

Hardware-Software-Codesign

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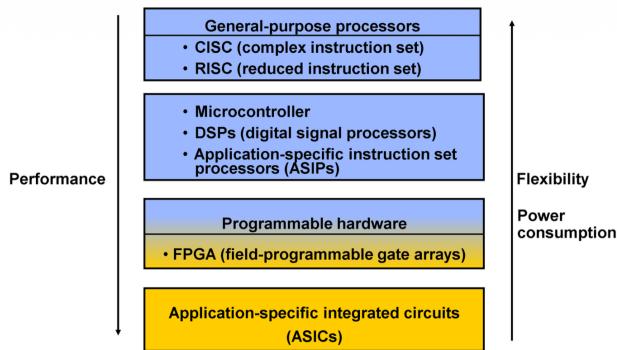


Abbildung 1: Implementation Styles

Architectures

See fig. 1

General-Purpose Processors

- Properties
 - high performance for a broad range of applications, not optimized for any particular application
 - high power consumption
- Design
 - highly optimized circuits
 - design times $\gtrsim 100$ person years
 - cost/device only cheap when fabricated in huge numbers
- Application areas
 - PCs
 - Smartphones

Reasons for High Performance

- Exploitation of parallelism
 - multiple scalar units (superscalar)
 - * Functional units: integer units, floating-point unit, load/store-unit
 - * Dynamic scheduling
 - * instruction compatibility

- * complex control unit
- deep instruction pipeline
 - * fetch | decode | read | execute | write back
 - * each scalar unit may have individual pipeline depth
 - * branch prediction
- Multi-level memory hierarchy
 - \uparrow Speed \Rightarrow \downarrow Size \Leftrightarrow \uparrow Size \Rightarrow \downarrow Speed
 - Register < Cache < Main Memory

General-Purpose Processors and Real-Time

- Execution time of programs is not well predictable
 - Dynamic scheduling
 - Caching
 - Branch prediction
- Complex I/O and memory interface

Multimedia - Extensions and Sub-words

- Multimedia Applications
 - 8 / 16 Bit data types
 - many arithmetic operations
 - huge data sets \Rightarrow Huge I/O-bandwidth
 - high data parallelism
- Sub-word execution
 - split 32/64-bit registers and ALUs into smaller sub-units
 - instructions execute in parallel on these sub-units
 - compromise between usage of parallelism and available data paths
 - currently most often based on hand-written assembly routines
 - Depends on language with defined bit width per data type and diverse overflow semantics
 - Compiler needs to automatically detect sub-word parallelism

Microcontrollers

- For control-dominant applications
 - control flow dominant programs (many branches and jumps)
 - few arithmetic operations
 - low throughput requirements
 - multitasking
- Microcontrollers are optimized for
 - Bit- and logic-level operations
 - Registers often realized in RAM: context switch through pointer operation, therefore shortest interrupt latencies
 - integrated peripheral units (e.g. A/D, D/A, CAN, Timer)
- Systems with 4/8 bit processors
- Microcontrollers with high performance
 - 16 - 64 bit processors
 - Application areas
 - * Systems with high control-dominant parts and additional demand
 - * High throughput (telecommunication, automotive)
 - * Computational power (industrial control, signal processing)
 - * As a part of an SOC

Digital Signal Processors

- Signal processing applications
 - data-flow dominant
 - many arithmetic operations, less branches and jumps
 - high degree of parallelism
 - high throughput requirements
- DSPs are optimized for
 - parallel instruction processing (MAC fig. 2)
 - Harvard Architecture, simultaneous access of multiple operands
 - zero-overhead loops
 - special addressing modes (circular, bit-revers)

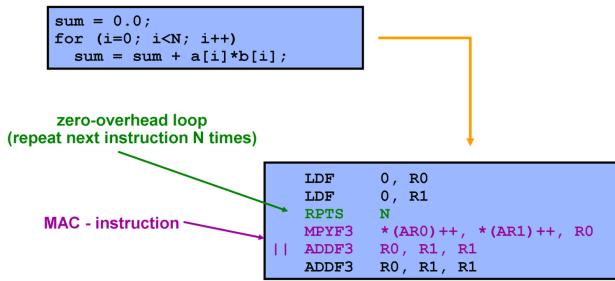


Abbildung 2: Multiply & accumulate

DSP - Arithmetics

- Number formats
 - Mantissa determines precision
 - Exponent determines dynamic range
- Fixed point
 - in case of equal mantissa length smaller (cheaper) and faster as floating-point
 - application design requires consideration of rounding and scaling problems
 - sufficient for many DSP applications
- Floating point
 - high dynamic range of numbers
 - easier application program development

DSP - Program Development

- Assembler, Complier
 - Many DSP features still only usable if code is written in assembly
 - Programming in C → profiling → time-critical parts in assembly code
- Libraries
 - Programming in C, call of hand-written optimized functions
- Code generation
 - Usage of design environments for modeling, simulation and code generation
 - e.g. Synopsis

DSP - Trends

- Multi-DSP Systems
 - for applications requiring highest performance
 - interfaces available to connect multiple processors
 - Multi-Processor SoC (MPSoC)
- VLIW (Very long instruction word)
 - multiple functional units
 - Compiler detects parallelism and creates a program that schedules multiple instructions jointly
 - Only useful for applications with high degree of instruction parallelism
 - suffers often from low code density
 - compilation difficult

Application-specific instruction set processors (ASIP)

- Specialization
 - instruction set (Operant chaining)
 - functional units (pixel operations, $1/\sqrt{x}$)
 - memory architecture (parallel access onto multiple memory banks)
- Advantages
 - higher performance
 - lower cost
 - smaller code images
 - lower power consumption

Integrated Circuit

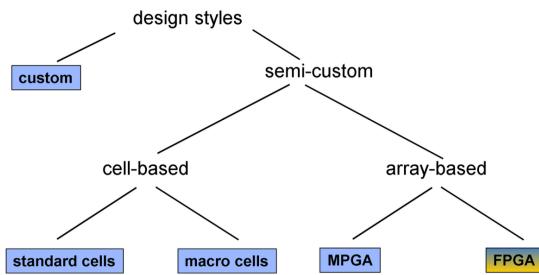
Phases of IC Design

1. Design
 - (a) Modeling
 - (b) Synthesis & Optimization
 - (c) Verification
2. Fabrication
 - (a) Masks
 - (b) Wafer
3. Testing

4. Packaging

- (a) Slicing
- (b) Packaging

Design Styles for ICs



- MPGA: mask-programmable gate array (beim Hersteller "programmiert")
- FPGA: field-programmable gate array (beim Anwender "programmiert")

Abbildung 3: Design Styles for ICs

Comparison of Design Styles

	Custom	Cell-based	MPGA	FPGA
Density	very high	high	high	medium-low
Performance	very high	high	high	medium-low
Design time	very long	short	short	very short
Manufacturing time	medium	medium	short	very short
Cost-low volume	very high	high	high	low
Cost-high volume	low	low	low	high

Abbildung 4: Comparison of Design Styles

FPGA (field programmable gate arrays)

- Logic blocks
- I/O-blocks
- Interconnect

FPGA Design Steps

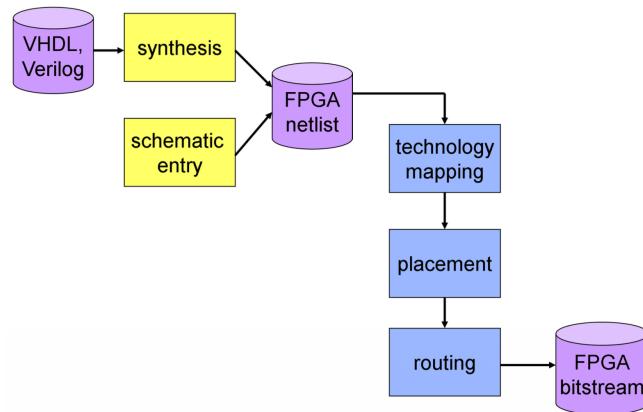


Abbildung 5: FPGA design steps

FPGA - Application Areas

- Glue Logic
- Rapid Prototyping, Emulation
- Embedded Systems
 - when processors are too slow or too power-inefficient and
 - * flexibility is a must
 - * the sale volumes are too low to afford ASIC
- Custom Computing
 - Goal: Combine flexibility of processors with efficient advantages of ASICs
 - e.g. Outsourcing a complex task from SW to HW

System models

Dataflow Graph (DFG)

