# Computer Architecture Final Project Report

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### 1 Architecture

#### 1.1 Datapath Design

My overall architecture is basically the same as the one in the textbook. The biggest difference is the newly-added mulDiv module and the relating control signals.

Most of the single-cycle instructions were mentioned in class, so I focus on four instructions that were not: jal, jalr, auipc, and lui.

- 1. jal: The control signals are
  - Jump = 1
  - RegWrite = 1
  - ALUSrc = 1

while others are set to 0. The PC address is set as  $PC_nxt = PC + imm$  (using the J-type immediate format), and the write-back data is  $rd_data = PC + 4$  (saved return address).

- 2. jalr: The control signals are
  - Jump = 1
  - RegWrite = 1
  - ALUSrc = 1

while others are set to 0. The PC address is set as PC\_nxt = (rs1\_data + imm) &  $\sim$ 1 (LSB set to 0 for alignment), and the write-back data is rd\_data = PC + 4 (saved return address).

3. auipc: The control signals are

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#### 1 ARCHITECTURE

- RegWrite = 1
- ALUSrc = 1

while others are set to 0. The ALU inputs for auipc are quite different. Input 1 is the value of PC, while Input 2 is the immediate. The write-back data is  $rd_{data} = PC + imm$ .

- 4. lui: The control signals are
  - RegWrite = 1
  - ALUSrc = 1

while others are set to 0. The ALU inputs are different from other instructions too. Input1 is 0, and Input2 is the immediate. The rd\_data is just the shifted immediate.

#### 1.2 Multi-Cycle Instructions Handling

For these instructions, I added a new control signal "mode", labeling mul, divu, remu as 2'b01, 2'b10, 2'b11 respectively. Meanwhile, for all three instructions, RegWrite is set to 1, MulDivEnable is set to 1, and others are set to 0.

The way I handle multi-cycle instructions is demonstrated in the figure below. When there is a need to run a multi-cycle instruction, the control unit will raise the signal "MulDivEnable" to 1, causing the CPU to enter state "CALC". During this state, the CPU is stalled, and the PC is kept at the same value. Meanwhile, the module "mulDiv" is doing the calculation based on the value of "mode" and will finish after 32 cycles.

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```
always @(posedge clk or negedge rst_n) begin
                if (!rst_n) begin
                    PC <= 32'h00010000;
186
                    state <= IDLE;</pre>
187
188
                    case (state)
                         IDLE: begin
191
                             if (MulDivEnable) begin
192
                                  state <= CALC;</pre>
193
                                  PC <= PC; // Hold PC
194
195
                             else begin
196
                                  PC <= PC_nxt;</pre>
197
                             end
198
                         CALC: begin
                             if (muldiv_ready) begin
                                  state <= IDLE;</pre>
                                  PC <= PC_nxt;</pre>
                             else begin
                                 PC <= PC;
                    endcase
           end
```

Figure 1: code of the design of finite state machine

After the calculation is completed, the "muldiv" signal is raised to 1, and CPU enters the state "IDLE" and PC is allowed to move forward.

## 1.3 Some Logic Update

Due to some added instructions, the PC updating logic and the writeback data logic are slightly different. The changes are shown below.

Figure 2: PC Updating Logic

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#### 2 REGISTER TABLE

```
// Write Back
assign rd_data = Jump ? (PC+4) : write_back_data;
assign write_back_data = MulDivEnable ? muldiv_result :
MemToReg ? mem_read_data : ALUResult;
```

Figure 3: Write-Back Logic

# 2 Register Table

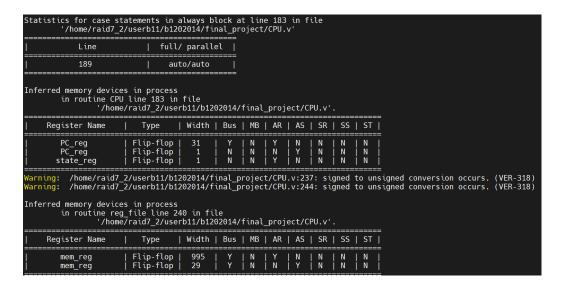


Figure 4: Register Table 1

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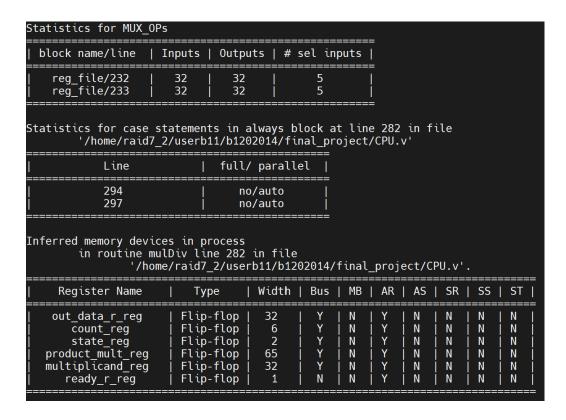


Figure 5: Register Table 2

## 3 Obversation

During my implementation, I encountered several challenges:

- 1. Control Signal Interactions: The ALUOp = 2'b10 for the branch instructions caused subtle bugs because it conflicted with R-type operations.
- 2. Multi-Cycle Instructions: The mulDiv operations required careful state management to prevent PC from advancing before computation finished.
- 3. Jump Instructions: Initially missed that jalr needs to clear the LSB of the target address (&  $\sim$ 1).
- 4. Architecture Designing: I decided to modulize every part of CPU, make my code look cleaner and easier for debugging.

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