currently in IF (**IF.Flush**)

WB add3 \$3,
MEM add2 \$4,
EX add1 \$1,
ID beq \$1, \$2, Loop
IF next_seq_instr

Supporting ID Stage Branches



12

Now IF.Flush is generated by the Hazard Unit for both jumps and for taken branches.
Book claims that you have to forward from the MEM/WB pipeline latch, but with RegFile write before read, I don't think that is the case!!

Delayed Decision

- ❑ If the branch hardware has been moved to the ID stage, then we can eliminate all branch stalls with **delayed branches** which are defined as always executing the next sequential instruction after the branch instruction – the branch takes effect *after* that next instruction

- MIPS compiler moves an instruction to immediately after the branch that is not affected by the branch (a **safe** instruction) thereby **hiding** the branch delay



- ❑ With deeper pipelines, the branch delay grows requiring more than one delay slot

- Delayed branches have lost popularity compared to more expensive but more flexible (dynamic) hardware branch prediction
 - Growth in available transistors has made hardware branch prediction relatively cheaper

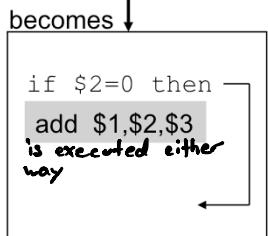
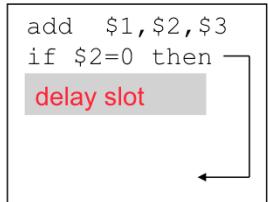


No processor uses delayed branches of more than 1 cycl.

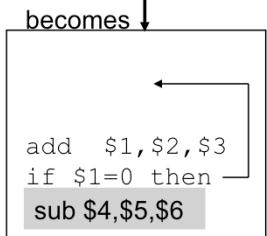
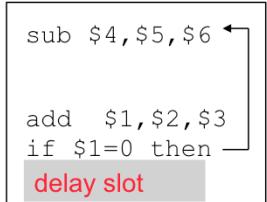
For longer branch delays, hardware-base branch prediction is used.

Scheduling Branch Delay Slots

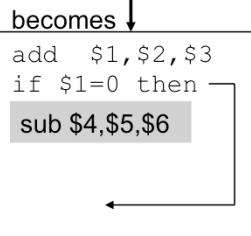
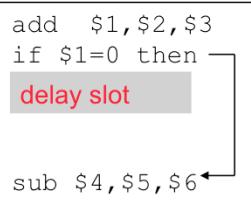
A. From before branch



B. From branch target



C. From fall through



- ❑ A is the best choice, fills delay slot and reduces IC
- ❑ In B and C, the `sub` instruction may need to be copied, increasing IC
- ❑ In B and C, must be okay to execute `sub` when branch fails



Limitations on delayed-branch scheduling come from 1) restrictions on the instructions that can be moved/copied into the delay slot and 2) limited ability to predict at compile time whether a branch is likely to be taken or not.

In B and C, the use of \$1 prevents the add instruction from being moved to the delay slot

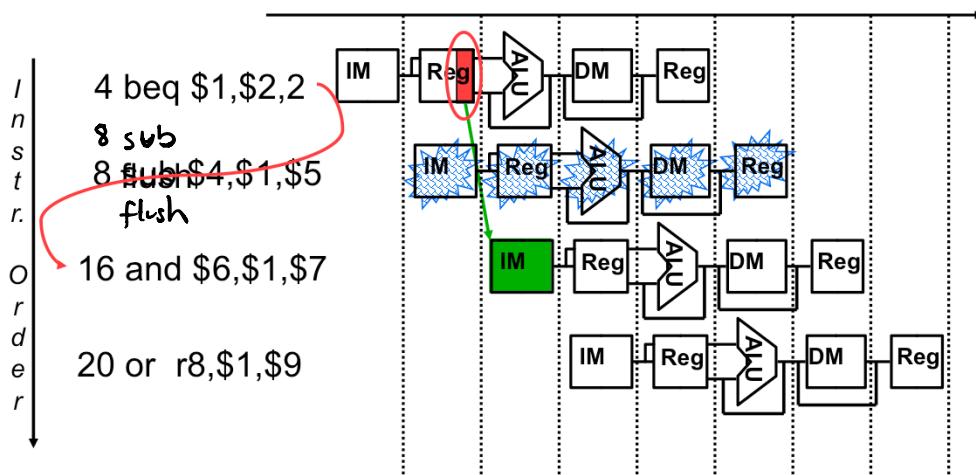
In B the sub may need to be copied because it could be reached by another path. B is preferred when the branch is taken with high probability (such as loop branches)