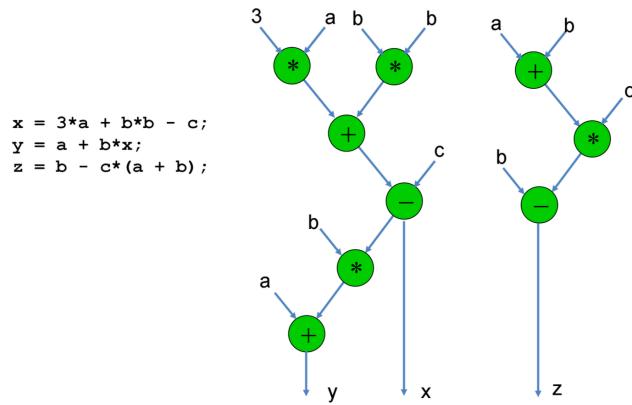


Abbildung 6: Data Flow Graph

Control flow graph (CFG)

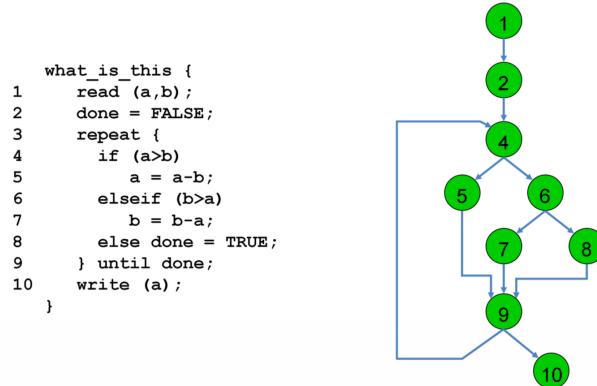


Abbildung 7: Control Flow Graph

Sequencing Graphs

- Hierarchy of entities
 - entities modeling the data flow
 - hierarchy modeling the control flow
- Special nodes
 - Start/End nodes: NOP
 - Branch nodes: BRANCH
 - Iteration nodes: LOOP
 - Module call nodes: CALL
- Attributes
 - Nodes: computation times, costs
 - Edges: conditions for branches, iterations

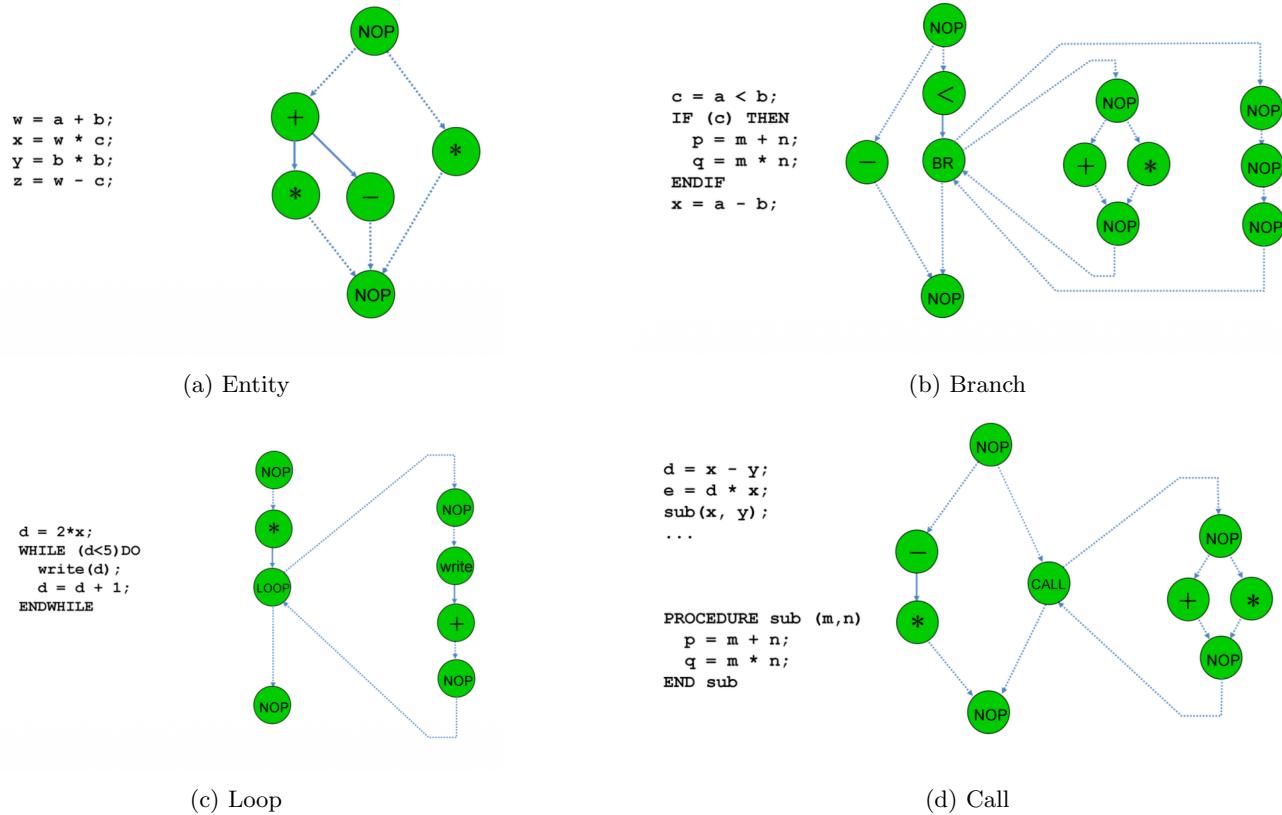


Abbildung 8: Sequencing Graph

Scheduling

- static vs. dynamic
- preemptive vs. non-preemptive
- with vs. without resource constraints
- aperiodic vs. periodic (iterative)

Scheduling without resource constraints

- ASAP (as soon as possible)
 - determines the earliest start times of tasks
 - computes the minimal latency
- ALAP (as late as possible)
 - determines the latest start times of tasks (for a given latency bound)
- Mobility of a task is given by the difference between ALAO and ASAP start times
 - Mobility 0 → task on critical path

Definition

Definition: Schedule

A schedule of a sequencing graph $G_S = (V_S, E_S)$ is a function $\tau : V_S \rightarrow \mathbb{N}$ that satisfies:

$$\tau(v_j) - \tau(v_i) \geq d_i \quad \forall (v_i, v_j) \in E_S$$

Definition: Latency

The latency L of a schedule τ of a sequencing graph $G_S = (V_S, E_S)$ is defined as:

$$L = \max_{v_i \in V_S} \{\tau(v_i) + d_i\} - \min_{v_j \in V_S} \{\tau(v_j)\}$$

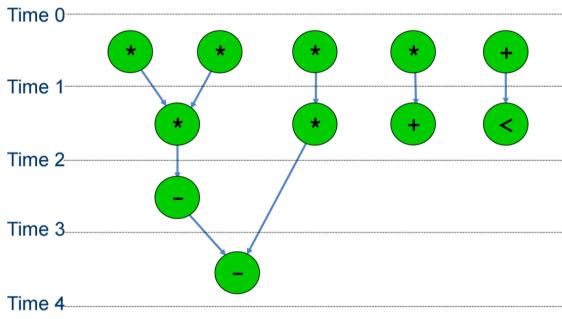
And therefore denotes the number of time steps of the smallest time interval that includes the execution of all nodes $v_i \in V_S$

ASAP

ALAP

List scheduling

- Tasks are sorted into a list according to some priority function
- In each step, each free resource will be assigned a schedulable task of highest priority
- Priority functions: number of successor nodes, mobility, ...