Static Branch Prediction

- Resolve branch hazards by assuming a given outcome and proceeding without waiting to see the actual branch outcome
- 1. Predict not taken – always predict branches will **not** be taken, continue to fetch from the sequential instruction stream, only when branch *is* taken does the pipeline stall
 - If taken, **flush** instructions **after** the branch (earlier in the pipeline)
 - in IF, ID, and EX stages if branch logic in MEM – **three** stalls
 - In IF and ID stages if branch logic in EX – **two** stalls
 - in IF stage if branch logic in ID – **one stall**
 - ensure that those flushed instructions have not changed the machine state – automatic in the MIPS pipeline since machine state changing operations are at the tail end of the pipeline (MemWrite (in MEM) or RegWrite (in WB))
 - restart the pipeline at the branch destination

This is a static scheme since the same decision is always made (not taken or taken).
This is just what we have already illustrated!

Flushing with Misprediction (Not Taken)



- To flush the IF stage instruction, assert `IF.Flush` to zero the instruction field of the IF/ID pipeline register (transforming it into a `noop`)

For lecture

Note branch address is PC-relative branch to $4+4+2 \cdot 4 = 16$

Branching Structures

- Predict not taken works well for “top of the loop” branching structures

- But such loops have jumps at the bottom of the loop to return to the top of the loop – and incur the jump stall overhead

```
Loop: beq $1,$2,Out
      1nd loop instr
      .
      .
      last loop instr
      j Loop
Out: fall out instr
```

- Predict not taken doesn't work well for “bottom of the loop” branching structures

```
Loop: 1st loop instr
      2nd loop instr
      .
      .
      last loop instr
      bne $1,$2,Loop
      fall out instr
```

Static Branch Prediction, con't

- ❑ Resolve branch hazards by assuming a given outcome and proceeding
- 2. **Predict taken** – predict branches will always be taken
 - Predict taken *always* incurs one stall cycle (if branch destination hardware has been moved to the ID stage)
 - Is there a way to “cache” the address of the branch target instruction ??
- ❑ As the branch penalty increases (for deeper pipelines), a simple static prediction scheme will hurt performance. With more hardware, it is possible to try to predict branch behavior **dynamically** during program execution
- 3. **Dynamic branch prediction** – predict branches at run-time using *run-time* information

Predict taken always incurs one stall at least – assuming the branch destination address hardware has been moved up to the ID stage.

So predict not taken is easier since sequential instruction address can be computed in the IF stage.

Dynamic Branch Prediction

- ❑ A branch prediction buffer (aka branch history table (BHT)) in the IF stage addressed by the lower bits of the PC, contains a bit passed to the ID stage through the IF/ID pipeline register that tells whether the branch was taken the last time it was executed
 - Prediction bit may predict incorrectly (may be a wrong prediction for this branch in this iteration or may be from a different branch with the same low order PC bits) but that does not affect correctness, just performance
 - Branch decision occurs in the ID stage after determining that the fetched instruction is a branch and checking the prediction bit
 - If the prediction is wrong, flush the incorrect instruction(s) in pipeline, restart the pipeline with the right instruction, and invert the prediction bit
 - A 4096 bit BHT varies from 1% misprediction (nasa7, tomcatv) to 18% (eqntott)

4096 entry table programs vary from 1% misprediction (nasa7, tomcatv Floating-Point Benchmark) to 18% (eqntott Wahrheitstabelle einer boolschen Fkt bestimmen, wohl eher ganzzahl), with spice at 9% and gcc at 12%

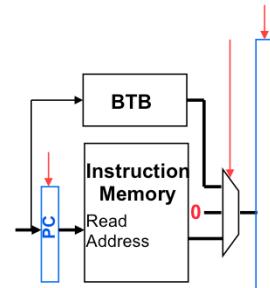
4096 about as good as infinite table, but 4096 is a lot of hardware

Branch Target Buffer

- ❑ The BHT predicts *when* a branch is taken, but does not tell *where* it is taken to!