(a) latency-optimal schedule: $L = 4$

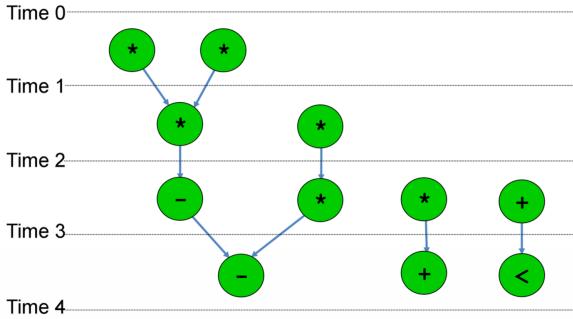
```

1: function ASAP( $G_S(V_S, E_S), d$ )
2:   for each  $v_i$  without predecessor do
3:      $\tau(v_i)^S \leftarrow 0$ 
4:   end for
5:   repeat
6:     Select a node  $v_i$  whose predecessors have all
      been scheduled
7:      $\tau(v_i)^S \leftarrow \max_{j:(v_j, v_i) \in E_S} \{\tau(v_j)^S + d_j\}$ 
8:   until all nodes  $v_i$  scheduled
9:   return  $\tau^S$ 
10: end function

```

(b) ASAP algorithm

Abbildung 9: ASAP



(a) latency bound: $\bar{L} = 4$

```

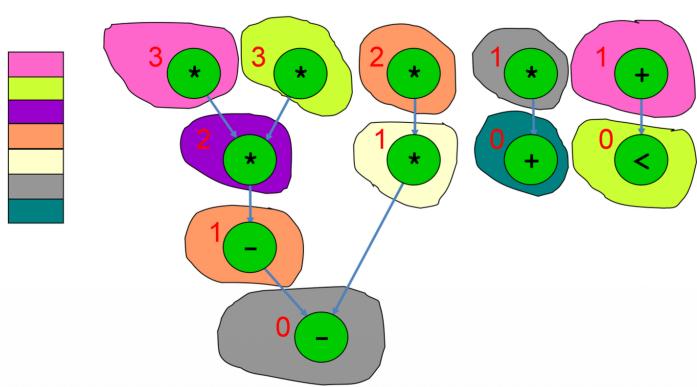
1: function ALAP( $G_S(V_S, E_S), d, \bar{L}$ )
2:   for each  $v_i$  without successor do
3:      $\tau(v_i)^L \leftarrow \bar{L} - d_i$ 
4:   end for
5:   repeat
6:     Select a node  $v_i$  whose successors have all
      been scheduled
7:      $\tau(v_i)^L \leftarrow \min_{j:(v_i, v_j) \in E_S} \{\tau(v_j)^L\} - d_i$ 
8:   until all nodes  $v_i$  scheduled
9:   return  $\tau^L$ 
10: end function

```

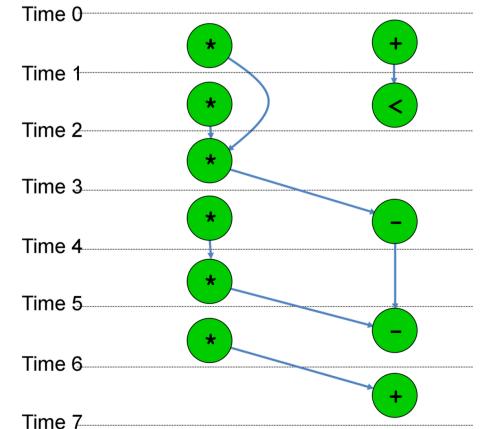
(b) ALAP algorithm

Abbildung 10: ALAP

Periodic scheduling



(a) Priority: Number of successor nodes
Resources: 1 multiplier, 1 ALU (+, -, <)



(b) Result

Abbildung 11: List schedule

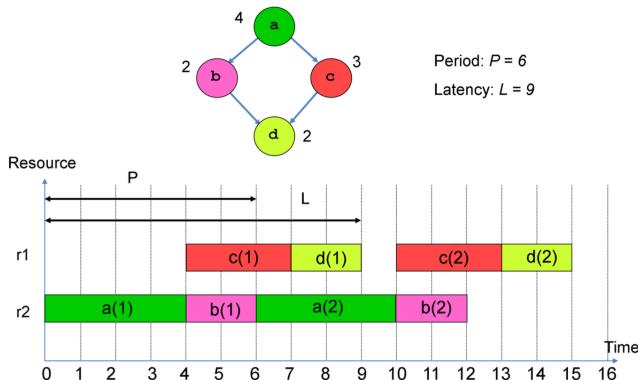


Abbildung 12: Periodic scheduling

Code generation

Double Roof

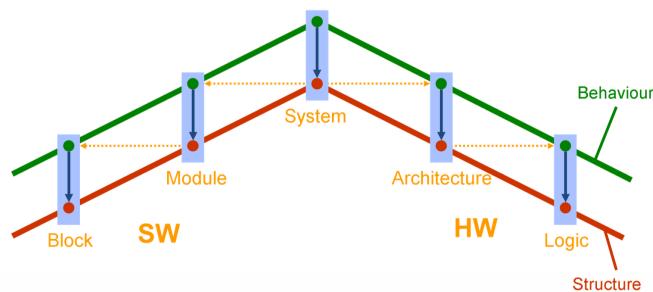
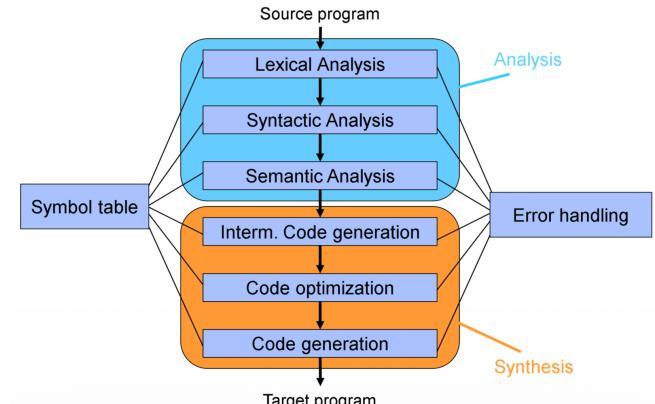
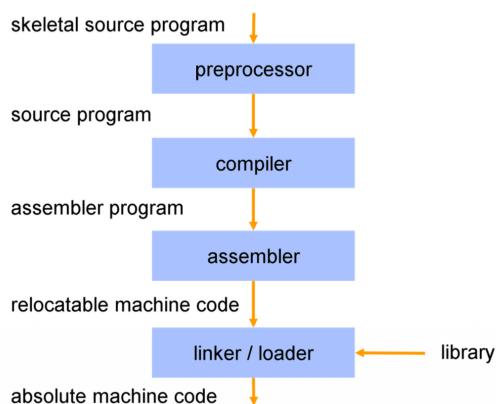


Abbildung 13: Double Roof

Compiler - Basics



(a) Compilation Process

(b) Compilation Process

Abbildung 14: Compiler

Analysis

- Lexical Analysis
 - scan source program and decompose it into symbols

- regular expression: recognition through finite automata
 - syntactic analysis
 - parse sequences of symbols and determine clauses
 - clauses are described by a context free grammar
 - * $Z \rightarrow \text{Identifier} := A$
 - * $A \rightarrow A + A \mid A * A \mid \text{Identifier} \mid \text{Number}$
 - semantic analysis
 - assure that the pieces fit together semantically
 - Example: type conversion

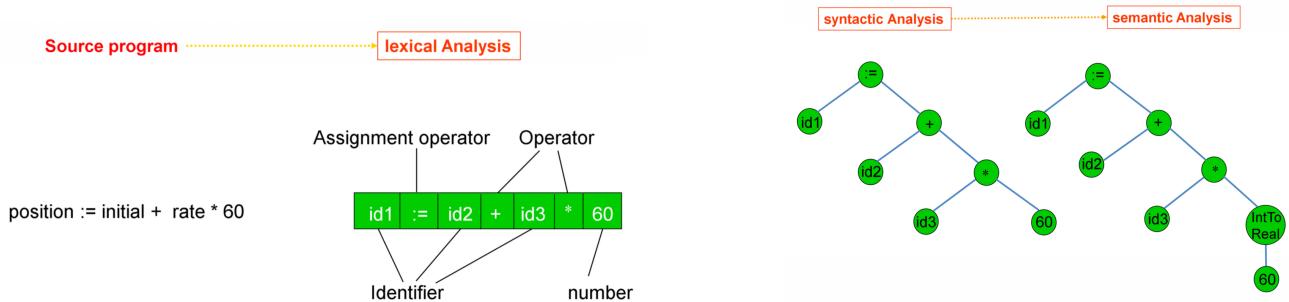


Abbildung 15: Analysis Example

Synthesis

- Generation of intermediate code
 - machine independent → retargeting easier
 - easy to generate
 - easy to be translated
 - Optimization
 - General-purpose processors: fast code, fast translation
 - Special processors: fast code, compact code, small memory image
 - of intermediate code or of target code
 - Code generation

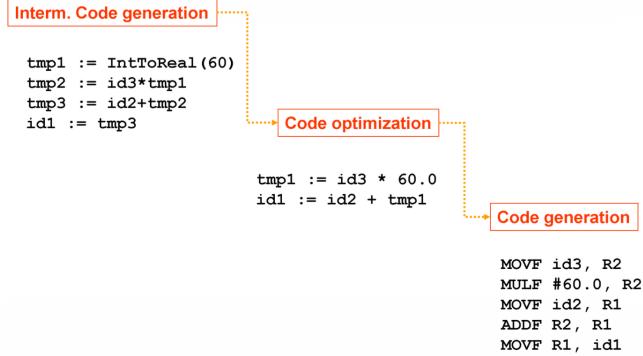


Abbildung 16: Synthesis Example

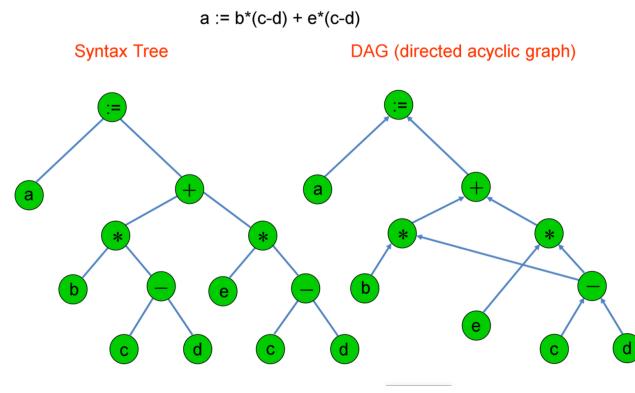


Abbildung 17: Syntax Tree and DAG

Syntax Tree abd DAG

3-Address Code

- Instructions
 - maximum 3 addresses (2 operands, 1 result)
 - maximum 2 operands
- Assignments
 - $x := y \text{ op } z$
 - $x := \text{op } y$
 - $x := y$
 - $x := y[i]$

- $x[i] := y$
- $x := &y$
- $y := *x$
- $*x := y$

- Control flow

- `goto L`
- `if x relop y goto L`

- Sub programs

- `param x`
- `call p,n`
- `return y`

- Advantages

- resolution of lengthy expressions and nested loops
- temporary names allow for easy reordering
- represents already a valid schedule

- Definition

- $x := y \text{ op } z$
- defines x and uses y and z

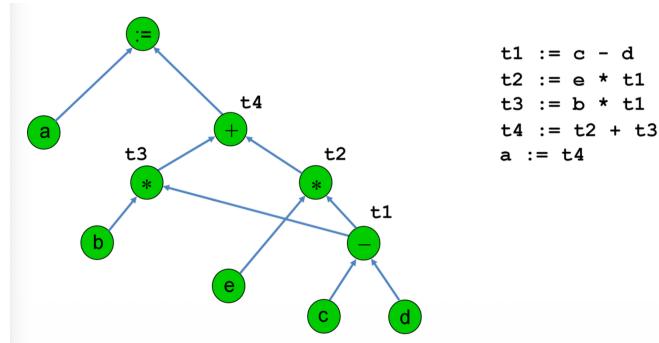


Abbildung 18: Generation of 3-address-code from DAG

Basic Block

Definition: A basic block is a sequence of consecutive instructions in which the control flow enters at the beginning and leaves at the end without branching except at the end.

Sequence of 3-address instructions → set of basic block:

- Determine block start points:

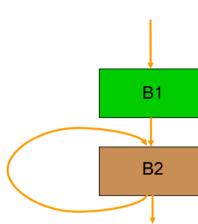
- the first instruction
- targets of branch and jump instructions
- instructions directly following a branch or jump instruction

- Determination of basic blocks

- each basic block includes its block start point
- includes all instructions (but excluding) the next block start point or until the program ends

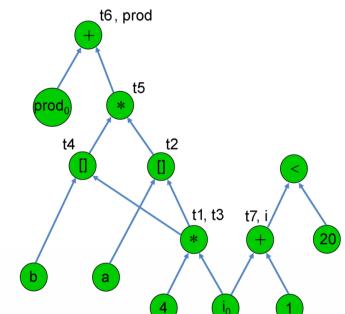
CFG and DAG for basic blocks

```
(1) prod := 0      B1
(2) i := 0
(3) t1 := 4 * i    B2
(4) t2 := a[t1]
(5) t3 := 4 * i
(6) t4 := b[t3]
(7) t5 := t2 * t4
(8) t6 := prod + t5
(9) prod := t6
(10) t7 := i + 1
(11) i := t7
(12) if i < 20 goto (3)
```



(a) Degenerated Control Flow Graph

```
t1 := 4 * i
t2 := a[t1]
t3 := 4 * i
t4 := b[t3]
t5 := t2 * t4
t6 := prod + t5
prod := t6
t7 := i + 1
i := t7
if i < 20 goto (3)
```



(b) Directed acyclic graph

Abbildung 19: CFG and DAG for basic blocks

Code generation

- Requirements
 - correct code
 - efficient code
 - efficient code generation
- Code generation = Software synthesis
 - Allocation: often given

- Binding:
 - * Register allocation, register binding
 - * Code (instruction) selection
- Scheduling
 - * Instruction sequencing
- Goal: efficient register usage
 - instructions on register operands typically shorter and faster as instructions with memory operands
- Register allocation, register binding
 - determine at each point of the program the set of variables that shall be stored in a register
 - bind each variable to a physical register
 - optimal register binding is a NP-complete problem
 - additional constraints given by special registers of the CPU architecture, compiler and operating system

Code (Instruction) Selection

- Code pattern for implementing a 3-address instruction [fig. 20]
- Problems
 - often inefficient code → Code optimization
 - There may be many alternative instructions
 - some instructions are only executable on certain registers
 - exploitation of special processor properties

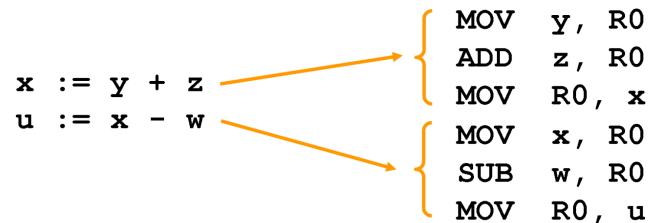


Abbildung 20: 3-address to assembler

Scheduling

Goal: efficient instruction execution sequences, as short as possible, using few registers

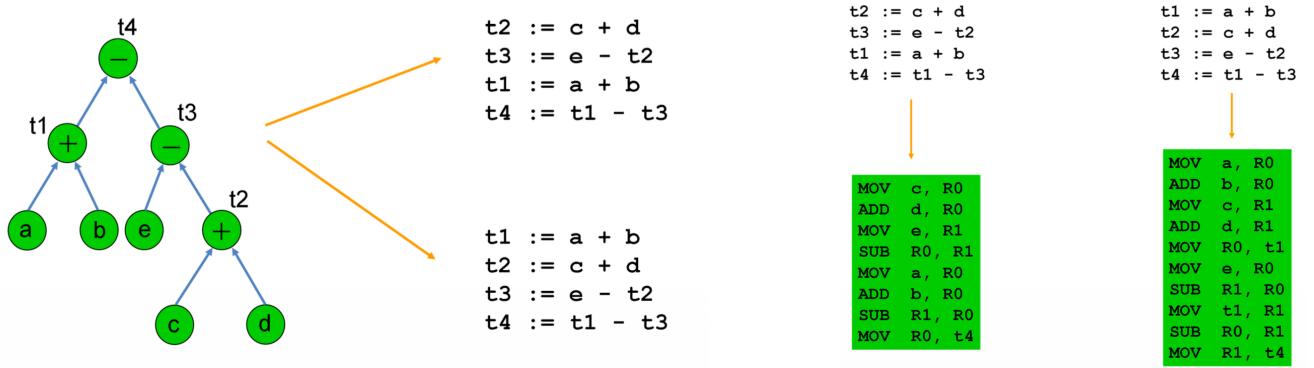


Abbildung 21: Scheduling differences

Register allocation

- global register allocation
 - reserve a certain number of registers
 - * for global variables
 - * for loop variables
 - * for variables in basic blocks
 - user-defined register allocation
 - * E.g. in programming language C:

```
register int i;
```
- Usage counters
- Register assignment through graph coloring

Usage Counters

- Let a loop L be composed of multiple basic blocks
- In case a variable **a** is kept in a register during execution of Loop L, we obtain cost savings
 - 1 cost unit for each reference to **a**
 - * ADD R0, R1 (cost 1) instead of ADD a, R1 (cost 2)
 - 2 cost units for each basic block, if **a** is defined in the basic block and active still thereafter
 - * no store necessary (MOV R0, a)
- Cost savings for the whole loop

$$\sum_{B \in L} (\text{verwendet}(a, B) + 2 \cdot \text{aktiv}(a, B))$$

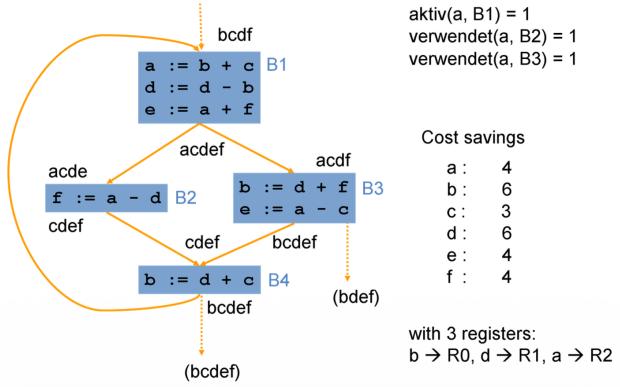


Abbildung 22: Usage Counter - Example

Variables in brackets are given. Start from bottom. Variables below basic block remain active. Basic block depends on variables above.