- A **branch target buffer (BTB)** in the IF stage can cache the branch target address, but we also need to fetch the next sequential instruction. The prediction bit in IF/ID selects which “next” instruction will be loaded into IF/ID at the next clock edge
 - Would need a two read port instruction memory

- Or the BTB can cache the branch taken **instruction** while the instruction memory is fetching the next sequential instruction



- ❑ If the prediction is correct, stalls can be avoided no matter which direction they go

Except for the first time the branch is encountered, when we don't have the branch instruction loaded into the BTB

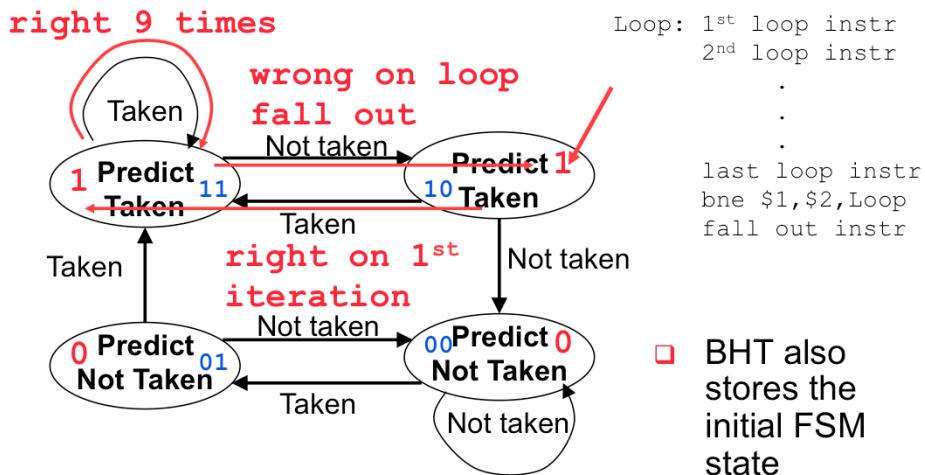
Its not quite this simple – what if the BTB instruction is for the wrong branch!! – but close enough for students at this level

1-bit Prediction Accuracy

- ❑ A 1-bit predictor will be incorrect twice when not taken
 - Assume predict_bit = 0 to start (indicating branch not taken) and loop control is at the bottom of the loop code
 - 1. First time through the loop, the predictor mispredicts the branch since the branch is taken back to the top of the loop; invert prediction bit (predict_bit = 1)
 - 2. As long as branch is taken (looping), prediction is correct
 - 3. Exiting the loop, the predictor again mispredicts the branch since this time the branch is not taken falling out of the loop; invert prediction bit (predict_bit = 0)
- ❑ For 10 times through the loop we have a 80% prediction accuracy for a branch that is taken 90% of the time

2-bit Predictors

- A 2-bit scheme can give 90% accuracy since a prediction must be wrong twice before the prediction bit is changed



For lecture

In a counter implementation, the counters are incremented when a branch is taken and decremented when not taken (and saturate at 00 or 11). Since we read the prediction bits on every cycle, a 2-bit predictor will need both a read and a write access port (for updating the prediction bits).

Dealing with Exceptions

- ❑ Exceptions (aka interrupts) are just another form of control hazard. Exceptions arise from
 - R-type arithmetic overflow
 - Trying to execute an undefined instruction
 - An I/O device request
 - An OS service request (e.g., a page fault, TLB exception)
 - A hardware malfunction
- ❑ The pipeline has to stop executing the offending instruction in midstream, let all prior instructions complete, flush all following instructions, set a register to show the cause of the exception, save the address of the offending instruction, and then jump to a prearranged address (the address of the exception handler code)
- ❑ The software (OS) looks at the cause of the exception and “deals” with it

For undefined instrs, hardware failure, or arith overflow – the OS normally kills the program and returns an indication of the reason to the user

For an I/O device request or an OS service call – the OS saves the state of the program, performs the desired task and, at some point in the future, restores the program to continue execution

MIPS convention: exception for both internal or external change of control flow
and interrupt for external only

Page Fault: access request to memory page in virtual memory but not loaded in physical memory

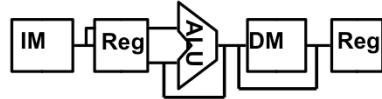
TLB : translation lookaside buffer (cache for virtual memory addressing)