- verwendet(a, B) denotes the number of uses of a in basic block B before potentially being defined therein
- aktiv(a, B) equals 1, if a has been defined in B and is active at the end of B ; else 0
- Approximation of cost savings for assumption that
 - all basic blocks are executed equally often
 - loop will be executed often

Register Binding using Graph Coloring

- Flow
 1. Apply code generation assuming unbounded number of available registers, i.e. each variable is assigned to a unique symbolic register
 2. Determine the life time of each variable
 3. Construct a conflict graph
 4. Mapping of symbolic registers onto physical registers through graph coloring
- Nodes represent the symbolic registers and edges represent conflict between variables
- Heuristics: Is a graph G colorable with I colors?
 1. Determine a node $v_i \in G$ of degree $\text{Grad}(v_i) < I$
 2. Eliminate v_i and all incident edges to obtain a graph G'
 3. If $G' = \emptyset$:
 - I -coloring possible

If all nodes in G' have degree $\geq I$:

- I -coloring not possible

$G = G'$ and goto 1

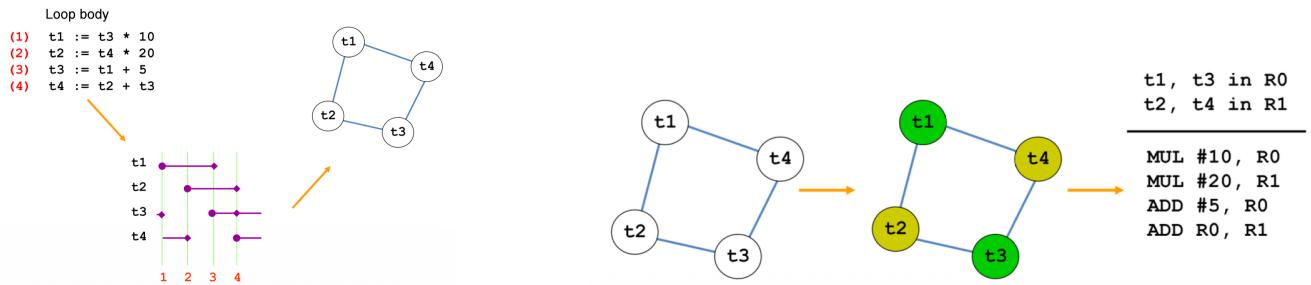


Abbildung 23: Register conflict graph - Example

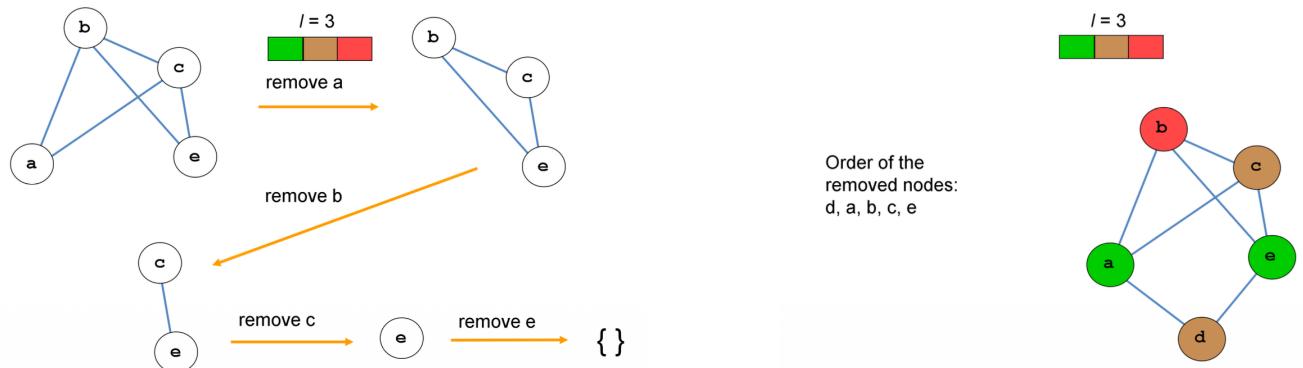


Abbildung 24: Graph coloring - Example

Code Generation for DAGs

- The order of evaluation of the nodes pf a DAG may have a great influence on the number of required instructions
- Heuristic for determination of a feasible evaluation order:

```

while there exists any non-ranked inner node do
    choose a node n whose parents have been ranked and rank it
    while the furthest left child m of n has no unranked parents and is no leaf do
        rank node m
  
```

```

n <- m
end while
end while

```

- For a DAG with n nodes that is a tree there is an algorithm that determines optimal code in time $\mathcal{O}(n)$
- common subexpressions
 - If the DAG is not a tree → split the DAG at nodes that represent common subexpressions and generate optimal code for each part

Dynamic Programming

- Machine model extended to more complex instructions
 - n Register $R_0 \dots R_{n-1}$
 - Instructions $R_i := E$
 E is an arbitrary expression including registers and memory locations as operands
 - In case E contains multiple registers, then R_i must be one of them
 - Load: $R_i := M$, Store: $M := R_i$, Move/Copy: $R_i := R_j$
- Examples
 - ADD $R_0, R_1 \rightarrow R_1 := R_1 + R_0$
 - ADD $*R_0, R_1 \rightarrow R_1 := R_1 + \text{ind } R_0$
 - SUB $a, R_0 \rightarrow R_0 := R_0 - a$
- Optimal code for $E = (T_1 \text{ op } T_2)$:
 1. Optimal code for T_1, T_2
 2. Either $T_1, T_2, \text{ op}$ or $T_2, T_1, \text{ op}$
- Method runs in 3 phases
 1. Computation of cost vectors
 2. Determination of execution orders
 3. Generation of target code
- Determination of cost vectors for each node n (bottom up)
 - $C[i]$ optimal cost for computing n with i available registers
 - $C[0]$ optimal cost for computing n when result is stored in memory

Code Optimization

- Transformations possible on either intermediate code or on target code
- Peephole Optimization
 - small window is moved over code
 - multiple runs, as one optimization may trigger another one
- Local Optimization
 - Transformation on basic blocks
- Global Optimization
 - Transformations affecting multiple basic blocks

Peephole Optimization

- Elimination of redundant assignments

(1) `MOV R0, a`
(2) `MOV a, R0`

↓

(1) `MOV R0, a`

- Algebraic simplification
 $x := y + 0 * a; \rightarrow x := y;$
- Control flow optimization

(1) `goto L1`
(2) `L2 goto L2`

↓

(1) `goto L2`
(2) `L1 goto L2`

- Operator (strength) reduction
 $x := y*8; \rightarrow x := y << 3;$
 $x := y**2; \rightarrow x := y*y;$
- Common subexpression elimination

```
(1) a := b + c  
(2) b := a - d  
(3) c := b + c  
(4) d := a - d
```

↓

```
(1) a := b + c  
(2) b := a - d  
(3) c := a  
(4) d := b
```

- Variable renaming

$t := b + c \rightarrow u := b + c$

- Instruction interchange

```
t1 := b + c  
t2 := x + y
```

↓

```
t2 := x + y  
t1 := b + c
```

Global Optimization

- Passive code elimination

– An assignment that defines x can be eliminated, if x is not used thereafter

- Copy propagation

```
(1) x := t1  
(2) a[t2] := t3  
(3) a[t4] := x  
(4) goto L
```

↓

```
(1) x := t1  
(2) a[t2] := t3  
(3) a[t4] := t1  
(4) goto L
```

- Code motion

```
while (i <= limit*4+2) {...}
```

↓

```
t = limit*4+2;  
while (i <= t)
```

- Induced variables and operators

```
j := n  
(1) j := j - 1  
(2) t4 := 4 * j  
(3) t5 := a[t4]  
(4) if t5 > v goto (1)
```