Two Types of Exceptions

- Interrupts – asynchronous to program execution
 - caused by **external events**
 - may be handled **between** instructions, so can let the instructions currently active in the pipeline *complete* before passing control to the OS interrupt handler
 - simply suspend and resume user program

- Traps (Exception) – synchronous to program execution
 - caused by **internal events**
 - condition must be remedied by the trap handler for **that** instruction, so must stop the offending instruction *midstream* in the pipeline and pass control to the OS trap handler
 - the offending instruction may be retried (or simulated by the OS) and the program may continue or it may be aborted

Where in the Pipeline Exceptions Occur



	Stage(s)?	Synchronous?
<input type="checkbox"/> Arithmetic overflow	EX	yes
<input type="checkbox"/> Undefined instruction	ID	yes
<input type="checkbox"/> TLB or page fault <small>the address we want to read is not in memory</small>	IF, MEM	yes
<input type="checkbox"/> I/O service request	any	no
<input type="checkbox"/> Hardware malfunction	any	no

Beware that multiple exceptions can occur simultaneously in a *single clock cycle*

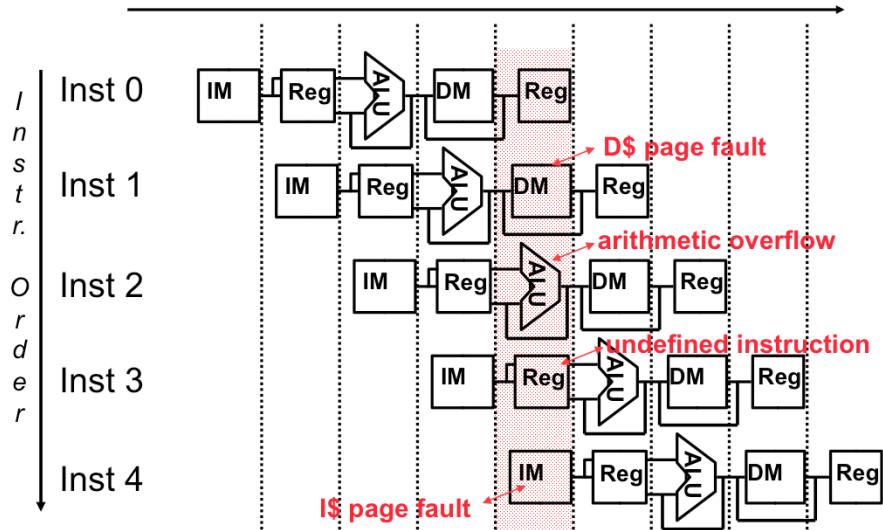
For lecture

Note that an I/O service request is not associated with any executing instruction so can be handled when the hardware decides (to some limit) –i.e., pick the most convenient place to handle the exception

TLB is a [three-letter acronym](#) that can refer to:

[Translation Lookaside Buffer](#), a memory buffer to improve the performance of [virtual memory](#) systems

Multiple Simultaneous Exceptions



- ❑ Hardware sorts the exceptions so that the earliest instruction is the one interrupted first

For lecture

Additions to MIPS to Handle Exceptions

- ❑ Cause register (records exceptions) – hardware to record in Cause the exceptions and a signal to control writes to it (`CauseWrite`)
- ❑ EPC register (records the addresses of the offending instructions) – hardware to record in EPC the address of the offending instruction and a signal to control writes to it (`EPCWrite`)
 - Exception software must match exception to instruction
- ❑ A way to load the PC with the address of the exception handler
 - Expand the PC input mux where the new input is hardwired to the exception handler address - (e.g., 8000 0180_{hex} for arithmetic overflow)
- ❑ A way to flush offending instruction and the ones that follow it

See (Fig 6.42)

Summary

- ❑ All modern day processors use pipelining for performance (a CPI of 1 and a fast CC)
- ❑ Pipeline clock rate limited by **slowest** pipeline stage – so designing a balanced pipeline is important
- ❑ Must detect and resolve hazards
 - Structural hazards – resolved by designing the pipeline correctly
 - Data hazards
 - Stall (impacts CPI)
 - Forward (requires hardware support)
 - Control hazards – put the branch decision hardware in as early a stage in the pipeline as possible
 - Stall (impacts CPI)
 - Delay decision (requires compiler support)
 - Static and **dynamic prediction** (requires hardware support)

CC = Clock Cycle (time)