↓

```
j := n  
t4 := 4 * j  
(1) j := j - 1  
(2) t4 := t4 - 4  
(3) t5 := a[t4]  
(4) if t5 > v goto (1)
```

Code generation for special-purpose processors

- Software design for embedded systems
 - transition from assembly to High-Level Language programming
- Major requirements on code generation
 - correctness
 - speed of generation
 - compact code
- Further requirements on HLL and compiler
 - safety: formal verification of compiler
 - specification of real-time constraints
 - support for DSP algorithms/architectures
 - retargetability: can the compiler be retargeted easily?
- Non-homogeneous register architectures, irregular data paths
 - Tight coupling of the phases of register binding, code selection and scheduling

- Assignment of memory addresses and address registers
 - Efficient usage of address registers and specialized address generation units
- Code compression
 - Reduction of memory footprint, important in cost-sensitive applications

Register Transfer Graph

- Definition: The register transfer graph of a processor is a directed graph, in which each node corresponds to a location in the data path where data may be stored. An edge between two nodes r_i and r_j is labeled with those instructions that read from r_i and write r_j

RTG - Criterion

- Definition: The RTG criterion is satisfied, if for all nodes r_1, r_2 and r_3 of the RTG for which
 - r_3 has incoming register nodes r_1 and r_2 with the same labeling
 - There exists at least a cycle between r_1 and r_2

In any cycle including r_1 and r_2 exists a memory node

→ Processors satisfying the RTG criterion, an optimal schedule may be generated in $\mathcal{O}(n)$ (n is the number of DAG nodes)

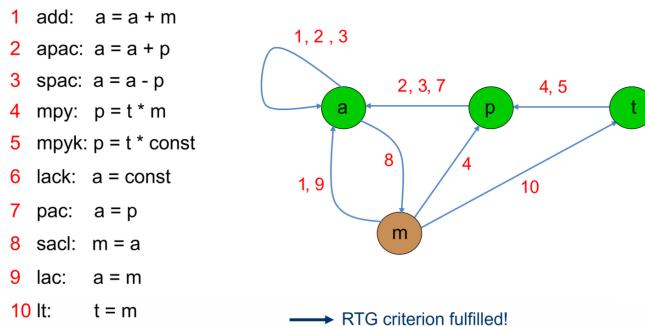


Abbildung 25: RTG for TMS320C25

Retargetable compiler

- Machine-independent compiler (automatically retargetable)
 - Compiler has built-in code generators for multiple targets
 - Often used in parametric architecture
- Compiler-Compiler (user retargetable)

- Compiler is generated from a description of target architecture
- portable Compiler (developer retargetable)

Processor Models

- Behavioral
 - Describes the instruction set
 - Relatively fast simulation possible
 - Inaccuracy
- Structural
 - Describes the processor at RTL
 - Accurate
 - Simulation much slower
 - Not always available
- Mixed models

Tree-translation schemes

- Rules for transforming a syntax tree (resp. DAG)

Partitioning

Models for System Synthesis

- Allocation + Binding = Partitioning
- Problem graph
 - Nodes: functional and communication task
 - Edges: dependencies
- Architecture graph
 - Nodes: functional and communication resources
 - Edges: directed communication resources
- Specification graph
 - Problem graph + Architecture graph + Mapping edges

Partitioning

- Abstraction level
 - Structural partitioning: RTL, netlists
 - * System relatively well known
 - * No more comparison of design alternatives possible
 - Functional partitioning: system level
 - * Comparison of design alternatives possible
 - * Quality of designs still not accurate → Estimation, Rapid Prototyping
- Cost(objective) function - Example:
 - $f(C, L, P) = k_1 \cdot h_c(C, \bar{C}) + k_2 \cdot h_L(L, \bar{L}) + k_3 \cdot h_p(P, \bar{P})$
 - System cost C , Latency L and Power consumption P
- Problem definition: Group n objects $O = \{o_1, \dots, o_n\}$ into m blocks $P = \{p_1, \dots, p_m\}$ such that
 - $p_1 \cup \dots \cup p_m = O$
 - $p_i \cap p_j = \emptyset \quad \forall i, j : i \neq j$
 - while minimizing the cost $c(P)$
 - The general partitioning problem is NP-complete

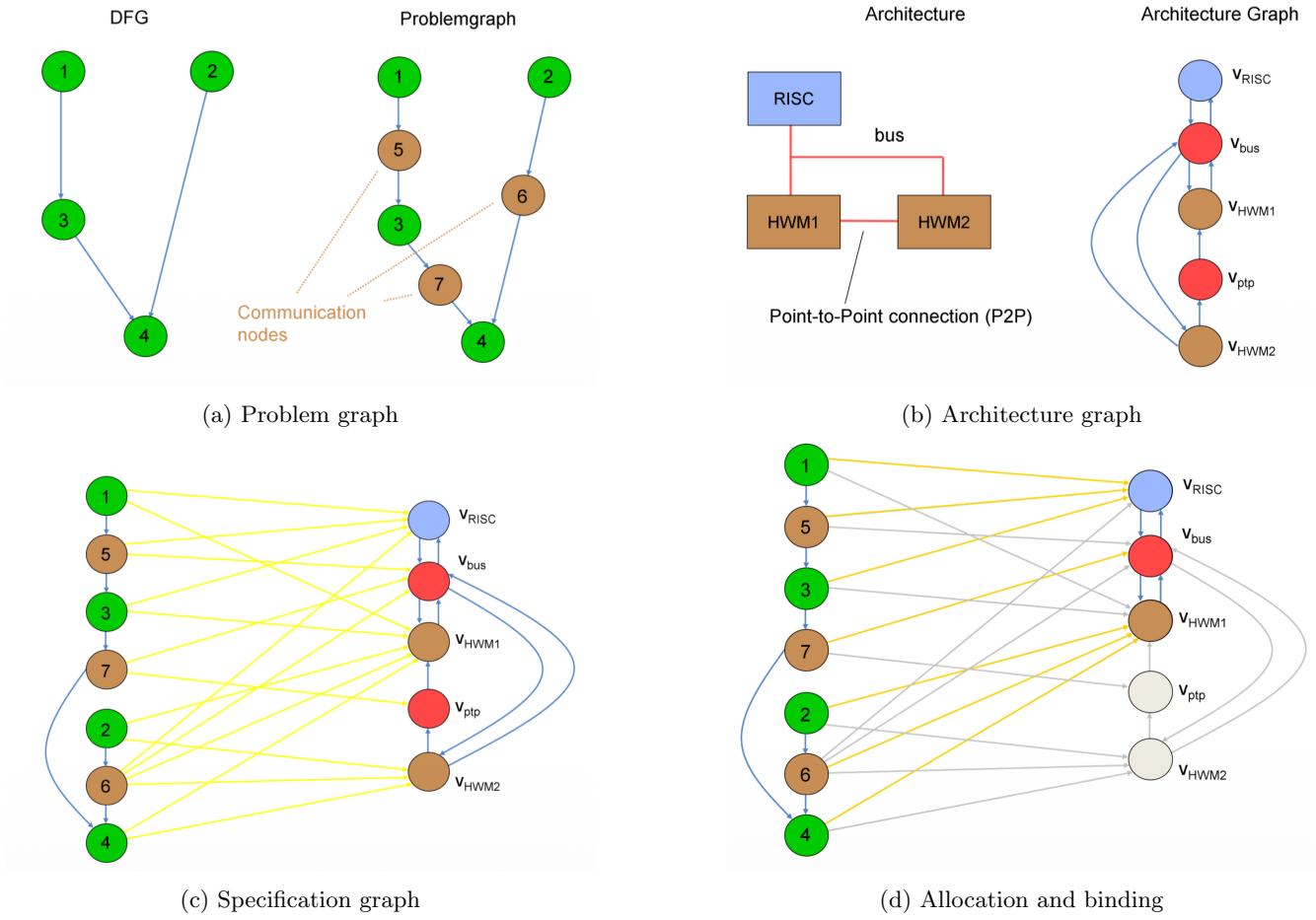


Abbildung 26: Models for System Synthesis

General partitioning methods

- Heuristics
 - Constructive methods
 - * Random mapping
 - * Hierarchical clustering (!!! Bullshit !!!)
 - Iterative improvement methods
 - * Kernighan-Lin algorithm
 - * Simulated Annealing
 - Evolutionary algorithms
- Exact techniques
 - Enumeration of solution space
 - Integer Linear Program (ILP)

Constructive Methods

- Random Mapping
 - Each object is mapped randomly to a block
- Hierarchical clustering
 - Stepwise grouping of objects using a closeness function that indicates how beneficial it is to group two objects together
- Constructive methods
 - Are often used to find an initial partition for methods of iterative improvement
 - Have a problem in defining suitable closeness functions

Kernighan-Lin Algorithm

- Creation of bi-partitions
 - Group the object into the other group that causes the greatest decrease in cost
 - May escape local minima
 - As long as a better partition is found
 - * Tentatively group of the n objects the "best", then from the $n - 1$ remaining again, until each object has been re-grouped at least once
 - * From these n partitions, take the one with the minimal cost and perform the respective re-grouping
 - * robust method, in $\mathcal{O}(n^2)$
 - Partitioning into m blocks: $\mathcal{O}(mn^2)$

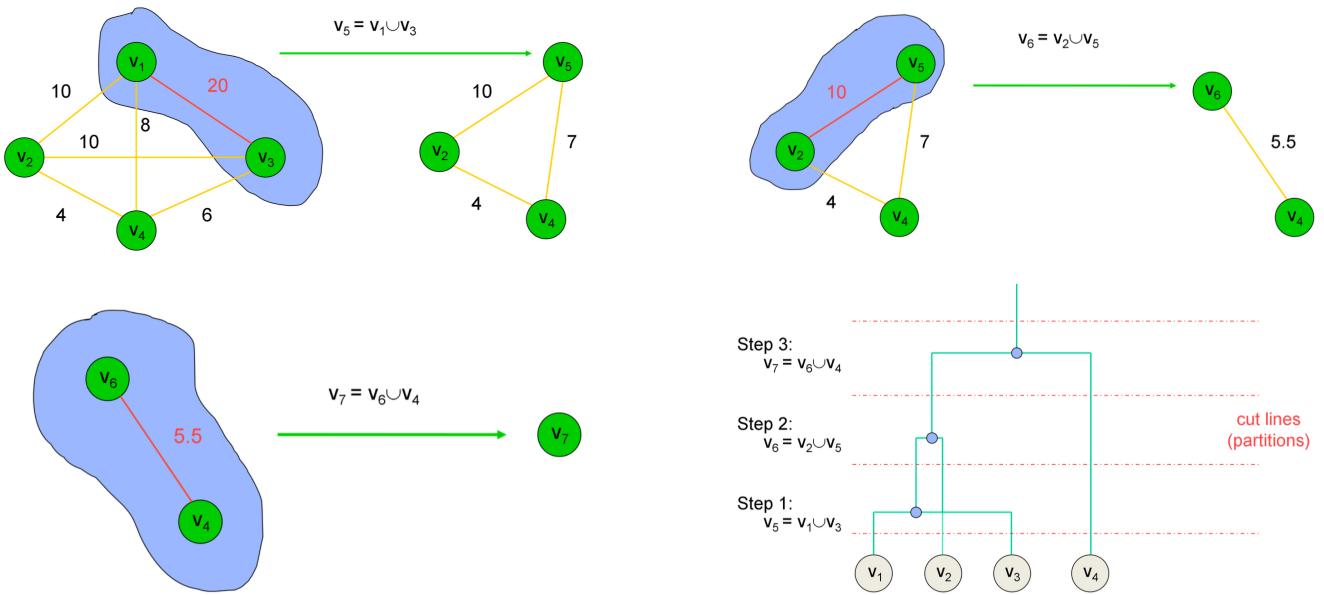


Abbildung 27: Hierarchical Clustering - Example

Simulated Annealing

- Time complexity:
 - From exponential to constant, depending on the implementation of the functions **Equilibrium**, **DecreaseTemp** and **Frozen**
 - The longer the executions times, the better the results
 - Goal: polynomial execution time

```

(1) temp <- temp_start
(2) cost <- c(P)
(3) while Frozen = false do
(4)   while Equilibrium = false do
(5)     P' <- RandomMove(P)
(6)     cost' <- c(P')
(7)     deltaxcost <- cost' - cost
(8)     if Accept(deltaxcost, temp) > Random(0, 1) then
(9)       P <- P'
(10)      cost <- cost'
(11)    end if
(12)  end while
(13)  temp <- DecreaseTemp(temp)
(14) end while
  
```

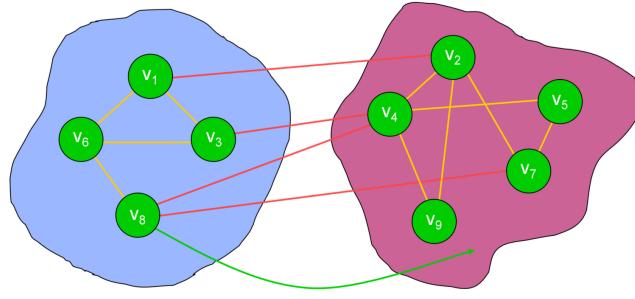


Abbildung 28: Kernighan-Lin Algorithm

Integer Linear Programs

- Conditions are modeled as constraints of the ILP
Example: maximum number h_k of objects in block p_k

$$\sum_{i=1}^n x_i, k \leq h_k \quad 1 \leq k \leq m$$

- ILP is an exact method, NP-complete
- may be applied successfully for problems
 - Of small size
 - If objective function and constraints are linear

Algorithms for HW/SW-Partitioning

- The easiest problem instance is a bi-partitioning problem $P = \{p_{SW}, p_{HW}\}$
- Software-oriented approach: $P = \{O, \emptyset\}$
 - Easy, as when starting with SW specification, all functions are implementable
 - Performance constraints may not be satisfied → Migration of objects to HW
- Hardware-oriented approach: $P = \{\emptyset, O\}$
 - Performance certainly satisfied if all objects are initially implemented in HW
 - Cost constraints may not be satisfied → Migration of objects to SW

Greedy Algorithms

- Migration of objects into the other block until no further improvements observable

```

(1) repeat
(2)   P_old <- P
(3)   for i <- 1 to n do
(4)     if f(MOVE(P, o_i)) < f(P) then
(5)       P < MOVE(P, o_j)
(6)     end if
(7)   end for
(8) until P = P_old

```

- $f(x)$ is cost function

Basic of Evolutionary Algorithms

- Algorithms that are based on the optimization of evolution
- „Individual“ → Structure (solution)
- „Genotype“ → Coded solution (only GAs)
- „Phenotype“ → Decoded solution (only GAs)
- „Population“ → Set of individuals
- „Fitness“ → Quality of an individual
- Evolutionary operators
 - Selection
 - Recombination
 - Mutation

Design space exploration

- Design space → Different implementations of a specification
- Design point → One Implementation
- Optimization → Determination of the „best“ implementation
- Pareto-point → Non-dominant design point

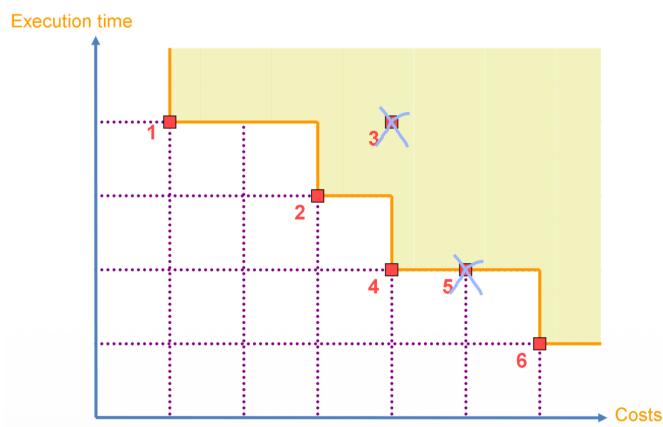
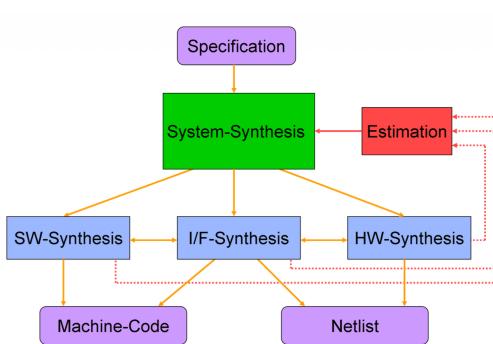


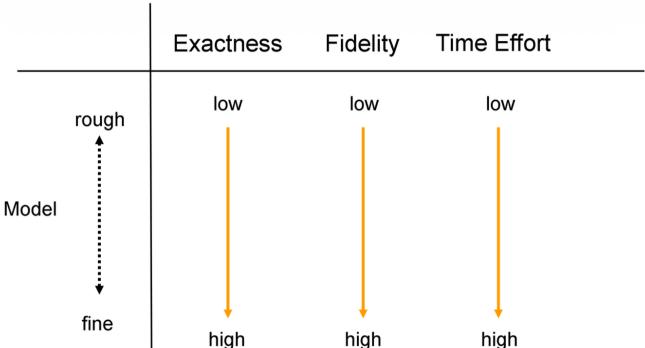
Abbildung 29: Pareto optimal design space exploration

Estimation

Properties of estimation techniques



(a) System-Level Design



Exactness

Let $E(D)$ be an estimated and $M(D)$ the exact quality of an implementation D . The exactness A is defined as

$$A = 1 - \frac{|E(D) - M(D)|}{M(D)}$$

Fidelity

Let $D = \{D_1, \dots, D_n\}$ be a set of implementations. The fidelity F of an estimation technique is the percentage of correct pairwise comparisons

$$F = 100 \cdot \frac{2}{n(n-1)} \cdot \sum_{i=1}^n \sum_{j=i+1}^n \mu_{i,j}$$

$$\mu_{i,j} = \begin{cases} 1 & \text{if } (E(D_i) > E(D_j) \wedge M(D_i) > M(D_j)) \\ & \vee (E(D_i) < E(D_j) \wedge M(D_i) < M(D_j)) \\ & \vee (E(D_i) = E(D_j) \wedge M(D_i) = M(D_j)) \\ 0 & \text{else} \end{cases}$$

Qualities

- Performance
 - Hardware (clock period, latency, execution time, data rate)
 - Software (execution time)
 - Communication (maximal/average bit rate)

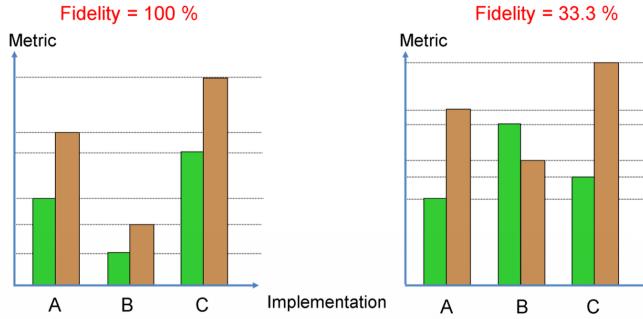


Abbildung 31: Fidelity
Green: Estimation
Brown: Measurement

- Cost
- Further qualities
 - Power consumption
 - Testability

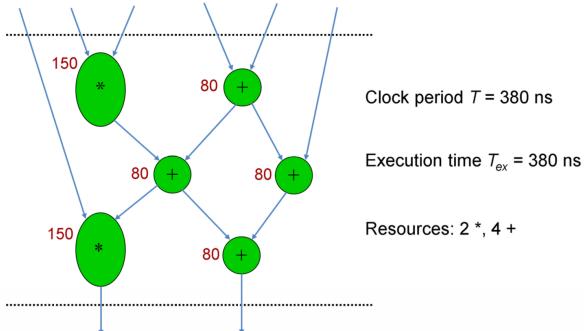
HW Performance

- Clock period $T \rightarrow$ Longest combinational path in circuits and technologies
- Latency $L \rightarrow$ Execution time in clock cycles
- Execution time $\rightarrow T_{ex} = T \cdot L$
- Data rate $R \rightarrow$ Pipelining with P steps of equal length: $R = \frac{P}{T_{ex}}$

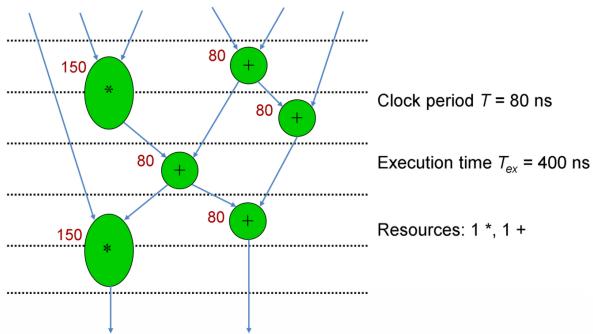
SW Performance

- Execution time T
 - I_c : Instruction count of a program
 - CPI : Cycles per instruction (average)
 - τ : Clock period
 - f : Clock frequency
- MIPS rate (million instructions per second)

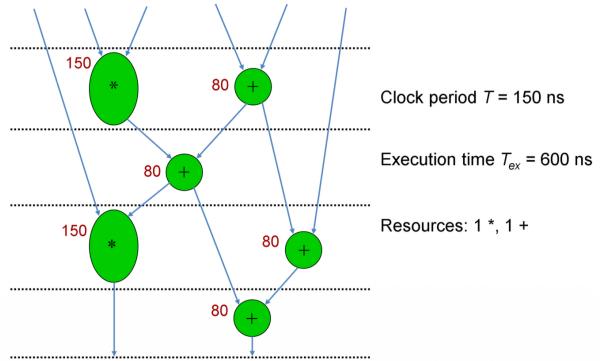
$$MIPS = \frac{I_c}{\tau \cdot 10^6} = \frac{f}{CPI \cdot 10^6}$$



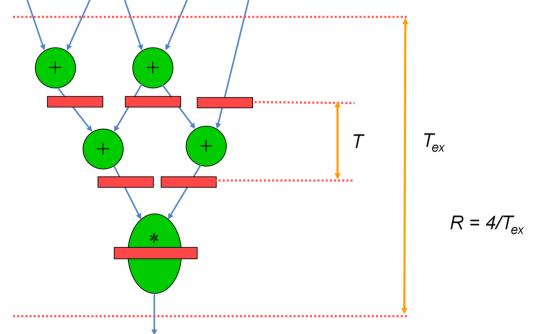
(a) Clock period T = longest path



(c) Clock period T = shortest unit



(b) Clock period T = longest unit



(d) Pipelining

- MFLOPS (million floating-point operations per second)
- MACS (million multiply and accumulates per second)
- MOPS (million operations per second)

Communication Performance

- Model for communication time T_{comm}

$$T_{comm} = T_{offset} + \frac{\text{message size}}{\text{bitrate}}$$

- T_{offset} : time for initialization
- message size in Bit
- bitrate in Bit/sec

Cost measures

- Hardware

- Cost often proportional to area of circuit:
 - * mm^2 , λ^2
 - * number of transistors
 - * number of gates
 - * number of CLBs (FPGA)
- number of pins
- Software
 - Size of required program and data memory

Estimation of hardware

- Given: functional units v_k with delay $\text{del}(v_k)$
 - Method of maximum operator delay:
- $$T = \max_k(\text{del}(v_k))$$
- Method for minimization of clock slack
 - Search in the interval $T_{\min} \dots T_{\max}$ for clock period T producing the highest clock utilization
 - ILP search

Clock slack minimization

- Let $\text{occ}(v_k)$ denote the number of occurrences of operations of type k and $|V_T|$ the number of different operation types.
Then, the average slack is given as

$$\text{avgslack}(T) = \frac{\sum_{k=1}^{|V_T|} (\text{occ}(v_k) \cdot \text{slack}(T, v_k))}{\sum_{k=1}^{|V_T|} \text{occ}(v_k)}$$

And the clock utilization as

$$\text{util}(T) = 1 - \frac{\text{avgslack}(T)}{T}$$

Estimation of Software

- Execution time
 - Profiling: compilation and many test runs \rightarrow statistical properties
 - Estimation on the level of source-/intermediate-/target-code
 - Important for applications with hard real-time constraints \rightarrow Worst-Case Execution Time (WCET)
- Memory requirements
 - Program memory: compilation, estimation
 - Data memory (only in case of static memory allocation)

Worst-Case Execution Time (WCET)

- May not be determined by profiling
- Estimation using program path analysis techniques

Program Path Analysis

- Delivers a WCET estimation that is greater or equal to WECT, but a good estimation is close to real WCET
- Processor model
 - Processor without interrupts and OS
- Programming model
 - No recursive function calls
 - No pointer operations
 - Loops must have static bounds

WECT Computation

Let a program consist of N basic blocks, each block B_i having an execution time of c_i and being executed x_i times during program execution. Then, a WCET estimate may be calculated as

$$\text{WECT} = \max \left\{ \sum_{i=1}^N c_i \cdot x_i \mid \text{constraints} \right\}$$

Functional Constraints

- Defined by the programmer
 - Bounds of loop counter
 - Knowledge of program context
- May be complex